

YASKAWA AC Drive P1000

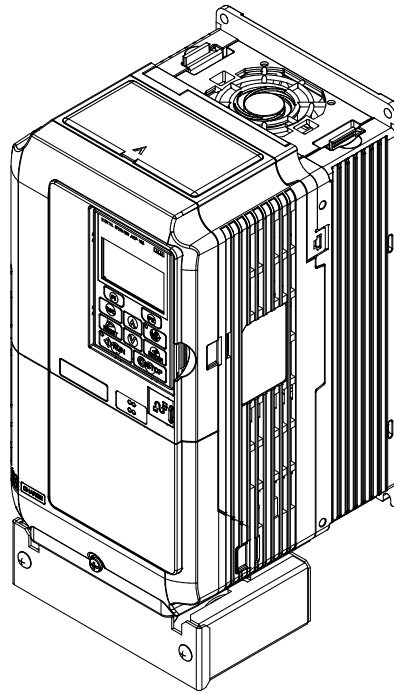
Industrial Fan and Pump Drive

Technical Manual

Type: CIMR-PU

Models: 200 V Class: 3/4 to 175 HP ND
400 V Class: 3/4 to 1000 HP ND
600 V Class: 1 to 250 HP ND

To properly use the product, read this manual thoroughly and retain for easy reference, inspection, and maintenance. Ensure the end user receives this manual.



Receiving **1**

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◆ Quick Reference

| Easily Set Parameters for Specific Applications | |
|--|---|
| Preset parameter defaults are available for setting up applications. Refer to Application Selection on page 126. |  |
| Perform Auto-Tuning | |
| Automatic tuning sets motor parameters. Refer to Auto-Tuning on page 129. | |
| Maintenance Check Using Drive Monitors | |
| Use drive monitors to check if fans, capacitors, or other components require maintenance. Refer to Performance Life Monitors Maintenance Monitors on page 343. | |
| Fault Display and Troubleshooting | |
| Refer to Drive Alarms, Faults, and Errors on page 291 and Refer to Troubleshooting without Fault Display on page 329. | |
| Standards Compliance | |
| Refer to European Standards on page 542 and Refer to UL and CSA Standards on page 550 ^{<1>} . |  |

<1> CE marking applies to 200 V class and 400 V class models only.

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Preface & General Safety

This section provides safety messages pertinent to this product that, if not heeded, may result in fatality, personal injury, or equipment damage. Yaskawa is not responsible for the consequences of ignoring these instructions.

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i.1 Preface

Yaskawa manufactures products used as components in a wide variety of industrial systems and equipment. The selection and application of Yaskawa products remain the responsibility of the equipment manufacturer or end user. Yaskawa accepts no responsibility for the way its products are incorporated into the final system design. Under no circumstances should any Yaskawa product be incorporated into any product or design as the exclusive or sole safety control. Without exception, all controls should be designed to detect faults dynamically and fail safely under all circumstances. All systems or equipment designed to incorporate a product manufactured by Yaskawa must be supplied to the end user with appropriate warnings and instructions as to the safe use and operation of that part. Any warnings provided by Yaskawa must be promptly provided to the end user. Yaskawa offers an express warranty only as to the quality of its products in conforming to standards and specifications published in the Yaskawa manual. **NO OTHER WARRANTY, EXPRESS OR IMPLIED, IS OFFERED.** Yaskawa assumes no liability for any personal injury, property damage, losses, or claims arising from misapplication of its products.

This manual is designed to ensure correct and suitable application of drives. Read this manual before attempting to install, operate, maintain, or inspect a drive and keep it in a safe, convenient location for future reference. Be sure you understand all precautions and safety information before attempting application.

◆ Applicable Documentation

The following manuals are available for P1000 series drives:

| | |
|--|---|
|  | P1000 Series AC Drive Technical Manual (SIEPYAIP1U01) |
| | This manual provides detailed information on parameter settings, drive functions, and MEMOBUS/Modbus specifications. Use this manual to expand drive functionality and to take advantage of higher performance features. This manual is available for download on our documentation website, www.yaskawa.com . |
| | P1000 Series AC Drive Quick Start Guide (TOEPYAIP1U01) |
| | Read this guide first. This guide is packaged together with the product and contains basic information required to install and wire the drive. It also gives an overview of fault diagnostics, maintenance, and parameter settings. The purpose of this guide is to prepare the drive for a trial run with an application and for basic operation. This manual is available for download on our documentation website, www.yaskawa.com . |

◆ Symbols

Note: Indicates a supplement or precaution that does not cause drive damage.



Indicates a term or definition used in this manual.

◆ Terms and Abbreviations



- **Drive:** Yaskawa P1000-Series Drive
- **BCD:** Binary Coded Decimal
- **H:** Hexadecimal Number Format
- **IGBT:** Insulated Gate Bipolar Transistor
- **kbps:** Kilobits per Second
- **MAC:** Media Access Control
- **Mbps:** Megabits per Second
- **r/min:** Revolutions per Minute
- **V/f:** V/f Control

◆ Trademarks

- BACnet is a trademark of the American Society of Heating, Refrigerating, and Air-Conditioning Engineers (ASHRAE).
- CANopen is a trademark of CAN in Automation (CiA).
- CC-Link is a trademark of CC-Link Partner Association (CLPA).
- CompoNet is a trademark of Open DeviceNet Vendor Association, Inc. (ODVA).
- DeviceNet is a trademark of Open DeviceNet Vendor Association, Inc. (ODVA).
- EtherCAT is a trademark of Beckhoff Automation GmbH, Germany.

- EtherNet/IP is a trademark of Open DeviceNet Vendor Association, Inc. (ODVA).
- LonWorks is a trademark of Echelon Corporation.
- MECHATROLINK-I/MECHATROLINK-II are trademarks of MECHATROLINK Members Association (MMA).
- Modbus is a trademark of Schneider Electric.
- PROFIBUS-DP is a trademark of PROFIBUS International (PI).
- PROFNET is a trademark of PROFIBUS International (PI).
- Other companies and product names mentioned in this manual are trademarks of those companies.

i.2 General Safety

◆ Supplemental Safety Information

General Precautions

- The diagrams in this manual may be indicated without covers or safety shields to show details. Replace the covers or shields before operating the drive and run the drive according to the instructions described in this manual.
- Any illustrations, photographs, or examples used in this manual are provided as examples only and may not apply to all products to which this manual is applicable.
- The products and specifications described in this manual or the content and presentation of the manual may be changed without notice to improve the product and/or the manual.
- When ordering a new copy of the manual due to damage or loss, contact your Yaskawa representative or the nearest Yaskawa sales office and provide the manual number shown on the front cover.
- If nameplate becomes worn or damaged, order a replacement from your Yaskawa representative or the nearest Yaskawa sales office.

WARNING

Read and understand this manual before installing, operating or servicing this drive. The drive must be installed according to this manual and local codes.

The following conventions are used to indicate safety messages in this manual. Failure to heed these messages could result in serious or fatal injury or damage to the products or to related equipment and systems.

DANGER

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

WARNING

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

WARNING! may also be indicated by a bold key word embedded in the text followed by an italicized safety message.

CAUTION

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

CAUTION! may also be indicated by a bold key word embedded in the text followed by an italicized safety message.

NOTICE

Indicates a property damage message.

NOTICE: may also be indicated by a bold key word embedded in the text followed by an italicized safety message.

◆ Safety Messages

DANGER

Heed the safety messages in this manual.

Failure to comply will result in death or serious injury.

The operating company is responsible for any injuries or equipment damage resulting from failure to heed the warnings in this manual.

Electrical Shock Hazard

Before servicing, disconnect all power to the equipment.

The internal capacitor remains charged even after the power supply is turned off. The charge indicator LED will extinguish when the DC bus voltage is below 50 Vdc. To prevent electric shock, wait for at least the time specified on the warning label, once all indicators are OFF, measure for unsafe voltages to confirm the drive is safe prior to servicing.

Failure to comply will result in death or serious injury.

WARNING

Sudden Movement Hazard

System may start unexpectedly upon application of power, resulting in death or serious injury.

Clear all personnel from the drive, motor and machine area before applying power. Secure covers, couplings, shaft keys and machine loads before applying power to the drive.

Electrical Shock Hazard

Do not attempt to modify or alter the drive in any way not explained in this manual.

Failure to comply could result in death or serious injury.

Yaskawa is not responsible for any modification of the product made by the user. This product must not be modified.

Do not allow unqualified personnel to use equipment.

Failure to comply could result in death or serious injury.

Installation, maintenance, inspection, and service must be performed only by authorized personnel familiar with installation, adjustment and maintenance of AC drives.

Do not remove covers or touch circuit boards while the power is on.

Failure to comply could result in death or serious injury.

Make sure the protective earthing conductor complies with technical standards and local safety regulations.

Because the leakage current exceeds 3.5 mA in models 4A0414 and larger, IEC/EN 61800-5-1 states that either the power supply must be automatically disconnected in case of discontinuity of the protective earthing conductor or a protective earthing conductor with a cross-section of at least 10 mm² (Cu) or 16 mm² (Al) must be used. Failure to comply may result in death or serious injury.

Always use appropriate equipment for Ground Fault Circuit Interrupters (GFCIs).

The drive can cause a residual current with a DC component in the protective earthing conductor. Where a residual current operated protective or monitoring device is used for protection in case of direct or indirect contact, always use a type B GFCI according to IEC/EN 60755.

Fire Hazard

Do not use an improper voltage source.

Failure to comply could result in death or serious injury by fire.

Verify that the rated voltage of the drive matches the voltage of the incoming power supply before applying power.

Install adequate branch circuit protection according to applicable local codes and this Installation Manual. Failure to comply could result in fire and damage to the drive or injury to personnel.

WARNING

The device is suitable for use on a circuit capable of delivering not more than 100,000 RMS symmetrical amperes, 240 Vac maximum (200 V class) and 480 Vac maximum (400 V class), and 600 Vac maximum (600 V class) when protected by branch circuit protection devices specified in this document.

Crush Hazard

Do not use this drive in lifting applications without installing external safety circuitry to prevent accidental dropping of the load.

The drive does not possess built-in load drop protection for lifting applications.

Failure to comply could result in death or serious injury from falling loads.

Install electrical and/or mechanical safety circuit mechanisms independent of drive circuitry.

CAUTION

Crush Hazard

Do not carry the drive by the front cover.

Failure to comply may result in minor or moderate injury from the main body of the drive falling.

NOTICE

Observe proper electrostatic discharge procedures (ESD) when handling the drive and circuit boards. Failure to comply may result in ESD damage to the drive circuitry.

Do not perform a withstand voltage test or megger test on any part of the drive.

Failure to comply could result in damage to the sensitive devices within the drive.

Do not operate damaged equipment.

Failure to comply could result in further damage to the equipment. Do not connect or operate any equipment with visible damage or missing parts.

If a fuse is blown or a Ground Fault Circuit Interrupter (GFCI) is tripped, check the wiring and the selection of the peripheral devices.

Check for short circuits or ground faults on the secondary side of fuses and GFCIs and check the wiring and the selection of peripheral devices. Remove the cause of the problem and then turn the power supply off and on again. If the cause cannot be identified, do not turn on the power supply or attempt to operate the equipment.

Do not restart the drive immediately operate the peripheral devices if a fuse is blown or a GFCI is tripped.

Check the wiring and the selection of peripheral devices to identify the cause. Contact your supplier before restarting the drive or the peripheral devices if the cause cannot be identified.

Do not expose the drive to halogen group disinfectants.

Failure to comply may cause damage to the electrical components in the drive.

Do not pack the drive in wooden materials that have been fumigated or sterilized. Do not sterilize the entire package after the product is packed.

◆ General Application Precautions

■ Selection

Installing a Reactor

Use an AC reactor or DC link choke in the following situations:

- to suppress harmonic current.
- to smooth peak current that results from capacitor switching.
- when the power supply is above 600 kVA.
- when the drive is running from a power supply system with thyristor converters.

Note: A DC link choke is built in to drive models 2A0110 to 2A0415, 4A0058 to 4A1200, and 5A0041 to 5A0242.

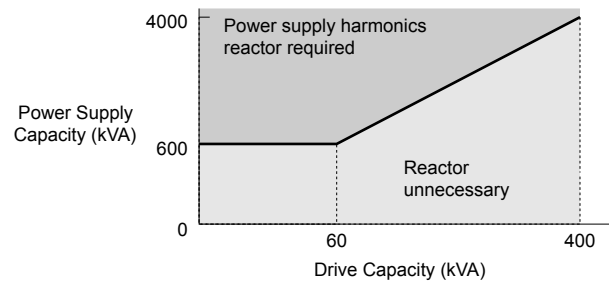


Figure i.1 Installing a Reactor

Drive Capacity

For specialized motors, make sure that the motor rated current is less than the rated output current for the drive.

When running more than one motor in parallel from a single drive, the capacity of the drive should be larger than [total motor rated current \times 1.1].

Starting Torque

The overload rating for the drive determines the starting and accelerating characteristics of the motor. Expect lower torque than when running from line power. To achieve a higher starting torque, use a larger drive or a drive and motor with larger capacity.

Emergency Stop

During a drive fault condition, the output shuts off but the motor does not stop immediately. A mechanical brake may be required when it is necessary to stop the motor faster than the ability of the Fast Stop function of the drive.

Options

NOTICE: The B1, B2, e, @1, @2, and @3 terminals are used to connect optional drive-specific compatible devices only. Connecting non-Yaskawa-approved devices to these terminals may damage the drive.

Repetitive Starting/Stopping

Laundry machines, punching presses, and other applications with frequent starts and stops often approach 150% of their rated output current values. Heat stress generated from repetitive high current will shorten the life span of the IGBTs.

Yaskawa recommends lowering the carrier frequency, particularly when audible noise is not a concern. It is beneficial to reduce the load, increase the acceleration and deceleration times, or switch to a larger drive to help keep peak current levels under 150%. Be sure to check the peak current levels when starting and stopping repeatedly during the initial test run, and make adjustments accordingly.

■ Installation

Enclosure Panels

Keep the drive in a clean environment by installing the drive in an enclosure panel or selecting an installation area free of airborne dust, lint, and oil mist. Be sure to leave the required space between drives to provide for cooling, and take proper measures so the ambient temperature remains within allowable limits and keep flammable materials away from the drive. Yaskawa offers protective designs for drives that must be used in areas subjected to oil mist and excessive vibration. Contact Yaskawa or your Yaskawa agent for details.

i.2 General Safety

Installation Direction

NOTICE: *Install the drive upright as specified in the manual. Refer to the Mechanical Installation section for more information on installation. Failure to comply may damage the drive due to improper cooling.*

■ Settings

Upper Limits

NOTICE: *The drive is capable of running the motor up to 400 Hz. Be sure to set the upper limit for the frequency of the drive to prevent the possible danger of accidentally operating equipment at higher than rated speed. The default setting for the maximum output frequency is 60 Hz.*

DC Injection Braking

NOTICE: *Excessive current during DC Injection Braking and excessive duration of DC Injection Braking can cause motor overheat.*

Acceleration/Deceleration Times

Acceleration and deceleration times are affected by the amount of torque generated by the motor, the load torque, and the moment of inertia. Set a longer accel/decel time when Stall Prevention is enabled. The accel/decel times are lengthened for as long as the Stall Prevention function is in operation. Install one of the available braking options or increase the capacity of the drive for faster acceleration and deceleration.

■ General Handling

Wiring Check

NOTICE: *Do not connect power supply lines to output terminals U/T1, V/T2, or W/T3. Failure to comply will destroy the drive. Be sure to perform a final check of all sequence wiring and other connections before turning on the power and also check for short circuits on the control terminals, which may damage the drive.*

Selecting a Circuit Breaker or Circuit Interrupter

Yaskawa recommends installing a Ground Fault Circuit Interrupter (GFCI) to the power supply side. The GFCI should be designed for use with AC drives (e.g., Type B according to IEC 60755).

Select a Molded Case Circuit Breaker (MCCB) or GFCI with a rated current 1.5 to 2 times higher than the drive rated current to avoid nuisance trips caused by harmonics in the drive input current. [Refer to Installing a Molded Case Circuit Breaker \(MCCB\) or Ground Fault Circuit Interrupter \(GFCI\) on page 385](#) for more information.

NOTICE: *Prevent Equipment Damage. Install a fuse and a GFCI in models 4A0930 and 4A1200. Failure to comply may result in serious damage to the facilities if the drive is defective. [Refer to Wiring Fuses for Models 4A0930 and 4A1200 on page 83](#) for details.*

Magnetic Contactor Installation

WARNING! Fire Hazard. *Shut off the drive with a magnetic contactor (MC) when a fault occurs in any external equipment such as braking resistors. [Refer to Installing a Magnetic Contactor at the Power Supply Side on page 385](#). Failure to comply may cause resistor overheating, fire, and injury to personnel.*

NOTICE: *To get the full performance life out of the electrolytic capacitors and circuit relays, refrain from switching the drive power supply off and on more than once every 30 minutes. Frequent use can damage the drive. Use the drive to stop and start the motor.*

Inspection and Maintenance

WARNING! Electrical Shock Hazard. *Capacitors in the drive do not immediately discharge after shutting off the power. Wait for at least the amount of time specified on the drive before touching any components after shutting off the power. Failure to comply may cause injury to personnel from electrical shock.*

WARNING! Burn Hazard. *Because the heatsink can get very hot during operation, take proper precautions to prevent burns. When replacing the cooling fan, shut off the power and wait at least 15 minutes to be sure that the heatsink has cooled down. Failure to comply may cause burn injury to personnel.*

Wiring

Yaskawa recommends using ring terminals on all drive models. Drive models 2A0069 to 2A0415, 4A0058 to 4A1200, and 5A0041 to 5A0242 require the use of use ring terminals for UL/cUL compliance. Use only the tools recommended by the terminal manufacturer for crimping.

Transporting the Drive

NOTICE: *Never steam clean the drive. During transport, keep the drive from coming into contact with salts, fluorine, bromine, phthalate ester, and other such harmful chemicals.*

◆ Motor Application Precautions

■ Standard Induction Motors

Low-Speed Range

The cooling fan of a standard motor should sufficiently cool the motor at the rated speed. As the self-cooling capability of such a motor decreases with the speed, applying full torque at low speed will possibly damage the motor. Reduce the load torque as the motor slows to prevent motor damage from overheating. *Figure i.2* shows the allowable load characteristics for a Yaskawa standard motor. Use a motor designed specifically for operation with a drive when 100% continuous torque is needed at low speeds.

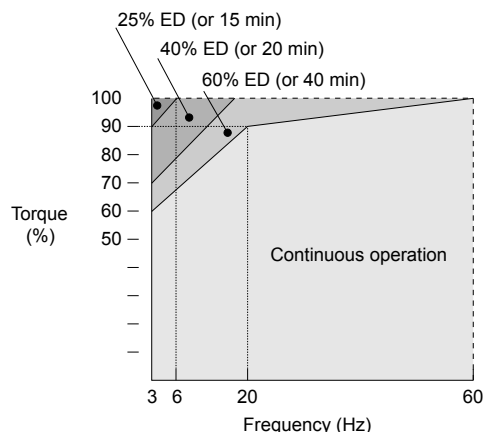


Figure i.2 Allowable Load Characteristics for a Yaskawa Motor

Insulation Tolerance

NOTICE: Consider motor voltage tolerance levels and motor insulation in applications with an input voltage of over 440 V or particularly long wiring distances.

High-Speed Operation

NOTICE: Problems may occur with the motor bearings and dynamic balance of the machine when operating a motor beyond its rated speed. Contact the motor or machine manufacturer.

Torque Characteristics

Torque characteristics differ compared to operating the motor directly from line power. The user should have a full understanding of the load torque characteristics for the application.

Vibration and Shock

The drive allows selection of high carrier PWM control and low carrier PWM. Selecting high carrier PWM can help reduce motor oscillation.

Take particular caution when adding a variable speed drive to an application running a motor from line power at a constant speed. If resonance occurs, install shock-absorbing rubber around the base of the motor and enable the Jump frequency selection to prevent continuous operation in the resonant frequency range.

Audible Noise

The audible noise of the motor varies based on the carrier frequency setting. However, drive current derating may be required. When using a high carrier frequency, audible noise from the motor is comparable to the motor noise generated when running from line power.

■ Synchronous Motors

- Contact Yaskawa or a Yaskawa agent when planning to use a synchronous motor not endorsed by Yaskawa.
- Use a standard induction motor when running multiple synchronous motors simultaneously. A single drive does not have this capability.
- A synchronous motor may rotate slightly in the opposite direction of the Run command at start depending on parameter settings and rotor position.
- The amount of generated starting torque differs depending on the control mode and motor type. Set up the motor with the drive after verifying the starting torque, allowable load characteristics, impact load tolerance, and speed control range.

Contact Yaskawa or a Yaskawa agent when planning to use a motor that does not fall within these specifications:

i.2 General Safety

- To restart a coasting motor rotating over 200 Hz while in V/f Control, first use the Short Circuit Braking function to bring the motor to a stop. Short Circuit Braking requires a special braking resistor. Contact Yaskawa or a Yaskawa agent for details.
- To restart a coasting motor rotating below 200 Hz, use the Speed Search function if the motor cable is not too long. If the motor cable is relatively long, stop the motor using Short Circuit Braking.

Specialized Motors

Multi-Pole Motor

The rated current of a multi-pole motor differs from that of a standard motor, so be sure to check the maximum current when selecting a drive. Always stop the motor before switching between the number of motor poles. The motor will coast to stop if a regenerative overvoltage (ov) fault occurs or if overcurrent (oC) protection is triggered.

Submersible Motor

The rated current of a submersible motor is greater than that of a standard motor, so select the drive accordingly. Use a motor cable large enough to avoid decreasing the maximum torque level from voltage drop caused by a long motor cable.

Explosion-Proof Motor

The motor and the drive must be tested together to be certified as explosion-proof. The drive is not designed for explosion-proof areas.

When attaching an encoder to an explosion-proof motor, make sure the encoder is also explosion-proof. Use an insulating signal converter to connect the encoder signal lines to the speed feedback option card.

Geared Motor

Make sure that the gear and the lubricant are rated for the desired speed range to avoid gear damage when operating at low speeds or very high speeds. Consult with the manufacturer for applications that require operation outside the rated speed range of the motor or gear box.

Single-Phase Motor

Variable speed drives are not designed to operate with single phase motors. Using capacitors to start the motor causes a high-frequency current to flow to the capacitors and can damage the capacitors. A split-phase start or a repulsion start can burn out the starter coils because the internal centrifugal switch is not activated. The drive is for use with three-phase motors only.

Motor with Brake

Take caution when using the drive to operate a motor with a built-in holding brake. If the brake is connected to the output side of the drive, it may not release at start due to low voltage levels, so be sure to install a separate power supply for the motor brake. Note that motors with built-in brakes tend to generate a fair amount of noise when running at low speeds.

■ Notes on Power Transmission Machinery

Installing an AC drive in machinery that was previously connected directly to the power supply will allow the machine to operate at variable speeds. Continuous operation outside of the rated speeds can wear out lubrication material in gear boxes and other power transmission parts. Make sure that lubrication is sufficient within the entire speed range to avoid machine damage. Note that operation above the rated speed can increase the noise generated by the machine.

◆ Drive Label Warning Example

Always heed the warning information listed in *Figure i.3* in the position shown in *Figure i.4*.

⚠ WARNING

⚡ Risk of electric shock.

- Read manual before installing.
- Wait 5 minutes for capacitor discharge after disconnecting power supply.
- To conform to **CE** requirements, make sure to ground the supply neutral for 400V class.
- After opening the manual switch between the drive and motor, please wait 5 minutes before inspecting, performing maintenance or wiring the drive.

🔥 Hot surfaces

- Top and Side surfaces may become hot. Do not touch.

Figure i.3 Warning Information Example

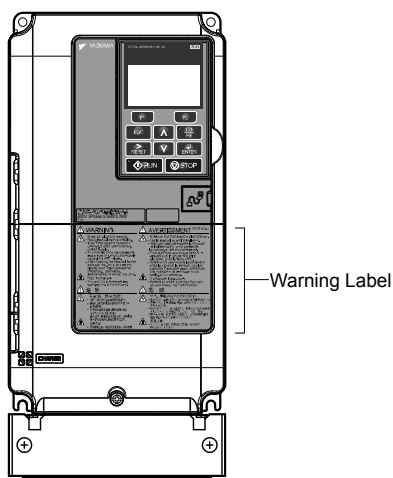


Figure i.4 Warning Information Position

◆ Warranty Information

■ Restrictions

The drive is not designed or manufactured for use in devices or systems that may directly affect or threaten human lives or health.

Customers who intend to use the product described in this manual for devices or systems relating to transportation, health care, space aviation, atomic power, electric power, or in underwater applications must first contact their Yaskawa representatives or the nearest Yaskawa sales office.

WARNING! *Injury to Personnel. This product has been manufactured under strict quality-control guidelines. However, if this product is to be installed in any location where failure of this product could involve or result in a life-and-death situation or loss of human life or in a facility where failure may cause a serious accident or physical injury, safety devices must be installed to minimize the likelihood of any accident.*

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Receiving

This chapter explains how to inspect the drive upon receipt, and gives an overview of the different enclosure types and components.

| | | |
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| 1.1 | SECTION SAFETY..... | 28 |
| 1.2 | GENERAL DESCRIPTION..... | 29 |
| 1.3 | MODEL NUMBER AND NAMEPLATE CHECK..... | 31 |
| 1.4 | DRIVE MODELS AND ENCLOSURE TYPES..... | 34 |
| 1.5 | COMPONENT NAMES..... | 36 |

1.1 Section Safety

CAUTION

Do not carry the drive by the front cover or the terminal cover.

Failure to comply may cause the main body of the drive to fall, resulting in minor or moderate injury.

NOTICE

Observe proper electrostatic discharge procedures (ESD) when handling the drive and circuit boards.

Failure to comply may result in ESD damage to the drive circuitry.

A motor connected to a PWM drive may operate at a higher temperature than a utility-fed motor and the operating speed range may reduce motor cooling capacity.

Ensure that the motor is suitable for drive duty and/or the motor service factor is adequate to accommodate the additional heating with the intended operating conditions.

1.2 General Description

◆ P1000 Model Selection

Refer to [Table 1.1](#) for drive selection depending on motor power.

Note: The models and capacities in shown here are based on standard settings and operation conditions. Higher carrier frequencies and higher ambient temperatures require derating.

Table 1.1 P1000 Models

| Motor Power HP | Three-Phase 200 V Class | | Three-Phase 400 V Class | | Three-Phase 600 V Class | |
|-------------------|-------------------------|---------------------------------|-------------------------|---------------------------------|-------------------------|---------------------------------|
| | Drive Model | Rated Output Current (A) <3> | Drive Model | Rated Output Current (A) <3> | Drive Model | Rated Output Current (A) <3> |
| 0.75 | 2A0004 | 3.5 | 4A0002 | 2.1 | – | – |
| 1 | 2A0006 | 6 | – | – | – | – |
| 2 | 2A0008 | 8 | 4A0004 | 4.1 | 5A0003 | 2.7 |
| 3 | 2A0010 | 9.6 | 4A0005 | 5.4 | 5A0004 | 3.9 |
| | 2A0012 | 12 | 4A0007 | 6.9 | – | – |
| 5 | 2A0018 | 17.5 | 4A0009 | 8.8 | 5A0006 | 6.1 |
| 7.5 | 2A0021 | 21 | 4A0011 | 11.1 | 5A0009 | 9 |
| 10 | 2A0030 | 30 | 4A0018 | 17.5 | 5A0011 | 11 |
| 15 | 2A0040 | 40 | 4A0023 | 23 | 5A0017 | 17 |
| 20 | 2A0056 | 56 | 4A0031 | 31 | 5A0022 | 22 |
| 25 | 2A0069 | 69 | 4A0038 | 38 | 5A0027 | 27 |
| 30 | 2A0081 | 81 | 4A0044 | 44 | 5A0032 | 32 |
| 40 | 2A0110 | 110 | 4A0058 | 58 | 5A0041 | 41 |
| 50 | 2A0138 | 138 | 4A0072 | 72 | 5A0052 | 52 |
| 60 | 2A0169 | 169 | 4A0088 | 88 | 5A0062 | 62 |
| 75 | 2A0211 | 211 | 4A0103 | 103 | 5A0077 | 77 |
| 100 | 2A0250 | 250 | 4A0139 | 139 | 5A0099 | 99 |
| 125 | 2A0312 | 312 | 4A0165 | 165 | 5A0125 | 125 |
| 150 | 2A0360 | 360 | 4A0208 | 208 | 5A0145 | 145 |
| 175 | 2A0415 | 415 | – | – | – | – |
| 200 | – | – | 4A0250 | 250 | 5A0192 | 192 |
| 250 | – | – | 4A0296 | 296 | 5A0242 | 242 |
| 300 | – | – | 4A0362 | 362 | – | – |
| 350 | – | – | 4A0414 | 414 | – | – |
| 400-450 | – | – | 4A0515 | 515 | – | – |
| 500-550 | – | – | 4A0675 | 675 | – | – |
| 750 | – | – | 4A0930 | 930 | – | – |
| 1000 | – | – | 4A1200 | 1200 | – | – |

<1> These values assume the carrier frequency is not set higher than 8 kHz.

<2> These values assume the carrier frequency is not set higher than 5 kHz.

<3> These values assume the carrier frequency is set to 2 kHz.

Note: Current derating is required when setting the carrier frequency higher. [Refer to Drive Derating Data on page 407](#) for details.

1.2 General Description

◆ Control Mode Details

Table 1.2 gives an overview of the various P1000 control mode features.

Table 1.2 Control Mode Details

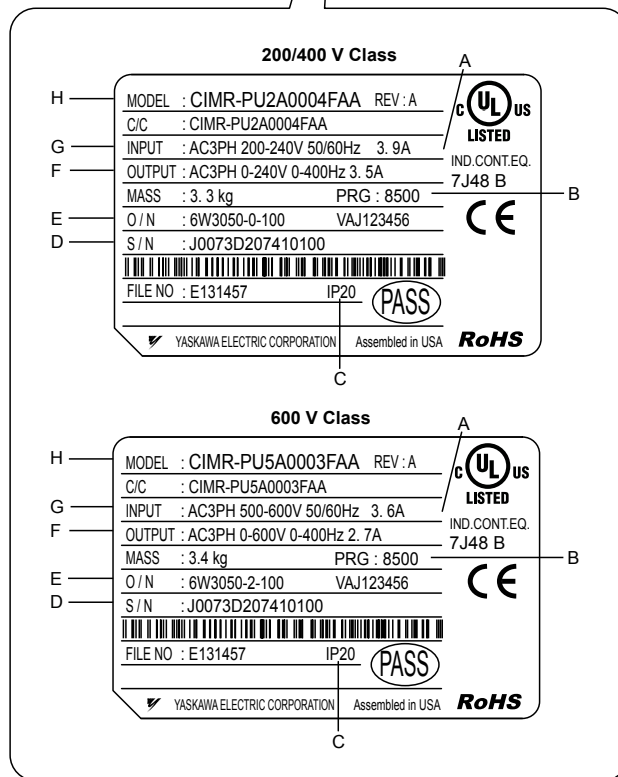
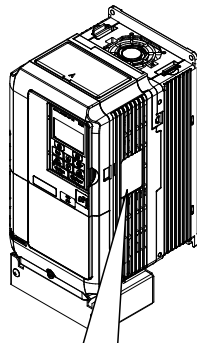
| Motor Type | | Induction Motors | Comments |
|-------------------------|------------------------------|---|--|
| Control Mode | | V/f | – |
| Basic Description | | V/f control | – |
| Type of Applications | Motor Type | IM | – |
| | Multi Motor | YES | – |
| | Motor data unknown | YES | – |
| Control Characteristics | Speed Control Range | 1:40 | May fluctuate with characteristics and motor temperature. |
| | Speed Accuracy | ±2 to 3% | Speed deviation when operating at constant speed may fluctuate with characteristics and motor temperature. |
| | Speed Response | 3 Hz (approx.) | Max. frequency of a speed reference signal that the drive can follow may fluctuate with characteristics and motor temperature. |
| | Starting Torque | 150% at 3 Hz | Starting torque may fluctuate with characteristics and motor temperature. Performance may differ by capacity. |
| Application-Specific | Auto-Tuning | <ul style="list-style-type: none"> • Energy Saving Tuning • Line to line resistance | Automatically adjusts parameter settings that concern electrical characteristics of the motor. |
| Application-Specific | Speed Search | YES | Bi-directional speed detection of a coasting motor to restart it without stopping. |
| | Energy-Saving Control | YES | Saves energy by always operating the motor at its maximum efficiency. |
| | High Slip Braking | YES | Increases motor loss to allow for faster deceleration than normal without a braking resistor. Effectiveness may vary based on motor characteristics. |
| | Kinetic Energy Buffering | YES | Decelerates the drive to allow it to ride through a momentary power loss and continue operation. |
| | Over-excitation Deceleration | YES | Provides fast deceleration without using a braking resistor. |
| | Overvoltage Suppression | YES | Prevents overvoltage by increasing speed during regeneration. |

1.3 Model Number and Nameplate Check

Please perform the following tasks after receiving the drive:

- Inspect the drive for damage.
- If the drive appears damaged upon receipt, contact the shipper immediately.
- Verify receipt of the correct model by checking the information on the nameplate.
- If you have received the wrong model or the drive does not function properly, contact your supplier.

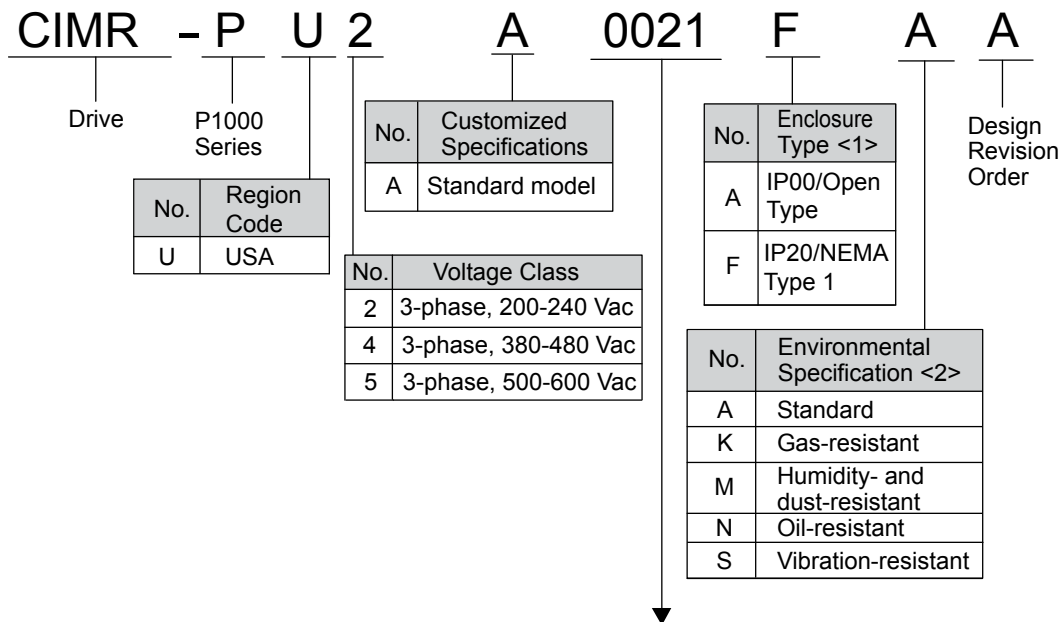
◆ Nameplate



- A – Normal Duty Amps
- B – Software version
- C – Enclosure type
- D – Serial number
- E – Lot number
- F – Output specifications
- G – Input specifications
- H – AC drive model

Figure 1.1 Nameplate Information Example

1.3 Model Number and Nameplate Check



Refer to the tables below

<1> [Refer to Drive Models and Enclosure Types on page 34](#) for differences regarding enclosure protection types and component descriptions.

<2> Drives with these specifications do not guarantee complete protection for the environmental conditions indicated.

■ Three-Phase 200 V Class

| Drive Model | Max. Motor Capacity kW (HP) | Rated Output Current A |
|-------------|-----------------------------|------------------------|
| 2A0004 | 0.75 (0.75) | 3.5 |
| 2A0006 | 1.1 (1) | 6.0 |
| 2A0008 | 1.5 (2) | 8.0 |
| 2A0010 | 2.2 (3) | 9.6 |
| 2A0012 | 3.0 (3) | 12 |
| 2A0018 | 3.7 (5) | 17.5 |
| 2A0021 | 5.5 (7.5) | 21 |
| 2A0030 | 7.5 (10) | 30 |
| 2A0040 | 11 (15) | 40 |
| 2A0056 | 15 (20) | 56 |
| 2A0069 | 18.5 (25) | 69 |
| 2A0081 | 22 (30) | 81 |
| 2A0110 | 30 (40) | 110 |
| 2A0138 | 37 (50) | 138 |
| 2A0169 | 45 (60) | 169 |
| 2A0211 | 55 (75) | 211 |
| 2A0250 | 75 (100) | 250 |
| 2A0312 | 90 (125) | 312 |
| 2A0360 | 110 (150) | 360 |
| 2A0415 | 110 (175) | 415 |

■ Three-Phase 400 V Class

| Drive Model | Max. Motor Capacity kW (HP) | Rated Output Current A |
|-------------|-----------------------------|------------------------|
| 4A0002 | 0.75 (0.75) | 2.1 |
| 4A0004 | 1.5 (2) | 4.1 |
| 4A0005 | 2.2 (3) | 5.4 |
| 4A0007 | 3.0 (3) | 6.9 |
| 4A0009 | 3.7 (5) | 8.8 |
| 4A0011 | 5.5 (7.5) | 11.1 |
| 4A0018 | 7.5 (10) | 17.5 |
| 4A0023 | 11 (15) | 23 |
| 4A0031 | 15 (20) | 31 |
| 4A0038 | 18.5 (25) | 38 |
| 4A0044 | 22 (30) | 44 |
| 4A0058 | 30 (40) | 58 |
| 4A0072 | 37 (50) | 72 |
| 4A0088 | 45 (60) | 88 |
| 4A0103 | 55 (75) | 103 |
| 4A0139 | 75 (100) | 139 |
| 4A0165 | 90 (125) | 165 |
| 4A0208 | 110 (150) | 208 |
| 4A0250 | 132 (200) | 250 |
| 4A0296 | 160 (250) | 296 |
| 4A0362 | 185 (300) | 362 |
| 4A0414 | 220 (350) | 414 |
| 4A0515 | 250 (400-450) | 515 |
| 4A0675 | 355 (500-550) | 675 |
| 4A0930 | 500 (750) | 930 |
| 4A1200 | 630 (1000) | 1200 |

■ Three-Phase 600 V Class

| Drive Model | Max. Motor Capacity kW (HP) | Rated Output Current A |
|-------------|-----------------------------|------------------------|
| 5A0003 | 1.5 (2) | 2.7 |
| 5A0004 | 2.2 (3) | 3.9 |
| 5A0006 | 3.7 (5) | 6.1 |
| 5A0009 | 5.5 (7.5) | 9 |
| 5A0011 | 7.5 (10) | 11 |
| 5A0017 | 11 (15) | 17 |
| 5A0022 | 15 (20) | 22 |
| 5A0027 | 18.5 (25) | 27 |
| 5A0032 | 22 (30) | 32 |
| 5A0041 | 30 (40) | 41 |
| 5A0052 | 37 (50) | 52 |
| 5A0062 | 45 (60) | 62 |
| 5A0077 | 55 (75) | 77 |
| 5A0099 | 75 (100) | 99 |
| 5A0125 | 90 (125) | 125 |
| 5A0145 | 110 (150) | 145 |
| 5A0192 | 160 (200) | 192 |
| 5A0242 | 185 (250) | 242 |

1.4 Drive Models and Enclosure Types

Two types of enclosures are offered for P1000 drives:

- IP20/NEMA Type 1 enclosure models mount to an indoor wall or in an enclosure panel.
- IP00/Open Type enclosure models are designed for installation in an enclosure panel that serves to protect personnel from injury caused by accidentally touching live parts.

Table 1.3 describes drive enclosures and models.

Table 1.3 Drive Models and Enclosure Types

| Voltage Class | Enclosure Type | |
|----------------------------|---|---|
| | IP20/NEMA Type 1 Enclosure <1> Drive Model | IP00/Open Type Enclosure Drive Model |
| Three-Phase 200 V Class | 2A0004F | <1> |
| | 2A0006F | <1> |
| | 2A0008F | <1> |
| | 2A0010F | <1> |
| | 2A0012F | <1> |
| | 2A0018F | <1> |
| | 2A0021F | <1> |
| | 2A0030F | <1> |
| | 2A0040F | <1> |
| | 2A0056F | <1> |
| | 2A0069F | <1> |
| | 2A0081F | <1> |
| | 2A0110F | <1> |
| | 2A0138F | <1> |
| | 2A0169F | <1> |
| | 2A0211F | <1> |
| | <1> | 2A0250A |
| | <1> | 2A0312A |
| | <1> | 2A0360A |
| <1> | 2A0415A | |
| Three-Phase 400 V Class | 4A0002F | <1> |
| | 4A0004F | <1> |
| | 4A0005F | <1> |
| | 4A0007F | <1> |
| | 4A0009F | <1> |
| | 4A0011F | <1> |
| | 4A0018F | <1> |
| | 4A0023F | <1> |
| | 4A0031F | <1> |
| | 4A0038F | <1> |
| | 4A0044F | <1> |
| | 4A0058F | <1> |
| | 4A0072F | <1> |

| Voltage Class | Enclosure Type | |
|----------------------------|---|---|
| | IP20/NEMA Type 1 Enclosure <1> Drive Model | IP00/Open Type Enclosure Drive Model |
| Three-Phase 400 V Class | 4A0088F | <1> |
| | 4A0103F | <1> |
| | 4A0139F | <1> |
| | 4A0165F | <1> |
| | <2> | 4A0208A |
| | <2> | 4A0250A |
| | <2> | 4A0296A |
| | <2> | 4A0362A |
| | <3> | 4A0414A |
| | <3> | 4A0515A |
| | <3> | 4A0675A |
| | <3> | 4A0930A |
| | <3> | 4A1200A |
| Three-Phase 600 V Class | 5A0003F | <1> |
| | 5A0004F | <1> |
| | 5A0006F | <1> |
| | 5A0009F | <1> |
| | 5A0011F | <1> |
| | 5A0017F | <1> |
| | 5A0022F | <1> |
| | 5A0027F | <1> |
| | 5A0032F | <1> |
| | 5A0041F | <1> |
| | 5A0052F | <1> |
| | 5A0062F | <1> |
| | 5A0077F | <1> |
| | 5A0099F | <1> |
| | <2> | 5A0125A |
| | <2> | 5A0145A |
| | <2> | 5A0192A |
| <2> | 5A0242A | |

- <1> Removing the top protective cover from a IP20/NEMA Type 1 enclosure drive voids NEMA Type 1 protection while retaining IP20 conformity.
- <2> Customers may convert these models to IP20/NEMA Type 1 enclosures using an IP20/NEMA Type 1 Kit. *Refer to IP20/NEMA 1, UL Type 1 Kit Selection on page 64* to select the appropriate kit.
- <3> Contact a Yaskawa representative for IP20/NEMA Type 1 Kit availability for these models.

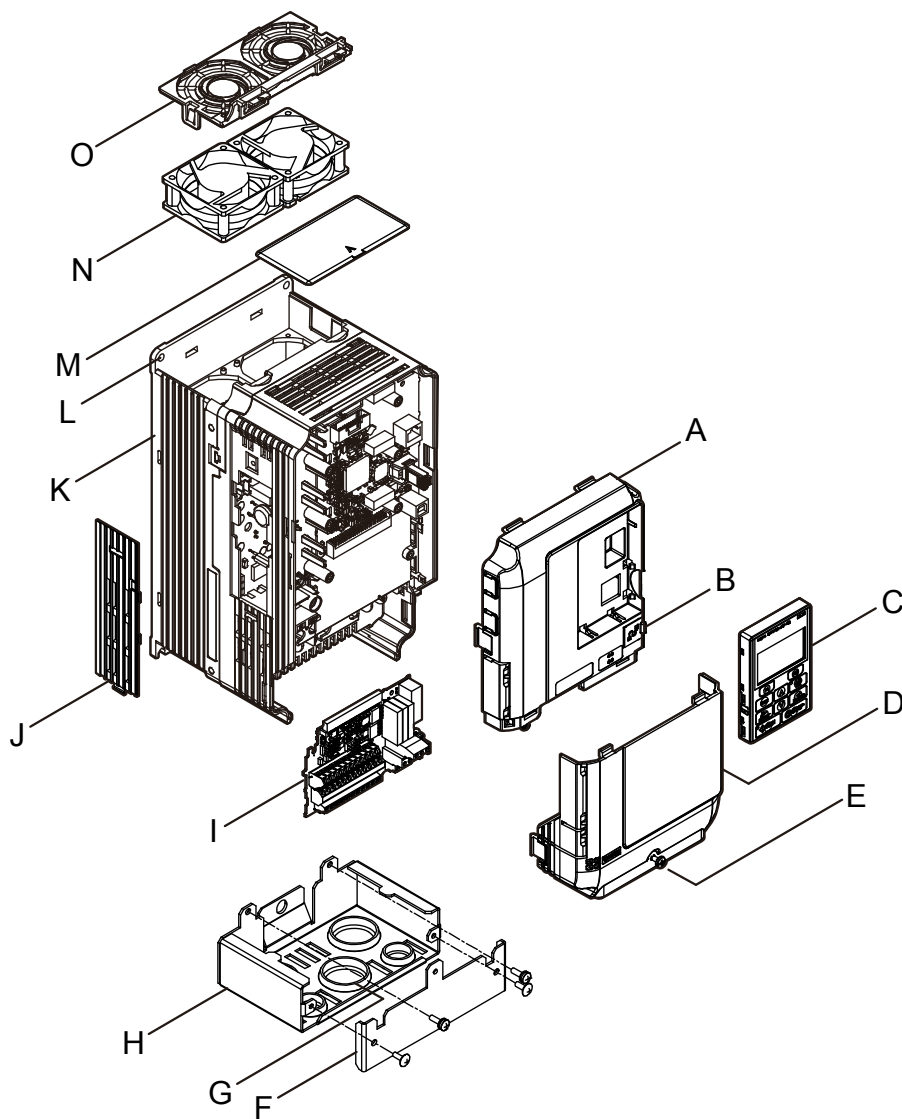
1.5 Component Names

This section gives an overview of the drive components and harmonic filter module components described in this manual.

- Note:**
1. Refer to *Using the Digital Operator on page 109* for a description of the operator keypad.
 2. The drive may have no cooling fans or up to two cooling fans depending on the model.

◆ IP20/NEMA 1, UL Type 1 Enclosure

- Three-Phase AC 200 V Models 2A0004F to 2A0081F
- Three-Phase AC 400 V Models 4A0002F to 4A0044F
- Three-Phase AC 600 V Models 5A0003F to 5A0032F

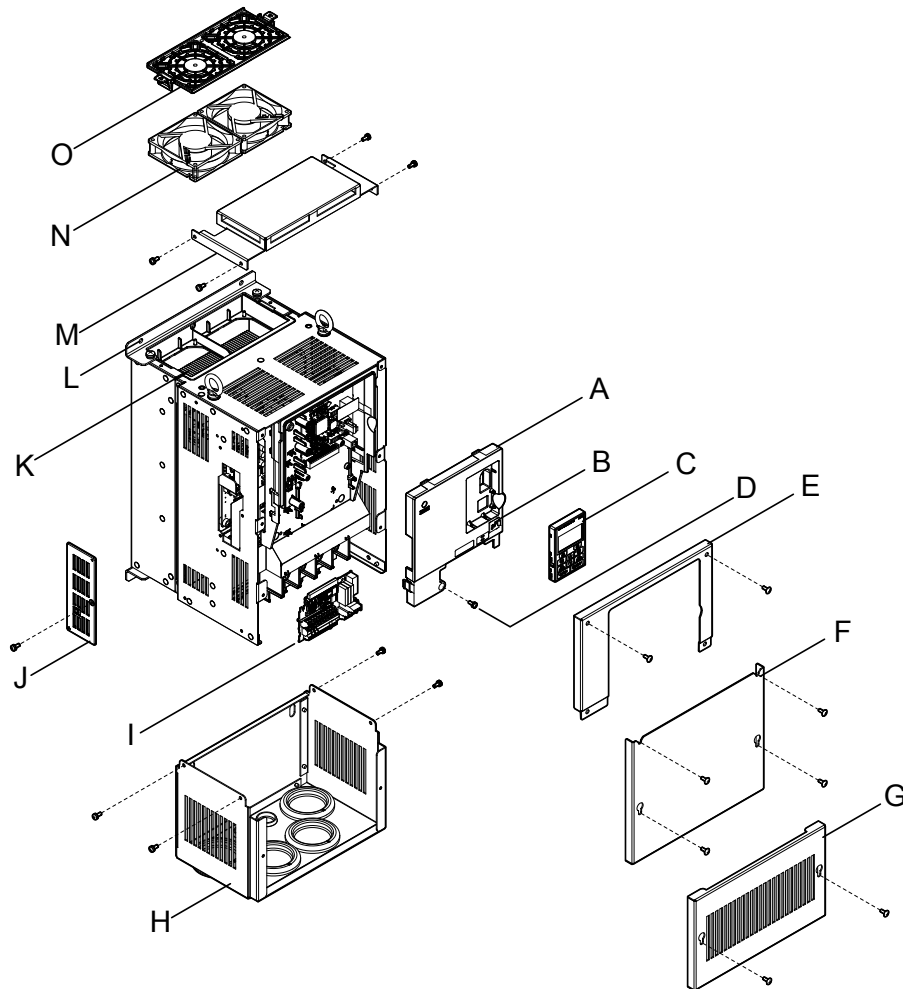


- | | |
|---------------------------------|---|
| A – Front cover | I – Terminal board |
| B – USB port (type-B) | J – Optional 24 V DC power supply connector cover |
| C – Digital operator | K – Heatsink |
| D – Terminal cover | L – Mounting hole |
| E – Terminal cover screw | M – Top protective cover |
| F – Conduit bracket front cover | N – Cooling fan <1> |
| G – Rubber bushing | O – Fan finger guard <1> |
| H – Conduit bracket | |

Figure 1.2 Exploded View of IP20/NEMA 1, UL Type 1 Components (Model 2A0030F)

<1> Drive models 2A0018, 2A0021, 4A0007 to 4A0011, 5A0006F, and 5A0009F have a single cooling fan. Drive models 2A0004 to 2A0012, 4A0002 to 4A0005, 5A0003F, and 5A0004F do not have a cooling fan or a fan finger guard.

- Three-Phase AC 200 V Models 2A0110F, 2A0138F
- Three-Phase AC 400 V Models 4A0058F to 4A0103F
- Three-Phase AC 600 V Models 5A0041F, 5A0052F

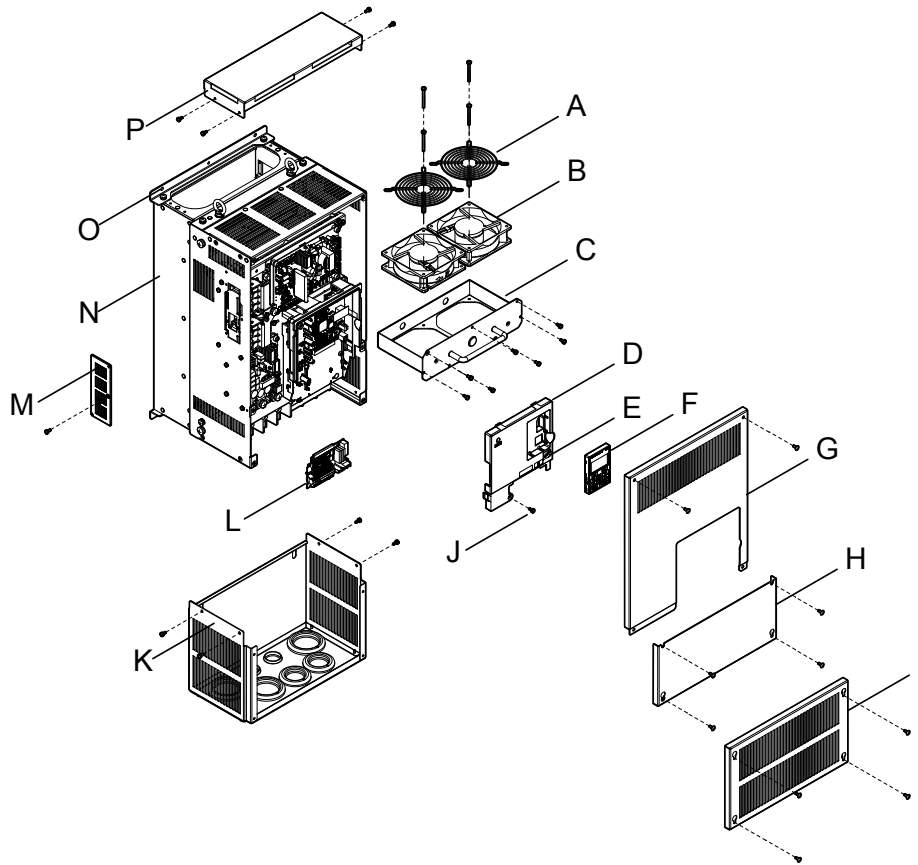


- | | |
|---------------------------------|---|
| A – Front cover | I – Terminal board |
| B – USB port (type-B) | J – Optional 24 V DC power supply connector cover |
| C – Digital operator | K – Heatsink |
| D – Front cover screw | L – Mounting hole |
| E – Drive cover | M – Top protective cover |
| F – Terminal cover | N – Cooling fan |
| G – Conduit bracket front cover | O – Fan finger guard |
| H – Conduit bracket | |

Figure 1.3 Exploded View of IP20/NEMA 1, UL Type 1 Enclosure Components (Model 2A0110F)

1.5 Component Names

- Three-Phase AC 200 V Models 2A0169F, 2A0211F
- Three-Phase AC 400 V Models 4A0139F to 4A0165F
- Three-Phase AC 600 V Models 5A0062F to 5A0099F

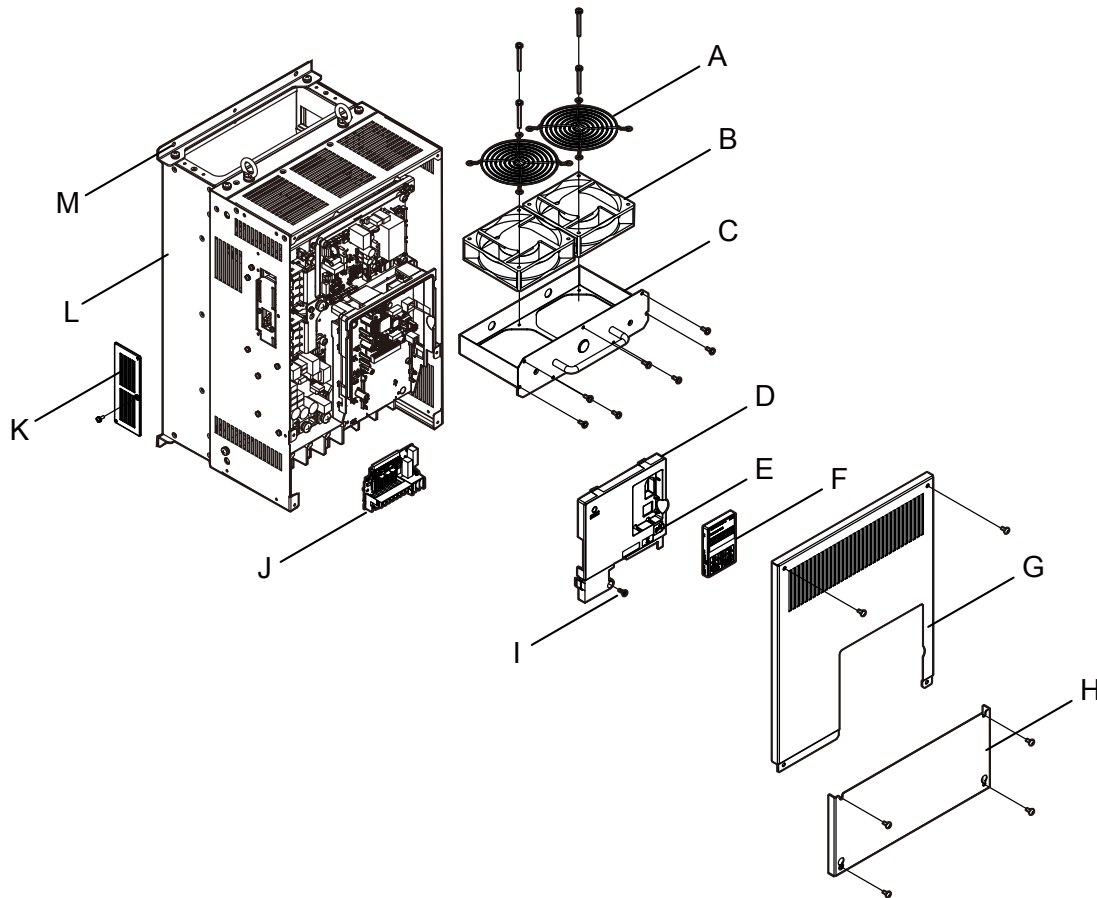


- | | |
|-----------------------|--|
| A – Fan guard | I – Conduit bracket front cover |
| B – Cooling fan | J – Front cover |
| C – Fan bracket | K – Conduit bracket |
| D – Front cover | L – Terminal board |
| E – USB port (type-B) | M – Optional 24 V DC power supply connector cover |
| F – Digital operator | N – Heatsink |
| G – Drive cover | O – Mounting hole |
| H – Terminal cover | P – Top protective cover |

Figure 1.4 Exploded View of IP20/NEMA 1, UL Type 1 Enclosure Components (Model 4A0165F)

◆ IP00/Open Type Enclosure

- Three-Phase AC 200 V Models 2A0250A, 2A0312A
- Three-Phase AC 400 V Model 4A0208A
- Three-Phase AC 600 V Models 5A0125A, 5A0145A

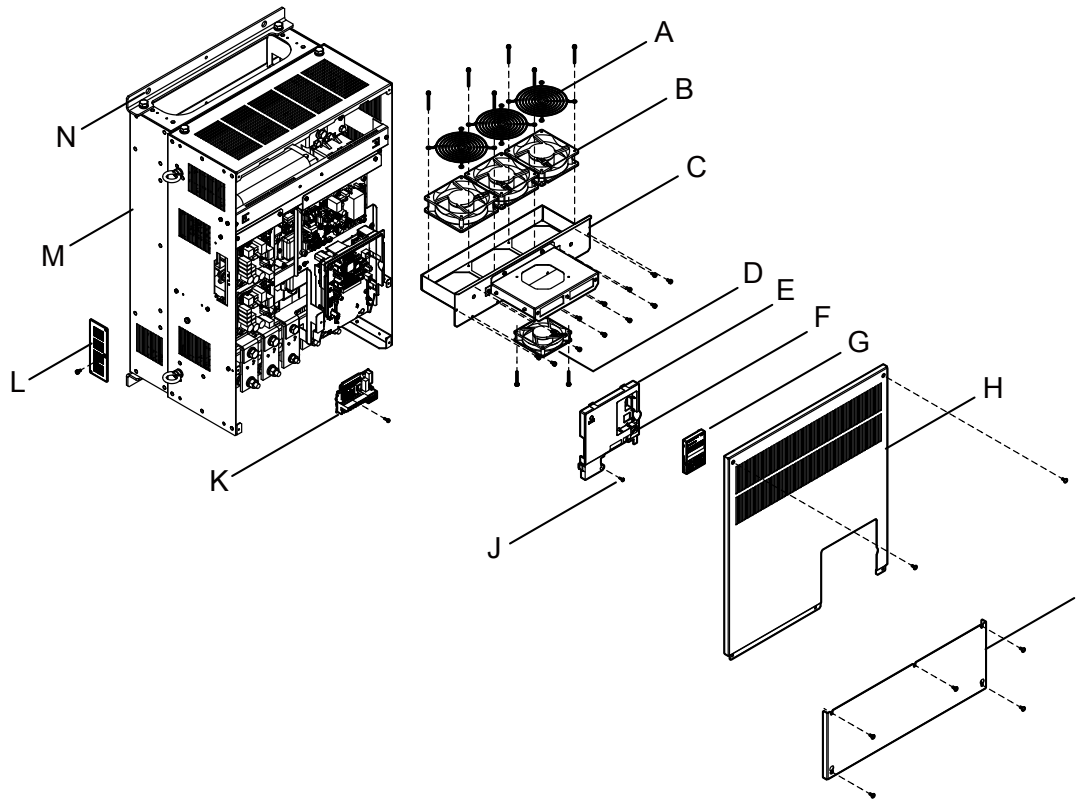


- | | |
|-----------------------|--|
| A – Fan guard | H – Terminal cover |
| B – Cooling fan | I – Front cover screw |
| C – Fan bracket | J – Terminal board |
| D – Front cover | K – Optional 24 V DC power supply connector cover |
| E – USB port (type-B) | L – Heatsink |
| F – Digital operator | M – Mounting hole |
| G – Drive cover | |

Figure 1.5 Exploded view of IP00/Open Type Enclosure Components (Model 4A0208A)

1.5 Component Names

- Three-Phase AC 200 V Models 2A0360A, 2A0415A
- Three-Phase AC 400 V Models 4A0250A to 4A0362A
- Three-Phase AC 600 V Models 5A0192A, 5A0242A



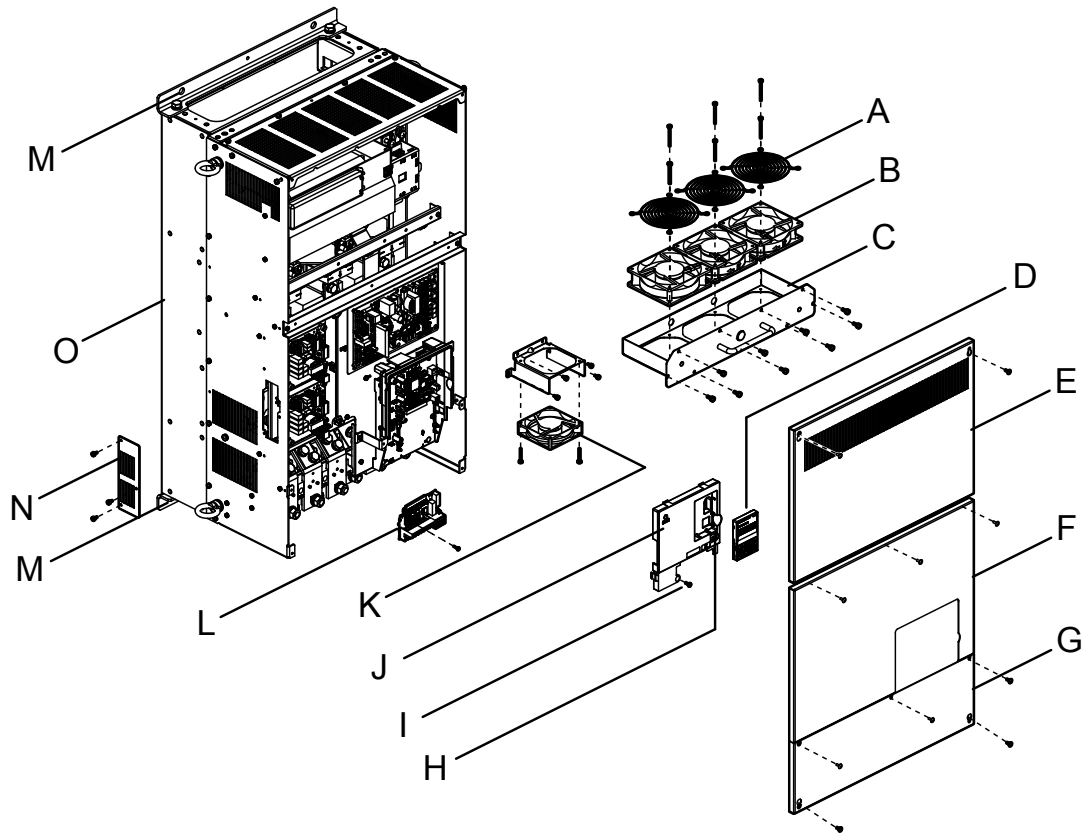
A – Fan guard
B – Cooling fan
C – Fan bracket
D – Circulation fan <1>
E – Front cover
F – USB port (type-B)
G – Digital operator

H – Drive cover
I – Terminal cover
J – Front cover screw
K – Terminal board
L – Optional 24 V DC power supply
connector cover
M – Heatsink
N – Mounting hole

Figure 1.6 Exploded view of IP00/Open Type Enclosure Components (Model 4A0362A)

<1> Drive models 2A0360, 2A0415, and 4A0362 have a built-in circulation fan.

■ Three-Phase AC 400 V Model 4A0414A



A – Fan guard
 B – Cooling fan
 C – Fan bracket
 D – Digital operator
 E – Drive cover 1
 F – Drive cover 2
 G – Terminal cover
 H – USB port (type-B)

I – Front cover screw
 J – Front cover
 K – Circulation fan
 L – Terminal board
 M – Mounting hole
 N – Optional 24 V DC power supply
 connector cover
 O – Heatsink

Figure 1.7 Exploded view of IP00/Open Type Enclosure Components (Model 4A0414A)

■ Three-Phase AC 400 V Models 4A0515A, 4A0675A

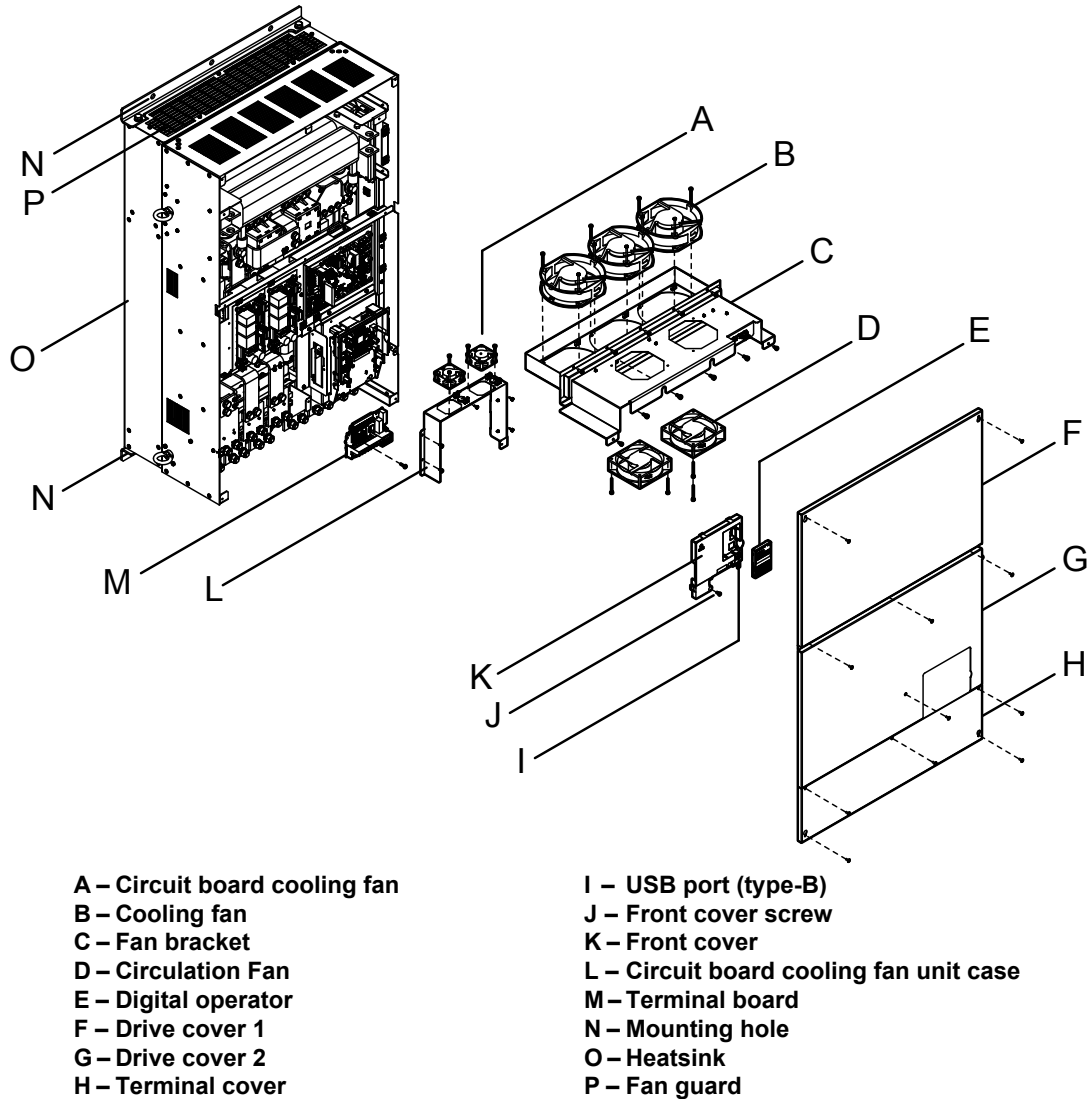
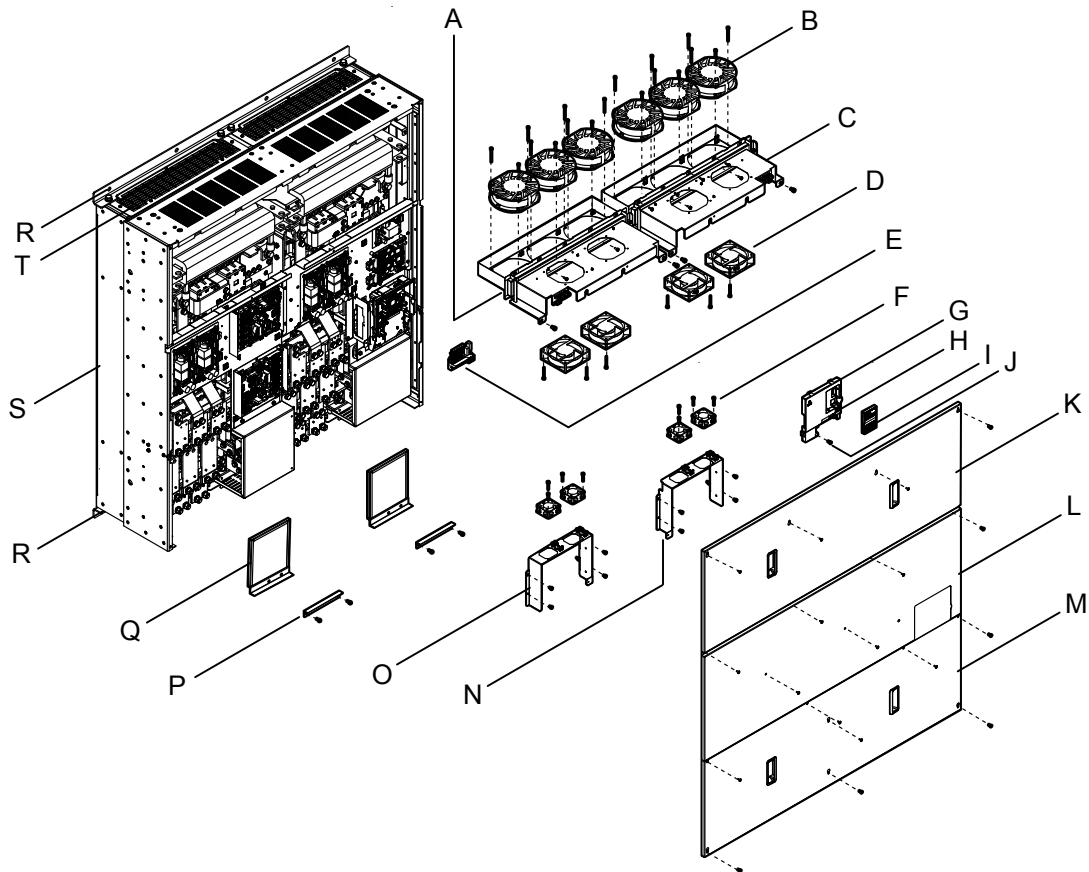


Figure 1.8 Exploded view of IP00/Open Type Enclosure Components (Model 4A0675A)

■ Three-Phase AC 400 V Models 4A0930A, 4A1200A



A – Fan unit case (L)

B – Cooling fan

C – Fan unit case (R)

D – Circulation Fan

E – Terminal board

F – Circuit board cooling fan

G – Front cover

H – USB port (type-B)

I – Digital operator

J – Front cover screw

K – Drive cover 1

L – Drive cover 2

M – Terminal cover

N – Circuit board cooling fan unit case (R)

O – Circuit board cooling fan unit case (L)

P – Blind cover

Q – Filter case

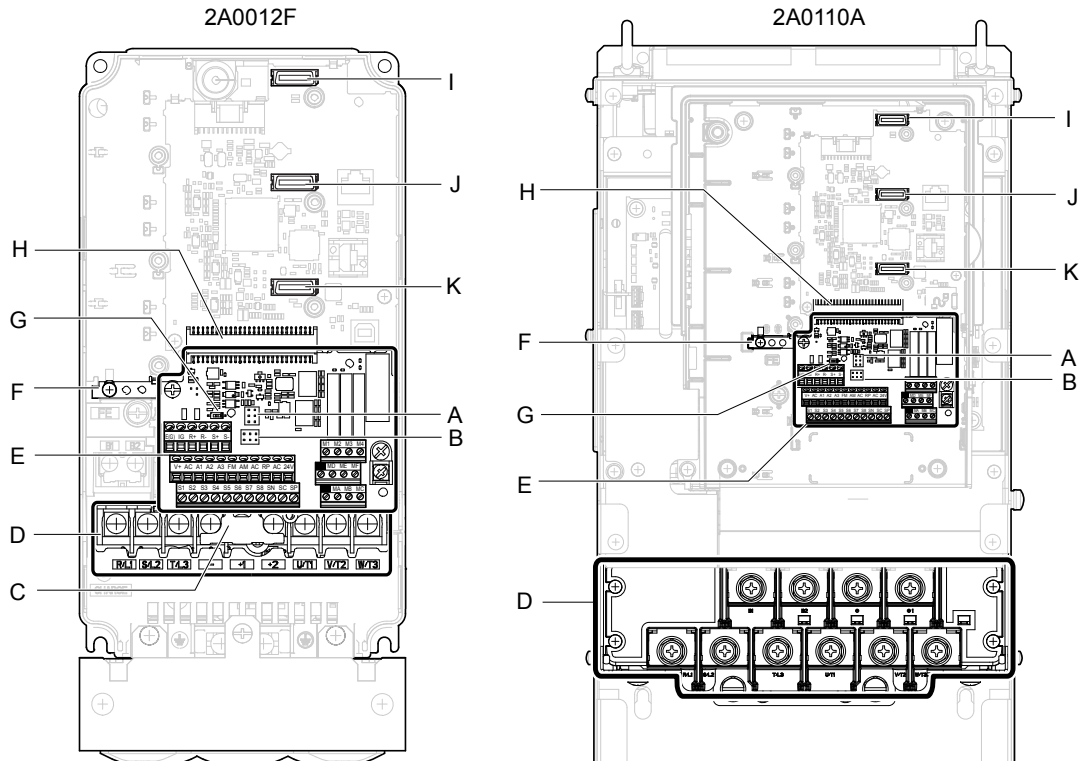
R – Mounting hole

S – Heatsink

T – Fan guard

Figure 1.9 Exploded view of IP00/Open Type Enclosure Components (Model 4A0930A)

◆ Front Views



- A – Jumper S5 (*Refer to Terminal AM/ FM Signal Selection on page 102*)
- B – Jumper S1 (*Refer to Terminals A1, A2, and A3 Input Signal Selection on page 101*)
- C – Protective cover to prevent miswiring
- D – Main circuit terminal (*Refer to Wiring the Main Circuit Terminal on page 94*)
- E – Terminal board (*Refer to Control Circuit Wiring on page 95*)
- F – Ground terminal

- G – DIP switch S2 (*Refer to MEMOBUS/ Modbus Termination on page 102*)
- H – Terminal board connector
- I – Option card connector (CN5-C)
- J – Option card connector (CN5-B)
- K – Option card connector (CN5-A)

Figure 1.10 Front View of Drives

Mechanical Installation

This chapter explains how to properly mount and install the drive.

| | | |
|------------|-------------------------------------|-----------|
| 2.1 | SECTION SAFETY..... | 46 |
| 2.2 | MECHANICAL INSTALLATION..... | 48 |

2.1 Section Safety

WARNING

Fire Hazard

Provide sufficient cooling when installing the drive inside an enclosed panel or cabinet.

Failure to comply could result in overheating and fire.

When multiple drives are placed inside the same enclosure panel, install proper cooling to ensure air entering the enclosure does not exceed 40 °C.

Crush Hazard

Use a dedicated lifter when transporting the drive by a lifter.

Failure to comply may result in serious injury or death from falling equipment.

Only use vertical suspension to temporarily lift the drive during installation to an enclosure panel. Do not use vertical suspension to transport the drive.

Failure to comply may result in serious injury or death from falling equipment.

Use screws to securely affix the drive front cover, terminal blocks, and other drive components prior to vertical suspension.

Failure to comply may result in serious injury or death from falling equipment.

Do not subject the drive to vibration or impact greater than 1.96 m/s² (0.2 G) while it is suspended by the cables.

Failure to comply may result in serious injury or death from falling equipment.

Do not attempt to flip the drive over or leave the drive unattended while it is suspended by the wires.

Failure to comply may result in serious injury or death from falling equipment.

CAUTION

Crush Hazard

Do not carry the drive by the front cover or the terminal cover.

Failure to comply may result in minor or moderate injury from the main body of the drive falling.

NOTICE

Equipment Hazard

Prevent foreign matter such as metal shavings or wire clippings from falling into the drive during drive installation and project construction.

Failure to comply could result in damage to the drive. Place a temporary cover over the top during installation. Be sure to remove the temporary cover before start-up, as the cover will reduce ventilation and cause the unit to overheat.

Observe proper electrostatic discharge (ESD) procedures when handling the drive.

Failure to comply could result in ESD damage to the drive circuitry.

Operating the motor in the low-speed range diminishes the cooling effects, increases motor temperature, and may lead to motor damage by overheating.

Reduce the motor torque in the low-speed range whenever using a standard blower cooled motor. If 100% torque is required continuously at low speed, consider using a special drive or vector-control motor. Select a motor that is compatible with the required load torque and operating speed range.

The speed range for continuous operation differs according to the lubrication method and motor manufacturer.

If the motor is to be operated at a speed higher than the rated speed, consult with the manufacturer.

Continuously operating an oil-lubricated motor in the low-speed range may result in burning.

NOTICE

When the input voltage is 440 V or higher or the wiring distance is greater than 100 meters, pay special attention to the motor insulation voltage or use a drive-rated motor with reinforced insulation.

Failure to comply could lead to motor winding failure.

Motor vibration may increase when operating a machine in variable-speed mode, if that machine previously operated at a constant speed.

Install vibration-proof rubber on the motor base or use the frequency jump function to skip a frequency resonating the machine.

The motor may require more acceleration torque with drive operation than with a commercial power supply.

Set a proper V/f pattern by checking the load torque characteristics of the machine to be used with the motor.

The rated input current of submersible motors is higher than the rated input current of standard motors.

Select an appropriate drive according to its rated output current. When the distance between the motor and drive is long, use a cable thick enough to connect the motor to the drive to prevent motor torque reduction.

The current rating differs for a motor with variable pole pitches differs from a standard motor.

Check the maximum current of the motor before selecting the drive capacity. Only switch motor poles when the motor is stopped. Switching between motor during run will trigger overcurrent protection circuitry or result in overvoltage from regeneration, and the motor will simply coast to stop.

When using an explosion-proof motor, it must be subject to an explosion-proof test in conjunction with the drive.

This is also applicable when an existing explosion-proof motor is to be operated with the drive. Since the drive itself is not explosion-proof, always install it in a safe place.

Never lift the drive up while the cover is removed.

This can damage the terminal board and other components.

2.2 Mechanical Installation

This section outlines specifications, procedures, and the environment for proper mechanical installation of the drive.

◆ Installation Environment

Install the drive in an environment matching the specifications in [Table 2.1](#) to help prolong the optimum performance life of the drive.

Table 2.1 Installation Environment

| Environment | Conditions |
|---------------------|--|
| Installation Area | Indoors |
| Ambient Temperature | -10 °C to +40 °C (IP20/NEMA 1, UL Type 1 enclosure) -10 °C to +50 °C (IP00/Open Type enclosure) Drive reliability improves in environments without wide temperature fluctuations. When using the drive in an enclosure panel, install a cooling fan or air conditioner in the area to ensure that the air temperature inside the enclosure does not exceed the specified levels. Do not allow ice to develop on the drive. |
| Humidity | 95% RH or less and free of condensation |
| Storage Temperature | -20 to +60 °C |
| Surrounding Area | Install the drive in an area free from: <ul style="list-style-type: none"> • oil mist and dust • metal shavings, oil, water, or other foreign materials • radioactive materials • combustible materials (e.g., wood) • harmful gases and liquids • excessive vibration • chlorides • direct sunlight. |
| Altitude | 1000 m or lower, up to 3000 m with derating. Refer to Drive Derating Data on page 407 for details. |
| Vibration | 10 to 20 Hz at 9.8 m/s ² (32.15 ft/s ²) ^{<1>} 20 to 55 Hz at 5.9 m/s ² (19.36 ft/s ²) (Models 2A0004 to 2A0211, 4A0002 to 4A0165, and 5A0003 to 5A0099) or 2.0 m/s ² (6.56 ft/s ²) (Models 2A0250 to 2A0415, 4A0208 to 4A1200, and 5A0125 to 5A0242) |
| Orientation | Install the drive vertically to maintain maximum cooling effects. |

<1> Models 4A0930 and 4A1200 are rated at 5.9 m/s² (19.36 ft/s²)

NOTICE: Avoid placing drive peripheral devices, transformers, or other electronics near the drive as the noise created can lead to erroneous operation. If such devices must be used in close proximity to the drive, take proper steps to shield the drive from noise.

NOTICE: Prevent foreign matter such as metal shavings and wire clippings from falling into the drive during installation. Failure to comply could result in damage to the drive. Place a temporary cover over the top of the drive during installation. Remove the temporary cover before drive start-up, as the cover will reduce ventilation and cause the drive to overheat.

◆ Installation Orientation and Spacing

NOTICE: Install the drive upright as illustrated in [Figure 2.1](#). Failure to comply may damage the drive due to improper cooling.

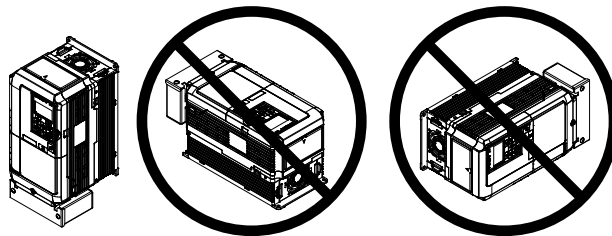


Figure 2.1 Correct Installation Orientation

NOTICE: Install the drive upright as specified in the manual. Failure to comply may damage the drive due to improper cooling.

Single Drive Installation

Figure 2.2 shows the installation distance required to maintain sufficient space for airflow and wiring. Install the heatsink against a closed surface to avoid diverting cooling air around the heatsink.

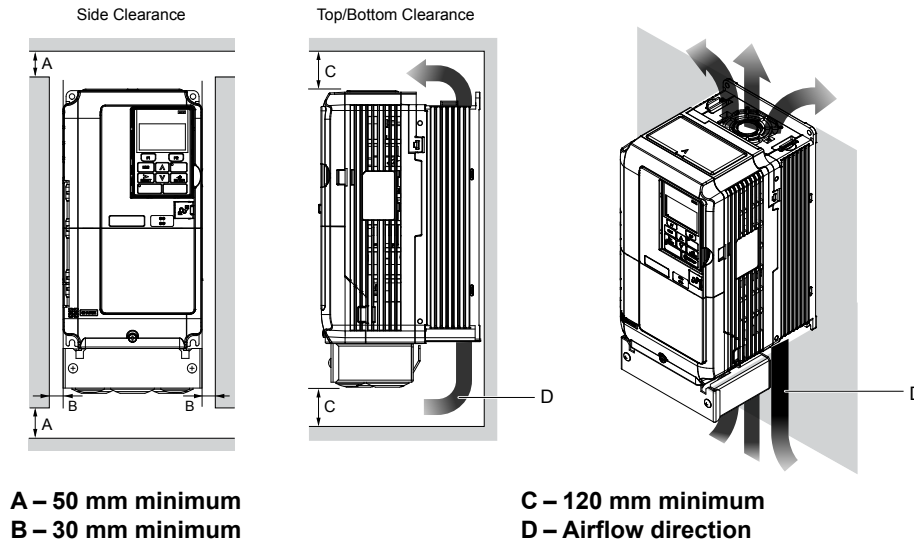


Figure 2.2 Correct Installation Spacing

Note: IP20/NEMA 1, UL Type 1 enclosure and IP00/Open Type enclosure models require the same amount of space above and below the drive for installation.

Multiple Drive Installation (Side-by-Side Installation)

Models 2A0004 to 2A0081, 4A0002 to 4A0044, and 5A0003 to 5A0032 can take advantage of Side-by-Side installation.

When installing multiple drives into the same enclosure panel, mount the drives according to **Figure 2.2** and set L8-35, Installation Method Selection, to 1 (Side-by-Side Mounting).

When mounting drives with the minimum clearance of 2 mm according to **Figure 2.3**, set parameter L8-35 to 1 while considering derating.

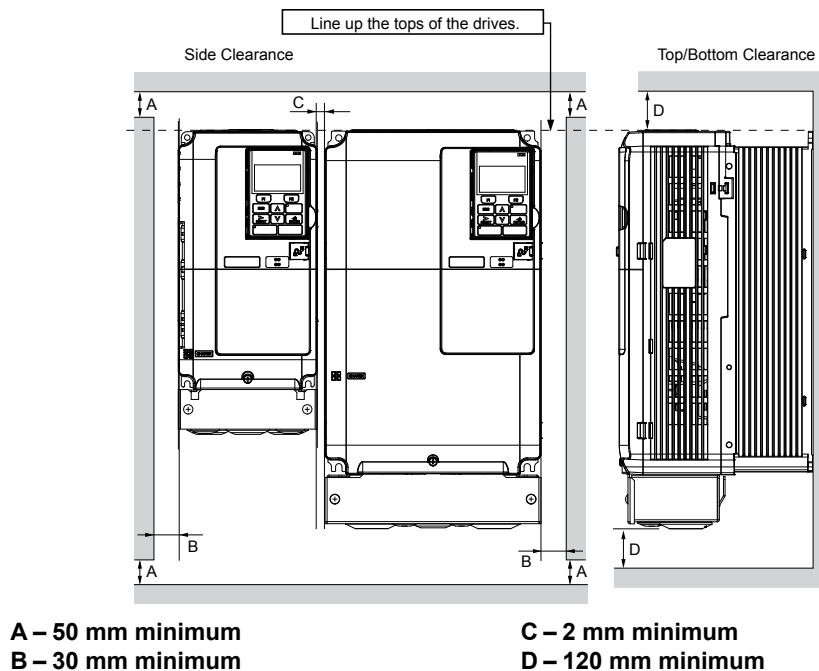


Figure 2.3 Space Between Drives (Side-by-Side Mounting)

Note: Align the tops of the drives when installing drives of different heights in the same enclosure panel. Leave space between the tops and bottoms of stacked drives for easier cooling fan replacement.

2.2 Mechanical Installation

Remove the top protective covers of all drives as shown in [Figure 2.4](#) when mounting IP20/NEMA 1, UL Type 1 enclosure drives side-by-side. [Refer to Top Protective Cover on page 82](#) to remove and reattach the top protective cover.

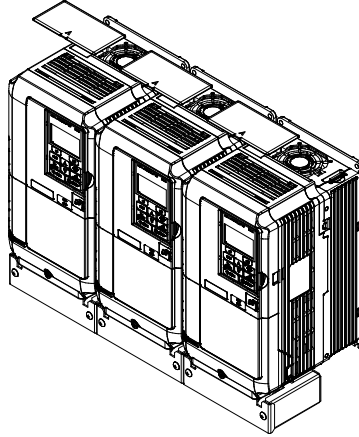


Figure 2.4 IP20/NEMA 1, UL Type 1 Side-by-Side Mounting in Enclosure

◆ Instructions on Installation Using the Eye Bolts

Eye bolts are used to install the drive or to temporarily lift the drive when replacing it. Using the eye bolts, the drive can be installed in an enclosure panel or on a wall. Do not leave the drive suspended by the wires in a horizontal or vertical position for long periods of time. Do not transport the drive over long distances. Read the following precautions and instructions before installing the drive.

WARNING! Crush Hazard. Observe the following instructions and precautions. Failure to comply could result in serious injury or death from falling equipment.

Only use vertical suspension to temporarily lift the drive during installation to an enclosure panel. Do not use vertical suspension to transport the drive.

Use screws to securely affix the drive front cover, terminal blocks, and other drive components prior to vertical suspension.

Do not subject the drive to vibration or impact greater than 1.96 m/s^2 (0.2 G) while it is suspended by the wires.

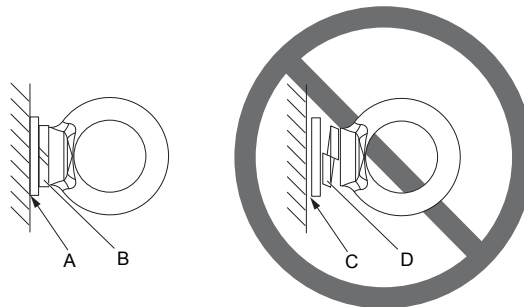
Do not leave the drive unattended while it is suspended by the wires.

Do not attempt to flip the drive over while it is suspended by the wires.

■ Horizontal Suspension of Drive Models 2A0360, 2A0415, and 4A0250 to 4A0675

To make a wire hanger or frame for use when lifting the drive with a crane, lay the drive in a horizontal position and pass a wire through the holes of the four eye bolts.

NOTICE: Damage to Equipment. When lifting the drive, confirm that the spring washer is fully closed. Failure to comply may deform or damage the drive when lifted.



A – No space between drive and washer
B – Spring washer fully closed

C – Space between drive and washer
D – Spring washer open

Figure 2.5 Spring Washer

■ Vertical Suspension of Drive Models 2A0360, 2A0415, and 4A0250 to 4A1200

Models 2A0360, 2A0415, and 4A0250 to 4A0675

When vertical suspension of the drive is required in an enclosure panel, change the orientation of the eye bolts for these models by turning the eye bolts counterclockwise 90 degrees.

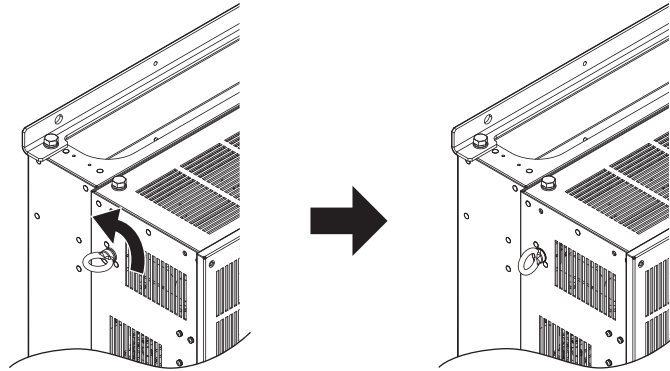


Figure 2.6 Adjusting Angle of Eye Bolts

Models 4A0930 and 4A1200

When suspending models 4A0930 or 4A1200 with wires, follow the procedure described below.

WARNING! Crush Hazard. Use an adequate length of wire to ensure a 50° or wider suspension angle as illustrated in [Figure 2.8](#). The maximum allowable load of the eye bolts cannot be guaranteed when the drive is suspended with the wires at angles less than 50°. Failure to comply may result in serious injury or death from falling equipment.

1. Remove the four eye bolts from the drive side panels and fix them securely on the top panel.

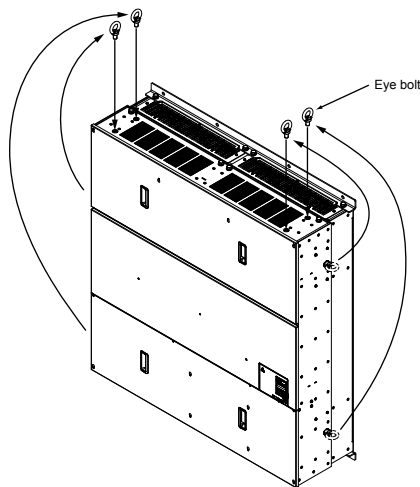
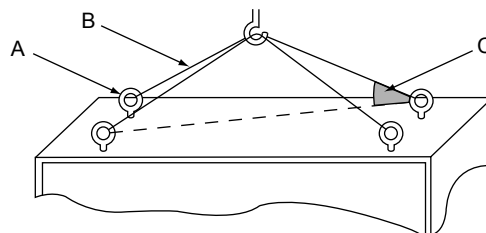


Figure 2.7 Eye Bolt Repositioning

2. Pass wire through the holes of all four eye bolts.



A – Eye bolt
B – Wires

C – Suspending angle: 50° or greater

Figure 2.8 Suspension Wire Angle Example

2.2 Mechanical Installation

3. Gradually take up the slack in the wires and hoist the drive after the wires are stretched tight.
4. Lower the drive when ready to install in the enclosure panel. Stop lowering the drive when it is near the floor then begin lowering the drive again very slowly until the drive is placed correctly.

◆ Digital Operator Remote Usage

■ Remote Operation

The digital operator mounted on the drive can be removed and connected to the drive using a remote control extension cable up to 3 m long to facilitate operation when the drive is installed in a location where it cannot be easily accessed.

The digital operator can also be permanently mounted remote locations such as panel doors using a remote control extension cable and an installation support set (depending on the installation type).

Note: Refer to *Drive Options and Peripheral Devices on page 376* for information on remote control extension cables and installation support sets.

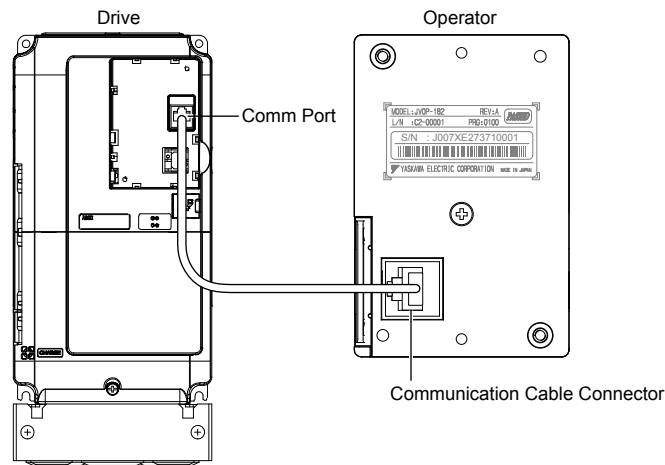


Figure 2.9 Communication Cable Connection

■ Digital Operator Remote Installation

Digital Operator Dimensions

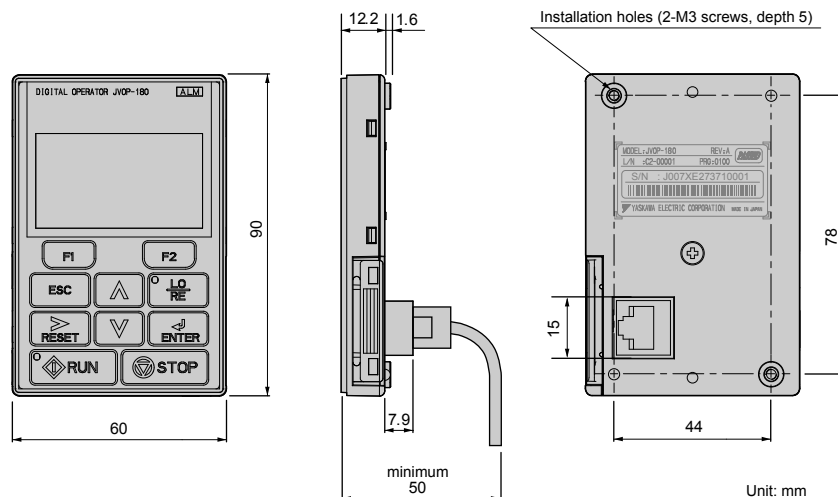


Figure 2.10 Digital Operator Dimensions

NEMA Keypad Kits

Provides digital operator functionality on an enclosure designed for IP20/NEMA 1, UL Type 1; NEMA 3R, UL Type 3R; NEMA 4, UL Type 4; NEMA 4X, UL Type 4X; NEMA 12, UL Type 12; or IPX6 environment.

Table 2.2 Installation Environment

| Keypad Kit Model | Description |
|------------------|-----------------------------------|
| UUX000526 | Blank label on the front. |
| UUX000527 | Yaskawa brand label on the front. |

Installation Types and Required Materials

The digital operator mounts to an enclosure two different ways:

- **External/face-mount** installs the operator outside the enclosure panel
- **Internal/flush-mount** installs the operator inside the enclosure panel

Table 2.3 Digital Operator Installation Methods and Required Tools

| Installation Method | Description | Installation Support Sets | Model | Required Tools |
|--------------------------|---|--|------------|--|
| External/ Face-Mount | Simplified installation with the digital operator is mounted on the outside of the panel with two screws. | - | - | Phillips screwdriver (#1) |
| Internal/ Flush-Mount | Encloses the digital operator in the panel. The front of the digital operator is flush with the outside of the panel. | Installation Support Set A (for mounting with screws through holes in the panel) | EZZ020642A | Phillips screwdriver (#1, #2) |
| | | Installation Support Set B (for use with threaded studs that are fixed to the panel) | EZZ020642B | Phillips screwdriver (#1) Wrench (7 mm) |

NOTICE: Prevent foreign matter such as metal shavings or wire clippings from falling into the drive during installation and project construction. Failure to comply could result in damage to the drive. Place a temporary cover over the top of the drive during installation. Remove the temporary cover before drive start-up, as the cover will reduce ventilation and cause the drive to overheat.

External/Face-Mount

1. Cut an opening in the enclosure panel for the digital operator as shown in [Figure 2.12](#).
2. Position the digital operator so the display faces outwards, and mount it to the enclosure panel as shown in [Figure 2.11](#).

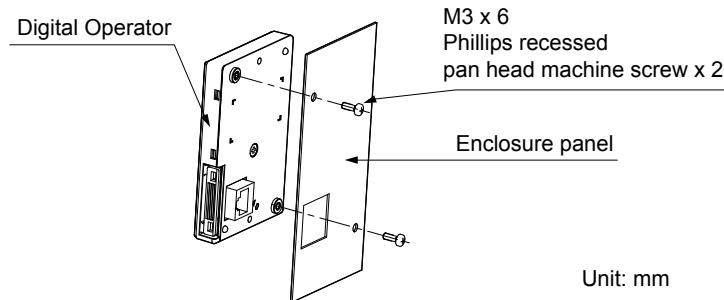


Figure 2.11 External/Face-Mount Installation

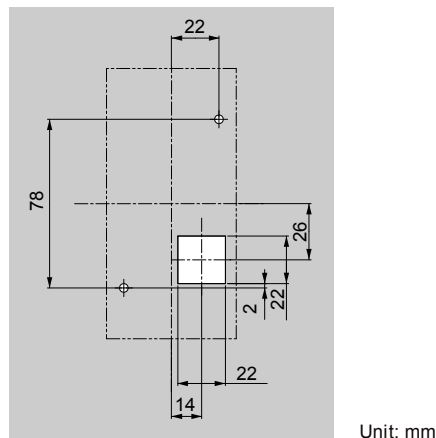


Figure 2.12 Panel Cut-Out Dimensions (External/Face-Mount Installation)

2.2 Mechanical Installation

Internal/Flush-Mount

An internal flush-mount requires an installation support set that must be purchased separately. Contact a Yaskawa representative to order an installation support set and mounting hardware. **Figure 2.13** illustrates how to attach the Installation Support Set A.

1. Cut an opening in the enclosure panel for the digital operator as shown in **Figure 2.14**.
2. Mount the digital operator to the installation support.
3. Mount the installation support set and digital operator to the enclosure panel.

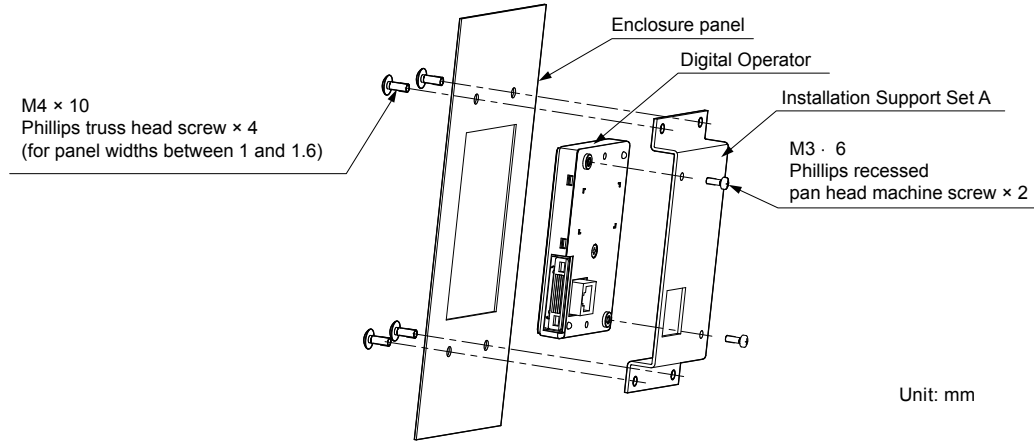


Figure 2.13 Internal/Flush Mount Installation

Note: Use a gasket between the enclosure panel and the digital operator in environments with a significant amount of dust or other airborne debris.

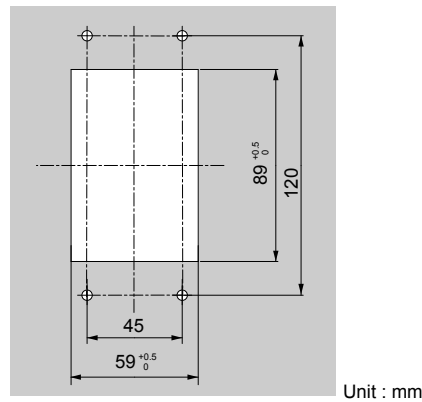


Figure 2.14 Panel Cut-Out Dimensions (Internal/Flush-Mount Installation)

◆ Exterior and Mounting Dimensions

Table 2.4 Drive Models and Types

| Protective Design | Drive Model | | | Page |
|----------------------------|-------------------------|-------------------------|-------------------------|------|
| | Three-Phase 200 V Class | Three-Phase 400 V Class | Three-Phase 600 V Class | |
| IP20/NEMA Type 1 Enclosure | 2A0004F | 4A0002F | | 56 |
| | 2A0006F | 4A0004F | 5A0003F | |
| | 2A0008F | 4A0005F | 5A0004F | |
| | 2A0010F | 4A0007F | 5A0006F | |
| | 2A0012F | 4A0009F | 5A0009F | |
| | 2A0018F | 4A0011F | 5A0011F | |
| | 2A0021F | 4A0018F | 5A0017F | |
| | 2A0030F | 4A0023F | 5A0022F | |
| | 2A0040F | 4A0031F | 5A0027F | |
| | 2A0056F | 4A0038F | 5A0032F | |
| | 2A0069F | 4A0044F | 5A0041F | |
| | 2A0081F | 4A0058F | 5A0052F | |
| | 2A0110F | 4A0072F | 5A0062F | |
| | 2A0138F | 4A0088F | 5A0077F | |
| | 2A0169F | 4A0103F | 5A0099F | |
| | 2A0211F | 4A0139F | | |
| | 4A0165F | | | |
| IP00/Open Type Enclosure | | 4A0208A <1> | | 62 |
| | | 4A0250A <1> | | |
| | 2A0250A <1> | 4A0296A <1> | 5A0125A <1> | |
| | 2A0312A <1> | 4A0362A <1> | 5A0145A <1> | |
| | 2A0360A <1> | 4A0414A <1> | 5A0192A <1> | |
| | 2A0415A <1> | 4A0515A <1> | 5A0242A <1> | |
| | | 4A0675A <1> | | |
| | | 4A0930A <1> | | |
| | | 4A1200A <1> | | |
| | | | | |

<1> Customers may convert these models to IP20/NEMA Type 1 enclosures using an IP20/NEMA Type 1 Kit. [Refer to IP20/NEMA 1, UL Type 1 Kit Selection on page 64](#) to select the appropriate kit.

<2> Contact a Yaskawa representative for IP20/NEMA Type 1 Kit availability for these models.

2.2 Mechanical Installation

■ IP20/NEMA 1, UL Type 1 Enclosure Drives

Note: Removing the top protective cover or bottom conduit bracket from an IP20/NEMA 1, UL Type 1 enclosure drive voids NEMA 1, UL Type 1 protection while maintaining IP20 conformity.

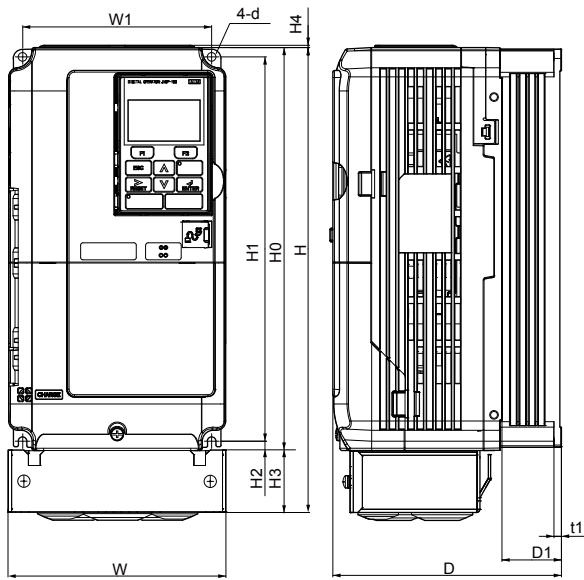


Figure 1

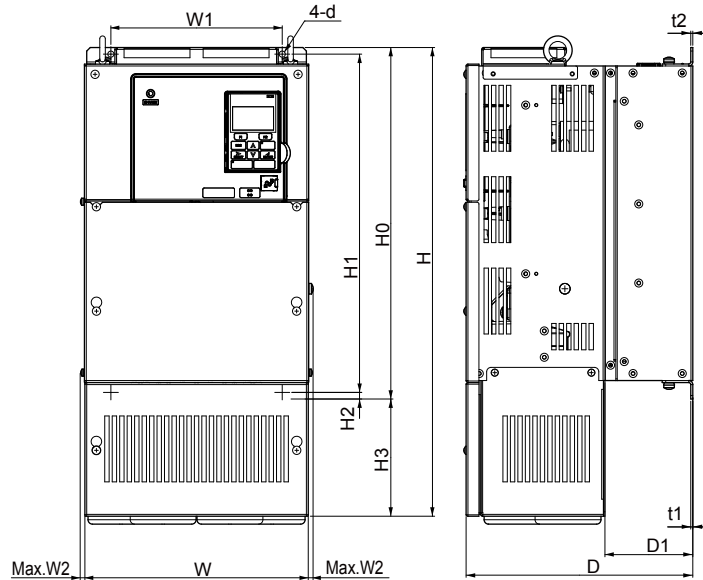


Figure 2

Table 2.5 Dimensions for IP20/NEMA 1, UL Type 1 Enclosure: 200 V Class

| Drive Model | Figure | Dimensions mm (in) | | | | | | | | | | | | | | Wt. kg (lb) | |
|-------------|----------------|--------------------|----------------|----------------|----------------|---------------|----------------|----------------|----------------|---------------|---------------|---------------|---------------|-----------------|-----------------|---------------|--------------|
| | | W | H | D | W1 | W2 | H0 | H1 | H2 | H3 | H4 | D1 | t1 | t2 | d | | |
| 2A0004F | 1 < > | 140 (5.51) | 300 (11.81) | 147 (5.79) | 122 (4.80) | - | 260 (10.24) | 248 (9.76) | 6 (0.24) | 40 (1.57) | 1.5 (0.06) | 38 (1.50) | 5 (0.20) | - | M5 | 3.3 (7.3) | |
| 2A0006F | | 140 (5.51) | 300 (11.81) | 147 (5.79) | 122 (4.80) | - | 260 (10.24) | 248 (9.76) | 6 (0.24) | 40 (1.57) | 1.5 (0.06) | 38 (1.50) | 5 (0.20) | - | M5 | 3.3 (7.3) | |
| 2A0008F | | 140 (5.51) | 300 (11.81) | 147 (5.79) | 122 (4.80) | - | 260 (10.24) | 248 (9.76) | 6 (0.24) | 40 (1.57) | 1.5 (0.06) | 38 (1.50) | 5 (0.20) | - | M5 | 3.4 (7.5) | |
| 2A0010F | | 140 (5.51) | 300 (11.81) | 147 (5.79) | 122 (4.80) | - | 260 (10.24) | 248 (9.76) | 6 (0.24) | 40 (1.57) | 1.5 (0.06) | 38 (1.50) | 5 (0.20) | - | M5 | 3.4 (7.5) | |
| 2A0012F | | 140 (5.51) | 300 (11.81) | 147 (5.79) | 122 (4.80) | - | 260 (10.24) | 248 (9.76) | 6 (0.24) | 40 (1.57) | 1.5 (0.06) | 38 (1.50) | 5 (0.20) | - | M5 | 3.4 (7.5) | |
| 2A0018F | | 140 (5.51) | 300 (11.81) | 164 (6.46) | 122 (4.80) | - | 260 (10.24) | 248 (9.76) | 6 (0.24) | 40 (1.57) | 1.5 (0.06) | 55 (2.17) | 5 (0.20) | - | M5 | 3.8 (8.2) | |
| 2A0021F | | 140 (5.51) | 300 (11.81) | 164 (6.46) | 122 (4.80) | - | 260 (10.24) | 248 (9.76) | 6 (0.24) | 40 (1.57) | 1.5 (0.06) | 55 (2.17) | 5 (0.20) | - | M5 | 3.8 (8.2) | |
| 2A0030F | | 140 (5.51) | 300 (11.81) | 167 (6.57) | 122 (4.80) | - | 260 (10.24) | 248 (9.76) | 6 (0.24) | 40 (1.57) | 1.5 (0.06) | 55 (2.17) | 5 (0.20) | - | M5 | 4.2 (9.3) | |
| 2A0040F | | 140 (5.51) | 300 (11.81) | 167 (6.57) | 122 (4.80) | - | 260 (10.24) | 248 (9.76) | 6 (0.24) | 40 (1.57) | 1.5 (0.06) | 55 (2.17) | 5 (0.20) | - | M5 | 4.2 (9.3) | |
| 2A0056F | | 180 (7.09) | 340 (13.39) | 187 (7.36) | 160 (6.30) | - | 300 (11.81) | 284 (11.18) | 7.9 (0.31) | 40 (1.57) | 1.5 (0.06) | 75 (2.95) | 5 (0.20) | - | M5 | 5.9 (13.0) | |
| 2A0069F | | 220 (8.66) | 400 (15.75) | 197 (7.76) | 192 (7.56) | - | 350 (13.78) | 335 (13.19) | 7.9 (0.31) | 50 (1.97) | 1.5 (0.06) | 78 (3.07) | 5 (0.20) | - | M6 | 9 (20.1) | |
| 2A0081F | | 220 (8.66) | 400 (15.75) | 197 (7.76) | 192 (7.56) | - | 350 (13.78) | 335 (13.19) | 7.9 (0.31) | 50 (1.97) | 1.5 (0.06) | 78 (3.07) | 5 (0.20) | - | M6 | 10 (22.0) | |
| 2A0110F | | 2 < > | 254 (10.00) | 534 (21.02) | 258 (10.16) | 195 (7.68) | 7.9 (0.31) | 400 (15.75) | 385 (15.16) | 7.7 (0.30) | 134 (5.28) | 1.5 (0.06) | 100 (3.94) | 2.2 (0.09) | 2.286 (0.09) | M6 | 23 (50.7) |
| 2A0138F | | | 279 (10.98) | 614 (24.17) | 258 (10.16) | 220 (8.66) | 7.9 (0.31) | 450 (17.72) | 435 (17.13) | 7.7 (0.30) | 164 (6.46) | - | 100 (3.94) | 2.2 (0.09) | 2.286 (0.09) | M6 | 28 (61.7) |
| 2A0169F | 329 (12.95) | | 730 (28.74) | 283 (11.14) | 260 (10.24) | 7.9 (0.31) | 550 (21.65) | 535 (21.06) | 7.7 (0.30) | 180 (7.09) | - | 110 (4.33) | 2.2 (0.09) | 2.286 (0.09) | M6 | 41 (90.4) | |
| 2A0211F | 329 (12.95) | | 730 (28.74) | 283 (11.14) | 260 (10.24) | 7.9 (0.31) | 550 (21.65) | 535 (21.06) | 7.7 (0.30) | 180 (7.09) | - | 110 (4.33) | 2.2 (0.09) | 2.286 (0.09) | M6 | 42 (92.6) | |

| Drive Model | Figure | Dimensions mm (in) | | | | | | | | | | | | | | Wt. kg (lb) |
|---|--------|--------------------|-----------------|----------------|----------------|---------------|----------------|----------------|--------------|----------------|----|---------------|---------------|----------------|-----|----------------|
| | | W | H | D | W1 | W2 | H0 | H1 | H2 | H3 | H4 | D1 | t1 | t2 | d | |
| Dimensions below are the dimensions of IP00/Open Type models after customer installation of the appropriate IP20/NEMA 1, UL Type 1 Kit. | | | | | | | | | | | | | | | | |
| 2A0250A | 2 | 456 (17.95) | 960 (37.80) | 330 (12.99) | 325 (12.80) | 7.9 (0.31) | 28 (27.76) | 680 (26.77) | 12 (0.49) | 255 (10.04) | - | 130 (5.12) | 3.3 (0.13) | 3.3 (0.13) | M10 | 83 (183.0) |
| 2A0312A | | 456 (17.95) | 960 (37.80) | 330 (12.99) | 325 (12.80) | 7.9 (0.31) | 28 (27.76) | 680 (26.77) | 12 (0.49) | 255 (10.04) | - | 130 (5.12) | 3.3 (0.13) | 3.30 (0.13) | M10 | 88 (194.0) |
| 2A0360A | | 194 (19.84) | 1168 (45.98) | 35 (13.78) | 370 (14.57) | 7.9 (0.31) | 800 (31.50) | 773 (30.43) | 13 (0.51) | 368 (14.49) | - | 130 (5.12) | 4.6 (0.18) | 4.6 (0.18) | M12 | 108 (238.1) |

<1> Removing the top protective cover from an IP20/NEMA 1, UL Type 1 enclosure drive voids NEMA 1, UL Type 1 protection while retaining IP20 conformity.

Table 2.6 Dimensions for IP20/NEMA 1, UL Type 1 Enclosure: 400 V Class

| Drive Model | Figure | Dimensions mm (in) | | | | | | | | | | | | | | Wt. kg (lb) |
|---|----------------|--------------------|-----------------|----------------|----------------|----------------|----------------|----------------|---------------|----------------|---------------|---------------|---------------|---------------|---------------|----------------|
| | | W | H | D | W1 | W2 | H0 | H1 | H2 | H3 | H4 | D1 | t1 | t2 | d | |
| 4A0002F | 1 </> | 140 (5.51) | 300 (11.81) | 147 (5.79) | 122 (4.80) | - | 260 (10.24) | 248 (9.76) | 6 (0.24) | 40 (1.57) | 1.5 (0.06) | 38 (1.50) | 5 (0.20) | - | M5 | 3.4 (7.5) |
| 4A0004F | | 140 (5.51) | 300 (11.81) | 147 (5.79) | 122 (4.80) | - | 260 (10.24) | 248 (9.76) | 6 (0.24) | 40 (1.57) | 1.5 (0.06) | 38 (1.50) | 5 (0.20) | - | M5 | 3.4 (7.5) |
| 4A0005F | | 140 (5.51) | 300 (11.81) | 147 (5.79) | 122 (4.80) | - | 260 (10.24) | 248 (9.76) | 6 (0.24) | 40 (1.57) | 1.5 (0.06) | 38 (1.50) | 5 (0.20) | - | M5 | 3.4 (7.5) |
| 4A0007F | | 140 (5.51) | 300 (11.81) | 164 (6.46) | 122 (4.80) | - | 260 (10.24) | 248 (9.76) | 6 (0.24) | 40 (1.57) | 1.5 (0.06) | 55 (2.17) | 5 (0.20) | - | M5 | 3.6 (7.9) |
| 4A0009F | | 140 (5.51) | 300 (11.81) | 164 (6.46) | 122 (4.80) | - | 260 (10.24) | 248 (9.76) | 6 (0.24) | 40 (1.57) | 1.5 (0.06) | 55 (2.17) | 5 (0.20) | - | M5 | 3.8 (8.2) |
| 4A0011F | | 140 (5.51) | 300 (11.81) | 164 (6.46) | 122 (4.80) | - | 260 (10.24) | 248 (9.76) | 6 (0.24) | 40 (1.57) | 1.5 (0.06) | 55 (2.17) | 5 (0.20) | - | M5 | 3.8 (8.2) |
| 4A0018F | | 140 (5.51) | 300 (11.81) | 167 (6.57) | 122 (4.80) | - | 260 (10.24) | 248 (9.76) | 6 (0.24) | 40 (1.57) | 1.5 (0.06) | 55 (2.17) | 5 (0.20) | - | M5 | 4.0 (9.0) |
| 4A0023F | | 140 (5.51) | 300 (11.81) | 167 (6.57) | 122 (4.80) | - | 260 (10.24) | 248 (9.76) | 6 (0.24) | 40 (1.57) | 1.5 (0.06) | 55 (2.17) | 5 (0.20) | - | M5 | 4.0 (9.0) |
| 4A0031F | | 180 (7.09) | 340 (13.39) | 167 (6.57) | 160 (6.30) | - | 300 (11.81) | 284 (11.18) | 7.9 (0.31) | 40 (1.57) | 1.5 (0.06) | 55 (2.17) | 5 (0.20) | - | M5 | 5.8 (12.6) |
| 4A0038F | | 180 (7.09) | 340 (13.39) | 187 (7.36) | 160 (6.30) | - | 300 (11.81) | 284 (11.18) | 7.9 (0.31) | 40 (1.57) | 1.5 (0.06) | 75 (2.95) | 5 (0.20) | - | M5 | 6.0 (13.2) |
| 4A0044F | | 220 (8.66) | 400 (15.75) | 197 (7.76) | 195 (7.68) | - | 35 (13.78) | 335 (13.19) | 7.9 (0.31) | 50 (1.97) | 1.5 (0.06) | 78 (3.07) | 5 (0.20) | - | M6 | 8.8 (19.2) |
| 4A0058F | | 254 (10.00) | 465 (18.31) | 258 (10.16) | 195 (7.68) | 7.9 (0.31) | 400 (15.75) | 385 (15.16) | 7.7 (0.30) | 65 (2.56) | - | 100 (3.94) | 2.2 (0.09) | 2.2 (0.09) | M6 | 23 (50.7) |
| 4A0072F | | 279 (10.98) | 515 (20.28) | 258 (10.16) | 220 (8.66) | 7.9 (0.31) | 450 (17.72) | 435 (17.13) | 7.7 (0.30) | 65 (2.56) | - | 100 (3.94) | 2.2 (0.09) | 2.2 (0.09) | M6 | 27 (59.5) |
| 4A0088F | | 329 (12.95) | 630 (24.80) | 258 (10.16) | 260 (10.24) | 7.9 (0.31) | 509 (20.08) | 495 (19.49) | 7.7 (0.30) | 120 (4.72) | - | 105 (4.13) | 2.2 (0.09) | 3.3 (0.13) | M6 | 39 (86.0) |
| 4A0103F | 329 (12.95) | 630 (24.80) | 258 (10.16) | 260 (10.24) | 7.9 (0.31) | 509 (20.08) | 495 (19.49) | 7.7 (0.30) | 120 (4.72) | - | 105 (4.13) | 2.2 (0.09) | 3.3 (0.13) | M6 | 39 (86.0) | |
| 4A0139F | 329 (12.95) | 730 (28.74) | 283 (11.14) | 260 (10.24) | 7.9 (0.31) | 550 (21.65) | 535 (21.06) | 7.7 (0.30) | 180 (7.09) | - | 110 (4.33) | 2.2 (0.09) | 2.2 (0.09) | M6 | 45 (99.2) | |
| 4A0165F | 329 (12.95) | 730 (28.74) | 283 (11.14) | 260 (10.24) | 7.9 (0.31) | 550 (21.65) | 535 (21.06) | 7.7 (0.30) | 180 (7.09) | - | 110 (4.33) | 2.2 (0.09) | 2.2 (0.09) | M6 | 46 (101.4) | |
| Dimensions below are the dimensions of IP00/Open Type models after customer installation of the appropriate IP20/NEMA 1, UL Type 1 Kit. | | | | | | | | | | | | | | | | |
| 4A0208A | 2 | 456 (17.95) | 960 (37.80) | 330 (12.99) | 325 (12.80) | 7.9 (0.31) | 28 (27.76) | 680 (26.77) | 12 (0.49) | 255 (10.04) | - | 130 (5.12) | 3.3 (0.13) | 3.3 (0.13) | M10 | 87 (191.8) |
| 4A0250A | | 194 (19.84) | 1168 (45.98) | 35 (13.78) | 370 (14.57) | 7.9 (0.31) | 800 (31.50) | 773 (30.43) | 13 (0.51) | 368 (14.49) | - | 130 (5.12) | 4.6 (0.18) | 4.6 (0.18) | M12 | 106 (233.7) |
| 4A0296A | | 194 (19.84) | 1168 (45.98) | 35 (13.78) | 370 (14.57) | 7.9 (0.31) | 800 (31.50) | 773 (30.43) | 13 (0.51) | 368 (14.49) | - | 130 (5.12) | 4.6 (0.18) | 4.6 (0.18) | M12 | 112 (246.9) |
| 4A0362A | | 194 (19.84) | 1168 (45.98) | 35 (13.78) | 370 (14.57) | 7.9 (0.31) | 800 (31.50) | 773 (30.43) | 13 (0.51) | 368 (14.49) | - | 130 (5.12) | 4.6 (0.18) | 4.6 (0.18) | M12 | 117 (257.9) |

<1> Removing the top protective cover from an IP20/NEMA 1, UL Type 1 enclosure drive voids NEMA 1, UL Type 1 protection while retaining IP20 conformity.

2.2 Mechanical Installation

Table 2.7 Dimensions for IP20/NEMA 1, UL Type 1 Enclosure: 600 V Class

| Drive Model | Figure | Dimensions mm (in) | | | | | | | | | | | | | | Wt. kg (lb) |
|--|----------------|--------------------|-----------------|----------------|----------------|---------------|----------------|----------------|----------------|----------------|---------------|---------------|---------------|---------------|---------------|----------------|
| | | W | H | D | W1 | W2 | H0 | H1 | H2 | H3 | H4 | D1 | t1 | t2 | d | |
| 5A0003F | 1 <1> | 140 (5.51) | 300 (11.81) | 147 (5.79) | 122 (4.80) | - | 260 (10.24) | 248 (9.76) | 6 (0.24) | 40 (1.57) | 1.5 (0.06) | 38 (1.50) | 5 (0.20) | - | M5 | 3.4 (7.5) |
| 5A0004F | | 140 (5.51) | 300 (11.81) | 147 (5.79) | 122 (4.80) | - | 260 (10.24) | 248 (9.76) | 6 (0.24) | 40 (1.57) | 1.5 (0.06) | 38 (1.50) | 5 (0.20) | - | M5 | 3.4 (7.5) |
| 5A0006F | | 140 (5.51) | 300 (11.81) | 164 (6.46) | 122 (4.80) | - | 260 (10.24) | 248 (9.76) | 6 (0.24) | 40 (1.57) | 1.5 (0.06) | 55 (2.17) | 5 (0.20) | - | M5 | 3.8 (8.2) |
| 5A0009F | | 140 (5.51) | 300 (11.81) | 164 (6.46) | 122 (4.80) | - | 260 (10.24) | 248 (9.76) | 6 (0.24) | 40 (1.57) | 1.5 (0.06) | 55 (2.17) | 5 (0.20) | - | M5 | 3.8 (8.2) |
| 5A0011F | | 140 (5.51) | 300 (11.81) | 167 (6.57) | 122 (4.80) | - | 260 (10.24) | 248 (9.76) | 6 (0.24) | 40 (1.57) | 1.5 (0.06) | 55 (2.17) | 5 (0.20) | - | M5 | 4.0 (9.0) |
| 5A0017F | | 180 (7.09) | 340 (13.39) | 187 (7.36) | 160 (6.30) | - | 300 (11.81) | 284 (11.18) | 7.9 (0.31) | 40 (1.57) | 1.5 (0.06) | 75 (2.95) | 5 (0.20) | - | M5 | 6.0 (13.2) |
| 5A0022F | | 180 (7.09) | 340 (13.39) | 187 (7.36) | 160 (6.30) | - | 300 (11.81) | 284 (11.18) | 7.9 (0.31) | 40 (1.57) | 1.5 (0.06) | 75 (2.95) | 5 (0.20) | - | M5 | 6.0 (13.2) |
| 5A0027F | | 220 (8.66) | 400 (15.75) | 197 (7.76) | 192 (7.56) | - | 35 (13.78) | 335 (13.19) | 7.9 (0.31) | 50 (1.97) | 1.5 (0.06) | 78 (3.07) | 5 (0.20) | - | M6 | 8.8 (19.2) |
| 5A0032F | | 220 (8.66) | 400 (15.75) | 197 (7.76) | 192 (7.56) | - | 35 (13.78) | 335 (13.19) | 7.9 (0.31) | 50 (1.97) | 1.5 (0.06) | 78 (3.07) | 5 (0.20) | - | M6 | 8.8 (19.2) |
| 5A0041F | | 2 | 279 (10.98) | 515 (20.28) | 258 (10.16) | 220 (8.66) | 7.9 (0.31) | 450 (17.72) | 435 (17.13) | 7.7 (0.30) | 65 (2.56) | - | 100 (3.94) | 2.2 (0.09) | 2.2 (0.09) | M6 |
| 5A0052F | 279 (10.98) | | 515 (20.28) | 258 (10.16) | 220 (8.66) | 7.9 (0.31) | 450 (17.72) | 435 (17.13) | 7.7 (0.30) | 65 (2.56) | - | 100 (3.94) | 2.2 (0.09) | 2.2 (0.09) | M6 | 27 (59.5) |
| 5A0062F | 329 (12.95) | | 730 (28.74) | 283 (11.14) | 260 (10.24) | 7.9 (0.31) | 550 (21.65) | 535 (21.06) | 7.7 (0.30) | 180 (7.09) | - | 110 (4.33) | 2.2 (0.09) | 2.2 (0.09) | M6 | 45 (99.2) |
| 5A0077F | 329 (12.95) | | 730 (28.74) | 283 (11.14) | 260 (10.24) | 7.9 (0.31) | 550 (21.65) | 535 (21.06) | 7.7 (0.30) | 180 (7.09) | - | 110 (4.33) | 2.2 (0.09) | 2.2 (0.09) | M6 | 45 (99.2) |
| 5A0099F | 329 (12.95) | | 730 (28.74) | 283 (11.14) | 260 (10.24) | 7.9 (0.31) | 550 (21.65) | 535 (21.06) | 7.7 (0.30) | 180 (7.09) | - | 110 (4.33) | 2.2 (0.09) | 2.2 (0.09) | M6 | 45 (99.2) |
| Dimensions below are the dimensions of IP00/Open Type models after customer installation of the appropriate IP20/NEMA 1, UL Type 1 Kit. | | | | | | | | | | | | | | | | |
| 5A0125A | 2 | 456 (17.95) | 960 (37.80) | 330 (12.99) | 325 (12.80) | 7.9 (0.31) | 28 (27.76) | 680 (26.77) | 12 (0.49) | 255 (10.04) | - | 130 (5.12) | 3.3 (0.13) | 3.3 (0.13) | M10 | 87 (191.8) |
| 5A0145A | | 456 (17.95) | 960 (37.80) | 330 (12.99) | 325 (12.80) | 7.9 (0.31) | 28 (27.76) | 680 (26.77) | 12 (0.49) | 255 (10.04) | - | 130 (5.12) | 3.3 (0.13) | 3.3 (0.13) | M10 | 87 (191.8) |
| 5A0192A | | 194 (19.84) | 1168 (45.98) | 35 (13.78) | 370 (14.57) | 7.9 (0.31) | 800 (31.50) | 773 (30.43) | 13 (0.51) | 368 (14.49) | - | 130 (5.12) | 4.6 (0.18) | 4.6 (0.18) | M12 | 106 (233.7) |
| 5A0242A | | 194 (19.84) | 1168 (45.98) | 35 (13.78) | 370 (14.57) | 7.9 (0.31) | 800 (31.50) | 773 (30.43) | 13 (0.51) | 368 (14.49) | - | 130 (5.12) | 4.6 (0.18) | 4.6 (0.18) | M12 | 117 (257.9) |

<1> Removing the top protective cover or bottom conduit bracket from an IP20/NEMA 1, UL Type 1 enclosure drive voids NEMA 1, UL Type 1 protection while maintaining IP20 conformity.

IP20/NEMA 1, UL Type 1 Enclosure Conduit Bracket Dimensions

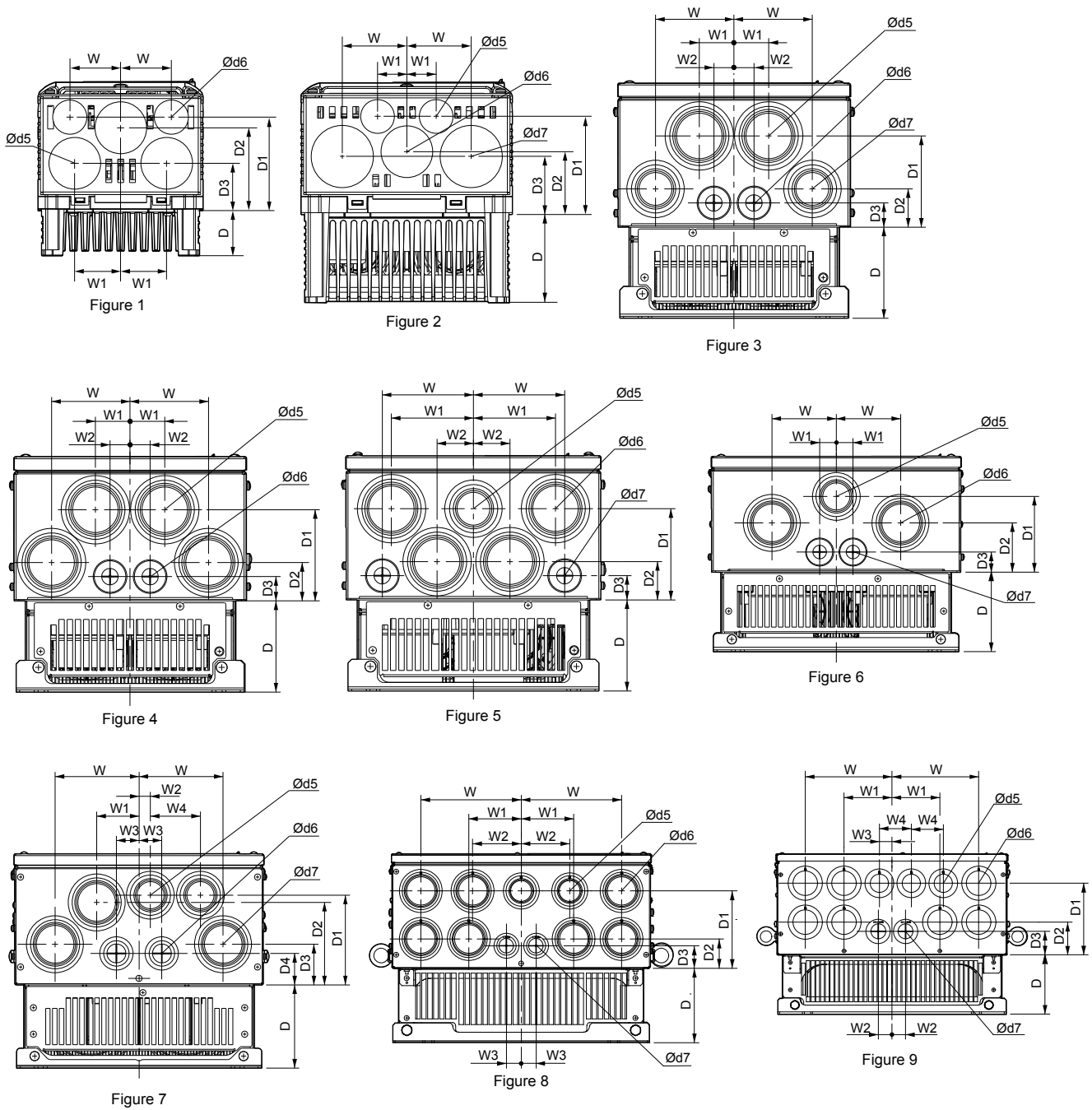


Table 2.8 Conduit Bracket Dimensions for IP20/NEMA 1, UL Type 1

| Drive Model | Figure | Dimensions mm (in) | | | | | | | | | | Diameter mm (in) | | |
|--------------------|--------|--------------------|-------------|-------------|----|----|----|-------------|-------------|-------------|----|------------------|-------------|----|
| | | W | D | W1 | W2 | W3 | W4 | D1 | D2 | D3 | D4 | d5 | d6 | d7 |
| 200 V Class | | | | | | | | | | | | | | |
| 2A0004F | 1 | 43 (1.7) | 38 (1.5) | 38 (1.5) | - | - | - | 41 (1.6) | 71 (2.8) | 79 (3.1) | - | 23 (0.9) | 36 (1.4) | - |
| 2A0006F | | 43 (1.7) | 38 (1.5) | 38 (1.5) | - | - | - | 41 (1.6) | 71 (2.8) | 79 (3.1) | - | 23 (0.9) | 36 (1.4) | - |
| 2A0008F | | 43 (1.7) | 38 (1.5) | 38 (1.5) | - | - | - | 41 (1.6) | 71 (2.8) | 79 (3.1) | - | - | - | - |
| 2A0010F | | 43 (1.7) | 38 (1.5) | 38 (1.5) | - | - | - | 41 (1.6) | 71 (2.8) | 79 (3.1) | - | 23 (0.9) | 36 (1.4) | - |
| 2A0012F | | 43 (1.7) | 56 (2.2) | 38 (1.5) | - | - | - | 41 (1.6) | 71 (2.8) | 79 (3.1) | - | 23 (0.9) | 36 (1.4) | - |

2.2 Mechanical Installation

| Drive Model | Figure | Dimensions mm (in) | | | | | | | | | | Diameter mm (in) | | |
|--------------------|--------|--------------------|--------------|--------------|-------------|-------------|-------------|--------------|--------------|-------------|-------------|------------------|-------------|-------------|
| | | W | D | W1 | W2 | W3 | W4 | D1 | D2 | D3 | D4 | d5 | d6 | d7 |
| 2A0018F | 2 | 43 (1.7) | 56 (2.2) | 38 (1.5) | - | - | - | 41 (1.6) | 71 (2.8) | 79 (3.1) | - | 36 (1.4) | 23 (0.9) | 43 (1.7) |
| 2A0021F | | 43 (1.7) | 56 (2.2) | 38 (1.5) | - | - | - | 41 (1.6) | 71 (2.8) | 79 (3.1) | - | 36 (1.4) | 23 (0.9) | 43 (1.7) |
| 2A0030F | | 43 (1.7) | 56 (2.2) | 38 (1.5) | - | - | - | 41 (1.6) | 71 (2.8) | 79 (3.1) | - | 36 (1.4) | 23 (0.9) | 43 (1.7) |
| 2A0040F | | 25 (1.0) | 76 (3.0) | 56 (2.2) | - | - | - | 48 (1.9) | 84 (3.3) | 53 (2.1) | - | 36 (1.4) | 23 (0.9) | 43 (1.7) |
| 2A0056F | | 25 (1.0) | 76 (3.0) | 56 (2.2) | - | - | - | 48 (1.9) | 84 (3.3) | 53 (2.1) | - | 36 (1.4) | 23 (0.9) | 43 (1.7) |
| 2A0069F | | 28 (1.1) | 79 (3.1) | 64 (2.5) | - | - | - | 51 (2.0) | 86 (3.4) | 56 (2.2) | - | 36 (1.4) | 23 (0.9) | 43 (1.7) |
| 2A0081F | | 28 (1.1) | 79 (3.1) | 64 (2.5) | - | - | - | 51 (2.0) | 86 (3.4) | 56 (2.2) | - | 36 (1.4) | 23 (0.9) | 43 (1.7) |
| 2A0110F | 4 | 86 (3.4) | 99 (3.9) | 38 (1.5) | 23 (0.9) | - | - | 99 (3.9) | 43 (1.7) | 25 (1.0) | - | 61 (2.4) | 28 (1.1) | - |
| 2A0138F | 5 | 99 (3.9) | 99 (3.9) | 89 (3.5) | 41 (1.6) | - | - | 99 (3.9) | 43 (1.7) | 25 (1.0) | - | 51 (2.0) | 61 (2.4) | 28 (1.1) |
| 2A0169F | 7 | 111 (4.4) | 109 (4.3) | 56 (2.2) | 15 (0.6) | 30 (1.2) | 66 (2.6) | 119 (4.7) | 109 (4.3) | 53 (2.1) | 41 (1.6) | 51 (2.0) | 36 (1.4) | 61 (2.4) |
| 2A0211F | | 111 (4.4) | 109 (4.3) | 56 (2.2) | 15 (0.6) | 30 (1.2) | 66 (2.6) | 119 (4.7) | 109 (4.3) | 53 (2.1) | 41 (1.6) | 51 (2.0) | 36 (1.4) | 61 (2.4) |
| 2A0250A | 8 | 175 (6.9) | 130 (5.1) | 91 (3.6) | 84 (3.3) | 25 (1.0) | - | 137 (5.4) | 51 (2.0) | 41 (1.6) | - | 51 (2.0) | 61 (2.4) | 36 (1.4) |
| 2A0312A | | 175 (6.9) | 130 (5.1) | 91 (3.6) | 84 (3.3) | 25 (1.0) | - | 137 (5.4) | 51 (2.0) | 41 (1.6) | - | 51 (2.0) | 61 (2.4) | 36 (1.4) |
| 2A0360A | 9 | 191 (7.5) | 130 (5.1) | 104 (4.1) | 30 (1.2) | 28 (1.1) | 71 (2.8) | 157 (6.2) | 71 (2.8) | 51 (2.0) | - | 51 (2.0) | 61 (2.4) | 43 (1.7) |
| 400 V Class | | | | | | | | | | | | | | |
| 4A0002F | 1 | 43 (1.7) | 38 (1.5) | 38 (1.5) | - | - | - | 41 (1.6) | 71 (2.8) | 79 (3.1) | - | 23 (0.9) | 36 (1.4) | - |
| 4A0004F | | 43 (1.7) | 38 (1.5) | 38 (1.5) | - | - | - | 41 (1.6) | 71 (2.8) | 79 (3.1) | - | 23 (0.9) | 36 (1.4) | - |
| 4A0005F | | 43 (1.7) | 38 (1.5) | 38 (1.5) | - | - | - | 41 (1.6) | 71 (2.8) | 79 (3.1) | - | 23 (0.9) | 36 (1.4) | - |
| 4A0007F | | 43 (1.7) | 56 (2.2) | 38 (1.5) | - | - | - | 41 (1.6) | 71 (2.8) | 79 (3.1) | - | 23 (0.9) | 36 (1.4) | - |
| 4A0009F | | 43 (1.7) | 56 (2.2) | 38 (1.5) | - | - | - | 41 (1.6) | 71 (2.8) | 79 (3.1) | - | 23 (0.9) | 36 (1.4) | - |
| 4A0011F | | 43 (1.7) | 56 (2.2) | 38 (1.5) | - | - | - | 41 (1.6) | 71 (2.8) | 79 (3.1) | - | 23 (0.9) | 36 (1.4) | - |
| 4A0018F | | 43 (1.7) | 56 (2.2) | 38 (1.5) | - | - | - | 41 (1.6) | 71 (2.8) | 79 (3.1) | - | 23 (0.9) | 36 (1.4) | - |
| 4A0023F | 2 | 25 (1.0) | 76 (3.0) | 56 (2.2) | - | - | - | 48 (1.9) | 84 (3.3) | 53 (2.1) | - | 36 (1.4) | 23 (0.9) | 43 (1.7) |
| 4A0031F | | 25 (1.0) | 76 (3.0) | 56 (2.2) | - | - | - | 48 (1.9) | 84 (3.3) | 53 (2.1) | - | 36 (1.4) | 23 (0.9) | 43 (1.7) |
| 4A0038F | | 28 (1.1) | 79 (3.1) | 64 (2.5) | - | - | - | 51 (2.0) | 86 (3.4) | 56 (2.2) | - | 36 (1.4) | 23 (0.9) | 43 (1.7) |
| 4A0044F | | 28 (1.1) | 79 (3.1) | 64 (2.5) | - | - | - | 51 (2.0) | 86 (3.4) | 56 (2.2) | - | 36 (1.4) | 23 (0.9) | 43 (1.7) |
| 4A0058F | 3 | 86 (3.4) | 99 (3.9) | 38 (1.5) | 23 (0.9) | - | - | 99 (3.9) | 43 (1.7) | 25 (1.0) | - | 61 (2.4) | 28 (1.1) | 51 (2.0) |
| 4A0072F | | 89 (3.5) | 99 (3.9) | 41 (1.6) | 23 (0.9) | - | - | 99 (3.9) | 43 (1.7) | 25 (1.0) | - | 61 (2.4) | 28 (1.1) | 51 (2.0) |
| 4A0088F | 6 | 84 (3.3) | 104 (4.1) | 23 (0.9) | - | - | - | 99 (3.9) | 66 (2.6) | 25 (1.0) | - | 51 (2.0) | 61 (2.4) | 28 (1.1) |
| 4A0103F | | 84 (3.3) | 104 (4.1) | 23 (0.9) | - | - | - | 99 (3.9) | 66 (2.6) | 25 (1.0) | - | 51 (2.0) | 61 (2.4) | 28 (1.1) |

| Drive Model | Figure | Dimensions mm (in) | | | | | | | | | | Diameter mm (in) | | |
|--------------------|--------|--------------------|--------------|--------------|-------------|-------------|-------------|--------------|--------------|-------------|-------------|------------------|-------------|-------------|
| | | W | D | W1 | W2 | W3 | W4 | D1 | D2 | D3 | D4 | d5 | d6 | d7 |
| 4A0139F | 7 | 111 (4.4) | 109 (4.3) | 56 (2.2) | 15 (0.6) | 30 (1.2) | 66 (2.6) | 119 (4.7) | 109 (4.3) | 53 (2.1) | 41 (1.6) | 51 (2.0) | 36 (1.4) | 61 (2.4) |
| 4A0165F | | 111 (4.4) | 109 (4.3) | 56 (2.2) | 15 (0.6) | 30 (1.2) | 66 (2.6) | 119 (4.7) | 109 (4.3) | 53 (2.1) | 41 (1.6) | 51 (2.0) | 36 (1.4) | 61 (2.4) |
| 4A0208A | 8 | 175 (6.9) | 130 (5.1) | 91 (3.6) | 84 (3.3) | 25 (1.0) | - | 137 (5.4) | 51 (2.0) | 41 (1.6) | - | 51 (2.0) | 61 (2.4) | 36 (1.4) |
| 4A0250A | 9 | 191 (7.5) | 130 (5.1) | 104 (4.1) | 30 (1.2) | 28 (1.1) | 71 (2.8) | 157 (6.2) | 71 (2.8) | 51 (2.0) | - | 51 (2.0) | 61 (2.4) | 43 (1.7) |
| 4A0296A | | 191 (7.5) | 130 (5.1) | 104 (4.1) | 30 (1.2) | 28 (1.1) | 71 (2.8) | 157 (6.2) | 71 (2.8) | 51 (2.0) | - | 51 (2.0) | 61 (2.4) | 43 (1.7) |
| 4A0362A | | 191 (7.5) | 130 (5.1) | 104 (4.1) | 30 (1.2) | 28 (1.1) | 71 (2.8) | 157 (6.2) | 71 (2.8) | 51 (2.0) | - | 51 (2.0) | 61 (2.4) | 43 (1.7) |
| 600 V Class | | | | | | | | | | | | | | |
| 5A0003F | 1 | 43 (1.7) | 38 (1.5) | 38 (1.5) | - | - | - | 41 (1.6) | 71 (2.8) | 79 (3.1) | - | 23 (0.9) | 36 (1.4) | - |
| 5A0004F | | 43 (1.7) | 38 (1.5) | 38 (1.5) | - | - | - | 41 (1.6) | 71 (2.8) | 79 (3.1) | - | 23 (0.9) | 36 (1.4) | - |
| 5A0006F | | 43 (1.7) | 56 (2.2) | 38 (1.5) | - | - | - | 41 (1.6) | 71 (2.8) | 79 (3.1) | - | 23 (0.9) | 36 (1.4) | - |
| 5A0009F | | 43 (1.7) | 56 (2.2) | 38 (1.5) | - | - | - | 41 (1.6) | 71 (2.8) | 79 (3.1) | - | 23 (0.9) | 36 (1.4) | - |
| 5A0011F | | 43 (1.7) | 56 (2.2) | 38 (1.5) | - | - | - | 41 (1.6) | 71 (2.8) | 79 (3.1) | - | 23 (0.9) | 36 (1.4) | - |
| 5A0017F | 2 | 25 (1.0) | 76 (3.0) | 56 (2.2) | - | - | - | 48 (1.9) | 84 (3.3) | 53 (2.1) | - | 36 (1.4) | 23 (0.9) | 43 (1.7) |
| 5A0022F | | 25 (1.0) | 76 (3.0) | 56 (2.2) | - | - | - | 48 (1.9) | 84 (3.3) | 53 (2.1) | - | 36 (1.4) | 23 (0.9) | 43 (1.7) |
| 5A0027F | | 28 (1.1) | 79 (3.1) | 64 (2.5) | - | - | - | 51 (2.0) | 86 (3.4) | 56 (2.2) | - | 36 (1.4) | 23 (0.9) | 43 (1.7) |
| 5A0032F | | 28 (1.1) | 79 (3.1) | 64 (2.5) | - | - | - | 51 (2.0) | 86 (3.4) | 56 (2.2) | - | 36 (1.4) | 23 (0.9) | 43 (1.7) |
| 5A0041F | 3 | 89 (3.5) | 99 (3.9) | 41 (1.6) | 23 (0.9) | - | - | 99 (3.9) | 43 (1.7) | 25 (1.0) | - | 61 (2.4) | 28 (1.1) | 51 (2.0) |
| 5A0052F | | 89 (3.5) | 99 (3.9) | 41 (1.6) | 23 (0.9) | - | - | 99 (3.9) | 43 (1.7) | 25 (1.0) | - | 61 (2.4) | 28 (1.1) | 51 (2.0) |
| 5A0062F | 7 | 111 (4.4) | 109 (4.3) | 56 (2.2) | 15 (0.6) | 30 (1.2) | 66 (2.6) | 119 (4.7) | 109 (4.3) | 53 (2.1) | 41 (1.6) | 51 (2.0) | 36 (1.4) | 61 (2.4) |
| 5A0077F | | 111 (4.4) | 109 (4.3) | 56 (2.2) | 15 (0.6) | 30 (1.2) | 66 (2.6) | 119 (4.7) | 109 (4.3) | 53 (2.1) | 41 (1.6) | 51 (2.0) | 36 (1.4) | 61 (2.4) |
| 5A0099F | | 111 (4.4) | 109 (4.3) | 56 (2.2) | 15 (0.6) | 30 (1.2) | 66 (2.6) | 119 (4.7) | 109 (4.3) | 53 (2.1) | 41 (1.6) | 51 (2.0) | 36 (1.4) | 61 (2.4) |
| 5A0125A | 8 | 175 (6.9) | 130 (5.1) | 91 (3.6) | 84 (3.3) | 25 (1.0) | - | 137 (5.4) | 51 (2.0) | 41 (1.6) | - | 51 (2.0) | 61 (2.4) | 36 (1.4) |
| 5A0145A | | 175 (6.9) | 130 (5.1) | 91 (3.6) | 84 (3.3) | 25 (1.0) | - | 137 (5.4) | 51 (2.0) | 41 (1.6) | - | 51 (2.0) | 61 (2.4) | 36 (1.4) |
| 5A0192A | 9 | 191 (7.5) | 130 (5.1) | 104 (4.1) | 30 (1.2) | 28 (1.1) | 71 (2.8) | 157 (6.2) | 71 (2.8) | 51 (2.0) | - | 51 (2.0) | 61 (2.4) | 43 (1.7) |
| 5A0242A | | 191 (7.5) | 130 (5.1) | 104 (4.1) | 30 (1.2) | 28 (1.1) | 71 (2.8) | 157 (6.2) | 71 (2.8) | 51 (2.0) | - | 51 (2.0) | 61 (2.4) | 43 (1.7) |

Note: Removing the top protective cover or bottom conduit bracket from an IP20/NEMA 1, UL Type 1 enclosure drive voids NEMA 1, UL Type 1 protection while maintaining IP20 conformity.

2.2 Mechanical Installation

■ IP00/Open Type Enclosure Drives

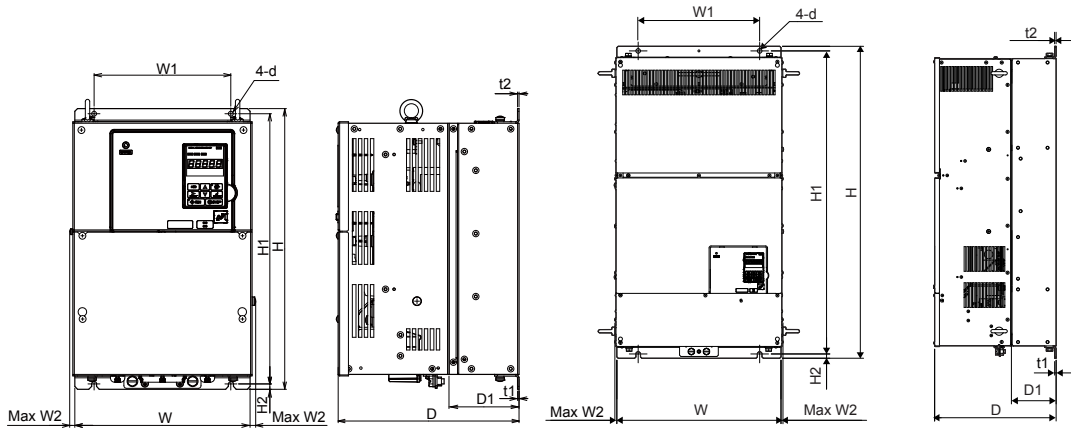


Figure 1

Figure 2

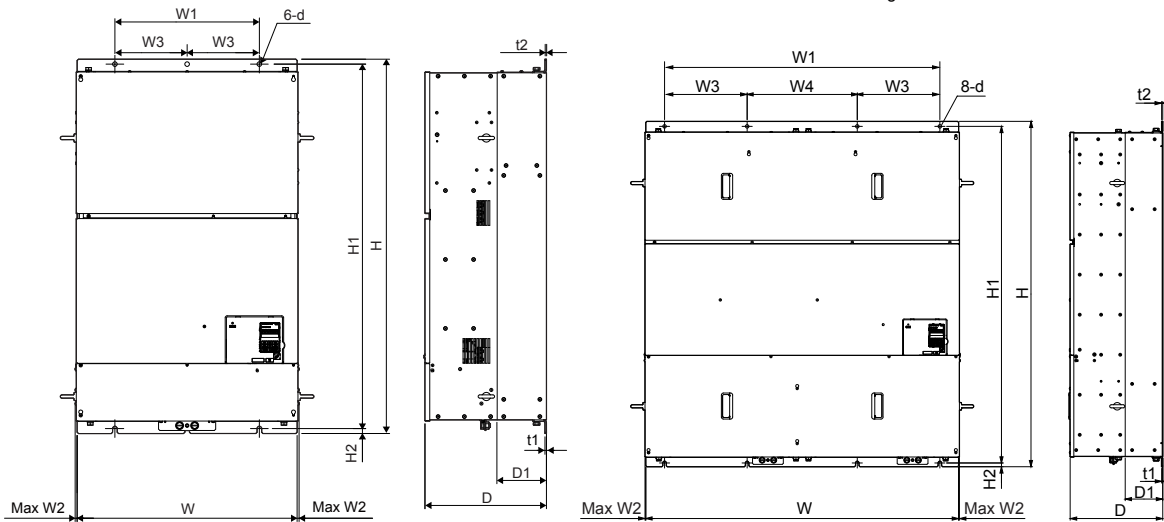


Figure 3

Figure 4

Table 2.9 Dimensions for IP00/Open Type Enclosure: 200 V Class

| Drive Model | Figure | Dimensions mm (in) | | | | | | | | | | | Wt. kg (lb) |
|----------------|--------|--------------------|----------------|----------------|----------------|--------------|----------------|--------------|---------------|---------------|---------------|-----|---------------|
| | | W | H | D | W1 | W2 | H1 | H2 | D1 | t1 | t2 | d | |
| 2A0250A <1> | 1 | 450 (17.72) | 705 (27.76) | 330 (12.99) | 325 (12.80) | 10 (0.39) | 680 (26.77) | 12 (0.49) | 130 (5.12) | 3.3 (0.13) | 3.3 (0.13) | M10 | 76 (167.6) |
| 2A0312A <1> | | 450 (17.72) | 705 (27.76) | 330 (12.99) | 325 (12.80) | 10 (0.39) | 680 (26.77) | 12 (0.49) | 130 (5.12) | 3.3 (0.13) | 3.3 (0.13) | M10 | 80 (176.4) |
| 2A0360A <1> | | 500 (19.69) | 800 (31.50) | 350 (13.78) | 370 (14.57) | 10 (0.39) | 773 (30.43) | 13 (0.51) | 130 (5.12) | 4.6 (0.18) | 4.6 (0.18) | M12 | 98 (216.1) |
| 2A0415A | | 500 (19.69) | 800 (31.50) | 350 (13.78) | 370 (14.57) | 10 (0.39) | 773 (30.43) | 13 (0.51) | 130 (5.12) | 4.6 (0.18) | 4.6 (0.18) | M12 | 99 (218.3) |

<1> Customers may convert these models to IP20/NEMA 1, UL Type 1 enclosures using an IP20/NEMA 1, UL Type 1 Kit.

Table 2.10 Dimensions for IP00/Open Type Enclosure: 400 V Class

| Drive Model | Figure | Dimensions mm (in) | | | | | | | | | | | | | Wt. kg (lb) |
|----------------|--------|--------------------|-----------------|----------------|-----------------|---------------|----------------|----------------|-----------------|----------------|---------------|---------------|---------------|-----|-----------------|
| | | W | H | D | W1 | W2 | W3 | W4 | H1 | H2 | D1 | t1 | t2 | d | |
| 4A0208A </> | 1 | 450 (17.72) | 705 (27.76) | 330 (12.99) | 325 (12.80) | 10 (0.39) | - | - | 680 (26.77) | 12.4 (0.49) | 130 (5.12) | 3.3 (0.13) | 3.3 (0.13) | M10 | 79 (174.2) |
| 4A0250A </> | | 500 (19.69) | 800 (31.50) | 350 (13.78) | 370 (14.57) | 10 (0.39) | - | - | 773 (30.43) | 13 (0.51) | 130 (5.12) | 4.6 (0.18) | 4.6 (0.18) | M12 | 96 (211.6) |
| 4A0296A </> | | 500 (19.69) | 800 (31.50) | 350 (13.78) | 370 (14.57) | 10 (0.39) | - | - | 773 (30.43) | 13 (0.51) | 130 (5.12) | 4.6 (0.18) | 4.6 (0.18) | M12 | 102 (224.9) |
| 4A0362A </> | | 500 (19.69) | 800 (31.50) | 350 (13.78) | 370 (14.57) | 10 (0.39) | - | - | 773 (30.43) | 13 (0.51) | 130 (5.12) | 4.6 (0.18) | 4.6 (0.18) | M12 | 107 (235.9) |
| 4A0414A | 2 | 500 (19.69) | 950 (37.40) | 370 (14.57) | 370 (14.57) | 7.9 (0.31) | - | - | 923 (36.34) | 13 (0.51) | 135 (5.31) | 4.6 (0.18) | 4.6 (0.18) | M12 | 125 (275.6) |
| 4A0515A | 3 | 670 (26.38) | 1140 (44.88) | 370 (14.57) | 440 (17.32) | 6 (0.24) | 220 (8.66) | - | 1110 (43.70) | 15 (0.59) | 150 (5.91) | 4.6 (0.18) | 4.6 (0.18) | M12 | 216 (476.2) |
| 4A0675A | | 670 (26.38) | 1140 (44.88) | 370 (14.57) | 440 (17.32) | 6 (0.24) | 220 (8.66) | - | 1110 (43.70) | 15 (0.59) | 150 (5.91) | 4.6 (0.18) | 4.6 (0.18) | M12 | 221 (487.2) |
| 4A0930A | 4 | 1250 (49.21) | 1380 (54.33) | 370 (14.57) | 1110 (43.70) | 6 (0.24) | 330 (13.00) | 440 (17.32) | 1345 (52.95) | 15 (0.59) | 150 (5.91) | 4.6 (0.18) | 4.6 (0.18) | M12 | 545 (1201.5) |
| 4A1200A | 4 | 1250 (49.21) | 1380 (54.33) | 370 (14.57) | 1110 (43.70) | 6 (0.24) | 330 (13.00) | 440 (17.32) | 1345 (52.95) | 15 (0.59) | 150 (5.91) | 4.6 (0.18) | 4.6 (0.18) | M12 | 555 (1223.6) |

<1> Customers may convert these models to IP20/NEMA 1, UL Type 1 enclosures using an IP20/NEMA 1, UL Type 1 Kit.

Table 2.11 Dimensions for IP00/Open Type Enclosure: 600 V Class

| Drive Model | Figure | Dimensions mm (in) | | | | | | | | | | | | | Wt. kg (lb) |
|----------------|--------|--------------------|----------------|----------------|----------------|--------------|----|----|----------------|----------------|---------------|---------------|---------------|-----|----------------|
| | | W | H | D | W1 | W2 | W3 | W4 | H1 | H2 | D1 | t1 | t2 | d | |
| 5A0125A </> | 1 | 450 (17.72) | 705 (27.76) | 330 (12.99) | 325 (12.80) | 10 (0.39) | - | - | 680 (26.77) | 12.4 (0.49) | 130 (5.12) | 3.3 (0.13) | 3.3 (0.13) | M10 | 79 (174.2) |
| 5A0145A </> | | 450 (17.72) | 705 (27.76) | 330 (12.99) | 325 (12.80) | 10 (0.39) | - | - | 680 (26.77) | 12.4 (0.49) | 130 (5.12) | 3.3 (0.13) | 3.3 (0.13) | M10 | 79 (174.2) |
| 5A0192A </> | | 500 (19.69) | 800 (31.50) | 350 (13.78) | 370 (14.57) | 10 (0.39) | - | - | 773 (30.43) | 13 (0.51) | 130 (5.12) | 4.6 (0.18) | 4.6 (0.18) | M12 | 107 (235.9) |
| 5A0242A </> | | 500 (19.69) | 800 (31.50) | 350 (13.78) | 370 (14.57) | 10 (0.39) | - | - | 773 (30.43) | 13 (0.51) | 130 (5.12) | 4.6 (0.18) | 4.6 (0.18) | M12 | 107 (235.9) |

<1> Customers may convert these models to IP20/NEMA 1, UL Type 1 enclosures using an IP20/NEMA 1, UL Type 1 Kit.

2.2 Mechanical Installation

IP20/NEMA 1, UL Type 1 Kit Selection

Customers may convert IP00/Open Type models to IP20/NEMA 1, UL Type 1 enclosures. Refer to [Table 2.12](#) to select the appropriate IP20/NEMA 1, UL Type 1 Kit when performing the conversion.

Contact a Yaskawa representative for IP20/NEMA 1, UL Type 1 Kit availability for IP00/Open Type models not listed.

Table 2.12 IP20/NEMA 1, UL Type 1 Kit Selection

| IP00/Open Type Drive Model | IP20/NEMA 1, UL Type 1 Kit Code | Comments |
|----------------------------|---------------------------------|--|
| 2A0250A | 100-054-503 | <i>Refer to IP20/NEMA 1, UL Type 1 Enclosure Drives on page 56 for drive dimensions with the IP20/NEMA 1, UL Type 1 Kit installed.</i> |
| 2A0312A | | |
| 2A0360A | | |
| 4A0208A | | |
| 4A0250A | 100-054-504 | |
| 4A0296A | | |
| 4A0362A | | |
| 5A0125A | 100-054-503 | |
| 5A0145A | | |
| 5A0192A | 100-054-504 | |
| 5A0242A | | |

Electrical Installation

This chapter explains proper procedures for wiring the control circuit terminals, motor, and power supply.

| | | |
|-------------|--|------------|
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3.1 Section Safety

DANGER

Electrical Shock Hazard

Before servicing, disconnect all power to the equipment. The internal capacitor remains charged even after the power supply is turned off. The charge indicator LED will extinguish when the DC bus voltage is below 50 Vdc. To prevent electric shock, wait for at least the time specified on the warning label, once all indicators are OFF, measure for unsafe voltages to confirm the drive is safe prior to servicing.

Failure to comply will result in death or serious injury.

WARNING

Electrical Shock Hazard

Do not operate equipment with covers removed.

Failure to comply could result in death or serious injury.

The diagrams in this section may show drives without covers or safety shields to show details. Be sure to reinstall covers or shields before operating the drives and run the drives according to the instructions described in this manual.

Make sure the protective earthing conductor complies with technical standards and local safety regulations.

Because the leakage current exceeds 3.5 mA in models 4A0414 and larger, IEC/EN 61800-5-1 states that either the power supply must be automatically disconnected in case of discontinuity of the protective earthing conductor or a protective earthing conductor with a cross-section of at least 10 mm² (Cu) or 16 mm² (Al) must be used. Failure to comply may result in death or serious injury.

Always use appropriate equipment for Ground Fault Circuit Interrupters (GFCIs).

The drive can cause a residual current with a DC component in the protective earthing conductor. Where a residual current operated protective or monitoring device is used for protection in case of direct or indirect contact, always use a type B GFCI according to IEC/EN 60755.

Always ground the motor-side grounding terminal.

Improper equipment grounding could result in death or serious injury by contacting the motor case.

Do not perform work on the drive while wearing loose clothing, jewelry or without eye protection.

Failure to comply could result in death or serious injury.

Remove all metal objects such as watches and rings, secure loose clothing, and wear eye protection before beginning work on the drive.

Do not remove covers or touch circuit boards while the power is on.

Failure to comply could result in death or serious injury.

Do not allow unqualified personnel to perform work on the drive.

Failure to comply could result in death or serious injury.

Installation, maintenance, inspection, and servicing must be performed only by authorized personnel familiar with installation, adjustment, and maintenance of AC drives.

Do not touch any terminals before the capacitors have fully discharged.

Failure to comply could result in death or serious injury.

Before wiring terminals, disconnect all power to the equipment. The internal capacitor remains charged even after the power supply is turned off. After shutting off the power, wait for at least the amount of time specified on the drive before touching any components.

⚠ WARNING**Fire Hazard****Tighten all terminal screws to the specified tightening torque.**

Loose electrical connections could result in death or serious injury by fire due to overheating of electrical connections.

Do not use improper combustible materials.

Failure to comply could result in death or serious injury by fire.

Do not install the drive to a combustible surface. Never place combustible materials on the drive.

Do not use an improper voltage source.

Failure to comply could result in death or serious injury by fire.

Verify that the rated voltage of the drive matches the voltage of the incoming power supply before applying power.

When installing dynamic braking options, perform all wiring exactly as specified in the wiring diagrams provided.

Failure to do so can result in fire. Improper wiring may damage braking components.

⚠ CAUTION**Do not carry the drive by the front cover or the terminal cover.**

Failure to comply may cause the main body of the drive to fall, resulting in minor or moderate injury.

NOTICE**Observe proper electrostatic discharge procedures (ESD) when handling the drive and circuit boards.**

Failure to comply may result in ESD damage to the drive circuitry.

Never connect or disconnect the motor from the drive while the drive is outputting voltage.

Improper equipment sequencing could result in damage to the drive.

Do not use unshielded cable for control wiring.

Failure to comply may cause electrical interference resulting in poor system performance. Use shielded, twisted-pair wires and ground the shield to the ground terminal of the drive.

Do not allow unqualified personnel to use the product.

Failure to comply could result in damage to the drive or braking circuit.

Carefully review instruction manual TOBPC72060000 or TOBPC72060001 when connecting a dynamic braking option to the drive.

Do not modify the drive circuitry.

Failure to comply could result in damage to the drive and will void warranty.

Yaskawa is not responsible for any modification of the product made by the user. This product must not be modified.

Check all the wiring to ensure that all connections are correct after installing the drive and connecting any other devices.

Failure to comply could result in damage to the drive.

3.2 Standard Connection Diagram

Connect the drive and peripheral devices as shown in [Figure 3.1](#). It is possible to set and run the drive via the digital operator without connecting digital I/O wiring. This section does not discuss drive operation; [Refer to Start-Up Programming & Operation on page 107](#) for instructions on operating the drive.

NOTICE: *Inadequate wiring could result in damage to the drive. Install adequate branch circuit short circuit protection per applicable codes. The drive is suitable for circuits capable of delivering not more than 100,000 RMS symmetrical amperes, 240 Vac maximum (200 V class), 480 Vac maximum (400 V class), 600 Vac maximum (600 V class).*

NOTICE: *When the input voltage is 440 V or higher or the wiring distance is greater than 100 meters, pay special attention to the motor insulation voltage or use a drive duty motor. Failure to comply could lead to motor insulation breakdown.*

NOTICE: *Do not connect AC control circuit ground to drive enclosure. Improper drive grounding can cause control circuit malfunction.*

Note: The minimum load for the relay outputs M1-M2, M3-M4, MA-MB-MC, and MD-ME-MF is 10 mA.

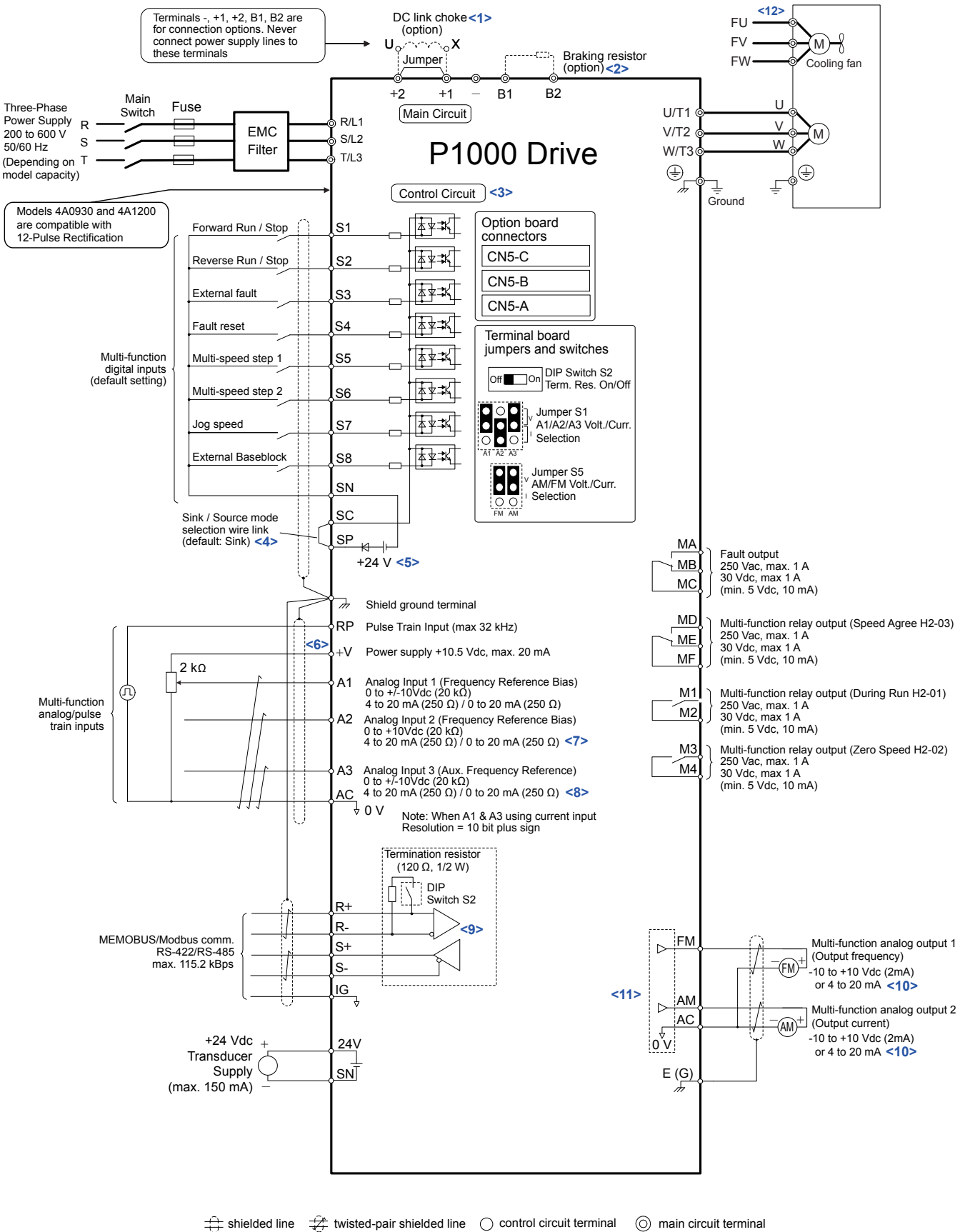


Figure 3.1 Drive Standard Connection Diagram (example: model 2A0040)

<1> Remove the jumper when installing a DC link choke. Models 2A0110 to 2A0415 and 4A0058 to 4A1200 come with a built-in DC link choke.

3.2 Standard Connection Diagram

- <2> Set L8-55 to 0 to disable the protection function of the built-in braking transistor of the drive when using an optional regenerative converter or dynamic braking option. Leaving L8-55 enabled may cause a braking resistor fault (rF). Additionally, disable Stall Prevention (L3-04 = 0) when using an optional regenerative converter, regenerative or braking units, or dynamic braking option. Leaving L3-04 enabled may prevent the drive from stopping within the specified deceleration time.
- <3> Supplying power to the control circuit separately from the main circuit requires 24 V power supply (option).
- <4> This figure illustrates an example of a sequence input to S1 through S8 using a non-powered relay or an NPN transistor. Install the wire link between terminals SC-SP for Sink mode, between SC-SN for Source mode, or leave the link out for external power supply. Never short terminals SP and SN, as it will damage the drive.
- <5> This voltage source supplies a maximum current of 150 mA.
- <6> The maximum output current capacity for the +V terminal on the control circuit is 20 mA. Never short terminals +V and AC, as it can cause erroneous operation or damage the drive.
- <7> Set jumper S1 to select between a voltage or current input signal to terminal A2. The default setting is for current input.
- <8> Set jumper S1 to select between a voltage or current input signal to terminal A1 and A3. The default setting is for voltage input.
- <9> Set DIP switch S2 to the ON position to enable the termination resistor in the last drive in a MEMOBUS/Modbus network.
- <10> Monitor outputs work with devices such as analog frequency meters, ammeters, voltmeters, and wattmeters. They are not intended for use as a feedback-type signal.
- <11> Use jumper S5 to select between voltage or current output signals at terminals AM and FM. Set parameters H4-07 and H4-08 accordingly.
- <12> Self-cooling motors do not require the same wiring necessary for motors with cooling fans.

WARNING! Sudden Movement Hazard. Do not close the wiring for the control circuit unless the multifunction input terminal parameters are properly set. Improper sequencing of run/stop circuitry could result in death or serious injury from moving equipment.

WARNING! Sudden Movement Hazard. Ensure start/stop and safety circuits are wired properly and in the correct state before energizing the drive. Failure to comply could result in death or serious injury from moving equipment. When programmed for 3-Wire control, a momentary closure on terminal S1 may cause the drive to start.

WARNING! Sudden Movement Hazard. When using a 3-Wire sequence, set the drive to 3-Wire sequence prior to wiring the control terminals and set parameter b1-17 to 0 so the drive will not accept a Run command at power up (default). If the drive is wired for a 3-Wire sequence but set up for a 2-Wire sequence (default), and parameter b1-17 is set to 1 so the drive accepts a Run command at power up, the motor will rotate in reverse direction at drive power up and may cause injury.

WARNING! Sudden Movement Hazard. Confirm the drive I/O signals and external sequence before executing the application preset function. Executing the application preset function or setting A1-03 ≠ 0 will change the drive I/O terminal functions and may cause unexpected equipment operation. Failure to comply may cause death or serious injury.

NOTICE: When using the automatic fault restart function with wiring designed to shut off the power supply upon drive fault, make sure the drive does not trigger a fault output during fault restart (L5-02 = 0, default). Failure to comply will prevent the automatic fault restart function from working properly.

3.3 Main Circuit Connection Diagram

Refer to diagrams in this section when wiring the main circuit of the drive. Connections may vary based on drive capacity. The DC power supply for the main circuit also provides power to the control circuit.

NOTICE: Do not use the negative DC bus terminal “-” as a ground terminal. This terminal is at high DC voltage potential. Improper wiring connections could damage the drive.

NOTICE: Route motor leads U/T1, V/T2 and W/T3 separate from all other leads to reduce possible interference and noise related issues. Failure to comply may result in abnormal operation of drive and nearby equipment.

◆ Three-Phase 200 V Class Models 2A0004 to 2A0081 Three-Phase 400 V Class Models 4A0002 to 4A0044 Three-Phase 600 V Class Models 5A0003 to 5A0032

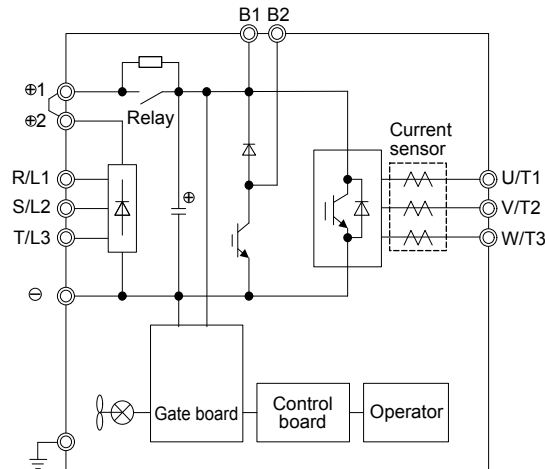


Figure 3.2 Connecting Main Circuit Terminals

◆ Three-Phase 200 V Class Models 2A0110, 2A0138 Three-Phase 400 V Class Models 4A0058, 4A0072 Three-Phase 600 V Class Models 5A0041, 5A0052

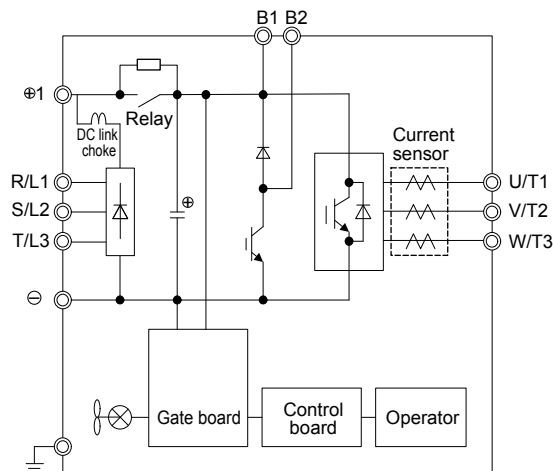


Figure 3.3 Connecting Main Circuit Terminals

3.3 Main Circuit Connection Diagram

- ◆ **Three-Phase 200 V Class Models 2A0169 to 2A0211**
- Three-Phase 400 V Class Models 4A0088 to 4A0139**
- Three-Phase 600 V Class Models 5A0062 to 5A0099**

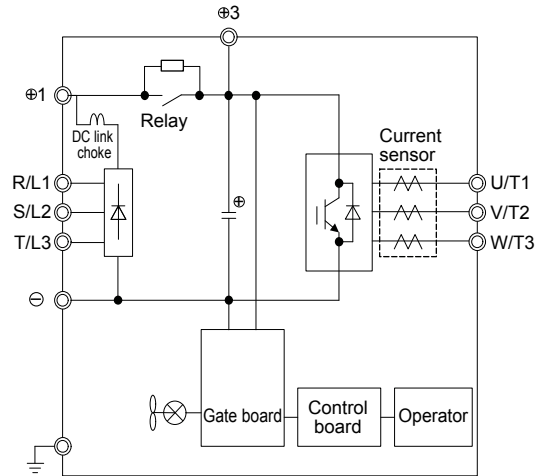


Figure 3.4 Connecting Main Circuit Terminals

- ◆ **Three-Phase 200 V Class Models 2A0250 to 2A0415**
- Three-Phase 400 V Class Models 4A0165 to 4A0675**
- Three-Phase 600 V Class Models 5A0125 to 5A0242**

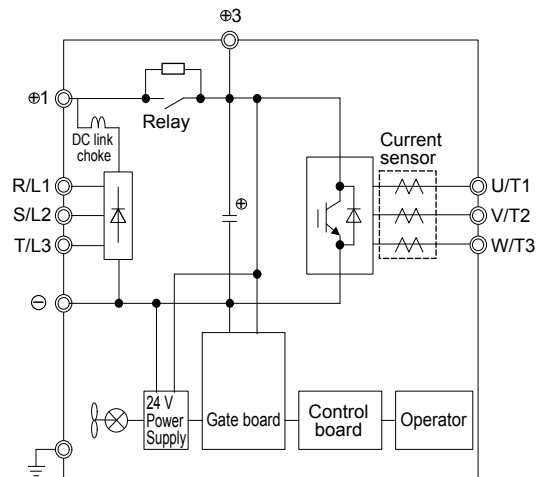


Figure 3.5 Connecting Main Circuit Terminals

◆ Three-Phase 400 V Class Models 4A0930, 4A1200

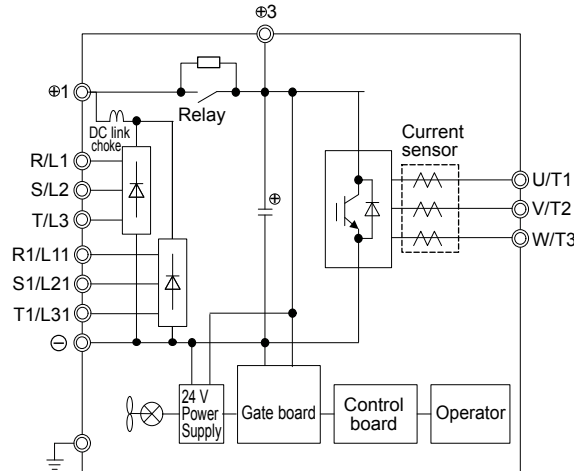


Figure 3.6 Connecting Main Circuit Terminals

Note: Models 4A0930 and 4A1200 are compatible for operation with 12-pulse rectification. *Refer to 12-Pulse Rectification on page 73* for details.

◆ 12-Pulse Rectification

■ Removing the Jumper

Models 4A0930 and 4A1200 are compatible for operation with 12-pulse rectification. Operation with 12-pulse rectification requires the user to separately prepare a 3-winding transformer for the power supply. Contact Yaskawa or your nearest sales representative for transformer specifications.

WARNING! Fire Hazard. Failure to remove jumpers shorting the power supply terminals on the main circuit when operating with 12-pulse rectification may cause death or serious injury by fire.

■ Application Notes

Models 4A0930 and 4A1200 are shipped from the factory with jumpers short-circuiting terminals R/L1-R1/L11, S/L2-S1/L21, and T/L3-T1/L31.

Remove M5 screws and jumpers as shown in *Figure 3.7* to operate with 12-pulse rectification.

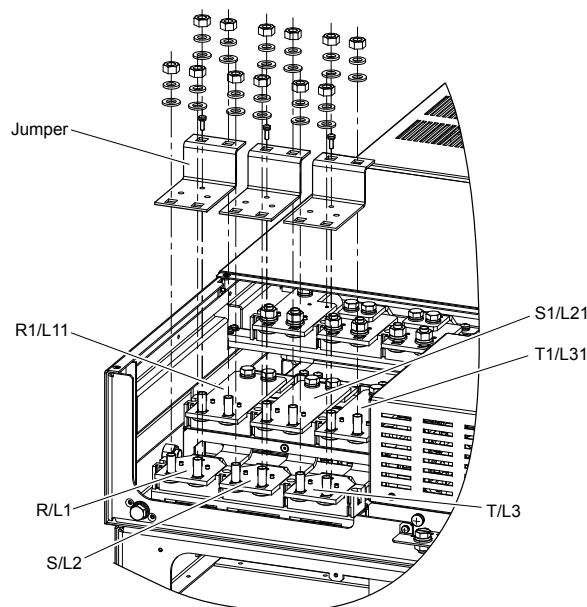


Figure 3.7 Removing the Jumper

3.3 Main Circuit Connection Diagram

■ Connection Diagram

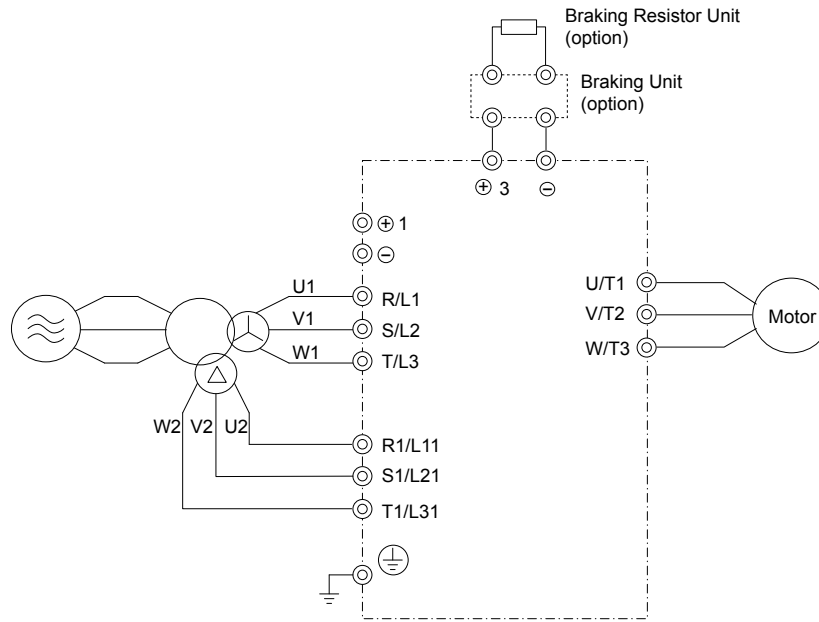


Figure 3.8 Connecting Main Circuit Terminals

3.4 Terminal Block Configuration

Figure 3.9 to Figure 3.12 show the different main circuit terminal arrangements for the drive capacities.

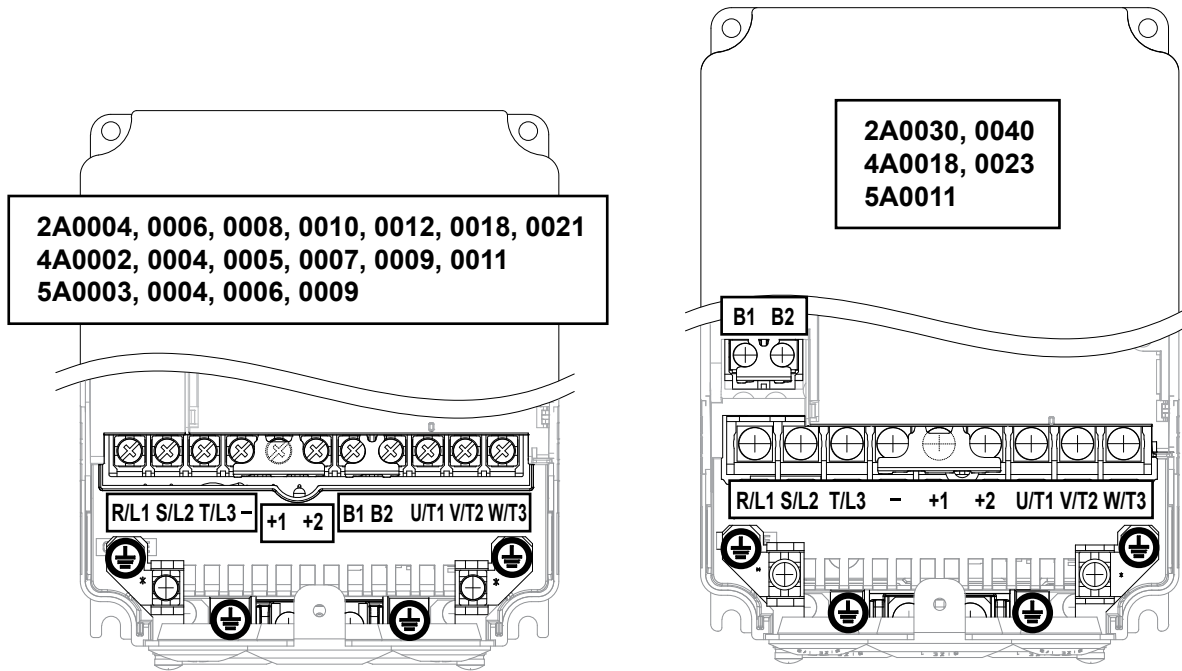


Figure 3.9 Main Circuit Terminal Block Configuration

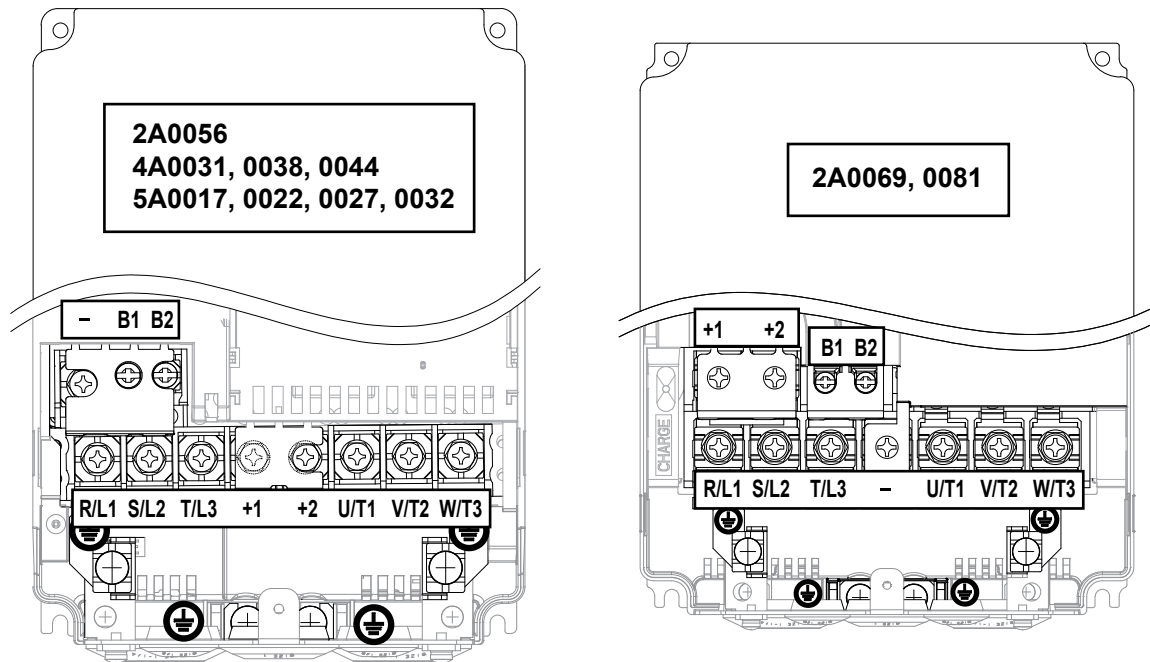


Figure 3.10 Main Circuit Terminal Block Configuration (continued)

3.4 Terminal Block Configuration

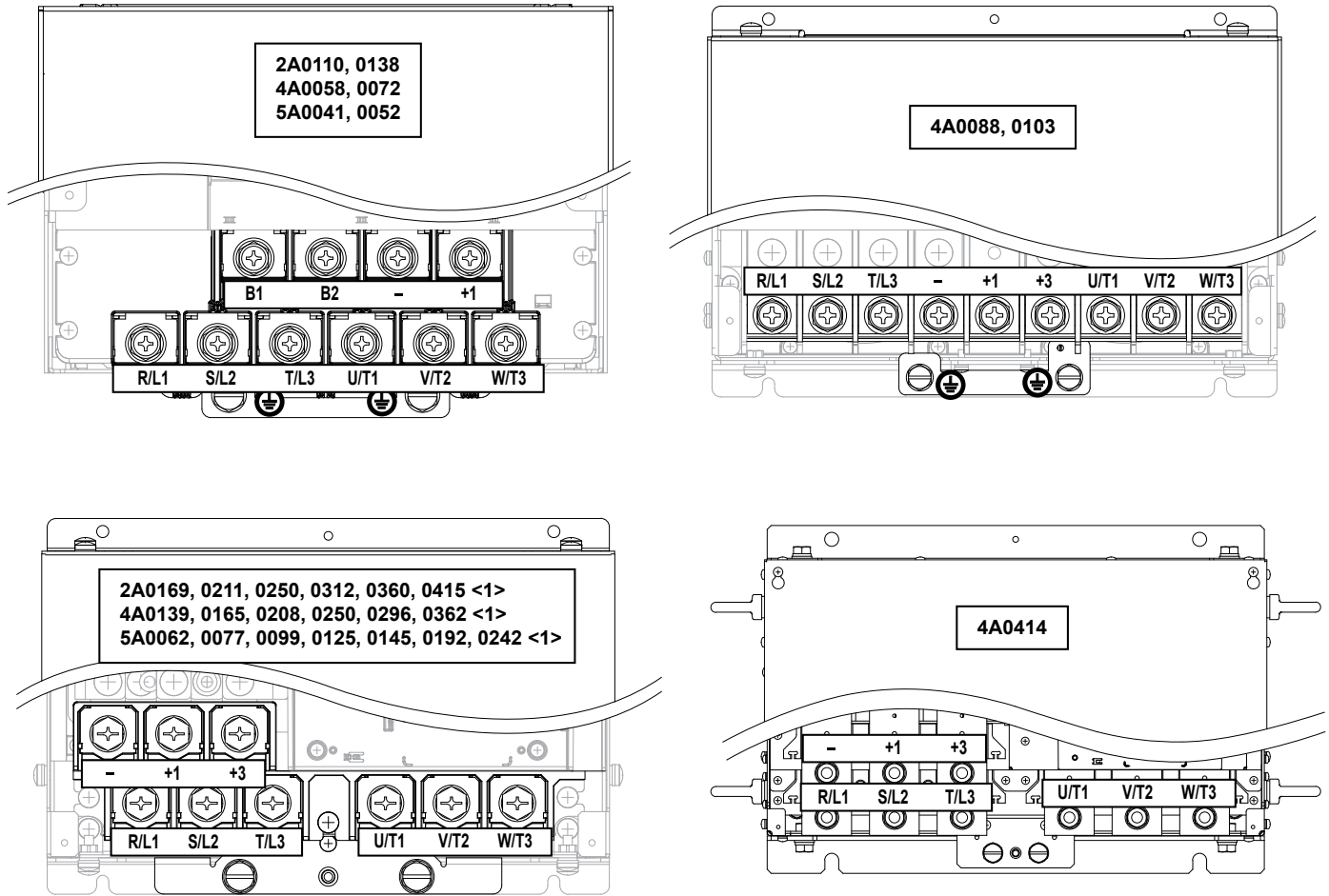


Figure 3.11 Main Circuit Terminal Block Configuration (continued)

<1> Terminal block design differs slightly for models 2A0250 to 2A0415, 4A0208 to 4A0362, and 5A0125 to 5A0242.

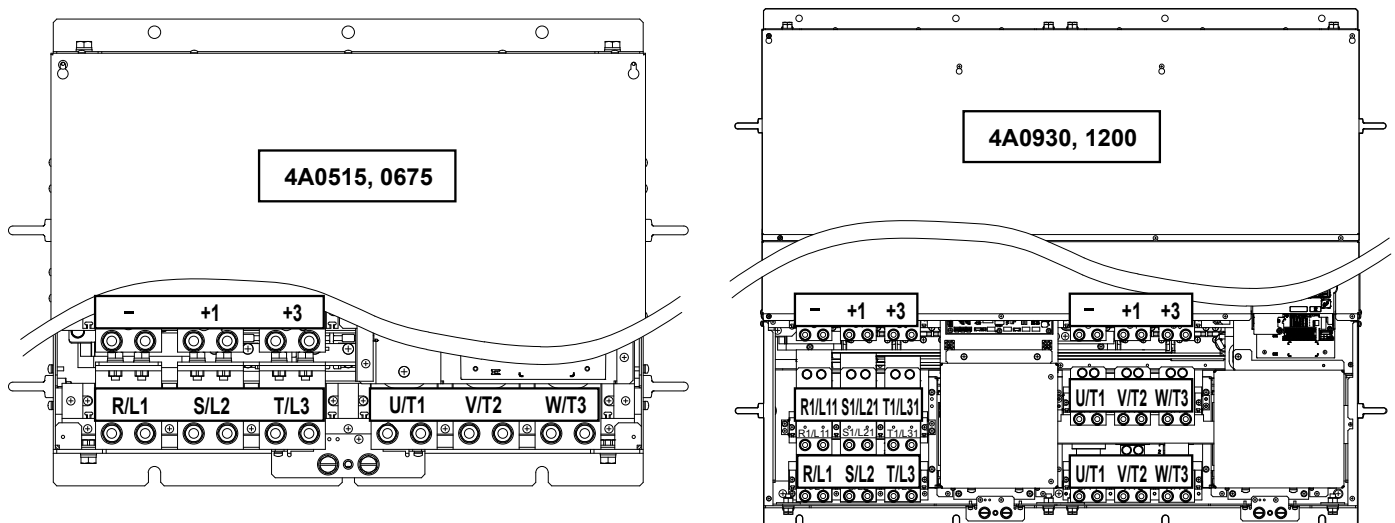


Figure 3.12 Main Circuit Terminal Block Configuration (continued)

3.5 Terminal Cover

Follow the procedure below to remove the terminal cover for wiring and to reattach the terminal cover after wiring is complete.

◆ Models 2A0004 to 2A0081, 4A0002 to 4A0044, 5A0003 to 5A0032 (IP20/NEMA 1, UL Type 1 Enclosure)

■ Removing the Terminal Cover

1. Loosen the terminal cover screw using a #2 Phillips screwdriver. Screw sizes vary by drive model.

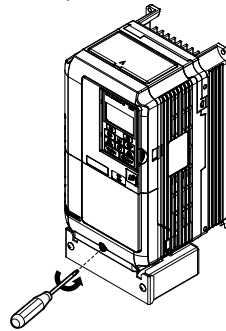


Figure 3.13 Removing the Terminal Cover on an IP20/NEMA 1, UL Type 1 Enclosure Drive

2. Push in on the tab located on the bottom of the terminal cover and gently pull forward to remove the terminal cover.

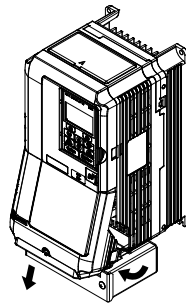


Figure 3.14 Removing the Terminal Cover on an IP20/NEMA 1, UL Type 1 Enclosure Drive

■ Reattaching the Terminal Cover

Power lines and signal wiring should pass through the opening provided. *Refer to [Wiring the Main Circuit Terminal on page 94](#) and [Wiring the Control Circuit Terminal on page 98](#) for details on wiring.*

Reattach the terminal cover after completing the wiring to the drive and other devices.

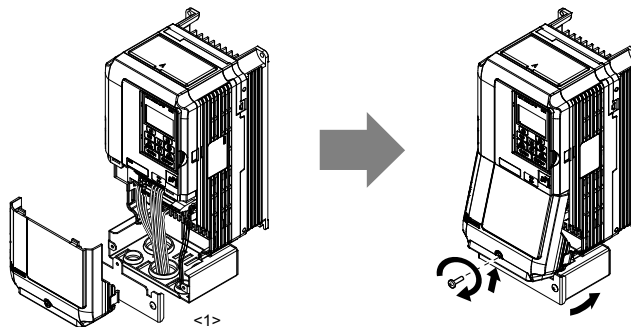


Figure 3.15 Reattaching the Terminal Cover on an IP20/NEMA 1, UL Type 1 Enclosure Drive

<1> Connect the ground wiring first, then the main circuit wiring, and finally the control circuit wiring.

◆ Models 2A0110 to 2A0250, 4A0208 to 4A0675, and 5A0125 to 5A0242 (IP00/Open Type Enclosure)

■ Removing the Terminal Cover

1. Loosen the screws on the terminal cover, then pull down on the cover.

Note: The terminal cover and the number of terminal cover screws differ depending on the drive model. [Refer to Component Names on page 36](#) for details.

CAUTION! Do not completely remove the cover screws, just loosen them. If the cover screws are removed completely, the terminal cover may fall off causing an injury.

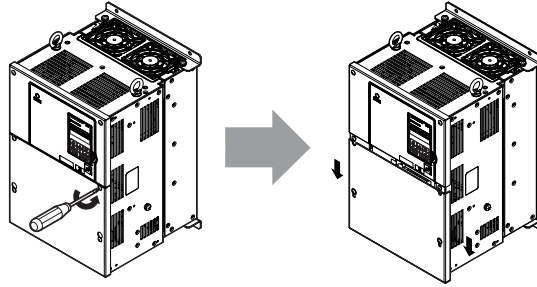


Figure 3.16 Removing the Terminal Cover on an IP00/Open Type Enclosure Drive

2. Pull forward on the terminal cover to free it from the drive.

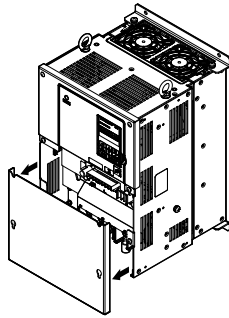


Figure 3.17 Removing the Terminal Cover on an IP00/Open Type Enclosure Drive

■ Reattaching the Terminal Cover

After wiring the terminal board and other devices, double-check connections and reattach the terminal cover. [Refer to Wiring the Main Circuit Terminal on page 94](#) and [Wiring the Control Circuit Terminal on page 98](#) for details on wiring.

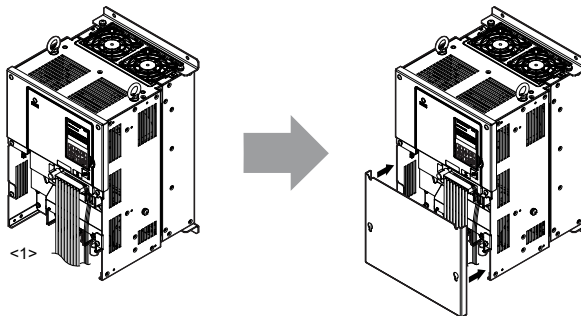


Figure 3.18 Reattaching the Terminal Cover on an IP00/Open Type Enclosure Drive

<1> Connect the ground wiring first, then the main circuit wiring, and finally the control circuit wiring.

3.6 Digital Operator and Front Cover

Detach the digital operator from the drive for remote operation or when opening the front cover to install an option card.

NOTICE: Be sure to remove the digital operator prior to opening or reattaching the front cover. Leaving the digital operator plugged into the drive when removing the front cover can result in erroneous operation caused by a poor connection. Firmly fasten the front cover back into place before reattaching the digital operator.

◆ Removing/Reattaching the Digital Operator

■ Removing the Digital Operator

While pressing on the tab located on the right side of the digital operator, pull the digital operator forward to remove it from the drive.

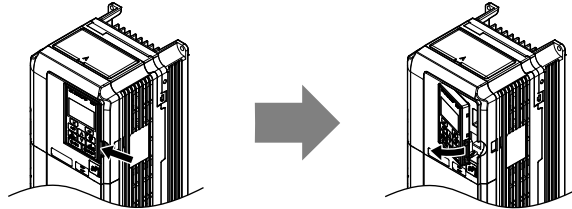


Figure 3.19 Removing the Digital Operator

■ Reattaching the Digital Operator

Insert the digital operator into the opening in the top cover while aligning it with the notches on the left side of the opening. Next, press gently on the right side of the operator until it clicks into place.

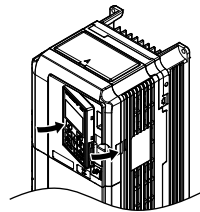


Figure 3.20 Reattaching the Digital Operator

◆ Removing/Reattaching the Front Cover

■ Removing the Front Cover

Models 2A0004 to 2A0081, 4A0002 to 4A0044, and 5A0003 to 5A0032

After removing the terminal cover and the digital operator, loosen the screw that affixes the front cover (models 2A0056, 4A0038, 5A0022, and 5A0027 do not use a screw to affix the front cover). Pinch in on the tabs found on each side of the front cover, then pull forward to remove it from the drive.

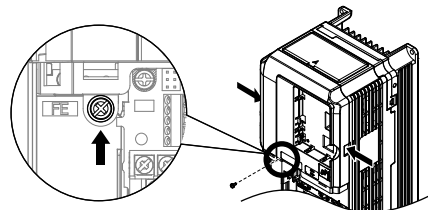


Figure 3.21 Remove the Front Cover (2A0004 to 2A0081, 4A0002 to 4A0044, and 5A0003 to 5A0032)

Models 2A0110 to 2A0415 and 4A0058 to 4A1200

1. Remove the terminal cover and the digital operator.
2. Loosen the installation screw on the front cover.
3. Use a straight-edge screwdriver to loosen the hooks on each side of the cover that hold it in place.

3.6 Digital Operator and Front Cover

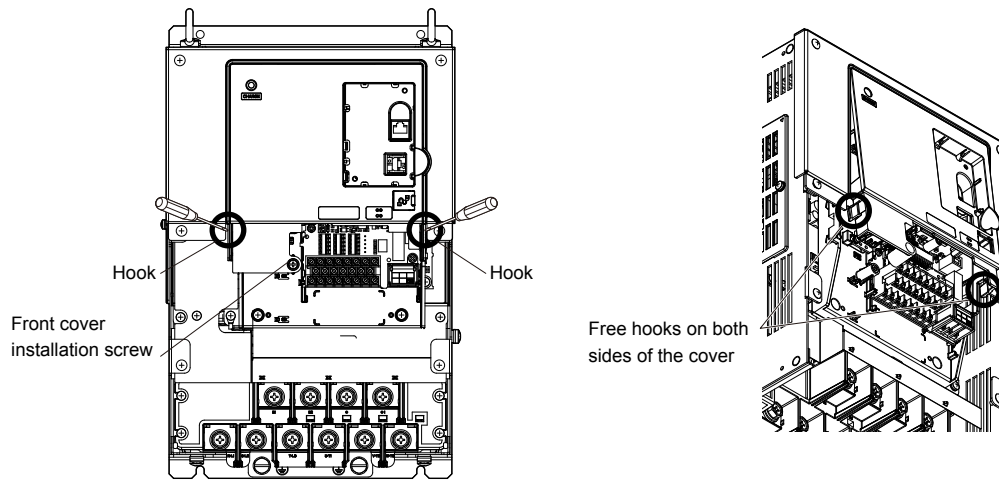


Figure 3.22 Remove the Front Cover (2A0010 to 2A0415 and 4A0058 to 4A1200)

4. Unhook the left side of the front cover then swing the left side towards you as shown in [Figure 3.23](#) until the cover comes off.

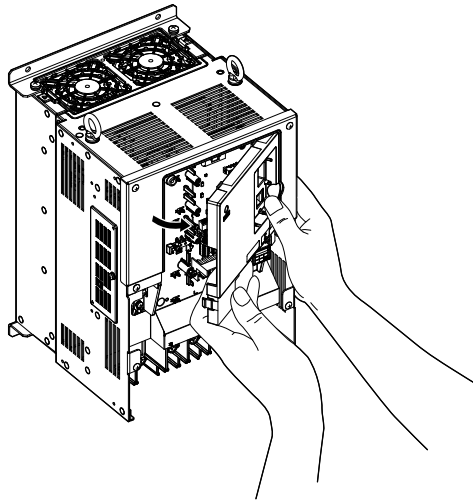


Figure 3.23 Remove the Front Cover (2A0010 to 2A0415 and 4A0058 to 4A1200)

■ Reattaching the Front Cover

Models 2A0004 to 2A0081, 4A0002 to 4A0044, and 5A0003 to 5A0032

Reverse the instructions given in *Remove the Front Cover (2A0004 to 2A0081, 4A0002 to 4A0044, and 5A0003 to 5A0032)* on page 79 to reattach the front cover. Pinch inwards on the hooks found on each side of the front cover while guiding it back into the drive. Make sure it clicks firmly into place.

Models 2A0110 to 2A0415 and 4A0058 to 4A1200

1. Slide the front cover so the hooks on the top connect to the drive.

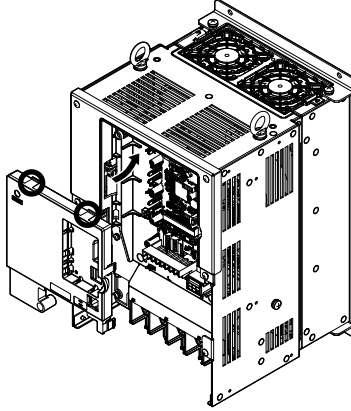


Figure 3.24 Reattach the Front Cover (2A0110 to 2A0415 and 4A0058 to 4A1200)

2. After connecting the hooks to the drive, press firmly on the cover to lock it into place.

3.7 Top Protective Cover

Drive models 2A0004 to 2A0081, 4A0002 to 4A0044, and 5A0003 to 5A0032 are designed to IP20/NEMA 1, UL Type 1 specifications with a protective cover on the top. Removing this top protective cover or the bottom conduit bracket from an IP20/NEMA 1, UL Type 1 enclosure drive voids the NEMA 1, UL Type 1 protection while maintaining IP20 conformity.

◆ Removing the Top Protective Cover

Insert the tip of a straight-edge screwdriver into the small opening located on the front edge of the top protective cover. Gently apply pressure as shown in the figure below to free the cover from the drive.

Note: Removing the top protective cover or the bottom conduit bracket from an IP20/NEMA 1, UL Type 1 enclosure drive voids the NEMA 1, UL Type 1 protection while maintaining IP20 conformity.

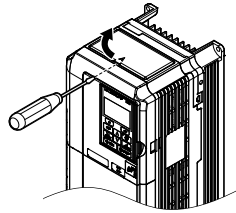


Figure 3.25 Removing the Top Protective Cover

◆ Reattaching the Top Protective Cover

Insert the two small protruding hooks on the rear side of the top protective cover into the provided mounting holes near the back of the drive, then press down on the front side of the top protective cover to fasten the cover into place.

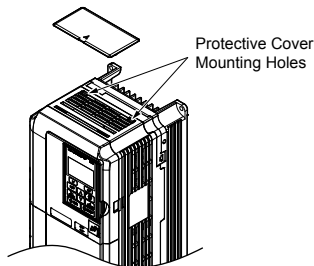


Figure 3.26 Reattaching the Protective Cover

3.8 Main Circuit Wiring

This section describes the functions, specifications, and procedures required to safely and properly wire the main circuit in the drive.

NOTICE: Do not solder the ends of wire connections to the drive. Soldered wiring connections can loosen over time. Improper wiring practices could result in drive malfunction due to loose terminal connections.

NOTICE: Do not switch the drive input to start or stop the motor. Frequently switching the drive on and off shortens the life of the DC bus charge circuit and the DC bus capacitors, and can cause premature drive failures. For the full performance life, refrain from switching the drive on and off more than once every 30 minutes.

Refer to [Input Fuse Installation on page 562](#) for details on fuse selection.

◆ Main Circuit Terminal Functions

Table 3.1 Main Circuit Terminal Functions

| Terminal | | Type | | | | Function | Page |
|-------------|--|-------------------------------|--|------------------|--|--|------|
| 200 V Class | Drive Model | 2A0004 to 2A0081 | 2A0110, 2A0138 | 2A0169 to 2A0415 | – | | |
| 400 V Class | | 4A0002 to 4A0044 | 4A0058, 4A0072 | 4A0088 to 4A0675 | 4A0930, 4A1200 | | |
| 600 V Class | | 5A0003 to 5A0032 | 5A0041, 5A0052 | 5A0062 to 5A0242 | – | | |
| R/L1 | Main circuit power supply input | | | | Connects line power to the drive | 69 | |
| S/L2 | | | | | | | |
| T/L3 | | | | | | | |
| R1-L11 | Not available | | | | Main circuit power supply input | 69 | |
| S1-L21 | | | | | | | |
| T1-L31 | | | | | Connects line power to the drive Remove the shorting bars connecting R/L1-R1/L11, S/L2-S1/L21, T/L3-T1/L31 when using 12-pulse rectification. | | |
| U/T1 | Drive output | | | | Connects to the motor | 69 | |
| V/T2 | | | | | | | |
| W/T3 | | | | | | | |
| B1 | Braking resistor | | Not available | | Available for connecting a braking resistor or a braking resistor unit option | 382 | |
| B2 | | | | | | | |
| ⊕2 | <ul style="list-style-type: none"> DC link choke connection (⊕1, ⊕2) (remove the shorting bar between ⊕1 and ⊕2) DC power supply input (⊕1, ⊖) | Not available | | | | For connecting: <ul style="list-style-type: none"> the drive to a DC power supply dynamic braking options a DC link choke | 386 |
| ⊕1 | | DC power supply input (⊕1, ⊖) | <ul style="list-style-type: none"> DC power supply input (⊕1, ⊖) Braking unit connection (⊕3, ⊖) | | | | |
| ⊖ | | | | | | | |
| ⊕3 | Not available | | | | | | |
| ⊕ | For 200 V class: 100 Ω or less For 400 V class: 10 Ω or less For 600 V class: 10 Ω or less | | | | Grounding terminal | 93 | |

Note: Use terminals B1 and ⊖ when installing a CDBR-type braking unit on drives with built-in braking transistors (Models 2A0004 to 2A0138, 4A0002 to 4A0072, and 5A0003 to 5A0052).

Wiring Fuses for Models 4A0930 and 4A1200

NOTICE: If a fuse is blown or an Ground Fault Circuit Interrupter (GFCI) is tripped, check the wiring and the selection of peripheral devices to identify the cause. Contact Yaskawa before restarting the drive or the peripheral devices if the cause cannot be identified.

Install a fuse on the input side to protect drive wiring and prevent other secondary damage. Wire the fuse so that leakage current in the upper controller power supply will trigger the fuse and shut off the power supply.

Select the appropriate fuse from [Table 3.2](#).

3.8 Main Circuit Wiring

Table 3.2 Input Fuses for Models 4A0930 and 4A1200

| Voltage Class | Model | Selection | | | Input Fuse (Example) | | | |
|-------------------------|-----------|---------------|---------|-----------------------------------|----------------------|-----------------|-----------------|-----------------------------------|
| | | Input Voltage | Current | Pre-arc I^2t (A ² s) | Model | Manufacturer | Rating | Pre-arc I^2t (A ² s) |
| Three-Phase 400 V Class | 4A0930 | 480 V | 1500 A | 140000 to 3100000 | CS5F-1200 | Fuji Electric | AC500 V, 1200 A | 276000 |
| | FWH-1200A | | | | Bussman | AC500 V, 1200 A | – | |
| | FWH-1000A | | | | Bussman | AC500 V, 1000 A | – | |
| | 4A1200 | 480 V | 1500 A | 320000 to 3100000 | CS5F-1500 | Fuji Electric | AC500 V, 1500 A | 351000 |
| | FWH-1600A | | | | Bussman | AC500 V, 1600 A | – | |
| | FWH-1200A | | | | Bussman | AC500 V, 1200 A | – | |

◆ Protecting Main Circuit Terminals

■ Insulation Caps or Sleeves

Use insulation caps or sleeves when wiring the drive with crimp terminals. Take particular care to ensure that the wiring does not touch nearby terminals or the surrounding case.

■ Insulation Barrier

Insulation barriers are packaged with drive models 4A0414 through 4A1200 to provide added protection between terminals. Yaskawa recommends using the provided insulation barriers to ensure proper wiring. Refer to [Figure 3.27](#) for instructions on placement of the insulation barriers.

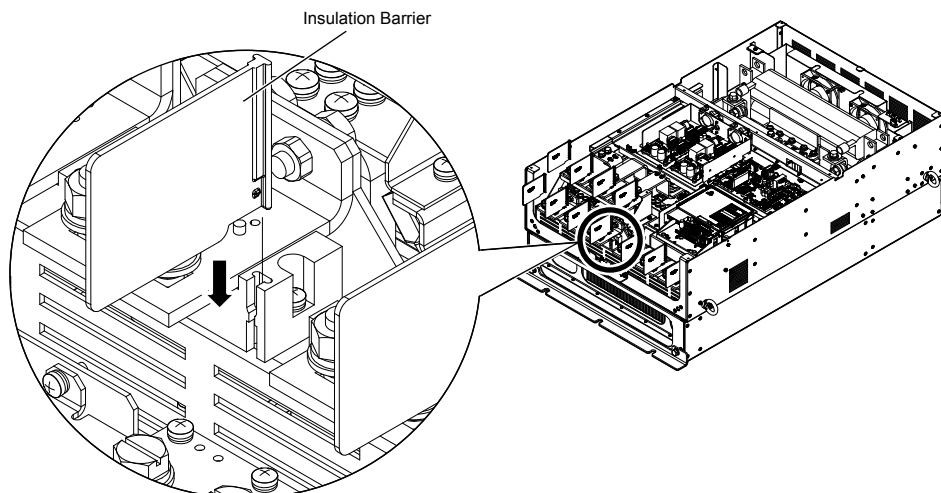


Figure 3.27 Installing Insulation Barriers

◆ Main Circuit Wire Gauges and Tightening Torques

Use the tables in this section to select the appropriate wires and crimp terminals.

Gauges listed in the tables are for use in the United States.

- Note:**
1. Wire gauge recommendations based on drive continuous current ratings (ND) using 75 °C 600 Vac vinyl-sheathed wire assuming ambient temperature within 40 °C and wiring distance less than 100 m.
 2. Terminals ⊕1, ⊕2, ⊕3, ⊖, B1 and B2 are for connecting optional power devices. Use caution to connect only approved devices to the correct terminal(s).

- Consider the amount of voltage drop when selecting wire gauges. Increase the wire gauge when the voltage drop is greater than 2% of motor rated voltage. Ensure the wire gauge is suitable for the terminal block. Use the following formula to calculate the amount of voltage drop:

$$\text{Line drop voltage (V)} = \sqrt{3} \times \text{wire resistance } (\Omega/\text{km}) \times \text{wire length (m)} \times \text{current (A)} \times 10^{-3}$$

- Refer to instruction manual TOBPC72060000 or TOBPC72060001 for braking transistor option or braking resistor option wire gauges.
- Use terminals ⊕1 and ⊖ when connecting a regenerative converter or a regen unit.

NOTICE: Do not connect a braking resistor to terminals ⊕1 or ⊖. Failure to comply may cause damage to the drive circuitry.

- Use terminals B1 and ⊖ when installing a CDBR-type braking unit on drives with built-in braking transistors (models 2A0004 to 2A0138, 4A0002 to 4A0072, and 5A0003 to 5A0052).

NOTICE: Do not connect a braking resistor to terminals ⊕1 or ⊖. Failure to comply may cause damage to the drive circuitry.

- **Refer to UL Standards Compliance on page 550** for information on UL compliance.

Yaskawa recommends using closed-loop crimp terminals on all drive models. UL/cUL approval requires the use of closed-loop crimp terminals when wiring the drive main circuit terminals on models 2A0110 to 2A0415 and 4A0058 to 4A1200. Use only the tools recommended by the terminal manufacturer for crimping. **Refer to Closed-Loop Crimp Terminal Size on page 558** for closed-loop crimp terminal recommendations.

The wire gauges listed in the following tables are Yaskawa recommendations. Refer to local codes for proper wire gauge selections.

■ Three-Phase 200 V Class

Table 3.3 Wire Gauge and Torque Specifications (Three-Phase 200 V Class)

| Drive Model | Terminal | Recomm. Gauge AWG, kcmil | Wire Range AWG, kcmil | Screw Size | Tightening Torque N·m (lb.in.) |
|--------------------------------------|------------------|-----------------------------|--------------------------|---------------|-----------------------------------|
| 2A0004 2A0006 2A0008 2A0010 | R/L1, S/L2, T/L3 | 14 | 14 to 10 | M4 | 1.2 to 1.5 (10.6 to 13.3) |
| | U/T1, V/T2, W/T3 | 14 | 14 to 10 | | |
| | ⊖, ⊕1, ⊕2 | – | 14 to 10 | | |
| | B1, B2 | – | 14 to 10 | | |
| | ⊕ | 10 <I> | 14 to 10 | | |
| 2A0012 | R/L1, S/L2, T/L3 | 12 | 14 to 10 | M4 | 1.2 to 1.5 (10.6 to 13.3) |
| | U/T1, V/T2, W/T3 | 14 | 14 to 10 | | |
| | ⊖, ⊕1, ⊕2 | – | 14 to 10 | | |
| | B1, B2 | – | 14 to 10 | | |
| | ⊕ | 10 <I> | 14 to 10 | | |
| 2A0018 | R/L1, S/L2, T/L3 | 10 | 12 to 10 | M4 | 1.2 to 1.5 (10.6 to 13.3) |
| | U/T1, V/T2, W/T3 | 10 | 14 to 10 | | |
| | ⊖, ⊕1, ⊕2 | – | 14 to 10 | | |
| | B1, B2 | – | 14 to 10 | | |
| | ⊕ | 10 <I> | 14 to 10 | | |
| 2A0021 | R/L1, S/L2, T/L3 | 10 | 12 to 10 | M4 | 1.2 to 1.5 (10.6 to 13.3) |
| | U/T1, V/T2, W/T3 | 10 | 12 to 10 | | |
| | ⊖, ⊕1, ⊕2 | – | 12 to 10 | | |
| | B1, B2 | – | 14 to 10 | | |
| | ⊕ | 10 <I> | 12 to 10 | | |

3.8 Main Circuit Wiring

| Drive Model | Terminal | Recomm. Gauge AWG, kcmil | Wire Range AWG, kcmil | Screw Size | Tightening Torque N·m (lb.in.) |
|-------------|------------------|--------------------------------|--------------------------|---------------|-----------------------------------|
| 2A0030 | R/L1, S/L2, T/L3 | 8 | 10 to 6 | M4 | 2.1 to 2.3 (18.6 to 20.4) |
| | U/T1, V/T2, W/T3 | 8 | 10 to 6 | | |
| | ⊖, ⊕1, ⊕2 | – | 10 to 6 | | |
| | B1, B2 | – | 14 to 10 | | |
| | ⊕ | 8 \leftrightarrow | 10 to 8 | M5 | 2.0 to 2.5 (17.7 to 22.1) |
| 2A0040 | R/L1, S/L2, T/L3 | 6 | 8 to 6 | M4 | 2.1 to 2.3 (18.6 to 20.4) |
| | U/T1, V/T2, W/T3 | 8 | 8 to 6 | | |
| | ⊖, ⊕1, ⊕2 | – | 6 | | |
| | B1, B2 | – | 12 to 10 | | |
| | ⊕ | 8 \leftrightarrow | 10 to 8 | M5 | 2.0 to 2.5 (17.7 to 22.1) |
| 2A0056 | R/L1, S/L2, T/L3 | 4 | 6 to 4 | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| | U/T1, V/T2, W/T3 | 4 | 6 to 4 | | |
| | ⊖, ⊕1, ⊕2 | – | 6 to 4 | | |
| | B1, B2 | – | 10 to 6 | M5 | 2.7 to 3.0 (23.9 to 26.6) |
| | ⊕ | 6 | 8 to 6 | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| 2A0069 | R/L1, S/L2, T/L3 | 3 | 4 to 3 | M8 | 9.9 to 11.0 (87.6 to 97.4) |
| | U/T1, V/T2, W/T3 | 3 | 4 to 3 | | |
| | ⊖, ⊕1, ⊕2 | – | 4 to 3 | | |
| | B1, B2 | – | 8 to 6 | M5 | 2.7 to 3.0 (23.9 to 26.6) |
| | ⊕ | 6 | 6 to 4 | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| 2A0081 | R/L1, S/L2, T/L3 | 2 | 3 to 2 | M8 | 9.9 to 11.0 (87.6 to 97.4) |
| | U/T1, V/T2, W/T3 | 2 | 3 to 2 | | |
| | ⊖, ⊕1, ⊕2 | – | 3 to 2 | | |
| | B1, B2 | – | 6 | M5 | 2.7 to 3.0 (23.9 to 26.6) |
| | ⊕ | 6 | 6 to 4 | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| 2A0110 | R/L1, S/L2, T/L3 | 1/0 | 3 to 1/0 | M8 | 9 to 11 (79.7 to 97.4) |
| | U/T1, V/T2, W/T3 | 1/0 | 3 to 1/0 | | |
| | ⊖, ⊕1 | – | 2 to 1/0 | | |
| | B1, B2 | – | 6 to 1/0 | | |
| | ⊕ | 6 | 6 to 4 | | |
| 2A0138 | R/L1, S/L2, T/L3 | 2/0 | 1 to 2/0 | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 2/0 | 1 to 2/0 | | |
| | ⊖, ⊕1 | – | 1/0 to 3/0 | | |
| | B1, B2 | – | 4 to 2/0 | | |
| | ⊕ | 4 | 4 | M8 | 9 to 11 (79.7 to 97.4) |
| 2A0169 | R/L1, S/L2, T/L3 | 4/0 | 2/0 to 4/0 | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 4/0 | 3/0 to 4/0 | | |
| | ⊖, ⊕1 | – | 1 to 4/0 | | |
| | ⊕3 | – | 1/0 to 4/0 | | |
| | ⊕ | 4 | 4 to 2 | | |
| 2A0211 | R/L1, S/L2, T/L3 | 1/0 × 2P | 1/0 to 2/0 | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 1/0 × 2P | 1/0 to 2/0 | | |
| | ⊖, ⊕1 | – | 1 to 4/0 | | |
| | ⊕3 | – | 1/0 to 4/0 | | |
| | ⊕ | 4 | 4 to 1/0 | | |

| Drive Model | Terminal | Recomm. Gauge AWG, kcmil | Wire Range AWG, kcmil | Screw Size | Tightening Torque N·m (lb.in.) |
|-------------|------------------|-----------------------------|--------------------------|---------------|-----------------------------------|
| 2A0250 | R/L1, S/L2, T/L3 | 3/0 × 2P | 3/0 to 300 | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 3/0 × 2P | 3/0 to 300 | | |
| | ⊖, ⊕1 | – | 3/0 to 300 | | |
| | ⊕3 | – | 2 to 300 | M10 | 18 to 23 (159 to 204) |
| | ⊕ | 3 | 3 to 300 | M12 | 32 to 40 (283 to 354) |
| 2A0312 | R/L1, S/L2, T/L3 | 4/0 × 2P | 3/0 to 300 | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 3/0 × 2P | 3/0 to 300 | | |
| | ⊖, ⊕1 | – | 3/0 to 300 | | |
| | ⊕3 | – | 3/0 to 300 | M10 | 18 to 23 (159 to 204) |
| | ⊕ | 2 | 2 to 300 | M12 | 32 to 40 (283 to 354) |
| 2A0360 | R/L1, S/L2, T/L3 | 250 × 2P | 4/0 to 600 | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 4/0 × 2P | 4/0 to 600 | | |
| | ⊖, ⊕1 | – | 250 to 600 | | |
| | ⊕3 | – | 3/0 to 600 | M10 | 18 to 23 (159 to 204) |
| | ⊕ | 1 | 1 to 350 | M12 | 32 to 40 (283 to 354) |
| 2A0415 | R/L1, S/L2, T/L3 | 350 × 2P | 250 to 600 | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 300 × 2P | 300 to 600 | | |
| | ⊖, ⊕1 | – | 300 to 600 | | |
| | ⊕3 | – | 3/0 to 600 | M10 | 18 to 23 (159 to 204) |
| | ⊕ | 1 | 1 to 350 | M12 | 32 to 40 (283 to 354) |

<1> Install a GFCI when using this wire gauge in accordance with IEC/EN 61800-5-1.

<2> Install a GFCI, or use 10 mm² (AWG 8) copper wire when using this wire gauge in accordance with IEC/EN 61800-5-1.

Note: When connecting peripheral devices or options to terminals ⊖, ⊕1, ⊕3, B1, and B2, refer to the instruction manual for each device. For more information, contact Yaskawa or your nearest sales representative.

■ Three-Phase 400 V Class

Table 3.4 Wire Gauge and Torque Specifications (Three-Phase 400 V Class)

| Drive Model | Terminal | Recomm. Gauge AWG, kcmil | Wire Range AWG, kcmil | Screw Size | Tightening Torque N·m (lb.in.) |
|----------------------------|------------------|-----------------------------|--------------------------|---------------|-----------------------------------|
| 4A0002 4A0004 | R/L1, S/L2, T/L3 | 14 | 14 to 10 | M4 | 1.2 to 1.5 (10.6 to 13.3) |
| | U/T1, V/T2, W/T3 | 14 | 14 to 10 | | |
| | ⊖, ⊕1, ⊕2 | – | 14 to 10 | | |
| | B1, B2 | – | 14 to 10 | | |
| | ⊕ | 12 <1> | 14 to 12 | | |
| 4A0005 4A0007 4A0009 | R/L1, S/L2, T/L3 | 14 | 14 to 10 | M4 | 1.2 to 1.5 (10.6 to 13.3) |
| | U/T1, V/T2, W/T3 | 14 | 14 to 10 | | |
| | ⊖, ⊕1, ⊕2 | – | 14 to 10 | | |
| | B1, B2 | – | 14 to 10 | | |
| | ⊕ | 10 <1> | 14 to 10 | | |
| 4A0011 | R/L1, S/L2, T/L3 | 12 | 14 to 10 | M4 | 1.2 to 1.5 (10.6 to 13.3) |
| | U/T1, V/T2, W/T3 | 14 | 14 to 10 | | |
| | ⊖, ⊕1, ⊕2 | – | 14 to 10 | | |
| | B1, B2 | – | 14 to 10 | | |
| | ⊕ | 10 <1> | 14 to 10 | | |

3.8 Main Circuit Wiring

| Drive Model | Terminal | Recomm. Gauge AWG, kcmil | Wire Range AWG, kcmil | Screw Size | Tightening Torque N·m (lb.in.) |
|-------------|------------------|-----------------------------|--------------------------|---------------|-----------------------------------|
| 4A0018 | R/L1, S/L2, T/L3 | 10 | 12 to 6 | M4 | 2.1 to 2.3 (18.6 to 20.4) |
| | U/T1, V/T2, W/T3 | 10 | 12 to 6 | | |
| | ⊖, ⊕1, ⊕2 | – | 12 to 6 | | |
| | B1, B2 | – | 12 to 10 | | |
| | ⊕ | 10 </> | 14 to 10 | M5 | 2.0 to 2.5 (17.7 to 22.1) |
| 4A0023 | R/L1, S/L2, T/L3 | 10 | 10 to 6 | M4 | 2.1 to 2.3 (18.6 to 20.4) |
| | U/T1, V/T2, W/T3 | 10 | 10 to 6 | | |
| | ⊖, ⊕1, ⊕2 | – | 12 to 6 | | |
| | B1, B2 | – | 12 to 10 | | |
| | ⊕ | 10 </> | 12 to 10 | M5 | 2.0 to 2.5 (17.7 to 22.1) |
| 4A0031 | R/L1, S/L2, T/L3 | 8 | 8 to 6 | M5 | 3.6 to 4.0 (31.8 to 35.4) |
| | U/T1, V/T2, W/T3 | 8 | 10 to 6 | | |
| | ⊖, ⊕1, ⊕2 | – | 10 to 6 | | |
| | B1, B2 | – | 10 to 8 | | |
| | ⊕ | 8 </> | 10 to 8 | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| 4A0038 | R/L1, S/L2, T/L3 | 6 | 8 to 6 | M5 | 3.6 to 4.0 (31.8 to 35.4) |
| | U/T1, V/T2, W/T3 | 8 | 8 to 6 | | |
| | ⊖, ⊕1, ⊕2 | – | 6 | | |
| | B1, B2 | – | 10 to 8 | | |
| | ⊕ | 6 | 10 to 6 | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| 4A0044 | R/L1, S/L2, T/L3 | 6 | 6 to 4 | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| | U/T1, V/T2, W/T3 | 6 | 6 to 4 | | |
| | ⊖, ⊕1, ⊕2 | – | 6 to 4 | | |
| | B1, B2 | – | 10 to 8 | M5 | 2.7 to 3.0 (23.9 to 26.6) |
| | ⊕ | 6 | 8 to 6 | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| 4A0058 | R/L1, S/L2, T/L3 | 4 | 6 to 4 | M8 | 9 to 11 (79.7 to 97.4) |
| | U/T1, V/T2, W/T3 | 4 | 6 to 4 | | |
| | ⊖, ⊕1 | – | 6 to 1 | | |
| | B1, B2 | – | 8 to 4 | | |
| | ⊕ | 6 | 8 to 6 | | |
| 4A0072 | R/L1, S/L2, T/L3 | 3 | 4 to 3 | M8 | 9 to 11 (79.7 to 97.4) |
| | U/T1, V/T2, W/T3 | 3 | 4 to 3 | | |
| | ⊖, ⊕1 | – | 4 to 1 | | |
| | B1, B2 | – | 6 to 3 | | |
| | ⊕ | 6 | 6 | | |
| 4A0088 | R/L1, S/L2, T/L3 | 2 | 3 to 1/0 | M8 | 9 to 11 (79.7 to 97.4) |
| | U/T1, V/T2, W/T3 | 2 | 3 to 1/0 | | |
| | ⊖, ⊕1 | – | 3 to 1/0 | | |
| | ⊕3 | – | 6 to 1/0 | | |
| | ⊕ | 4 | 6 to 4 | | |
| 4A0103 | R/L1, S/L2, T/L3 | 1/0 | 2 to 1/0 | M8 | 9 to 11 (79.7 to 97.4) |
| | U/T1, V/T2, W/T3 | 1 | 2 to 1/0 | | |
| | ⊖, ⊕1 | – | 3 to 1/0 | | |
| | ⊕3 | – | 4 to 1/0 | | |
| | ⊕ | 4 | 6 to 4 | | |

| Drive Model | Terminal | Recomm. Gauge AWG, kcmil | Wire Range AWG, kcmil | Screw Size | Tightening Torque N·m (lb.in.) |
|-------------|------------------|-----------------------------|--------------------------|---------------|-----------------------------------|
| 4A0139 | R/L1, S/L2, T/L3 | 3/0 | 1/0 to 4/0 | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 2/0 | 1/0 to 4/0 | | |
| | ⊖, ⊕1 | – | 1/0 to 4/0 | | |
| | ⊕3 | – | 3 to 4/0 | | |
| | ⊕ | 4 | 4 | | |
| 4A0165 | R/L1, S/L2, T/L3 | 4/0 | 3/0 to 4/0 | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 4/0 | 3/0 to 4/0 | | |
| | ⊖, ⊕1 | – | 1 to 4/0 | | |
| | ⊕3 | – | 1/0 to 4/0 | | |
| | ⊕ | 4 | 4 to 2 | | |
| 4A0208 | R/L1, S/L2, T/L3 | 300 | 2 to 300 | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 300 | 2 to 300 | | |
| | ⊖, ⊕1 | – | 1 to 250 | | |
| | ⊕3 | – | 3 to 3/0 | | |
| | ⊕ | 4 | 4 to 300 | | |
| 4A0250 | R/L1, S/L2, T/L3 | 400 | 1 to 600 | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 400 | 1/0 to 600 | | |
| | ⊖, ⊕1 | – | 3/0 to 600 | | |
| | ⊕3 | – | 1 to 325 | | |
| | ⊕ | 2 | 2 to 350 | | |
| 4A0296 | R/L1, S/L2, T/L3 | 500 | 2/0 to 600 | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 500 | 2/0 to 600 | | |
| | ⊖, ⊕1 | – | 3/0 to 600 | M10 | 18 to 23 (159 to 204) |
| | ⊕3 | – | 1 to 325 | | |
| | ⊕ | 2 | 2 to 350 | | |
| 4A0362 | R/L1, S/L2, T/L3 | 4/0 × 2P | 3/0 to 600 | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 4/0 × 2P | 3/0 to 600 | | |
| | ⊖, ⊕1 | – | 4/0 to 600 | M10 | 18 to 23 (159 to 204) |
| | ⊕3 | – | 3/0 to 600 | | |
| | ⊕ | 1 | 1 to 350 | | |
| 4A0414 | R/L1, S/L2, T/L3 | 300 × 2P | 4/0 to 300 | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 300 × 2P | 4/0 to 300 | | |
| | ⊖, ⊕1 | – | 3/0 to 300 | | |
| | ⊕3 | – | 3/0 to 300 | | |
| | ⊕ | 1 | 1 to 3/0 | | |
| 4A0515 | R/L1, S/L2, T/L3 | 3/0 × 4P | 3/0 to 300 | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 4/0 × 4P | 3/0 to 300 | | |
| | ⊖, ⊕1 | – | 1/0 to 300 | | |
| | ⊕3 | – | 1/0 to 300 | | |
| | ⊕ | 1/0 | 1/0 to 300 | | |
| 4A0675 | R/L1, S/L2, T/L3 | 300 × 4P | 4/0 to 300 | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 300 × 4P | 4/0 to 300 | | |
| | ⊖, ⊕1 | – | 1/0 to 300 | | |
| | ⊕3 | – | 1/0 to 300 | | |
| | ⊕ | 2/0 | 2/0 to 300 | | |

3.8 Main Circuit Wiring

| Drive Model | Terminal | Recomm. Gauge AWG, kcmil | Wire Range AWG, kcmil | Screw Size | Tightening Torque N·m (lb.in.) |
|-------------|--|-----------------------------|--------------------------|---------------|-----------------------------------|
| 4A0930 | R/L1, S/L2, T/L3, R1/L11, S1/L21, T1/L31 | 4/0 × 4P×2 | 3/0 to 300 | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 4/0 × 4P×2 | 3/0 to 300 | | |
| | ⊖, ⊕1 | – | 4/0 to 300 | | |
| | ⊕3 | – | 4/0 to 300 | | |
| | ⊕ | 3/0 | 3/0 to 250 | | |
| 4A1200 | R/L1, S/L2, T/L3, R1/L11, S1/L21, T1/L31 | 300 × 4P×2 | 4/0 to 300 | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 300 × 4P×2 | 4/0 to 300 | | |
| | ⊖, ⊕1 | – | 250 to 300 | | |
| | ⊕3 | – | 4/0 to 300 | | |
| | ⊕ | 4/0 | 4/0 to 250 | | |

<1> Install a GFCI when using this wire gauge in accordance with IEC/EN 61800-5-1.

<2> Install a GFCI or use 10 mm² (AWG 8) copper wire when using this wire gauge in accordance with IEC/EN 61800-5-1.

Note: When connecting peripheral devices or options to terminals ⊖, ⊕1, ⊕3, B1, and B2, refer to the instruction manual for each device. For more information, contact Yaskawa or your nearest sales representative.

■ Three-Phase 600 V Class

Table 3.5 Wire Gauge and Torque Specifications (Three-Phase 600 V Class)

| Drive Model | Terminal | Recomm. Gauge mm ² (AWG, kcmil) | Wire Range mm ² (AWG, kcmil) | Screw Size | Tightening Torque N·m (lb.in.) |
|----------------------------|------------------|---|--|---------------|-----------------------------------|
| 5A0003 5A0004 5A0006 | R/L1, S/L2, T/L3 | 2.5 (14) | 2.5 to 6.0 (14 to 10) | M4 | 1.2 to 1.5 (10.6 to 13.3) |
| | U/T1, V/T2, W/T3 | 2.5 (14) | 2.5 to 6.0 (14 to 10) | | |
| | ⊖, ⊕1, ⊕2 | – | 2.5 to 6.0 (14 to 10) | | |
| | B1, B2 | – | 2.5 to 6.0 (14 to 10) | | |
| | ⊕ | 6.0 (10) | 2.5 to 6.0 (14 to 10) | | |
| 5A0009 | R/L1, S/L2, T/L3 | 2.5 (14) | 2.5 to 6.0 (14 to 10) | M4 | 1.2 to 1.5 (10.6 to 13.3) |
| | U/T1, V/T2, W/T3 | 2.5 (14) | 2.5 to 6.0 (14 to 10) | | |
| | ⊖, ⊕1, ⊕2 | – | 2.5 to 6.0 (14 to 10) | | |
| | B1, B2 | – | 2.5 to 6.0 (14 to 10) | | |
| | ⊕ | 6.0 (10) | 4.0 to 6.0 (12 to 10) | | |
| 5A0011 | R/L1, S/L2, T/L3 | 6.0 (10) | 2.5 to 16 (14 to 6) | M4 | 2.1 to 2.3 (18.6 to 20.4) |
| | U/T1, V/T2, W/T3 | 2.5 (14) | 2.5 to 16 (14 to 6) | | |
| | ⊖, ⊕1, ⊕2 | – | 2.5 to 16 (14 to 6) | | |
| | B1, B2 | – | 2.5 to 6.0 (14 to 10) | | |
| | ⊕ | 10 (8) | 4.0 to 6.0 (12 to 8) | M5 | 2.0 to 2.5 (17.7 to 22.1) |

| Drive Model | Terminal | Recomm. Gauge mm ² (AWG, kcmil) | Wire Range mm ² (AWG, kcmil) | Screw Size | Tightening Torque N·m (lb.in.) |
|------------------|------------------|---|--|---------------|-----------------------------------|
| 5A0017 | R/L1, S/L2, T/L3 | 6.0 (10) | 6.0 to 16 (10 to 6) | M5 | 3.6 to 4.0 (31.8 to 35.4) |
| | U/T1, V/T2, W/T3 | 6.0 (10) | 6.0 to 16 (10 to 6) | | |
| | ⊖, ⊕1, ⊕2 | – | 6.0 to 16 (10 to 6) | | |
| | B1, B2 | – | 6.0 to 10 (10 to 8) | M6 | 2.7 to 3.0 (23.9 to 26.6) |
| | ⊕ | 10 (8) | 6.0 to 10 (12 to 8) | | 5.4 to 6.0 (47.8 to 53.1) |
| 5A0022 | R/L1, S/L2, T/L3 | 10 (8) | 6.0 to 16 (10 to 6) | M5 | 3.6 to 4.0 (31.8 to 35.4) |
| | U/T1, V/T2, W/T3 | 6.0 (10) | 6.0 to 16 (10 to 6) | | |
| | ⊖, ⊕1, ⊕2 | – | 6.0 to 16 (10 to 6) | | |
| | B1, B2 | – | 6.0 to 10 (10 to 8) | M6 | 2.7 to 3.0 (23.9 to 26.6) |
| | ⊕ | 10 (8) | 6.0 to 10 (10 to 6) | | 5.4 to 6.0 (47.8 to 53.1) |
| 5A0027 5A0032 | R/L1, S/L2, T/L3 | 16 (6) | 16 to 25 (6 to 4) | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| | U/T1, V/T2, W/T3 | 16 (6) | 16 to 25 (6 to 4) | | |
| | ⊖, ⊕1, ⊕2 | – | 16 to 25 (6 to 4) | | |
| | B1, B2 | – | 6.0 to 10 (10 to 8) | M5 | 2.7 to 3.0 (23.9 to 26.6) |
| | ⊕ | 16 (6) | 10 to 16 (10 to 6) | | M6 |
| 5A0041 | R/L1, S/L2, T/L3 | 16 (6) | 6.0 to 25 (10 to 3) | M8 | 9.0 to 11 (79.7 to 97.4) |
| | U/T1, V/T2, W/T3 | 16 (6) | 6.0 to 25 (10 to 3) | | |
| | ⊖, ⊕1 | – | (6 to 1) | | |
| | B1, B2 | – | 4.0 to 25 (12 to 3) | | |
| | ⊕ | 16 (6) | 10 to 16 (6) | | |
| 5A0052 | R/L1, S/L2, T/L3 | 25 (4) | 6.0 to 25 (10 to 3) | M8 | 9.0 to 11 (79.7 to 97.4) |
| | U/T1, V/T2, W/T3 | 16 (6) | 6.0 to 25 (10 to 3) | | |
| | ⊖, ⊕1 | – | 16 to 35 (6 to 1) | | |
| | B1, B2 | – | 10 to 25 (8 to 3) | | |
| | ⊕ | 16 (6) | 10 to 16 (6) | | |
| 5A0062 | R/L1, S/L2, T/L3 | 25 (4) | 6.0 to 95 (10 to 4/0) | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 25 (4) | 6.0 to 95 (10 to 4/0) | | |
| | ⊖, ⊕1 | – | 25 to 95 (4 to 4/0) | | |
| | ⊕3 | – | 16 to 95 (6 to 4/0) | | |
| | ⊕ | 25 (4) | 25 (4) | | |

3.8 Main Circuit Wiring

| Drive Model | Terminal | Recomm. Gauge mm ² (AWG, kcmil) | Wire Range mm ² (AWG, kcmil) | Screw Size | Tightening Torque N·m (lb.in.) |
|-------------|------------------|---|--|---------------|-----------------------------------|
| 5A0077 | R/L1, S/L2, T/L3 | 25 (3) | 6.0 to 95 (10 to 4/0) | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 25 (3) | 6.0 to 95 (10 to 4/0) | | |
| | ⊖, ⊕1 | – | 25 to 95 (3 to 4/0) | | |
| | ⊕3 | – | 16 to 95 (6 to 4/0) | | |
| | ⊕ | 25 (4) | 25 (4) | | |
| 5A0099 | R/L1, S/L2, T/L3 | 70 (1/0) | 6.0 to 95 (10 to 4/0) | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 50 (1) | 6.0 to 95 (10 to 4/0) | | |
| | ⊖, ⊕1 | – | 35 to 95 (2 to 4/0) | | |
| | ⊕3 | – | 25 to 95 (4 to 4/0) | | |
| | ⊕ | 25 (4) | 25 (4) | | |
| 5A0125 | R/L1, S/L2, T/L3 | 70 (2/0) | 35 to 150 (1 to 300) | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 70 (2/0) | 35 to 150 (1 to 300) | | |
| | ⊖, ⊕1 | – | 70 (2/0 to 3/0) | | |
| | ⊕3 | – | 35 to 50 (1 to 1/0) | | |
| | ⊕ | 35 (3) | 35 to 150 (3 to 300) | | |
| 5A0145 | R/L1, S/L2, T/L3 | 95 (3/0) | 95 to 150 (2/0 to 300) | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 95 (3/0) | 95 to 150 (2/0 to 300) | | |
| | ⊖, ⊕1 | – | 70 to 95 (3/0 to 4/0) | | |
| | ⊕3 | – | 70 to 95 (1/0 to 2/0) | | |
| | ⊕ | 35 (3) | 35 to 150 (3 to 300) | | |
| 5A0192 | R/L1, S/L2, T/L3 | 185 (300) | 95 to 300 (2/0 to 600) | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 150 (250) | 95 to 300 (2/0 to 600) | | |
| | ⊖, ⊕1 | – | 95 to 185 (2/0 to 400) | M10 | 18 to 23 (159 to 204) |
| | ⊕3 | – | 95 to 120 (2/0 to 250) | | |
| | ⊕ | 50 (1) | 35 to 300 (1 to 350) | M12 | 32 to 40 (283 to 354) |
| 5A0242 | R/L1, S/L2, T/L3 | 240 (400) | 95 to 300 (2/0 to 600) | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 185 (350) | 95 to 300 (2/0 to 600) | | |
| | ⊖, ⊕1 | – | 95 to 240 (2/0 to 500) | M10 | 18 to 23 (159 to 204) |
| | ⊕3 | – | 150 (250 to 300) | | |
| | ⊕ | 50 (1) | 35 to 300 (1 to 350) | M12 | 32 to 40 (283 to 354) |

Note: When connecting peripheral devices or options to terminals ⊖, ⊕1, ⊕3, B1, and B2, refer to the instruction manual for each device. For more information, contact Yaskawa or your nearest sales representative.

◆ Main Circuit Terminal and Motor Wiring

This section outlines the various steps, precautions, and checkpoints for wiring the main circuit terminals and motor terminals.

WARNING! Electrical Shock Hazard. Do not connect the AC power line to the output terminals of the drive. Failure to comply could result in death or serious injury by fire as a result of drive damage from line voltage application to output terminals.

NOTICE: When connecting the motor to the drive output terminals U/T1, V/T2, and W/T3, the phase order for the drive and motor should match. Failure to comply with proper wiring practices may cause the motor to run in reverse if the phase order is backward.

NOTICE: Route motor leads U/T1, V/T2, and W/T3 separate from all other leads to reduce possible interference related issues. Failure to comply may result in abnormal operation of drive and nearby equipment.

NOTICE: Do not connect phase-advancing capacitors or LC/RC noise filters to the output circuits. Failure to comply could result in damage to the drive, phase-advancing capacitors, LC/RC noise filters or ground fault circuit interrupters.

■ Cable Length Between Drive and Motor

Voltage drop along the motor cable may cause reduced motor torque when the wiring between the drive and the motor is too long, especially at low frequency output. This can also be a problem when motors are connected in parallel with a fairly long motor cable. Drive output current will increase as the leakage current from the cable increases. An increase in leakage current may trigger an overcurrent situation and weaken the accuracy of the current detection.

Adjust the drive carrier frequency according to [Table 3.6](#). If the motor wiring distance exceeds 100 m because of the system configuration, reduce the ground currents. [Refer to C6-02: Carrier Frequency Selection on page 180.](#)

Table 3.6 Cable Length Between Drive and Motor

| Cable Length | 50 m or less | 100 m or less | Greater than 100 m |
|-------------------|----------------|---------------|--------------------|
| Carrier Frequency | 15 kHz or less | 5 kHz or less | 2 kHz or less |

Note: When setting carrier frequency for drives running multiple motors, calculate cable length as the total wiring distance to all connected motors.

■ Ground Wiring

Follow the precautions below when wiring the ground for one drive or a series of drives.

WARNING! Electrical Shock Hazard. Make sure the protective earthing conductor complies with technical standards and local safety regulations. Because the leakage current exceeds 3.5 mA in models 4A0414 and larger, IEC/EN 61800-5-1 states that either the power supply must be automatically disconnected in case of discontinuity of the protective earthing conductor or a protective earthing conductor with a cross-section of at least 10 mm² (Cu) or 16 mm² (Al) must be used. Failure to comply may result in death or serious injury.

WARNING! Electrical Shock Hazard. Always use a ground wire that complies with technical standards on electrical equipment and minimize the length of the ground wire. Improper equipment grounding may cause dangerous electrical potentials on equipment chassis, which could result in death or serious injury.

WARNING! Electrical Shock Hazard. Be sure to ground the drive ground terminal (200 V class: ground to 100 Ω or less; 400 V class: ground to 10 Ω or less; 600 V class: ground to 10 Ω or less). Improper equipment grounding could result in death or serious injury by contacting ungrounded electrical equipment.

NOTICE: Do not share the ground wire with other devices such as welding machines or large-current electrical equipment. Improper equipment grounding could result in drive or equipment malfunction due to electrical interference.

NOTICE: When using more than one drive, ground multiple drives according to instructions. Improper equipment grounding could result in abnormal operation of drive or equipment.

Refer to [Figure 3.28](#) when using multiple drives. Do not loop the ground wire.

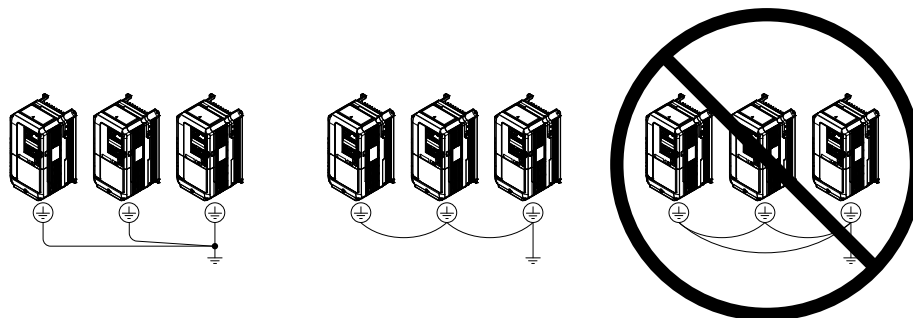


Figure 3.28 Multiple Drive Wiring

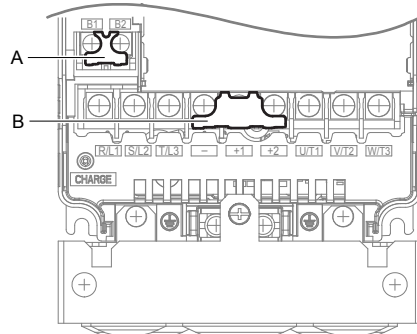
3.8 Main Circuit Wiring

■ Wiring the Main Circuit Terminal

WARNING! Electrical Shock Hazard. Shut off the power supply to the drive before wiring the main circuit terminals. Failure to comply may result in death or serious injury.

Wire the main circuit terminals after the terminal board has been properly grounded.

Models 2A0004 to 2A0081, 4A0002 to 4A0044, and 5A0003 to 5A0032 have a cover placed over the DC bus and braking circuit terminals prior to shipment to help prevent miswiring. Use wire cutters to cut away covers as needed for terminals.



A – Braking circuit protective cover

B – DC bus protective cover

Figure 3.29 Protecting Cover to Prevent Miswiring (Model 5A0011)

■ Main Circuit Connection Diagram

Refer to Main Circuit Connection Diagram on page 71 when wiring terminals on the main power circuit of the drive.

WARNING! Fire Hazard. The braking resistor connection terminals are B1 and B2. Do not connect braking resistors to any other terminals. Improper wiring connections could cause the braking resistor to overheat and cause death or serious injury by fire. Failure to comply may result in damage to the braking circuit or drive.

3.9 Control Circuit Wiring

◆ Control Circuit Connection Diagram

Refer to [Figure 3.1](#) on page [69](#) when wiring terminals on the drive control circuit.

◆ Control Circuit Terminal Block Functions

Drive parameters determine which functions apply to the multi-function digital inputs (S1 to S8), multi-function digital outputs (M1 to M4), multi-function analog inputs (A1 to A3), and multi-function analog monitor output (FM, AM). The default setting is listed next to each terminal in [Figure 3.1](#) on page [69](#).

WARNING! Sudden Movement Hazard. Always check the operation and wiring of control circuits after being wired. Operating a drive with untested control circuits could result in death or serious injury.

WARNING! Sudden Movement Hazard. Confirm the drive I/O signals and external sequence before starting test run. Setting parameter A1-03 may change the I/O terminal function automatically from the factory setting. Failure to comply may result in death or serious injury.

■ Input Terminals

[Table 3.7](#) lists the input terminals on the drive. Text in parenthesis indicates the default setting for each multi-function input.

Table 3.7 Control Circuit Input Terminals

| Type | No. | Terminal Name (Function) | Function (Signal Level) Default Setting | Page | |
|-------------------------------|--|---|--|------|--|
| Multi-Function Digital Inputs | S1 | Multi-function input 1 (Closed: Forward run, Open: Stop) | <ul style="list-style-type: none"> • Photocoupler • 24 Vdc, 8 mA • Refer to Sinking/Sourcing Mode for Digital Inputs on page 101. | 205 | |
| | S2 | Multi-function input 2 (Closed: Reverse run, Open: Stop) | | | |
| | S3 | Multi-function input 3 (External fault, N.O.) | | | |
| | S4 | Multi-function input 4 (Fault reset) | | | |
| | S5 | Multi-function input 5 (Multi-step speed reference 1) | | | |
| | S6 | Multi-function input 6 (Multi-step speed reference 2) | | | |
| | S7 | Multi-function input 7 (Jog reference) | | | |
| | S8 | Multi-function input 8 (Baseblock command (N.O.)) | | | |
| | SC | Multi-function input common | | | Multi-function input common |
| | SP | Digital input power supply +24 Vdc | | | 24 Vdc power supply for digital inputs, 150 mA max |
| SN | Digital input power supply 0 V 24 V transducer power supply 0 V | NOTICE: Do not jumper or short terminals SP and SN. Failure to comply will damage the drive. | 101 | | |

3.9 Control Circuit Wiring

| Type | No. | Terminal Name (Function) | Function (Signal Level) Default Setting | Page |
|-----------------------------------|-------|--|---|-------------------|
| Analog Inputs / Pulse Train Input | RP | Multi-function pulse train input (Frequency reference) | <ul style="list-style-type: none"> Input frequency range: 0 to 32 kHz Signal Duty Cycle: 30 to 70% High level: 3.5 to 13.2 Vdc, low level: 0.0 to 0.8 Vdc Input impedance: 3 kΩ | 148 232 |
| | +V | Power supply for analog inputs | 10.5 Vdc (max allowable current 20 mA) | 147 |
| | 24 V | +24 Vdc transducer power supply for customer use | 150 mA maximum capacity | – |
| | A1 | Multi-function analog input 1 (Frequency reference bias) | <ul style="list-style-type: none"> -10 to 10 Vdc, 0 to 10 Vdc (input impedance: 20 kΩ) 4 to 20 mA, 0 to 20 mA (input impedance: 250 Ω) Voltage or current input must be selected by jumper S1 and H3-01. | 147 225 |
| | A2 | Multi-function analog input 2 (Frequency reference bias) | <ul style="list-style-type: none"> -10 to 10 Vdc, 0 to 10 Vdc (input impedance: 20 kΩ) 4 to 20 mA, 0 to 20 mA (input impedance: 250 Ω) Voltage or current input must be selected by jumper S1 and H3-09. | 147 147 226 |
| | A3 | Multi-function analog input 3 (Frequency reference bias) | <ul style="list-style-type: none"> -10 to 10 Vdc, 0 to 10 Vdc (input impedance: 20 kΩ) 4 to 20 mA, 0 to 20 mA (input impedance: 250 Ω) Voltage or current input must be selected by jumper S1 and H3-05. | 147 |
| | AC | Frequency reference common | 0 V | 147 |
| | E (G) | Ground for shielded lines and option cards | – | – |

Output Terminals

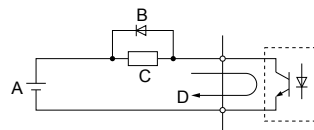
Table 3.8 lists the output terminals on the drive. Text in parenthesis indicates the default setting for each multi-function output.

Table 3.8 Control Circuit Output Terminals

| Type | No. | Terminal Name (Function) | Function (Signal Level) Default Setting | Page |
|-----------------------------------|-----|--|---|------|
| Fault Relay Output | MA | N.O. | 30 Vdc, 10 mA to 1 A; 250 Vac, 10 mA to 1 A Minimum load: 5 Vdc, 10 mA | 215 |
| | MB | N.C. output | | |
| | MC | Fault output common | | |
| Multi-Function Digital Output <1> | MD | N.O. | 30 Vdc, 10 mA to 1 A; 250 Vac, 10 mA to 1 A Minimum load: 5 Vdc, 10 mA | 215 |
| | ME | N.C. Output | | |
| | MF | Common (Speed agree) | | |
| | M1 | Multi-function digital output (During run) | | |
| | M2 | | | |
| | M3 | Multi-function digital output (Zero speed) | | |
| M4 | | | | |
| Monitor Output | FM | Analog monitor output 1 (Output frequency) | -10 to +10 Vdc, or 0 to +10 Vdc | 230 |
| | AM | Analog monitor output 2 (Output current) | | |
| | AC | Monitor common | | |

<1> Refrain from assigning functions to digital relay outputs that involve frequent switching, as doing so may shorten relay performance life. Switching life is estimated at 200,000 times (assumes 1 A, resistive load).

Connect a suppression diode as shown in Figure 3.30 when driving a reactive load such as a relay coil. Ensure the diode rating is greater than the circuit voltage.



A – External power, 48 V max.
B – Suppression diode

C – Coil
D – 50 mA or less

Figure 3.30 Connecting a Suppression Diode

Serial Communication Terminals

Table 3.9 Control Circuit Terminals: Serial Communications

| Type | No. | Signal Name | Function (Signal Level) | |
|----------------------------------|-----|---------------------------|---|---|
| MEMOBUS/Modbus Communication <1> | R+ | Communications input (+) | MEMOBUS/Modbus communication: Use an RS-422 or RS-485 cable to connect the drive. | RS-422/RS-485 MEMOBUS/Modbus communication protocol 115.2 kbps (max.) |
| | R- | Communications input (-) | | |
| | S+ | Communications output (+) | | |
| | S- | Communications output (-) | | |
| | IG | Shield ground | 0 V | |

<1> Enable the termination resistor in the last drive in a MEMOBUS/Modbus network by setting DIP switch S2 to the ON position. Refer to the manual section on *Control I/O Connections* for more information.

Terminal Configuration

The control circuit terminals are arranged as shown in *Figure 3.31*.

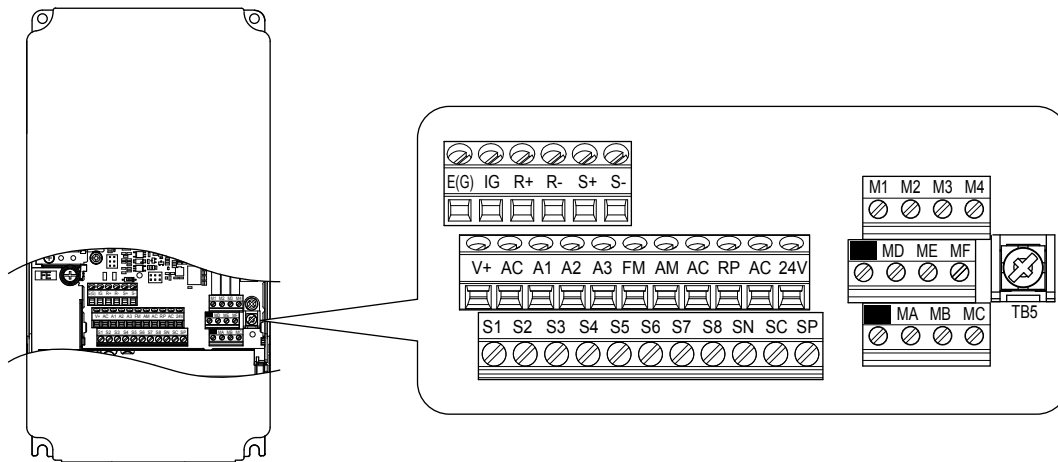


Figure 3.31 Control Circuit Terminal Arrangement

Wire Size and Torque Specifications

Select appropriate wire type and gauges from *Table 3.10*. For simpler and more reliable wiring, use crimp ferrules on the wire ends. Refer to *Table 3.11* for ferrule terminal types and sizes.

Table 3.10 Wire Gauges

| Terminal | Screw Size | Tightening Torque N·m (lb. in) | Bare Wire Terminal | | Ferrule-Type Terminal | | Wire Type |
|------------------------------|------------|--------------------------------|---|---|--|---|---------------------|
| | | | Applicable wire size mm ² (AWG) | Recomm. wire size mm ² (AWG) | Applicable wire size mm ² (AWG) | Recomm. wire size mm ² (AWG) | |
| S1-S8, SC, SN, SP | M3 | 0.5 to 0.6 (4.4 to 5.3) | Stranded wire: 0.2 to 1.0 (24 to 16) Solid wire: 0.2 to 1.5 (24 to 16) | 0.75 (18) | 0.25 to 0.5 (24 to 20) | 0.5 (20) | Shielded wire, etc. |
| RP, V+, A1, A2, A3, AC, 24 V | | | | | | | |
| MA, MB, MC, MD, ME, MF | | | | | | | |
| M1-M4 | | | | | | | |
| FM, AM, AC | | | | | | | |
| R+, R-, S+, S-, IG | | | | | | | |

3.9 Control Circuit Wiring

■ Ferrule-Type Wire Terminals

Yaskawa recommends using CRIMPFOX 6, a crimping tool manufactured by PHOENIX CONTACT, to prepare wire ends with insulated sleeves before connecting to the drive. See [Table 3.11](#) for dimensions.

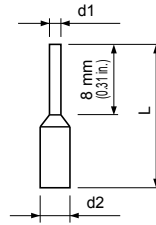


Figure 3.32 Ferrule Dimensions

Table 3.11 Ferrule Terminal Types and Sizes

| Size mm ² (AWG) | Type | L mm (in) | d1 mm (in) | d2 mm (in) | Manufacturer |
|----------------------------|--------------------------|-------------|------------|------------|-----------------|
| 0.25 (24) | AI 0.25-8YE | 12.5 (0.49) | 0.8 (0.03) | 2.0 (0.08) | PHOENIX CONTACT |
| 0.34 (22) | AI 0.34-8TQ | 12.5 (0.49) | 0.8 (0.03) | 2.0 (0.08) | |
| 0.5 (20) | AI 0.5-8WH AI 0.5-8OG | 14.0 (0.55) | 1.1 (0.04) | 2.5 (0.10) | |

◆ Wiring the Control Circuit Terminal

This section describes the proper procedures and preparations for wiring the control terminals.

WARNING! *Electrical Shock Hazard. Do not remove covers or touch the circuit boards while the power is on. Failure to comply could result in death or serious injury.*

NOTICE: *Separate control circuit wiring from main circuit wiring (terminals R/L1, S/L2, T/L3, B1, B2, U/T1, V/T2, W/T3, ϕ , ϕ 1, ϕ 2) and other high-power lines. Improper wiring practices could result in drive malfunction due to electrical interference.*

NOTICE: *Separate wiring for digital output terminals MA, MB, MC, MD, ME, MF and M1 to M4 from wiring to other control circuit lines. Improper wiring practices could result in drive or equipment malfunction or nuisance trips.*

NOTICE: *Use a class 2 power supply when connecting to the control terminals. Improper application of peripheral devices could result in drive performance degradation due to improper power supply. Refer to NEC Article 725 Class 1, Class 2, and Class 3 Remote-Control, Signaling, and Power Limited Circuits for requirements concerning class 2 power supplies.*

NOTICE: *Insulate shields with tape or shrink tubing to prevent contact with other signal lines and equipment. Improper wiring practices could result in drive or equipment malfunction due to short circuit.*

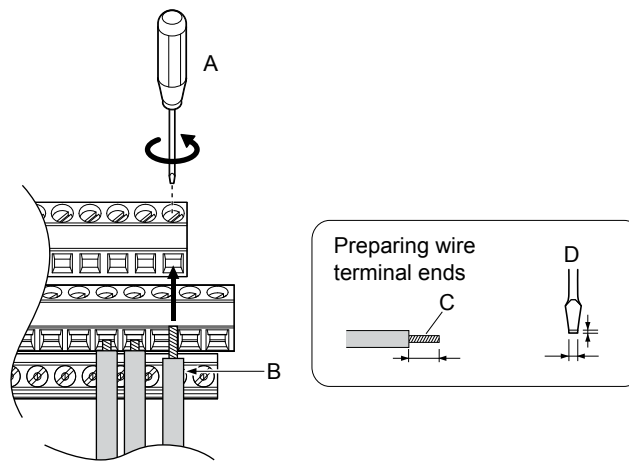
NOTICE: *Connect the shield of shielded cable to the appropriate ground terminal. Improper equipment grounding could result in drive or equipment malfunction or nuisance trips.*

NOTICE: *Do not tighten screws beyond the specified tightening torque. Failure to comply may result in erroneous operation, damage to the terminal block, or cause a fire.*

NOTICE: *Use shielded twisted-pair cables as indicated to prevent operating faults. Improper wiring practices could result in drive or equipment malfunction due to electrical interference.*

Wire the control circuit only after terminals have been properly grounded and main circuit wiring is complete. [Refer to Terminal Board Wiring Guide on page 99](#) for details. Prepare the ends of the control circuit wiring as shown in [Figure 3.35](#). [Refer to Wire Gauges on page 97](#).

Connect control wires as shown in [Figure 3.33](#) and [Figure 3.34](#).



A – Loosen screw to insert wire.
 B – Single wire or stranded wire

C – Avoid fraying wire strands when stripping insulation from wire. Strip length 5.5 mm.
 D – Blade depth of 0.4 mm or less
 Blade width of 2.5 mm or less

Figure 3.33 Terminal Board Wiring Guide

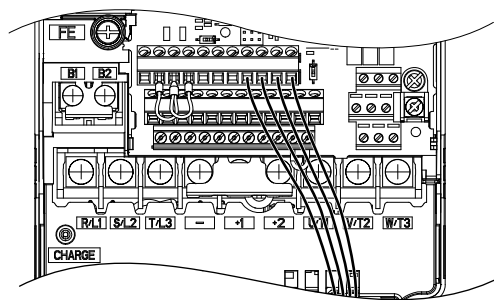
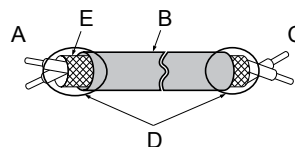


Figure 3.34 Terminal Board Location Inside the Drive

When setting the frequency by analog reference from an external potentiometer, use shielded twisted-pair wires (preparing wire ends as shown in [Figure 3.35](#)) and connect the shield to the ground terminal of the drive.



A – Drive side
 B – Insulation
 C – Control device side

D – Shield sheath (insulate with tape)
 E – Shield

Figure 3.35 Preparing the Ends of Shielded Cables

NOTICE: The analog signal wiring between the drive and the operator station or peripheral equipment should not exceed 50 meters when using an analog signal from a remote source to supply the frequency reference. Failure to comply could result in poor system performance.

◆ Switches and Jumpers on the Terminal Board

The terminal board is equipped with several switches used to adapt the drive I/Os to the external control signals. *Figure 3.36* shows the location of these switches. *Refer to Control I/O Connections on page 101* for setting instructions.

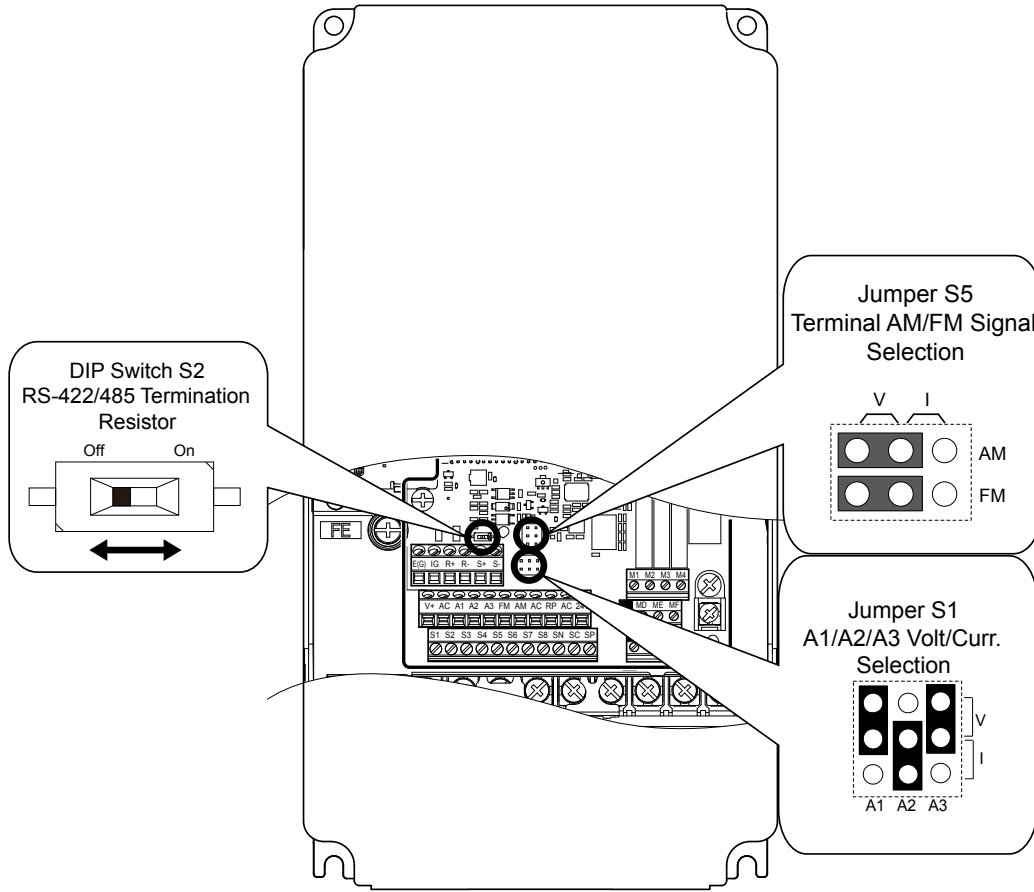


Figure 3.36 Locations of Jumpers and Switches on the Terminal Board

3.10 Control I/O Connections

◆ Sinking/Sourcing Mode for Digital Inputs

Use the wire jumper between terminals SC and SP or SC and SN to select between Sink mode, Source mode or external power supply for the digital inputs S1 to S8 as shown in [Table 3.12](#) (Default: Sink mode, internal power supply).

NOTICE: Do not short terminals SP and SN. Failure to comply will damage the drive.

Table 3.12 Digital Input Sink/Source/External Power Supply Selection

| Mode | Drive Internal Power Supply (Terminals SN and SP) | External 24 Vdc Power Supply |
|---------------------|---|------------------------------|
| Sinking Mode (NPN) | | |
| Sourcing Mode (PNP) | | |

◆ Terminals A1, A2, and A3 Input Signal Selection

Terminals A1, A2, and A3 can be used to input either a voltage or a current signal. Select the signal type using jumper S1 as explained in [Table 3.13](#). Set parameters H3-01, H3-05, and H3-09 accordingly as shown in [Table 3.14](#). Refer to [Switches and Jumpers on the Terminal Board on page 100](#) for locating jumper S1.

Note: If terminals A1 and A2 are both set for frequency bias (H3-02 = 0 and H3-10 = 0), both input values will be combined to create the frequency reference.

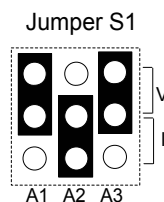


Figure 3.37 Terminal A2 Set to Current Input; A1 and A3 Set to Voltage Input

Table 3.13 Jumper S1 Settings

| Setting | Description |
|---------------------|---|
| V (top position) | Voltage input (-10 to +10 V or 0 to 10 V) |
| I (bottom position) | Current input (4 to 20 mA or 0 to 20 mA) |

3.10 Control I/O Connections

Table 3.14 Voltage/Current Selection Parameter Details

| No. | Parameter Name | Description | Setting Range | Default Setting |
|-------|------------------------------------|---|---------------|-----------------|
| H3-01 | Terminal A1 signal level selection | Selects the signal level for terminal A1. 0: 0 to 10 Vdc 1: 0 to 10 Vdc Bipolar 2: 4 to 20 mA 3: 0 to 20 mA | 0 to 3 | 0 |
| H3-05 | Terminal A3 signal level selection | Selects the signal level for terminal A3. 0: 0 to 10 Vdc 1: 0 to 10 Vdc Bipolar 2: 4 to 20 mA 3: 0 to 20 mA | 0 to 3 | 0 |
| H3-09 | Terminal A2 signal level selection | Selects the signal level for terminal A2. 0: 0 to 10 Vdc 1: 0 to 10 Vdc Bipolar 2: 4 to 20 mA 3: 0 to 20 mA | 0 to 3 | 2 |

◆ Terminal AM/FM Signal Selection

The signal type for terminals AM and FM can be set to either voltage or current output using jumper S5 on the terminal board as explained in [Table 3.15](#). When changing the setting of jumper S5, parameters H4-07 and H4-08 must be set accordingly. The default selection is voltage output for both terminals. *Refer to Switches and Jumpers on the Terminal Board on page 100* for locating jumper S5.

Table 3.15 Jumper S5 Settings





| Terminal | Voltage Output | Current Output |
|-------------|---|---|
| Terminal AM |  |  |
| Terminal FM |  |  |

Table 3.16 Parameter H4-07 and H4-08 Details

| No. | Parameter Name | Description | Setting Range | Default Setting |
|-------|------------------------------------|------------------------------------|---------------|-----------------|
| H4-07 | Terminal FM signal level selection | 0: 0 to 10 Vdc 1: -10 to 10 Vdc | 0 to 2 | 0 |
| H4-08 | Terminal AM signal level selection | 2: 4 to 20 mA | | |

◆ MEMOBUS/Modbus Termination

This drive is equipped with a built-in termination resistor for the RS-422/RS-485 communication port. DIP switch S2 enables or disabled the termination resistor as shown in [Table 3.17](#). The OFF position is the default. The termination resistor should be placed to the ON position when the drive is the last in a series of slave drives.

Refer to Switches and Jumpers on the Terminal Board on page 100 to locate switch S2.

Table 3.17 MEMOBUS/Modbus Switch Settings

| S2 Position | Description |
|-------------|---|
| ON | Internal termination resistor ON |
| OFF | Internal termination resistor OFF (default setting) |

Note: *Refer to MEMOBUS/Modbus Communications on page 505* for details on MEMOBUS/Modbus.

3.11 Connect to a PC

This drive is equipped with a USB port (type-B).

The drive can connect to a USB port on a PC using a USB 2.0, AB-type cable (sold separately). After connecting the drive to a PC, Yaskawa DriveWizard Industrial software can be used to monitor drive performance and manage parameter settings. Contact Yaskawa for more information on DriveWizard Industrial.

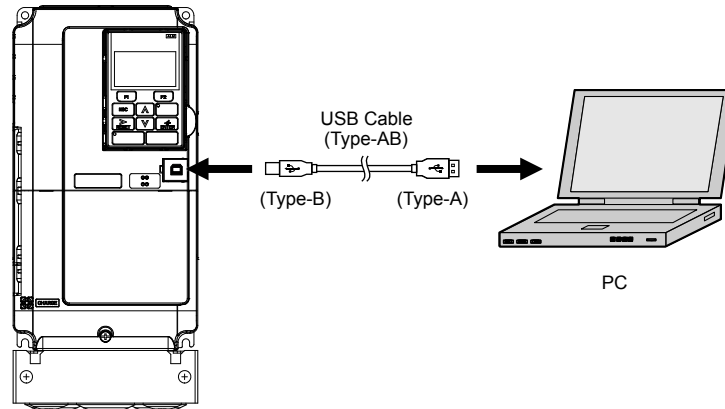


Figure 3.38 Connecting to a PC (USB)

3.12 External Interlock

Systems that may be affected during drive fault conditions should be interlocked with the drive fault output and ready signal.

◆ Drive Ready

When the “Drive ready” signal has been set to one of the multi-function contact outputs, that output will close whenever the drive is ready to accept a Run command or is already running.

The “Drive ready” signal switches off when operation is not possible for a Run command input under the following conditions regardless of whether a fault exists:

- when the power supply is shut off
- during a fault
- when there is problem with the control power supply
- when a parameter setting error makes the drive unable to run even if a Run command has been entered
- when a fault such as overvoltage or undervoltage is triggered as soon as the Run command is entered
- when the drive is in the Programming mode and will not accept a Run command even when entered

■ Interlock Circuit Example

Two drives running a single application might interlock with the controller using the Drive Ready and Fault output signals as shown below. *Figure 3.39* illustrates how the application would not be able to run if either drive experiences a fault or is unable to supply a Drive Ready signal.

| Terminal | Output Signal | Parameter Setting |
|------------|---------------|-------------------|
| MA, MB, MC | Fault | — |
| M1-M2 | Drive Ready | H2-01 = 06 |

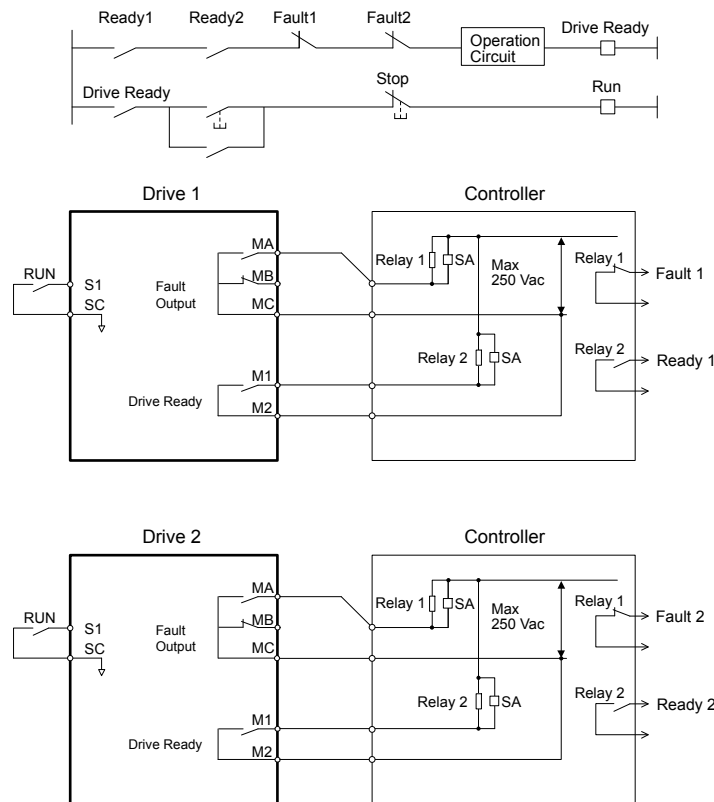
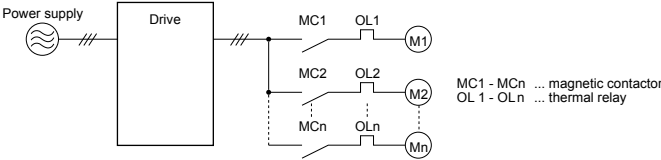


Figure 3.39 Interlock Circuit Example

3.13 Wiring Checklist

| <input checked="" type="checkbox"/> | No. | Item | Page(s) |
|---|-----|---|----------|
| Drive, Peripherals, Option Cards | | | |
| <input type="checkbox"/> | 1 | Check drive model number to ensure receipt of correct model. | 31 |
| <input type="checkbox"/> | 2 | Make sure you have the correct braking resistors, DC link chokes, noise filters, and other peripheral devices. | 376 |
| <input type="checkbox"/> | 3 | Check the option card model number. | 376 |
| Installation Area and Physical Setup | | | |
| <input type="checkbox"/> | 4 | Ensure that the area surrounding the drive complies with specifications. | 48 |
| Power Supply Voltage, Output Voltage | | | |
| <input type="checkbox"/> | 5 | The voltage from the power supply should be within the input voltage specification range of the drive. | 191 |
| <input type="checkbox"/> | 6 | The voltage rating for the motor should match the drive output specifications. | 31 |
| <input type="checkbox"/> | 7 | Verify that the drive is properly sized to run the motor. | 285 |
| Main Circuit Wiring | | | |
| <input type="checkbox"/> | 8 | Confirm proper branch circuit protection as specified by national and local codes. | 68 |
| <input type="checkbox"/> | 9 | Properly wire the power supply to drive terminals R/L1, S/L2, and T/L3. Note: Confirm the following when wiring models 4A0930 and 4A1200: <ul style="list-style-type: none"> Remove the jumpers shorting terminals R/L1-R1/L11, S/L2-S1/L21, and T/L3-T1/L31 when operating with 12-pulse rectification. <i>Refer to 12-Pulse Rectification on page 73</i> for details. When operating without 12-pulse rectification, properly wire terminals R1/L11, S1/L21, and T1/L31 in addition to terminals R/L1, S/L2, and T/L3. | 71 |
| <input type="checkbox"/> | 10 | Properly wire the drive and motor together. The motor lines and drive output terminals R/T1, V/T2, and W/T3 should match in order to produce the desired phase order. If the phase order is incorrect, the drive will rotate in the opposite direction. | 93 |
| <input type="checkbox"/> | 11 | Use 600 Vac vinyl-sheathed wire for the power supply and motor lines. | 85 |
| <input type="checkbox"/> | 12 | Use the correct wire gauges for the main circuit. <i>Refer to Main Circuit Wire Gauges and Tightening Torques on page 85.</i> <ul style="list-style-type: none"> Consider the amount of voltage drop when selecting wire gauges. Increase the wire gauge when the voltage drop is greater than 2% of motor rated voltage. Ensure the wire gauge is suitable for the terminal block. Use the following formula to calculate the amount of voltage drop: $\text{Line drop voltage (V)} = \sqrt{3} \times \text{wire resistance } (\Omega/\text{km}) \times \text{wire length (m)} \times \text{current (A)} \times 10^{-3}$ If the cable between the drive and motor exceeds 50 m, adjust the carrier frequency set to C6-02 accordingly. | 85 93 |
| <input type="checkbox"/> | 13 | Properly ground the drive. Review page 93. | 93 |
| <input type="checkbox"/> | 14 | Tighten control circuit and grounding terminal screws. <i>Refer to Main Circuit Wire Gauges and Tightening Torques on page 85.</i> | 85 |
| <input type="checkbox"/> | 15 | Set up overload protection circuits when running multiple motors from a single drive.  <p>Note: Close MC1 – MCn before operating the drive. MC1 – MCn cannot be switched off during run.</p> | – |
| <input type="checkbox"/> | 16 | Install a magnetic contactor when using a dynamic braking option. Properly install the resistor and ensure that overload protection shuts off the power supply using the magnetic contactor. | 382 |
| <input type="checkbox"/> | 17 | Verify phase advancing capacitors, input noise filters, or GFCIs are NOT installed on the output side of the drive. | – |
| Control Circuit Wiring | | | |
| <input type="checkbox"/> | 18 | Use twisted-pair line for all drive control circuit wiring. | 98 |
| <input type="checkbox"/> | 19 | Ground the shields of shielded wiring to the GND ⊕ terminal. | 98 |
| <input type="checkbox"/> | 20 | For 3-Wire sequence, set parameters for multi-function contact input terminals S1 – S8, and wire control circuits. | – |
| <input type="checkbox"/> | 21 | Properly wire any option cards. | 98 |
| <input type="checkbox"/> | 22 | Check for any other wiring mistakes. Only use a multimeter to check wiring. | – |
| <input type="checkbox"/> | 23 | Properly fasten drive control circuit terminal screws. <i>Refer to Main Circuit Wire Gauges and Tightening Torques on page 85.</i> | 85 |

3.13 Wiring Checklist

| <input checked="" type="checkbox"/> | No. | Item | Page(s) |
|-------------------------------------|-----|--|---------|
| <input type="checkbox"/> | 24 | Pick up all wire clippings. | – |
| <input type="checkbox"/> | 25 | Ensure that no frayed wires on the terminal block are touching other terminals or connections. | – |
| <input type="checkbox"/> | 26 | Properly separate control circuit wiring and main circuit wiring. | – |
| <input type="checkbox"/> | 27 | Analog signal line wiring should not exceed 50 m. | – |
| <input type="checkbox"/> | 28 | Safe Disable input wiring should not exceed 30 m. | – |

Start-Up Programming & Operation

This chapter explains the functions of the digital operator and how to program the drive for initial operation.

| | | |
|-------------|---|------------|
| 4.1 | SECTION SAFETY..... | 108 |
| 4.2 | USING THE DIGITAL OPERATOR..... | 109 |
| 4.3 | THE DRIVE, PROGRAMMING, AND CLOCK ADJUSTMENT MODES..... | 114 |
| 4.4 | START-UP FLOWCHART..... | 124 |
| 4.5 | POWERING UP THE DRIVE..... | 125 |
| 4.6 | APPLICATION SELECTION..... | 126 |
| 4.7 | AUTO-TUNING..... | 129 |
| 4.8 | NO-LOAD OPERATION TEST RUN..... | 134 |
| 4.9 | TEST RUN WITH LOAD CONNECTED..... | 136 |
| 4.10 | VERIFYING PARAMETER SETTINGS AND BACKING UP CHANGES..... | 137 |
| 4.11 | TEST RUN CHECKLIST..... | 139 |

4.1 Section Safety

DANGER

Electrical Shock Hazard

Do not connect or disconnect wiring while the power is on.

Failure to comply will result in death or serious injury.

WARNING

Electrical Shock Hazard

Do not operate equipment with covers removed.

Failure to comply could result in death or serious injury.

The diagrams in this section may include drives without covers or safety shields to illustrate details. Be sure to reinstall covers or shields before operating the drives and run the drives according to the instructions described in this manual.

Do not remove covers or touch circuit boards while the power is on.

Failure to comply could result in death or serious injury.

Prepare a separate holding brake.

Wire the holding brake so when a fault occurs, it is activated by an external sequence and shuts the power off or triggers an emergency switch. Failure to comply could result in death or serious injury.

4.2 Using the Digital Operator

Use the digital operator to enter Run and Stop commands, edit parameters, and display data including fault and alarm information.

◆ Digital Operator Keys and Displays

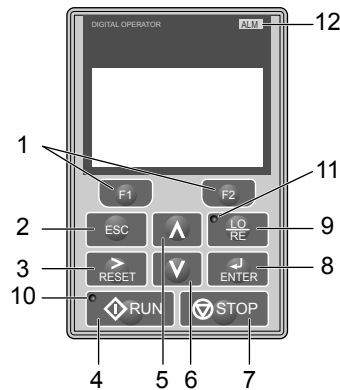


Figure 4.1 Keys and Displays on the Digital Operator

| No. | Display | Name | Function |
|-----|---------|-------------------------|---|
| 1 | | Function Key (F1, F2) | The functions assigned to F1 and F2 vary depending on the currently displayed menu. The name of each function appears in the lower half of the display window. |
| 2 | | ESC Key | <ul style="list-style-type: none"> Returns to the previous display. Moves the cursor one space to the left. Pressing and holding this button will return to the Frequency Reference display. |
| 3 | | RESET Key | <ul style="list-style-type: none"> Moves the cursor to the right. Resets the drive to clear a fault situation. |
| 4 | | RUN Key | Starts the drive in LOCAL mode. |
| 5 | | Up Arrow Key | Scrolls up to display the next item, selects parameter numbers, and increments setting values. |
| 6 | | Down Arrow Key | Scrolls down to display the previous item, selects parameter numbers, and decrements setting values. |
| 7 | | STOP Key <1> | Stops drive operation. |
| 8 | | ENTER Key | <ul style="list-style-type: none"> Enters parameter values and settings. Selects a menu item to move between displays |
| 9 | | LO/RE Selection Key <2> | Switches drive control and frequency setting between the operator (LOCAL) and an external source (REMOTE). |
| 10 | | RUN Light | Lit while the drive is operating the motor. Refer to page 111 for details. |
| 11 | | LO/RE Light | Lit while the operator is selected to run the drive (LOCAL mode). Refer to page 111 for details. |
| 12 | | ALM LED Light | Refer to ALARM (ALM) LED Displays on page 111. |

<1> The STOP key has highest priority. Pressing the STOP key will always cause the drive to stop the motor, even if a Run command is active at any external Run command source. To disable the STOP key priority, set parameter o2-02 to 0.

<2> The LO/RE key can only switch between LOCAL and REMOTE when the drive is stopped. To disable the LO/RE key to prohibit switching between LOCAL and REMOTE, set parameter o2-01 to 0.

◆ LCD Display

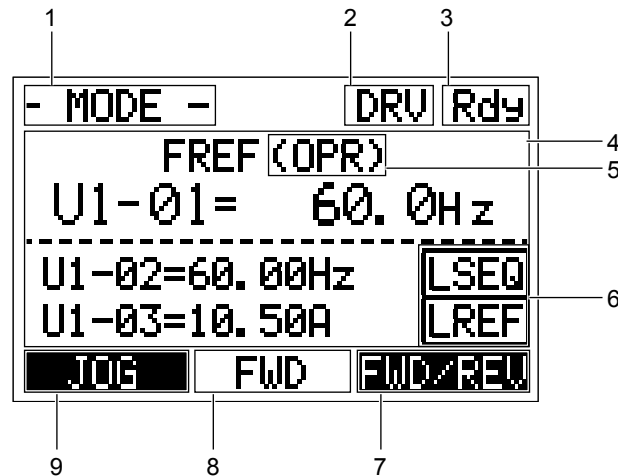











Figure 4.2 LCD Display

Table 4.1 Display and Contents




| No. | Name | Display | Content |
|-----|------------------------------------|---------|---|
| 1 | Operation Mode Menus | MODE | Displayed when in Mode Selection. |
| | | MONITR | Displayed when in Monitor Mode. |
| | | VERIFY | Indicates the Verify Menu. |
| | | PRMSET | Displayed when in Parameter Setting Mode. |
| | | A.TUNE | Displayed during Auto-Tuning. |
| | | SETUP | Displayed when in Setup Mode. |
| 2 | Mode Display Area | DRV | Displayed when in Drive Mode. |
| | | PRG | Displayed when in Programming Mode. |
| 3 | Ready | Rdy | Indicates the drive is ready to run. |
| 4 | Data Display | — | Displays specific data and operation data. |
| 5 | Frequency Reference Assignment </> | OPR | Displayed when the frequency reference is assigned to the LCD Operator Option. |
| | | AI | Displayed when the frequency reference is assigned to the Analog Input of the drive. |
| | | COM | Displayed when the frequency reference is assigned to the MEMOBUS/Modbus Communication Inputs of the drive. |
| | | OP | Displayed when the frequency reference is assigned to an Option Unit of the drive. |
| | | RP | Displayed when the frequency reference is assigned to the Pulse Train Input of the drive. |
| 6 | LO/RE Display <2> | RSEQ | Displayed when the run command is supplied from a remote source. |
| | | LSEQ | Displayed when the run command is supplied from the operator keypad. |
| | | RREF | Displayed when the run command is supplied from a remote source. |
| | | LREF | Displayed when the run command is supplied from the operator keypad. |
| 7 | Function Key 2 (F2) | FWD/REV | Pressing  switches between forward and reverse. |
| | | DATA | Pressing  scrolls to the next display. |
| | | → | Pressing  scrolls the cursor to the right. |
| | | RESET | Pressing  resets the existing drive fault error. |
| 8 | FWD/REV | FWD | Indicates forward motor operation. |
| | | REV | Indicates reverse motor operation. |

| No. | Name | Display | Content |
|-----|---------------------|---------|---|
| 9 | Function Key 1 (F1) | JOG | Pressing  executes the Jog function. |
| | | HELP | Pressing  displays the Help menu. |
| | | ← | Pressing  scrolls the cursor to the left. |
| | | HOME | Pressing  returns to the top menu (Frequency Reference). |
| | | ESC | Pressing  returns to the previous display. |

- <1> Displayed when in Frequency Reference Mode.
- <2> Displayed when in Frequency Reference Mode and Monitor Mode.







◆ ALARM (ALM) LED Displays

Table 4.2 ALARM (ALM) LED Status and Contents

| State | Content | Display |
|-------------|---|---|
| Illuminated | When the drive detects an alarm or error. |  |
| Flashing | <ul style="list-style-type: none"> • When an alarm occurs. • When an oPE is detected. • When a fault or error occurs during Auto-Tuning. |  |
| Off | Normal operation (no fault or alarm). |  |

◆ LO/RE LED and RUN LED Indications

Table 4.3 LO/RE LED and RUN LED Indications

| LED | Lit | Flashing <1> | Flashing Quickly <1> <2> | Off |
|---|---|--|---|--|
|  | When the operator is selected for Run command and frequency reference control (LOCAL) | — | — | When a device other than the operator is selected for Run command and frequency reference control (REMOTE) |
|  | During run | <ul style="list-style-type: none"> • During deceleration to stop • When a Run command is input and frequency reference is 0 Hz | <ul style="list-style-type: none"> • While the drive was set to LOCAL, a Run command was entered to the input terminals then the drive was switched to REMOTE. • A Run command was entered via the input terminals while the drive was not in Drive Mode. • During deceleration or stop when a Fast Stop command was entered. • The drive output is shut off by the Safe Disable function. • The STOP key was pressed while drive was running in REMOTE. • The drive was powered up with b1-17 = 0 (default) while the Run command is active. | During stop |
| Examples |  |  |  |  |

- <1> Refer to [Figure 4.3](#) for the difference between “flashing” and “flashing quickly”.
- <2> The drive cannot start operation.

4.2 Using the Digital Operator

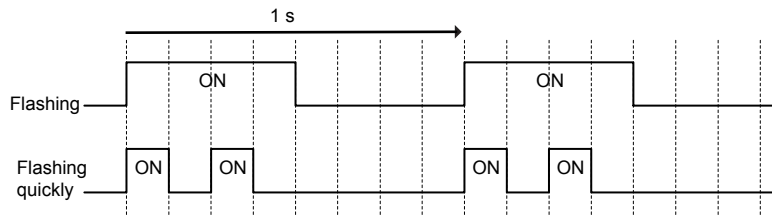


Figure 4.3 RUN LED Status and Meaning

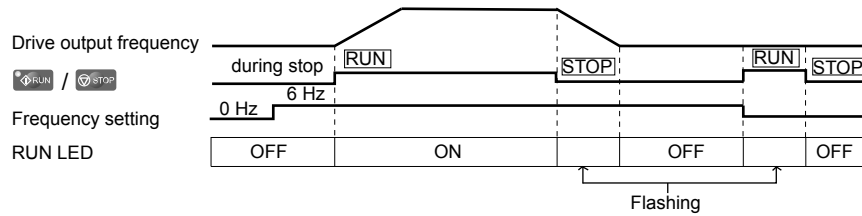


Figure 4.4 RUN LED and Drive Operation

◆ Menu Structure for Digital Operator

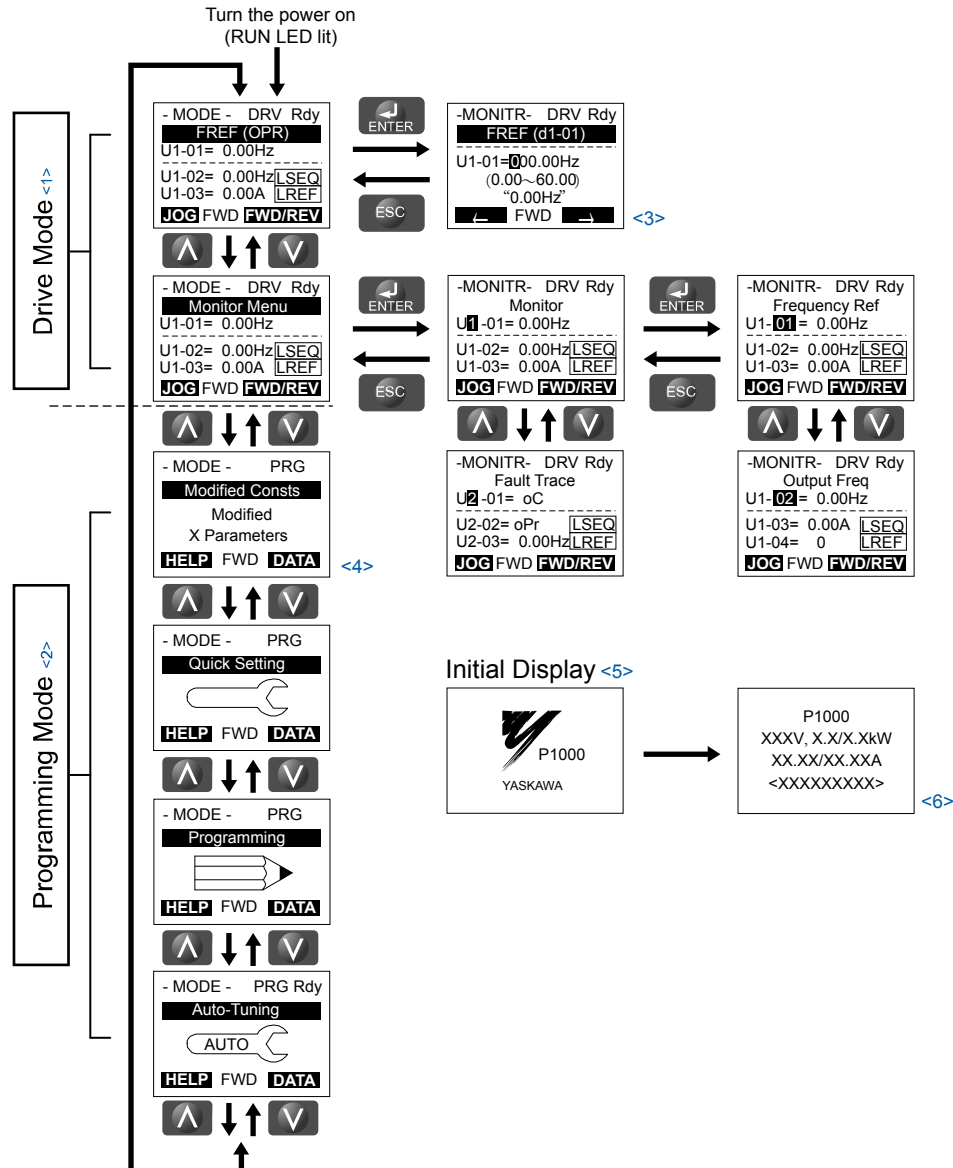



Figure 4.5 Digital Operator Menu and Screen Structure

- <1> Pressing  will start the motor.
- <2> Drive cannot operate motor.
- <3> Flashing characters are shown as **0**.
- <4> "X" characters are used as examples in this manual. The LCD Operator will display the actual setting values.
- <5> The Frequency Reference appears after the initial display that shows the product name.
- <6> The information that appears on the display will vary depending on the drive.

4.3 The Drive, Programming, and Clock Adjustment Modes

The drive has a Drive Mode to operate the motor, a Programming Mode to edit parameter settings, and a Clock Adjustment Mode to adjust the Real Time Clock.

Drive Mode: In Drive Mode the user can operate the motor and observe U Monitor parameters. Parameter settings cannot be edited or changed when in Drive Mode.

Programming Mode: In Programming Mode the user can edit and verify parameter settings and perform Auto-Tuning. When the drive is in Programming Mode it will not accept a Run command unless b1-08 is set to 1.

- Note:**
1. If b1-08 is set to 0, the drive will only accept a Run command in Drive Mode. After editing parameters, the user must exit the Programming Mode and enter Drive Mode before operating the motor.
 2. Set b1-08 to 1 to allow motor operation from the drive while in Programming Mode.

◆ Real-Time Clock (RTC)

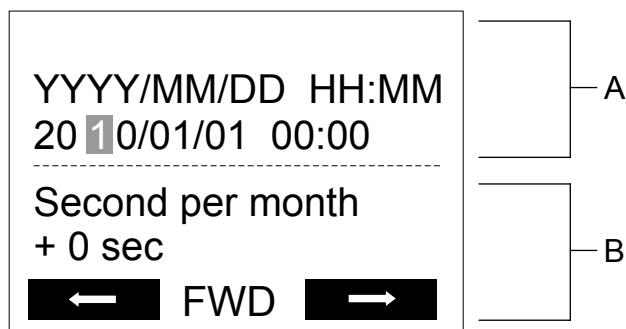
The drive has a Clock Adjustment Mode to set and adjust the Real-Time Clock.

Clock Adjustment Mode: When o4-17 is set to 1, the digital operator will show the Clock Adjustment display. In Clock Adjustment Mode, the user can adjust the Real-Time Clock. When the drive is in Clock Adjustment Mode, it will not accept a Run command.

◆ Clock Adjustment

The digital operator will display the Real Time Clock Adjustment Display in [Figure 4.6](#) when the drive is powered up for the first time. [Refer to Manual Clock Adjustment Procedure by Setting o4-17 to 1 on page 115](#) for the Real-Time Clock setting procedure.

Note: Setting the Real-Time Clock will clear a “TIM” alarm.



A – Real Time Clock Setting Display

B – Gain/Loss Adjustment Display

Figure 4.6 Real Time Clock Adjustment Display

| Display | Description |
|------------------|--|
| YYYY | Set the year with the last two digits. |
| MM | Set the month with two digits. |
| DD | Set the day with two digits. |
| HH:MM | Set the hours and minutes, with two digits for each. |
| Second per month | Set the gain or loss in seconds per month. |

Moving the Cursor

Pressing the F2 key or the RESET key will move the cursor to the digit on the right. Pressing the F1 key will move the cursor to the left.

Changing Settings

- **Changing YYYY/MM/DD HH:MM:** Pressing the up arrow key will increase the number selected by the cursor from 0 to 9. Pressing the down arrow key will decrease the number selected by the cursor from 0 to 9.
- **Setting the Seconds per Month:** Pressing the up arrow key will increase the number selected by the cursor from -504 to +488 in increments of 8. Pressing the down arrow key will decrease the number selected by the cursor from -504 to +488 in increments of 8.

Verifying the New Time Setting

After pressing ENTER , the display will indicate “Entry accepted” and the new time value will be saved to the Real-Time Clock (RTC).

If there is a problem with the entered time, the operator will indicate “Input error” and the screen will return to the time setting display.

Canceling the Input

Pressing the ESC key will display “Aborted” on the operator, and no value will be saved to the RTC. Pressing OFF will abort the setting process without any display, and no setting changes will be saved to the RTC.

Exiting from the Time Setting Screen Without Making Any Changes

If no changes are entered, the display will exit Real Time Clock Adjustment Display after a few seconds and no changes will be saved.

■ Real-Time Clock Setting at Initial Power-up of a New Drive

Setting the Real-time clock is required at power-up of a new drive or after keypad battery replacement.

Table 4.4 illustrates how to set the Real-Time Clock at initial power-up of a new drive.

Table 4.4 Clock Adjustment Procedure at Power-up of a New Drive

| Procedure | | Display |
|-----------|---|---------|
| 1 | Turn the power on. The Real Time Clock Adjustment Display will appear. Use the right arrow key to select the desired digit, then set the correct date and time using the up and down arrow keys. | |
| 2 | After entering the Real-Time Clock data, press the ENTER key to save the changes. The display will indicate “Entry Accepted” and return to the initial display in step 3 and the alarm LED will be OFF. | |
| 3 | Initial display. | |

■ Manual Clock Adjustment by Setting o4-17 to 1

The following actions are possible in the Clock Adjustment Mode:

- Set the current time
- Check the time set to the drive Real-Time Clock

Table 4.5 illustrates how to set the Real-Time Clock manually.

Table 4.5 Manual Clock Adjustment Procedure by Setting o4-17 to 1

| Procedure | | Display |
|-----------|--|---------|
| 1 | The “Time Not Set” (TIM) display will appear if the Real-Time Clock data is not entered within 30 seconds of power-up on a new drive. Refer to 308 for details on the TIM display. | |
| 2 | Use the up and down arrow keys to scroll through display menu until the screen shows “Programming”. | |

4.3 The Drive, Programming, and Clock Adjustment Modes

| Procedure | | Display |
|-----------|--|---------|
| 3 | Press the ENTER key to enter select the parameter setting mode. | |
| 4 | Use the up and down arrow keys to scroll through display menu until parameter o4-17 appears. | |
| 5 | Press the ENTER key until "0" flashes. | |
| 6 | Press the up arrow key so that the display changes to "1". | |
| 7 | Press the ENTER key and the time setting screen will appear. Use the right arrow key to select the desired digit, then set the correct date and time using the up and down arrow keys. | |
| 8 | After entering the correct time, press the ENTER key to save the changes. The display will return to the display shown in step 5 and the alarm LED will be OFF. | |

■ o4-17: Real-Time Clock Setting

| No. (Addr. Hex) | Name | Description | Values |
|-----------------|---------------------------------------|---|-----------------------------|
| o4-17 (3100) | Set/Reset Real-time Clock Set Time | Sets the current date and time for the Real-Time Clock. 0: — — No Setting ⁰ : — — 1: Real-Time Clock Set 1: Set 2: Real-Time Clock Reset ² : Reset | Default: 0 Range: 0 to 2 |

Setting 0: — —

No Setting (Default)



Setting 1: Set

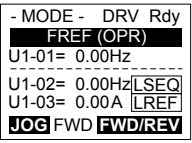
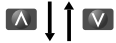
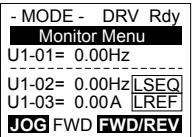
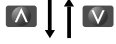
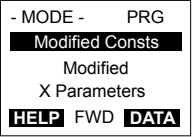
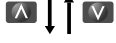
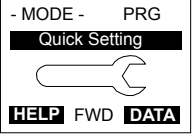
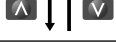
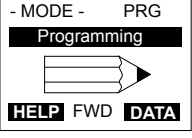

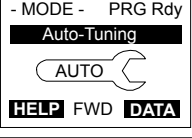

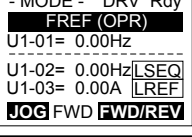
When o4-17 is set to 1, the digital operator will show the Clock Adjustment display. In Clock Adjustment Mode the user can adjust the Real-Time Clock.

Setting 2: Reset

When o4-17 is set to 2, the Real-Time Clock data is cleared. A TIM fault will occur until o4-17 is set to 1 and the Real-Time Clock is set.

◆ Navigating the Drive and Programming Modes

The drive is set to operate in Drive Mode when it is first powered up. Switch between display screens by using the  and  keys.

| Mode | Contents | Operator Display | Description |
|------------------|-------------------------------|---|---|
| Power Up | Frequency Reference (default) |  | <p>This display screen allows the user to monitor and change the frequency reference while the drive is running. <i>Refer to The Drive, Programming, and Clock Adjustment Modes on page 114.</i></p> <p>Note: Use parameter o1-02 to select the data displayed when the drive is first powered up. Setting parameter A1-02 to 6 or 7 (AOLV/PM or CLV/PM control) will change display units to percent.</p> |
| Drive Mode | |  | |
| | Monitor Display |  | <p>Lists the monitor parameters (U□-□□ parameters) available in the drive. Press the Enter Key and then use the Up, Down, ESC, and Reset keys to navigate through the drive monitors.</p> |
| Programming Mode | |  | |
| | Verify Menu |  | <p>Lists all parameters that have been edited or changed from default settings. → <i>Refer to Verifying Parameter Changes: Verify Menu on page 120.</i></p> |
| | |  | |
| | Setup Group |  | <p>A select list of parameters necessary to get the drive operating quickly. → <i>Refer to Using the Setup Groups on page 121.</i></p> <p>Note: Parameters listed in the Setup Group differ depending the Application Preset in parameter A1-06. <i>Refer to Application Selection on page 126.</i></p> |
| | |  | |
| | Parameter Setting Mode |  | <p>Allows the user to access and edit all parameter settings. → <i>Refer to Parameter List on page 431.</i></p> |
| | |  | |
| | Auto-Tuning Mode |  | <p>Motor parameters are calculated and set automatically. → <i>Refer to Auto-Tuning on page 129.</i></p> |
| | |  | |
| Drive Mode | Frequency Reference |  | <p>Returns to the frequency reference display screen.</p> |

■ Drive Mode Details

The following actions are possible in the Drive Mode:

- Run and stop the drive
- Monitor the operation status of the drive (frequency reference, output frequency, output current, output voltage, etc.)
- View information on an alarm
- View a history of alarms that have occurred

4.3 The Drive, Programming, and Clock Adjustment Modes

Figure 4.7 illustrates how to change the frequency reference from F 0.00 (0 Hz) to F 6.00 (6 Hz) while in the Drive Mode. This example assumes the drive is set to LOCAL.

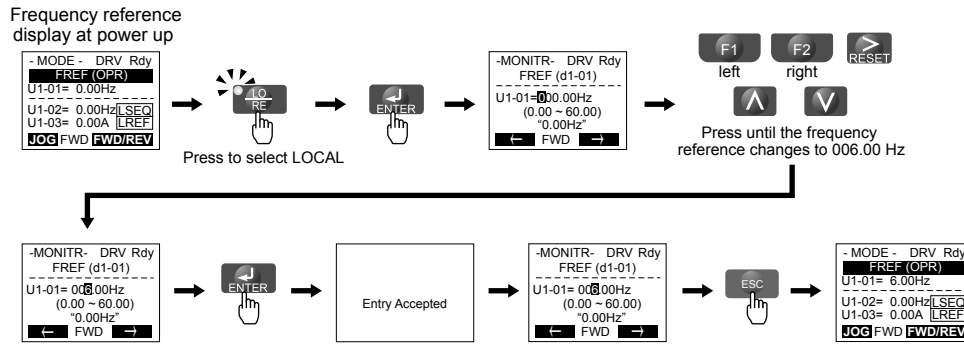


Figure 4.7 Setting the Frequency Reference while in the Drive Mode

Note: The drive will not accept a change to the frequency reference until the ENTER key is pressed after the frequency reference is entered. This feature prevents accidental setting of the frequency reference. To have the drive accept changes to the frequency reference as soon as changes are made without requiring the ENTER key, set o2-05 to 1.

■ Programming Mode Details

The following actions are possible in the Programming Mode:










- **Parameter Setting Mode:** Access and edit all parameter settings.
- **Verify Menu:** View a list of parameters that have been changed from the default values.
- **Setup Group:** Access a list of commonly used parameters to simplify setup (*Refer to Simplified Setup Using the Setup Groups on page 121*).
- **Auto-Tuning Mode:** Automatically calculate and set motor parameters to optimize drive performance.

◆ Changing Parameter Settings or Values

This example explains changing C1-02 (Deceleration Time 1) from 10.0 seconds (default) to 20.0 seconds.

| Step | | Display/Result |
|------|--|----------------|
| 1. | Turn on the power to the drive. The initial display appears. | |
| 2. | Press or until the Parameter Setting Mode screen appears. | |
| 3. | Press to enter the parameter menu tree. | |
| 4. | Press or to select the C parameter group. | |
| 5. | Press two times. | |

4.3 The Drive, Programming, and Clock Adjustment Modes

| Step | | | Display/Result |
|------|---|---|--|
| 6. | Press  or  to select parameter C1-02. | → | <pre> -PRMSET- PRG Decel Time 1 ----- C1-02= 10.0Sec (0.0-6000.0) "10.0 sec" ← FWD → </pre> |
| 7. | Press  to view the current setting value (10.0 s). The leftmost digit flashes. | → | <pre> -PRMSET- PRG Decel Time 1 ----- C1-02=<u>0</u>10.0Sec (0.0-6000.0) "10.0 sec" ← FWD → </pre> |
| 8. | Press  ,  , or  until the desired number is selected. "1" flashes. | → | <pre> -PRMSET- PRG Decel Time 1 ----- C1-02=<u>00</u>10.0Sec (0.0-6000.0) "10.0 sec" ← FWD → </pre> |
| 9. | Press  and enter 0020.0. | → | <pre> -PRMSET- PRG Decel Time 1 ----- C1-02=<u>00</u>20.0Sec (0.0-6000.0) "10.0 sec" ← FWD → </pre> |
| 10. | Press  to confirm the change. | → | <pre> Entry Accepted </pre> |
| 11. | The display automatically returns to the screen shown in Step 4. | → | <pre> -PRMSET- PRG Decel Time 1 ----- C1-02= 20.0Sec (0.0-6000.0) "10.0 sec" ← FWD → </pre> |
| 12. | Press  as many times as necessary to return to the initial display. | → | <pre> - MODE - DRV Rdy FREF (OPR) U1-01= 0.00Hz ----- U1-02= 0.00HzLSEQ U1-03= 0.00A LREF JOG FWD FWD/REV </pre> |







◆ Verifying Parameter Changes: Verify Menu

The Verify Menu lists edited parameters from the Programming Mode or as a result of Auto-Tuning. The Verify Menu helps determine which settings have been changed, and is particularly useful when replacing a drive. If no settings have been changed, the Verify Menu will read “None”. The Verify Menu also allows users to quickly access and re-edit any parameter settings that have been changed.

Note: The Verify Menu will not display parameters from the A1 group (except for A1-02) or E5-01 even if those parameters have been changed from their default settings.

The following example is a continuation of the steps above. Here, parameter C1-02 is accessed using the Verify Menu, and is changed again from 10.0 s to 20.0 s.

To check the list of edited parameters:

| Step | | | Display/Result |
|------|--|---|--|
| 1. | Turn on the power to the drive. The initial display appears. | → | <pre> - MODE - DRV Rdy FREF (OPR) U1-01= 0.00Hz ----- U1-02= 0.00Hz [SEQ] U1-03= 0.00A [LREF] JOG FWD FWD/REV </pre> |
| 2. | Press  or  until the display shows the top of the Verify Menu. | → | <pre> - MODE - PRG Modified Consts Modified X Parameters HELP FWD DATA </pre> |
| 3. | Press  to enter the list of parameters that have been edited from their original default settings. If parameters other than C1-02 have been changed, use  or  to scroll until C1-02 appears. | → | <pre> - VERIFY - PRG Rdy Accel Time 1 ----- C1-02 = 20.0sec (0.0-6000.0) *10.0sec Home FWD DATA </pre> |
| 4. | Press  to access the setting value. Left digit flashes. | → | <pre> - VERIFY - PRG Rdy Accel Time 1 ----- C1-01 = 020.0sec (0.0-6000.0) *10.0sec Home FWD DATA </pre> |

◆ Simplified Setup Using the Setup Groups

The Setup Groups list the basic parameters necessary to set up the drive for a given application. Setup groups expedite the startup process for an application by showing only the most important parameters for the application.

■ Using the Setup Groups

Figure 4.8 illustrates how to enter and how to change parameters in the Setup Group.

The default setting for the Setup Group is a group of parameters most commonly use in general-purpose applications. *Refer to Application Selection on page 126* to select an Application Preset and change the Setup Group to parameters optimal for the application selected. .

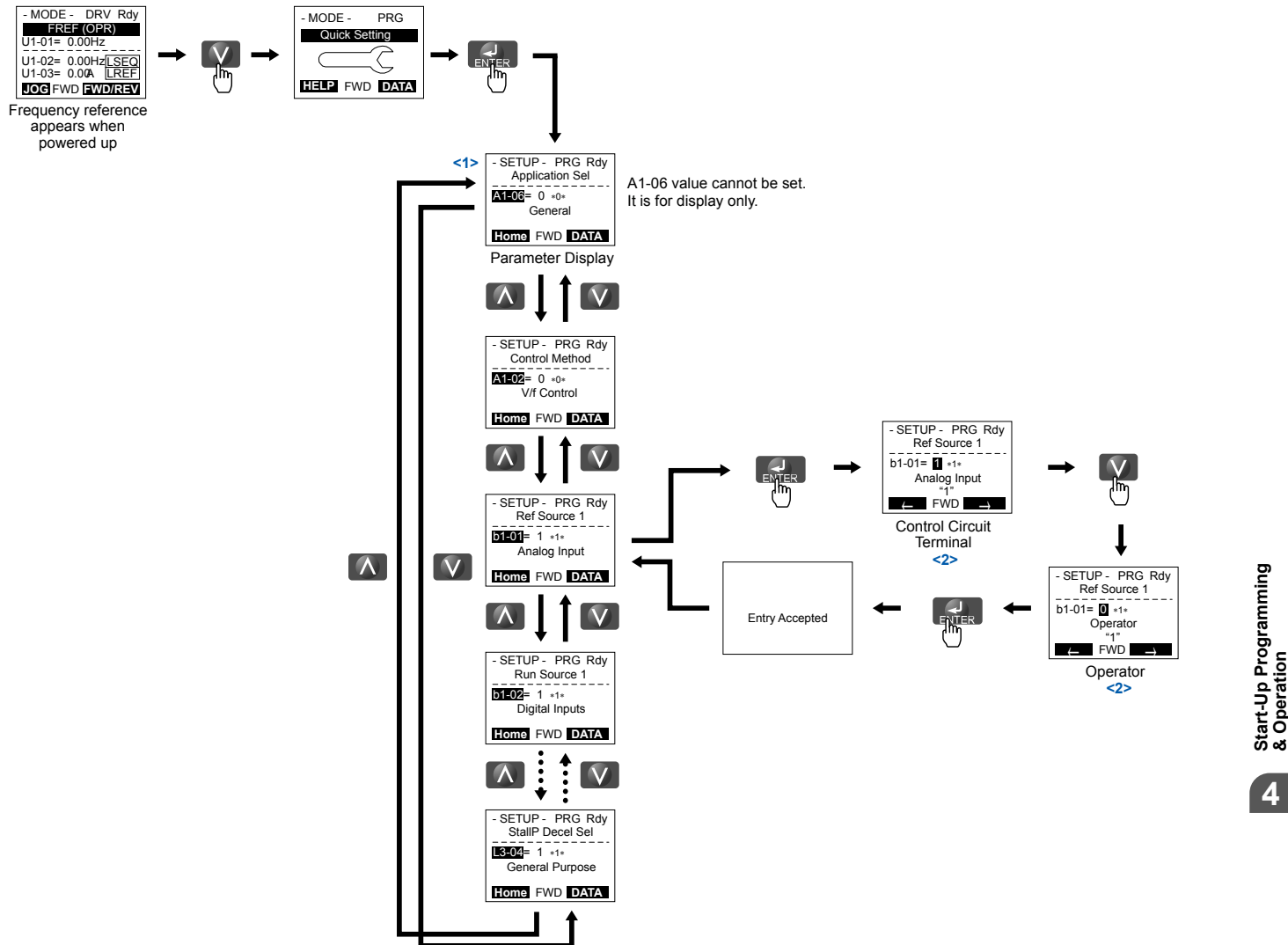


Figure 4.8 Setup Group Example

- <1> Use the up and down arrow keys to scroll through the Setup Group. Press the ENTER key to view or change parameter settings.
- <2> To return to the previous menu without saving changes, press the ESC key.

4.3 The Drive, Programming, and Clock Adjustment Modes

■ Setup Group Parameters

Table 4.6 lists the parameters available by default in the Setup Group. Selecting an Application Preset in through initialization in parameter A1-03 automatically changes the parameters selected for the Setup Group. *Refer to Application Selection on page 126* for details on parameters and default values for the fan and pump Setup Groups.

| No. | Parameter Name | Setting Range | Default |
|-------|-----------------------|---|---------|
| A1-03 | Initialize Parameters | 0, 1110, 2220, 3330, 5550, 8008, 8009, 8010, 8011 | 0 |

Setting 0: No initialization (default)

Setting 1110: User Initialize (parameter values must be stored using parameter o2-03)

Setting 2220: 2-Wire Initialize

Setting 3330: 3-Wire Initialize

Setting 5550: Terminal/Control Initialize

Setting 8008: Pump

Setting 8009: Pump w/ PI

Setting 8010: Fan

Setting 8011: Fan w/ PI

Use the Programming Mode to access parameters not displayed in the Setup Group.

Table 4.6 General Purpose Application Setup Group Parameters (A1-03 = 0)

| Parameter | Name | Parameter | Name |
|-----------|---|-----------|--|
| A1-06 | Application Preset Selection (Monitor only) | E2-01 | Motor Rated Current |
| b1-01 | Frequency Reference Selection 1 | L2-01 | Momentary Power Loss Operation Selection |
| b1-02 | Run Command Selection 1 | L5-01 | Number of Auto Restart Attempts |
| b1-03 | Stopping Method Selection | L6-01 | Torque Detection 1 Selection |
| b1-04 | Reverse Operation Selection | L6-02 | Torque Detection 1 Level |
| C1-01 | Acceleration Time 1 | L6-03 | Torque Detection 1 Time |
| C1-02 | Deceleration Time 1 | o1-06 | User Monitor Selection Mode |
| d1-01 | Frequency Reference 1 | o1-07 | Second Line Monitor Selection |
| d2-01 | Frequency Reference Upper Limit | o1-08 | Third Line Monitor Selection |
| d2-02 | Frequency Reference Lower Limit | | |

◆ Switching Between LOCAL and REMOTE

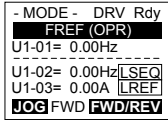





LOCAL mode is when the drive is set to accept the Run command from the digital operator RUN key. REMOTE mode is when the drive is set to accept the Run command from an external device (i.e., input terminals or serial communications).

WARNING! *Sudden Movement Hazard. The drive may start unexpectedly if the Run command is already applied when switching from LOCAL mode to REMOTE mode when b1-07 = 1, resulting in death or serious injury. Be sure all personnel are clear of rotating machinery.*

Switch the operation between LOCAL and REMOTE using the LO/RE key on the digital operator or via a digital input.

- Note:**
1. After selecting LOCAL, the LO/RE light will remain lit.
 2. The drive will not allow the user to switch between LOCAL and REMOTE during run.

■ Using the LO/RE Key on the Digital Operator

| Step | | Display/Result |
|------|--|--|
| 1. | Turn on the power to the drive. The initial display appears. |  |
| 2. | Press  . The LO/RE light will light up. The drive is now in LOCAL. To set the drive for REMOTE operation, press the  key again. |   →  |

■ Using Input Terminals S1 through S8 to Switch between LOCAL and REMOTE

It is possible to switch between LOCAL and REMOTE modes using one of the digital input terminals S1 through S8 (set the corresponding parameter H1-□□ to “1”).

Setting H1-□□ to 1 disables the LO/RE key on the digital operator. *Refer to H1: Multi-Function Digital Inputs on page 205* for details.

4.4 Start-Up Flowchart

Figure 4.9 summarizes steps required to start the drive and gives quick references to help familiarize the user with start-up procedures.

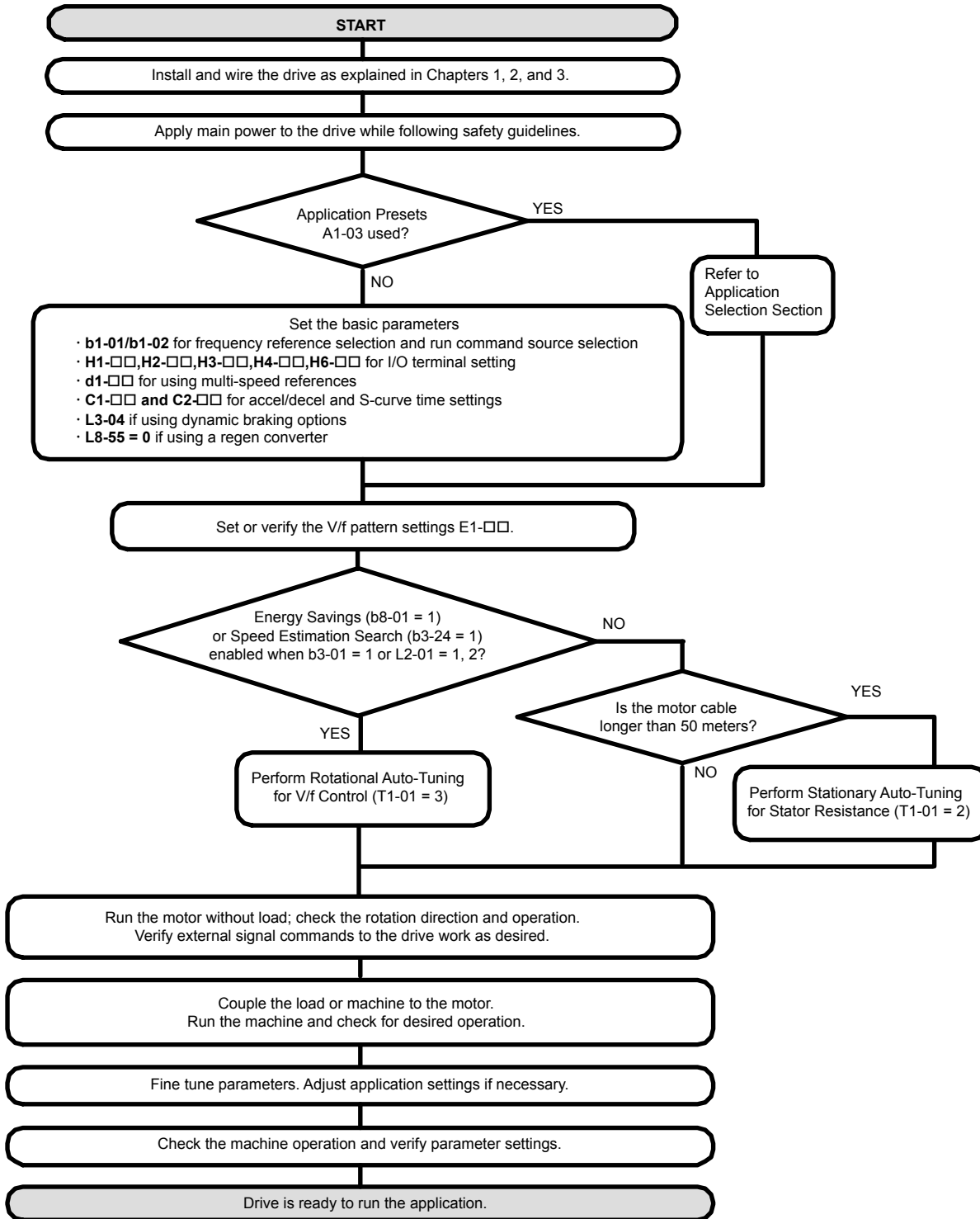


Figure 4.9 Simple Setup with Energy Savings or Speed Search

- Note:**
1. Execute Stationary Auto-Tuning for Line-to-Line Resistance if the drive has been Auto-Tuned and then moved to a different location where the motor cable length exceeds 50 m.
 2. Perform Auto-Tuning again after installing an AC reactor or other such components to the output side of the drive.

4.5 Powering Up the Drive

◆ Powering Up the Drive and Operation Status Display

■ Powering Up the Drive

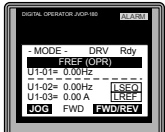

Review the following checklist before turning the power on.

| Item to Check | Description |
|--|--|
| Power supply voltage | 200 V class: Three-phase 200 to 240 Vac 50/60 Hz 400 V class: Three-phase 380 to 480 Vac 50/60 Hz 600 V class: Three-phase 500 to 600 Vac 50/60 Hz |
| | Properly wire the power supply input terminals (R/L1, S/L2, T/L3). <1> |
| | Check for proper grounding of drive and motor. |
| Drive output terminals and motor terminals | Properly wire drive output terminals U/T1, V/T2, and W/T3 with motor terminals U, V, and W. |
| Control circuit terminals | Check control circuit terminal connections. |
| Drive control terminal status | Open all control circuit terminals (off). |
| Status of the load and connected machinery | Decouple the motor from the load. |

<1> Confirm the following when connecting models 4A0930 and 4A1200: Remove the jumpers on R1/L11, S1/L21, and T1/L31 when using 12-pulse rectification. [Refer to 12-Pulse Rectification on page 73](#) for details. When operating without 12-pulse rectification, properly wire terminals R1/L11, S1/L21, and T1/L31 in addition to terminals R/L1, S/L2, and T/L3.

■ Status Display

When the power supply to the drive is turned on, the digital operator lights will appear as follows:

| Status | Name | Description |
|------------------|---|--|
| Normal Operation |  | The data display area displays the frequency reference. [DRV] is lit. |
| Fault |  External fault (example) | Data displayed varies by the type of fault. Refer to Fault Displays, Causes, and Possible Solutions on page 295 for more information. [ALM] and [DRV] are lit. |

4.6 Application Selection

Application Presets are available to facilitate drive setup for commonly used applications. Selecting one of these Application Presets automatically assigns functions to the input and output terminals and sets a predefined group of parameters to values appropriate for the selected application.

In addition, the parameters most likely to be changed are assigned to the group of User Parameters, A2-01 through A2-16. User Parameters are part of the Setup Group, which provides quicker access by eliminating the need to scroll through multiple menus.

- Note:**
1. Application Presets can only be selected if all drive parameters are at their original default settings.
 2. Entering a value to A1-03 to enable an Application Preset will fix that value to the parameter. The value cannot be changed without first setting A1-03 to 2220 or 3330 to initialize the drive.

WARNING! Sudden Movement Hazard. Confirm the drive I/O signals and external sequence before performing a test run. Setting parameter A1-03 may automatically change the I/O terminal function from the default setting. Failure to comply may result in death or serious injury.

| No. | Parameter Name | Settings | Default |
|-------|------------------------------------|--|---------|
| A1-03 | Initialize Parameters | 0: No initialization (default) 1110: User Initialize (parameter values must be stored using parameter o2-03) 2220: 2-Wire Initialize 3330: 3-Wire Initialize 5550: Terminal/Control Initialize 8008: Pump 8009: Pump w/ PI 8010: Fan 8011: Fan w/ PI | 0 |
| A1-06 | Application Presets (monitor only) | 0: Disabled 8: Pump 9: Pump w/ PI 10: Fan 11: Fan w/ PI | 0 |

◆ A1-03 = 8008: Pump

Table 4.7 Pump Application Parameters

| Parameter | Name | Page |
|-----------|---|---------------------|
| A1-06 | Application Preset Selection (monitor only) | 126 |
| b1-01 | Frequency Reference Selection | 147 |
| b1-02 | Run Command Selection | 148 |
| b1-03 | Stopping Method Selection | 149 |
| b1-04 | Reverse Operation Selection | 151 |
| C1-01 | Acceleration Time 1 | 177 |
| C1-02 | Deceleration Time 1 | 177 |
| d1-01 | Frequency Reference 1 | 182 |
| E2-01 | Motor Rated Current | 195 |
| L2-01 | Momentary Power Loss Operation Selection | 240 |
| L5-01 | Number of Auto Restart Attempts | 254 |
| L5-04 | Fault Reset Interval Time | 255 |
| o1-06 | User Monitor Selection Mode | 268 |
| o1-07 | Second Line Monitor Selection | 268 |
| o1-08 | Third Line Monitor Selection | 268 |

◆ A1-03 = 8009: Pump w/ PI

Table 4.8 Pump w/ PI Application Parameters

| Parameter | Name | Page |
|-----------|---|---------------------|
| A1-06 | Application Preset Selection (monitor only) | 126 |
| b1-02 | Run Command Selection | 148 |

| Parameter | Name | Page |
|-----------|------------------------------------|------|
| b1-03 | Stopping Method Selection | 149 |
| b1-04 | Reverse Operation Selection | 151 |
| b5-19 | PID Setpoint Value | 168 |
| b5-38 | PID Setpoint User Display | 170 |
| b5-39 | PID Setpoint Display Digits | 170 |
| b5-46 | PID Unit Selection | 170 |
| b5-90 | EZ Sleep Unit | 171 |
| b5-91 | EZ Minimum Speed | 171 |
| b5-92 | EZ Sleep Level | 171 |
| b5-94 | EZ Wake-up Level | 171 |
| C1-01 | Acceleration Time 1 | 177 |
| C1-02 | Deceleration Time 1 | 177 |
| E2-01 | Motor Rated Current | 195 |
| H3-09 | Terminal A2 Signal Level Selection | 226 |
| L5-01 | Number of Auto Restart Attempts | 254 |
| L5-04 | Fault Reset Interval Time | 255 |
| o1-07 | Second Line Monitor Selection | 268 |
| o1-08 | Third Line Monitor Selection | 268 |

◆ A1-03 = 8010: Fan

Table 4.9 Fan Application Parameters

| Parameter | Name | Page |
|-----------|---|------|
| A1-06 | Application Preset Selection (monitor only) | 126 |
| b1-01 | Frequency Reference Selection | 147 |
| b1-02 | Run Command Selection | 148 |
| b1-03 | Stopping Method Selection | 149 |
| b1-04 | Reverse Operation Selection | 151 |
| C1-01 | Acceleration Time 1 | 177 |
| C1-02 | Deceleration Time 1 | 177 |
| d1-01 | Frequency Reference 1 | 182 |
| d2-01 | Frequency Reference Upper Limit | 184 |
| d2-02 | Frequency Reference Lower Limit | 184 |
| E2-01 | Motor Rated Current | 195 |
| L5-01 | Number of Auto Restart Attempts | 254 |
| L5-04 | Fault Reset Interval Time | 255 |
| o1-06 | User Monitor Selection Mode | 268 |
| o1-07 | Second Line Monitor Selection | 268 |
| o1-08 | Third Line Monitor Selection | 268 |

◆ A1-03 = 8011: Fan w/ PI

Table 4.10 Fan Application Parameters

| Parameter | Name | Page |
|-----------|---|------|
| A1-06 | Application Preset Selection (monitor only) | 126 |
| b1-02 | Run Command Selection | 148 |
| b1-03 | Stopping Method Selection | 149 |
| b1-04 | Reverse Operation Selection | 151 |
| b5-12 | PI Feedback Loss Detection Selection | 166 |
| b5-19 | PID Setpoint Value | 168 |
| b5-38 | PID Setpoint User Display | 170 |

4.6 Application Selection

| Parameter | Name | Page |
|-----------|------------------------------------|------|
| b5-39 | PID Setpoint Display Digits | 170 |
| b5-46 | PID Unit Selection | 170 |
| b5-90 | EZ Sleep Unit | 171 |
| b5-91 | EZ Minimum Speed | 171 |
| b5-92 | EZ Sleep Level | 171 |
| b5-94 | EZ Wake-up Level | 171 |
| C1-01 | Acceleration Time 1 | 177 |
| C1-02 | Deceleration Time 1 | 177 |
| E2-01 | Motor Rated Current | 195 |
| H3-09 | Terminal A2 Signal Level Selection | 226 |
| L5-01 | Number of Auto Restart Attempts | 254 |
| L5-04 | Fault Reset Interval Time | 255 |
| o1-07 | Second Line Monitor Selection | 268 |
| o1-08 | Third Line Monitor Selection | 268 |

◆ Default Values for Fan and Pump Applications

Table 4.11 Fan and Pump Application Defaults

| Parameter | A1-03 Setting | | | |
|-----------|-------------------|-----------------------|---------------------|-----------------------|
| | 8008 | 8009 | 8010 | 8011 |
| A1-02 | 0: V/f Control | 0: V/f Control | 0: V/f Control | 0: V/f Control |
| b1-04 | – | – | 1: Reverse Disabled | 1: Reverse Disabled |
| b3-05 | – | – | 10.0 s | 10.0 s |
| b5-01 | – | 1: PID Enabled | – | 1: PID Enabled |
| b5-03 | – | – | – | 5.0 s |
| b5-08 | – | – | – | 2.00 s |
| b5-13 | – | – | – | 2% |
| b5-14 | – | – | – | 25.0 s |
| b5-18 | – | 1: Enabled (b5-19) | – | 1: Enabled (b5-19) |
| b5-20 | – | 3: User Set | – | 3: User Set |
| b5-46 | – | – | – | 1: PSI |
| b5-89 | – | 1: EZ Sleep/Wake Up | – | 1: EZ Sleep/Wake Up |
| C1-01 | – | – | 90.0 s | 60.0 s |
| C1-02 | – | – | 90.0 s | 60.0 s |
| C2-01 | – | – | 5.00 s | 5.00 s |
| C2-02 | – | – | 5.00 s | 5.00 s |
| C2-03 | – | – | 5.00 s | 5.00 s |
| C2-04 | – | – | 5.00 s | 5.00 s |
| H3-10 | – | B: PID Feedback | – | B: PID Feedback |
| L2-01 | 2: CPU Active | 2: CPU Active | 2: CPU Active | 2: CPU Active |
| L3-02 | – | – | 110% | 110% |
| L3-06 | – | – | 100% | 100% |
| L4-05 | – | – | 0: Stop | – |
| L5-04 | – | – | 180.0 s | 180.0 s |
| L5-05 | 1: L5-04 Interval | 1: L5-04 Interval | 1: L5-04 Interval | 1: L5-04 Interval |
| o1-06 | – | 1: Selectable | – | 1: Selectable |
| o1-07 | – | 102: Output Frequency | – | 102: Output Frequency |
| o1-08 | – | 501: Feedback | – | 501: Feedback |

4.7 Auto-Tuning

◆ Types of Auto-Tuning

The drive offers different types of Auto-Tuning for induction motors. Refer to the tables below to select the type of Auto-Tuning that best suits the application. [Refer to Start-Up Flowchart on page 124](#) for directions on executing Auto-Tuning.

■ Auto-Tuning for Induction Motors

This feature automatically sets the V/f pattern and motor parameters E1-□□ and E2-□□ for an induction motor.

Table 4.12 Types of Auto-Tuning for Induction Motors

| Type | Setting | Application Conditions and Benefits |
|--|-----------|---|
| Stationary Auto-Tuning for Line-to-Line Resistance | T1-01 = 2 | <ul style="list-style-type: none"> The drive is used in V/f Control and other Auto-Tuning selections are not possible. Perform when entering motor data manually while using motor cables longer than 50 m. Drive and motor capacities differ. Tunes the drive after the cable between the drive and motor has been replaced with a cable over 50 m long. Assumes Auto-Tuning has already been performed. |
| Rotational Auto-Tuning for V/f Control | T1-01 = 3 | <ul style="list-style-type: none"> Recommended for applications using Speed Estimation Speed Search or using the Energy Saving function in V/f Control. Assumes motor can rotate while Auto-Tuning is executed. Increases accuracy for certain functions like torque compensation, slip compensation, Energy Saving, and Speed Search. |

[Table 4.13](#) lists the data that must be entered for Auto-Tuning. Make sure this data is available before starting Auto-Tuning. The necessary information is usually listed on the motor nameplate or in the motor test report provided by the motor manufacturer. [Refer to Start-Up Flowchart on page 124](#) for details on the Auto-Tuning process.

Table 4.13 Auto-Tuning Input Data

| Input Value | Input Parameter | Unit | Tuning Type (T1-01) | |
|-----------------------|-----------------|-------|------------------------------|---------------------------------|
| | | | 2 Line-to-Line Resistance | 3 Rotational for V/f Control |
| Motor rated power | T1-02 | kW | YES | YES |
| Motor rated voltage | T1-03 | Vac | – | YES |
| Motor rated current | T1-04 | A | YES | YES |
| Motor rated frequency | T1-05 | Hz | – | YES |
| Number of motor poles | T1-06 | - | – | YES |
| Motor rated Speed | T1-07 | r/min | – | YES |
| Motor iron loss | T1-11 | W | – | YES |

◆ Before Auto-Tuning the Drive

Check the items below before Auto-Tuning the drive.

■ Basic Auto-Tuning Preparations

- Auto-Tuning requires the user to input data from the motor nameplate or motor test report. Make sure this data is available before Auto-Tuning the drive.
- For best performance, the drive input supply voltage must be at least equal to or greater than the motor rated voltage.

Note: Better performance is possible when using a motor with a base voltage that is lower than the input supply voltage (20 V for 200 V class models, 40 V for 400 V class models, and 60 V for 600 V class models). This is particularly important when operating the motor above 90% of base speed, where high torque precision is required.
- To cancel Auto-Tuning, press the STOP key on the digital operator.
- When using a motor contactor, make sure it is closed throughout the Auto-Tuning process.

[Table 4.14](#) describes digital input and output terminal operation while Auto-Tuning is executed.

4.7 Auto-Tuning

Table 4.14 Auto-Tuning Input Data

| Motor Type | Auto-Tuning Type | Digital Input | Digital Output |
|------------|--|---------------------------------------|---|
| IM Motor | Stationary Auto-Tuning for Line-to-Line Resistance | Digital input functions are disabled. | Digital output functions are disabled. |
| | Rotational Auto-Tuning for V/f Control | | Functions the same as during normal operation |

■ Notes on Rotational Auto-Tuning

- Decouple the load from the motor to achieve optimal performance from Rotational Auto-Tuning. Rotational Auto-Tuning is best suited for applications requiring high performance over a wide speed range.
- If it is not possible to decouple the motor and load, reduce the load so it is less than 30% of the rated load. Performing Rotational Auto-Tuning with a higher load will set motor parameters incorrectly, and can cause irregular motor rotation.
- Ensure the motor-mounted brake is fully released, if installed.
- Connected machinery should be allowed to rotate the motor.

■ Notes on Stationary Auto-Tuning

Stationary Auto-Tuning modes analyze motor characteristics by injecting current into the motor for approximately one minute.

WARNING! Electrical Shock Hazard. When executing stationary Auto-Tuning, voltage is applied to the motor before the motor rotates. Do not touch the motor until Auto-Tuning is completed. Failure to comply may result in injury or death from electrical shock.

WARNING! Sudden Movement Hazard. If installed, do not release the mechanical brake during Stationary Auto-Tuning. Inadvertent brake release may cause damage to equipment or injury to personnel. Ensure that the mechanical brake release circuit is not controlled by the drive multi-function digital outputs.

◆ Auto-Tuning Interruption and Fault Codes

If tuning results are abnormal or the STOP key is pressed before completion, Auto-Tuning will be interrupted and a fault code will appear on the digital operator.

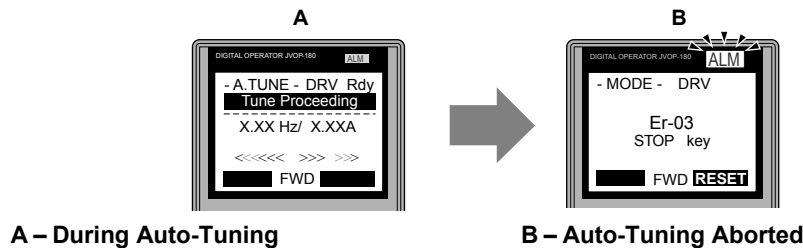



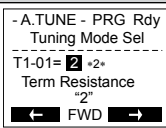

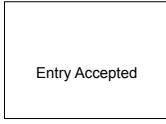
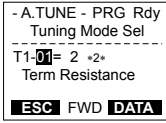
Figure 4.10 Auto-Tuning Aborted Display

◆ Auto-Tuning Operation Example

The following example demonstrates Stationary Auto-Tuning for Line-to-Line Resistance.

■ Selecting the Type of Auto-Tuning


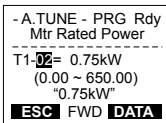

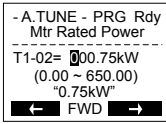





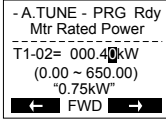

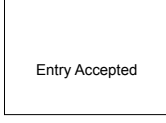
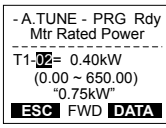
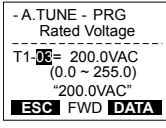

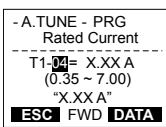
| Step | Display/Result |
|---|---|
| 1. Turn on the power to the drive. The initial display appears. | <pre> - MODE - DRV Rdy FREF (OPR) U1-01= 0.00Hz U1-02= 0.00Hz LSEQ U1-03= 0.00A LREF JOG FWD FWD/REV </pre> |
| 2. Press or until the Auto-Tuning display appears. | <pre> - MODE - PRG Auto-Tuning AUTO HELP FWD DATA </pre> |
| 3. Press to begin setting parameters. | <pre> - A.TUNE - PRG Rdy Tuning Mode Sel T1-01= 2 *2* Term Resistance ESC FWD DATA </pre> |

| Step | | | Display/Result |
|------|---|---|---|
| 4. | Press  to display the value for T1-01. | → |  |
| 5. | Save the setting by pressing  . | → |  |
| 6. | The display automatically returns to the display shown in Step 3. | → |  |

■ Enter Data from the Motor Nameplate

After selecting the type of Auto-Tuning, enter the data required from the motor nameplate.

Note: These instructions continue from Step 6 in “Selecting the Type of Auto-Tuning”.

| Step | | | Display/Result |
|------|---|---|---|
| 1. | Press  to access the motor output power parameter T1-02. | → |  |
| 2. | Press  to view the default setting. | → |  |
| 3. | Press  left,  right,  ,  , and  to enter the motor power nameplate data in kW. | → |  |
| 4. | Press  to save the setting. | → |  |
| 5. | The display automatically returns to the display in Step 1. | → |  |
| 6. | Repeat Steps 1 through 5 to set the following parameters: <ul style="list-style-type: none"> • T1-03, Motor Rated Voltage (Rotational Auto-Tuning for V/f Control only) • T1-04, Motor Rated Current • T1-05, Motor Base Frequency (Rotational Auto-Tuning for V/f Control only) • T1-06, Number of Motor Poles (Rotational Auto-Tuning for V/f Control only) • T1-07, Motor Base Frequency (Rotational Auto-Tuning for V/f Control only) | → |    |


4.7 Auto-Tuning

■ Starting Auto-Tuning


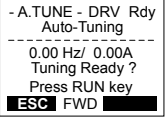

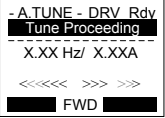
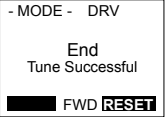
WARNING! Sudden Movement Hazard. The drive and motor may start unexpectedly during Auto-Tuning, which could result in death or serious injury. Ensure the area surrounding the drive motor and load are clear before proceeding with Auto-Tuning.

WARNING! Electrical Shock Hazard. High voltage will be supplied to the motor when Stationary Auto-Tuning is performed even with the motor stopped, which could result in death or serious injury. Do not touch the motor until Auto-Tuning has been completed.

NOTICE: Rotational Auto-Tuning will not function properly if a holding brake is engaged on the load. Failure to comply could result in improper operation of the drive. Ensure the motor can freely spin before beginning Auto-Tuning.

Enter the required information from the motor nameplate. Press  to proceed to the Auto-Tuning start display.

Note: These instructions continue from Step 6 in “Enter Data from the Motor Nameplate”.

| Step | | | Display/Result |
|------|---|---|---|
| 1. | After entering the data listed on the motor nameplate, press  to confirm. | → |  |
| 2. | Press  to activate Auto-Tuning. DRV flashes. The drive begins by injecting current into the motor for about 1 min, and then starts to rotate the motor. Note: The first digit on the display indicates which motor is undergoing Auto-Tuning. The second digit indicates the type of Auto-Tuning being performed. | → |  |
| 3. | Auto-Tuning finishes in approximately one to two minutes. | → |  |

◆ T1: Parameter Settings during Induction Motor Auto-Tuning

The T1-□□ parameters set the Auto-Tuning input data for induction motor tuning.

Note: For motors operating in the field weakening range, first perform the Auto-Tuning with the base data. After Auto-Tuning is complete, change E1-04, Maximum Output Frequency, to the desired value.

■ T1-01: Auto-Tuning Mode Selection

Sets the type of Auto-Tuning to be used. [Refer to Auto-Tuning for Induction Motors on page 129](#) for details on the different types of Auto-Tuning.

| No. | Name | Setting Range | Default |
|-------|----------------------------|---------------|---------|
| T1-01 | Auto-Tuning Mode Selection | 2, 3 | 2 |

Setting 2: Stationary Auto-Tuning for Line-to-Line Resistance

Setting 3: Rotational Auto-Tuning for V/f Control

■ T1-02: Motor Rated Power

Sets the motor rated power according to the motor nameplate value.

| No. | Name | Setting Range | Default |
|-------|-------------------|-------------------|---------------------|
| T1-02 | Motor Rated Power | 0.00 to 650.00 kW | Determined by o2-04 |

■ T1-03: Motor Rated Voltage (T1-01 = 3)

Sets the motor rated voltage according to the motor nameplate value. Enter the voltage base speed here if the motor is operating above base speed.

Enter the voltage needed to operate the motor under no-load conditions at rated speed to T1-03 for better control precision around rated speed when using a vector control mode. The no-load voltage can usually be found in the motor test report available from the manufacturer. If the motor test report is not available, enter approximately 90% of the rated voltage printed on the motor nameplate. This may increase the output current and reduce the overload margin.

| No. | Name | Setting Range | Default |
|-------|---------------------|--------------------|-------------|
| T1-03 | Motor Rated Voltage | 0.0 to 255.5 V <I> | 200.0 V <I> |

<I> Values shown are specific to 200 V class drives. Double value for 400 V class drives. Multiply value by 2.875 for 600 V class drives.

■ T1-04: Motor Rated Current

Sets the motor rated current according to the motor nameplate value. Enter the current at the motor base speed.

| No. | Name | Setting Range | Default |
|-------|---------------------|-----------------------------------|---------|
| T1-04 | Motor Rated Current | 10 to 200% of drive rated current | o2-04 |

■ T1-05: Motor Base Frequency (T1-01 = 2)

Sets the motor rated frequency according to the motor nameplate value. If a motor with an extended speed range is used or the motor is used in the field weakening area, enter the maximum frequency to E1-04 after Auto-Tuning is complete.

| No. | Name | Setting Range | Default |
|-------|----------------------|-----------------|---------|
| T1-05 | Motor Base Frequency | 0.0 to 400.0 Hz | 60.0 Hz |

■ T1-06: Number of Motor Poles (T1-01 = 3)

Sets the number of motor poles according to the motor nameplate value.

| No. | Name | Setting Range | Default |
|-------|-----------------------|---------------|---------|
| T1-06 | Number of Motor Poles | 2 to 48 | 4 |

■ T1-07: Motor Base Speed (T1-01 = 3)

Sets the motor rated speed according to the motor nameplate value. Enter the speed at base frequency when using a motor with an extended speed range or if using the motor in the field weakening area.

| No. | Name | Setting Range | Default |
|-------|------------------|---------------|------------|
| T1-07 | Motor Base Speed | | 1750 r/min |

■ T1-11: Motor Iron Loss

Provides iron loss information to determine the Energy Saving coefficient. T1-11 will first display the value for the motor iron loss that was automatically calculated when motor capacity was entered to T1-02. Enter the motor iron loss value listed to T1-11 if the motor test report is available.

| No. | Name | Setting Range | Default |
|-------|-----------------|---------------|--|
| T1-11 | Motor Iron Loss | 0 to 65535 W | 14 W Differs depending on motor code and motor parameter settings. |

4.8 No-Load Operation Test Run

◆ No-Load Operation Test Run

This section explains how to operate the drive with the motor decoupled from the load during a test run.

■ Before Starting the Motor

Check the following items before operation:

- Ensure the area around the motor is safe.
- Ensure external emergency stop circuitry is working properly and other safety precautions have been taken.

■ During Operation

Check the following items during operation:



- The motor should rotate smoothly (i.e., no abnormal noise or oscillation).
- The motor should accelerate and decelerate smoothly.

■ No-Load Operation Instructions

The following example illustrates a test run procedure using the digital operator.

Note: Before starting the motor, set the frequency reference d1-01 to 6 Hz.

| Step | | Display/Result |
|------|--|----------------|
| 1. | Turn on the power to the drive. The initial display appears. | |
| 2. | Press to select LOCAL. The LO/RE light will turn on. | |
| 3. | Press to give the drive a Run command. RUN will light and the motor will rotate at 6 Hz. | |
| 4. | Ensure the motor is rotating in the correct direction and that no faults or alarms occur. | |
| 5. | If there is no error in step 4, press to increase the frequency reference. Increase the frequency in increments of 10 Hz, verifying smooth operation at all speeds. For each frequency, check the drive output current using monitor U1-03. The current should be well below the motor rated current. | — |

| | Step | | Display/Result |
|----|---|---|---|
| 6. | The drive should operate normally. Press  to stop the motor. RUN flashes until the motor comes to a complete stop. | ➔ |  |

4.9 Test Run with Load Connected

◆ Test Run with the Load Connected

After performing a no-load test run, connect the motor and proceed to run the motor and load together.

■ Precautions for Connected Machinery

WARNING! *Sudden Movement Hazard. Clear all personnel from the drive, motor, and machine area before applying power. System may start unexpectedly upon application of power, causing death or serious injury.*

WARNING! *Sudden Movement Hazard. Always check the operation of any fast stop circuits after they are wired. Fast stop circuits are required to provide safe and quick shutdown of the drive. Prepare to initiate an emergency stop during the test run. Operating a drive with untested emergency circuits could result in death or serious injury.*

- The motor should come to a complete stop without problems.
- Connect the load and machinery to the motor.
- Fasten all installation screws properly and check that the motor and connected machinery are held in place.

■ Checklist Before Operation

- The motor should rotate in the proper direction.
- The motor should accelerate and decelerate smoothly.

■ Operating the Motor under Loaded Conditions

Test run the application similarly to the no-load test procedure when connecting the machinery to the motor.

- Monitor U1-03 for overcurrent during operation.
- If the application permits running the load in the reverse direction, change the motor direction and the frequency reference while watching for abnormal motor oscillation or vibration.
- Correct any problems that occur with hunting, oscillation, and other control-related issues. *Refer to Motor Performance Fine-Tuning on page 290* for details.

4.10 Verifying Parameter Settings and Backing Up Changes

Use the Verify Menu to check all changes to parameter settings. *Refer to Verifying Parameter Changes: Verify Menu on page 120.*

It is convenient to check all changes to parameters then save the verified parameters as User parameters.

Change the access level or set a password to the drive to prevent accidental modification of parameter settings.

◆ Backing Up Parameter Values: o2-03

Setting o2-03 to 1 saves all parameter settings before resetting o2-03 to 0. The drive can now recall all the saved parameters by performing a User Initialization (A1-03 = 1110).

| No. | Parameter Name | Description | Setting Range | Default Setting |
|-------|-----------------------|--|---------------|-----------------|
| o2-03 | User Defaults | Lets the user create a set of default settings for a User Initialization. 0: Saved/Not Set 1: Set Defaults - Saves current parameter settings as the default values for a User Initialization. 2: Clear All - Clears the currently saved user settings. After saving the user parameter set value, the items of 1110 (User Initialization) are displayed in A1-03 (User Parameter Default Value). | 0 to 2 | 0 |
| A1-03 | Initialize Parameters | Selects a method to initialize the parameters. 0: No initialization 1110: User Initialize (parameter values must be stored using parameter o2-03) 2220: 2-Wire Initialize (parameter initialized prior to shipment) 3330: 3-Wire Initialize 5550: Terminal/Control Initialize 8008: Pump 8009: Pump w/ PI 8010: Fan 8011: Fan w/ PI | 0 to 8011 | 0 |

◆ Parameter Access Level: A1-01



Setting the Access Level for “Operation only” (A1-01 = 0) allows the user to access parameters A1-□□ and U□-□□ only. Other parameters are not displayed.

Setting the Access Level for “User Parameters” (A1-01 = 1) allows the user to access only the parameters that have been previously saved as User Parameters. This is helpful when displaying only the relevant parameters for a specific application.

| No. | Parameter Name | Description | Setting Range | Default |
|----------------|------------------------------------|---|----------------|---------|
| A1-01 | Access Level Selection | 1: User Parameters. Only recently changed parameters from application parameters A2-01 to A2-16 and A2-17 to A2-32 can be set and monitored. 2: Advanced Access Level. All parameters can be set and monitored. | 0 to 2 | 2 |
| A2-01 to A2-32 | User Parameters 1 to 32 | Parameters selected by the user are saved as User Parameters, including recently viewed parameters and parameters specifically selected for quick access. If parameter A2-33 is set to 1, recently viewed parameters will be listed between A2-17 and A2-32. Parameters A2-01 through A2-16 must be manually selected by the user. If A2-33 is set to 0, recently viewed parameters will not be saved to the group of User Parameters. A2-□□ parameters are now available for manual programming. | b1-01 to o□-□□ | – |
| A2-33 | User Parameter Automatic Selection | 0: Parameters A2-01 through A2-32 are reserved for the user to create a group of User Parameters. 1: Save history of recently viewed parameters. Recently edited parameters will be saved to A2-17 through A2-32 for quick access. The most recently changed parameter is saved to A2-17. The second most recently changed parameter is saved to A2-18, etc. | 0, 1 | 0 |

◆ Password Settings: A1-04, A1-05

The user can set a password in parameter A1-05 to restrict access to the drive. The password must be entered to A1-04 to unlock parameter access (i.e., parameter setting A1-04 must match the value programmed into A1-05). The following parameters cannot be viewed or edited until the value entered to A1-04 correctly matches the value set to A1-05: A1-01, A1-03, A1-06, and A2-01 through A2-33.

Note: Parameter A1-05 is hidden from view. To display A1-05, access parameter A1-04 and press  and  simultaneously.

◆ Copy Function

Parameter settings can be copied to another drive to simplify parameter restoration or multiple drive setup. The drive supports the following copy options:

- **LCD Operator (standard in all models)**

The LCD operator used to operate the drive supports copying, importing, and verifying parameter settings and contains a Real Time Clock. *Refer to o3: Copy Function on page 272* for details.

- **USB Copy Unit and CopyUnitManager**

The copy unit is an external option connected to the drive to copy parameter settings from one drive and save those settings to another drive. Refer to the manual supplied with the USB Copy Unit for instructions.

The CopyUnitManager is a PC software tool. It allows the user to load parameter settings from the Copy Unit onto a PC, or from the PC onto a Copy Unit. This is useful when managing parameters for various drives or applications. Refer to the manual supplied with the CopyUnitManager for instructions.

- **DriveWizard Industrial**

DriveWizard Industrial is a PC software tool for parameter management, monitoring, and diagnosis. DriveWizard Industrial can load, store, and copy drive parameter settings. For details, refer to Help in the DriveWizard Industrial software.

4.11 Test Run Checklist

Review the checklist before performing a test run. Check each item that applies.

| <input checked="" type="checkbox"/> | No. | Checklist | Page |
|-------------------------------------|-----|--|------|
| <input type="checkbox"/> | 1 | Thoroughly read the manual before performing a test run. | – |
| <input type="checkbox"/> | 2 | Turn the power on. | 125 |
| <input type="checkbox"/> | 3 | Set the voltage for the power supply to E1-01. | 191 |

Check the items that correspond to the control mode being used.

WARNING! Sudden Movement Hazard. Ensure start/stop and safety circuits are wired properly and in the correct state before energizing the drive. Failure to comply could result in death or serious injury from moving equipment. When programmed for 3-Wire control, a momentary closure on terminal S1 may cause the drive to start.

| <input checked="" type="checkbox"/> | No. | Checklist | Page |
|-------------------------------------|-----|---|------|
| <input type="checkbox"/> | 4 | Select the best V/f pattern according to the application and motor characteristics. | – |
| <input type="checkbox"/> | 5 | Select Stationary Auto-Tuning for Line-to-Line Resistance or Rotational Auto-Tuning for V/f Control if using Energy Saving functions. | 129 |
| <input type="checkbox"/> | 6 | Decouple the motor for Rotational Auto-Tuning for V/f Control. | 129 |
| <input type="checkbox"/> | 7 | Enter the following data depending on Auto-Tuning method according to the information listed on the motor nameplate: <ul style="list-style-type: none"> • Motor rated power to T1-02 (kW) • Motor rated voltage to T1-03 (V) • Motor rated current to T1-04 (A) • Motor base frequency to T1-05 (Hz) • Number of motor poles to T1-06 • Motor base speed to T1-07 (r/min) | – |
| <input type="checkbox"/> | 8 | The DRV should light after giving a Run command. | – |
| <input type="checkbox"/> | 9 | To give Run command and frequency reference from the digital operator, press “LO/RE” key to set to LOCAL. | 122 |
| <input type="checkbox"/> | 10 | If the motor rotates in the opposite direction during test run, switch two of U/T1, V/T2, W/T3, or change b1-14. | 125 |
| <input type="checkbox"/> | 11 | Set motor rated current (E2-01) and motor protection (L1-01) values for motor thermal protection. | – |
| <input type="checkbox"/> | 12 | Set the drive for REMOTE when control circuit terminals provide the Run command and frequency reference. | 122 |
| <input type="checkbox"/> | 13 | If the control circuit terminals should supply the frequency reference, select the correct voltage input signal level (0 to +10 V or -10 to +10 V) or the correct current input signal level (4 to 20 mA or 0 to 20 mA). | 147 |
| <input type="checkbox"/> | 14 | Set the proper signal level to terminals A1, A2, A3 (0 to 20 mA, 4 to 20 mA, 0 to +10 V or -10 to +10 V). | 147 |
| <input type="checkbox"/> | 15 | For A1, A2, and A3, when current input is used, switch the jumper on S1 from the V-side to I-side. Set the level for current signal used with parameter H3-01 for terminal A1, H3-09 for terminal A2, H3-05 for terminal A3, (set “2” for 4 to 20 mA, or “3” for 0 to 20 mA). V = Voltage, I = Current analog input signal. | 147 |
| <input type="checkbox"/> | 16 | If an analog input supplies the frequency reference, make sure it produces the desired frequency reference. Make the following adjustments if the drive does not operate as expected: Gain adjustment: Set the maximum voltage/current signal and adjust the analog input gain (H3-03 for A1, H3-11 for A2, H3-07 for A3) until the frequency reference value reaches the desired value. Bias adjustment: Set the minimum voltage/current signal and adjust the analog input bias (H3-04 for A1, H3-12 for A2, H3-08 for A3) until the frequency reference value reaches the desired minimum value. | – |

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Parameter Details

| | | |
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5.1 A: Initialization

The initialization group contains parameters associated with initial drive setup, including parameters involving the display language, access levels, initialization, and password.

◆ A1: Initialization

■ A1-00: Language Selection

Selects the display language for the digital operator.

Note: This parameter is not reset when the drive is initialized using parameter A1-03.

| No. | Parameter Name | Setting Range | Default |
|-------|--------------------|---------------|---------|
| A1-00 | Language Selection | 0 to 7 | 0 |

Setting 0: English

Setting 1: Japanese

Setting 2: German

Setting 3: French

Setting 4: Italian

Setting 5: Spanish

Setting 6: Portuguese

Setting 7: Chinese

■ A1-01: Access Level Selection

Allows or restricts access to drive parameters.

| No. | Parameter Name | Setting Range | Default |
|-------|------------------------|---------------|---------|
| A1-01 | Access Level Selection | 0 to 2 | 2 |

Setting 0: Operation only

Allows access and programming of parameters A1-01, A1-04, and Drive Mode.

Allows access to all U monitor parameters.

Does not allow access to Verify Mode, Setup Mode, or Auto-Tuning Mode.

Setting 1: User Parameters

Allows access and programming of parameters A1-00, A1-01, A1-04, and Drive Mode.

Allows access to all U monitor parameters.

Allows access to parameters set in A2-01 to A2-32 in Setup Mode.

Does not allow access to Verify Mode or Auto-Tuning Mode.

Setting 2: Advanced Access Level (A) and Setup Access Level (S)

Allows access and programming of all parameters.

Notes on Parameter Access

- If the drive parameters are password protected by A1-04 and A1-05, parameters A1-01 through A1-03, A1-06, A1-07, and A2-01 through A2-32 cannot be modified.
- If a digital input terminal programmed for “Program lockout” (H1-□□ = 1B) is enabled, parameter values cannot be modified, even if A1-01 is set to 1 or 2.
- If parameters are changed via serial communication, it will not be possible to edit or change parameter settings with the digital operator until an Enter command is issued to the drive from the serial communication.

■ A1-03: Initialize Parameters

Resets parameters to default values or performs an Application Preset for fan or pump applications. After initialization, the setting for A1-03 automatically returns to 0.

| No. | Parameter Name | Setting Range | Default |
|-------|-----------------------|---|---------|
| A1-03 | Initialize Parameters | 0, 1110, 2220, 3330, 5550, 8008, 8009, 8010, 8011 | 0 |

Setting 0: No Initialize

Setting 1110: User Initialize

Resets parameters to the values selected by the user as User Settings. User Settings are stored when parameter o2-03 is set to “1: Set defaults”.

Note: User Initialization resets all parameters to a user-defined set of default values previously saved to the drive. Set parameter o2-03 to 2 to clear the user-defined default values.

Setting 2220: 2-Wire Initialization

Resets parameters to default settings with digital inputs S1 and S2 configured as Forward run and Reverse run, respectively. [Refer to Setting 40, 41: Forward Run, Reverse Run Command for 2-Wire Sequence on page 212](#) for more information on digital input functions.

Setting 3330: 3-Wire Initialization

Resets parameters to default settings with digital inputs S1, S2, and S5 configured as Run, Stop, and Forward/Reverse respectively. [Refer to Setting 0: 3-Wire Sequence on page 206](#) for more information on digital input functions.

Notes on Parameter Initialization

The parameters shown in [Table 5.1](#) will not be reset when the drive is initialized by setting A1-03 = 2220 or 3330.

Table 5.1 Parameters Not Changed by Drive Initialization

| No. | Parameter Name |
|-------|-------------------------------|
| A1-00 | Language Selection |
| E1-03 | V/f Pattern Selection |
| F6-08 | Communication Parameter Reset |
| L8-35 | Installation Selection |
| o2-04 | Drive/kVA Selection |

Setting 5550: Terminal/Control Initialize

An oPE04 error appears on the digital operator when a terminal block with settings saved to its built-in memory is installed in a drive that has edited parameters. Set A1-03 to 5550 to use the parameter settings saved to the terminal block memory.

Setting 8008: Pump

Application Preset for pump applications. [Refer to Application Selection on page 126](#) for a list of parameters and default values for this Application Preset.

Setting 8009: Pump w/ PI

Application Preset for pump applications. [Refer to Application Selection on page 126](#) for a list of parameters and default values for this Application Preset.

Setting 8010: Fan

Application Preset for pump applications. [Refer to Application Selection on page 126](#) for a list of parameters and default values for this Application Preset.

Setting 8011: Fan w/ PI

Application Preset for pump applications. [Refer to Application Selection on page 126](#) for a list of parameters and default values for this Application Preset.

■ A1-04, A1-05: Password and Password Setting

Parameter A1-04 enters the password when the drive is locked; parameter A1-05 is a hidden parameter that sets the password.

| No. | Parameter Name | Setting Range | Default |
|-------|------------------|---------------|---------|
| A1-04 | Password | 0000 to 9999 | 0000 |
| A1-05 | Password Setting | | |

5.1 A: Initialization

How to Use the Password

The user can set a password in parameter A1-05 to restrict access to the drive. The password must be entered to A1-04 to unlock parameter access (i.e., parameter setting A1-04 must match the value programmed into A1-05). The following parameters cannot be viewed or edited until the value entered to A1-04 correctly matches the value set to A1-05: A1-01, A1-03, A1-06, and A2-01 through A2-33.

The instructions below demonstrate how to set password “1234”. An explanation follows on how to enter that password to unlock the parameters.

Table 5.2 Setting the Password for Parameter Lock

| Step | | Display/Result |
|------|---|----------------|
| 1. | Turn on the power to the drive. The initial display appears. | |
| 2. | Press or until the Parameter Setting Mode screen appears. | |
| 3. | Press to enter the parameter menu tree. | |
| 4. | Select the flashing digits by pressing , , or . | |
| 5. | Select A1-04 by pressing . | |
| 6. | Press while holding down at the same time. A1-05 will appear. Note: A1-05 is hidden and will not display by pressing only . | |
| 7. | Press . | |
| 8. | Use , , , , and to enter the password. | |
| 9. | Press to save what was entered. | |
| 10. | The display automatically returns to the display shown in step 6. | |

Table 5.3 Check if A1-03 Init Parameters is Locked (continuing from step 10 above)


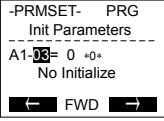


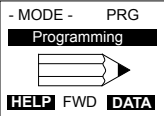

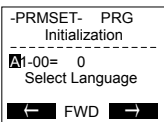



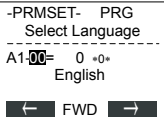


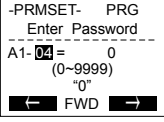
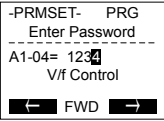


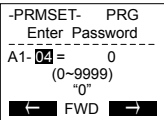

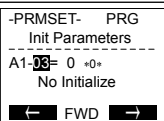

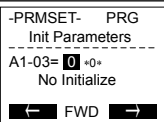


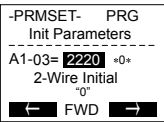



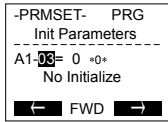
| Step | | Display/Result |
|------|--|---|
| 1. | Press  to display A1-03. |  |
| 2. | Press  , making sure that the setting values cannot be changed. | |
| 3. | Press  to return to the first display. |  |

Table 5.4 Enter the Password to Unlock Parameters (continuing from step 3 above)

| Step | | Display/Result |
|------|---|---|
| 1. | Press  to enter the parameter setup display. |  |
| 2. | Press  ,  ,  to select the flashing digits as shown. |  |
| 3. | Press  to scroll to A1-04 and  . |  |
| 4. | Enter the password "1234". |  |
| 5. | Press  to save the new password. |  |
| 6. | Drive returns to the parameter display. |  |
| 7. | Press  and scroll to A1-03. |  |
| 8. | Press  to display the value set to A1-03. If the first "0" blinks, parameter settings are unlocked. |  |
| 9. | Use  and  to change the value if desired (though changing the Init Parameters at this point is not typically done). |  |

5.1 A: Initialization

| Step | | | Display/Result |
|------|---|---|---|
| 10. | Press  to save the setting, or press  to return to the previous display without saving changes. | → |  |
| 11. | The display automatically returns to the parameter display. | → |  |

- Note:**
1. Parameter settings can be edited after entering the correct password.
 2. Performing a 2-Wire or 3-Wire initialization resets the password to “0000”.

■ A1-06: Application Preset

Several Application Presets are available to facilitate drive setup for commonly used applications. Selecting one of these Application Presets automatically assigns functions to the input and output terminals and sets a predefined group of parameters to values appropriate for the selected application.

In addition, the parameters most likely to be changed are assigned to the group of User Parameters, A2-01 through A2-16. User Parameters are part of the Setup Group, which provides quicker access by eliminating the need to scroll through multiple menus.

◆ A2: User Parameters

■ A2-01 to A2-32: User Parameters 1 to 32

The user can select up to 32 parameters and assign them to parameters A2-01 through A2-32 to provide quicker access by eliminating the need to scroll through multiple menus. The User Parameter list can also save the most recently edited parameters.

| No. | Parameter Name | Setting Range | Default |
|----------------|-------------------------|----------------|---------------------|
| A2-01 to A2-32 | User Parameters 1 to 32 | b1-01 to s6-07 | Determined by A1-03 |

Saving User Parameters

To save specific parameters to A2-01 through A2-32, set parameter A1-01 to 2 to allow access to all parameters, then enter the parameter number to one of the A2-□□ parameters to assign it to the list of User Parameters. Finally, set A1-01 to 1 to restrict access so users can only set and refer to the parameters saved as User Parameters.

■ A2-33: User Parameter Automatic Selection

Determines whether recently edited parameters are saved to the second half of the User Parameters (A2-17 to A2-32) for quicker access.

| No. | Parameter Name | Setting Range | Default |
|-------|------------------------------------|---------------|---------|
| A2-33 | User Parameter Automatic Selection | 0, 1 | 0 |

Setting 0: Do not save list of recently edited parameters

Set A2-33 to 0 to manually select the parameters listed in the User Parameter group.

Setting 1: Save list of recently edited parameters

Set A2-33 to 1 to automatically save recently edited parameters to A2-17 through A2-32. A total of 16 parameters are saved with the most recently edited parameter set to A2-17, the second most recently to A2-18, and so on. Access the User Parameters using the Setup Mode of the digital operator.

5.2 b: Application

◆ b1: Operation Mode Selection

■ b1-01: Frequency Reference Selection 1

Selects the frequency reference source 1 for the REMOTE mode.

- Note:**
1. If a Run command is input to the drive but the frequency reference entered is 0 or below the minimum frequency, the RUN indicator LED on the digital operator will light and the STOP indicator will flash. However, the RUN indicator LED will light in zero speed control when A1-02 is set to 3, 6, or 7.
 2. Press the LO/RE key to set the drive to LOCAL and use the operator keypad to enter the frequency reference.

| No. | Parameter Name | Setting Range | Default |
|-------|---------------------------------|---------------|---------|
| b1-01 | Frequency Reference Selection 1 | 0 to 4 | 1 |

Setting 0: Operator keypad

Input the frequency reference using the operator keypad with this setting.

Setting 1: Terminals (analog input terminals)

Using this setting, an analog frequency reference can be entered as a voltage or current signal from terminals A1, A2, or A3.

Voltage Input

Voltage input can be used at any of the three analog input terminals. Make the settings as described in [Table 5.5](#) for the input used.

Table 5.5 Analog Input Settings for Frequency Reference Using Voltage Signals

| Terminal | Signal Level | Parameter Settings | | | Notes | |
|----------|----------------|------------------------|---|-------|-------|---|
| | | Signal Level Selection | Function Selection | Gain | | Bias |
| A1 | 0 to 10 Vdc | H3-01 = 0 | H3-02 = 0 (Frequency Reference Bias) | H3-03 | H3-04 | – |
| | -10 to +10 Vdc | H3-01 = 1 | | | | |
| A2 | 0 to 10 Vdc | H3-09 = 0 | H3-10 = 0 (Frequency Reference Bias) | H3-11 | H3-12 | Set jumper S1 on the terminal board to “V” for voltage input. |
| | -10 to +10 Vdc | H3-09 = 1 | | | | |
| A3 | 0 to 10 Vdc | H3-05 = 0 | H3-06 = 0 (Frequency Reference Bias) | H3-07 | H3-08 | Set DIP switch S4 on the terminal board to “AI”. |
| | -10 to +10 Vdc | H3-05 = 1 | | | | |

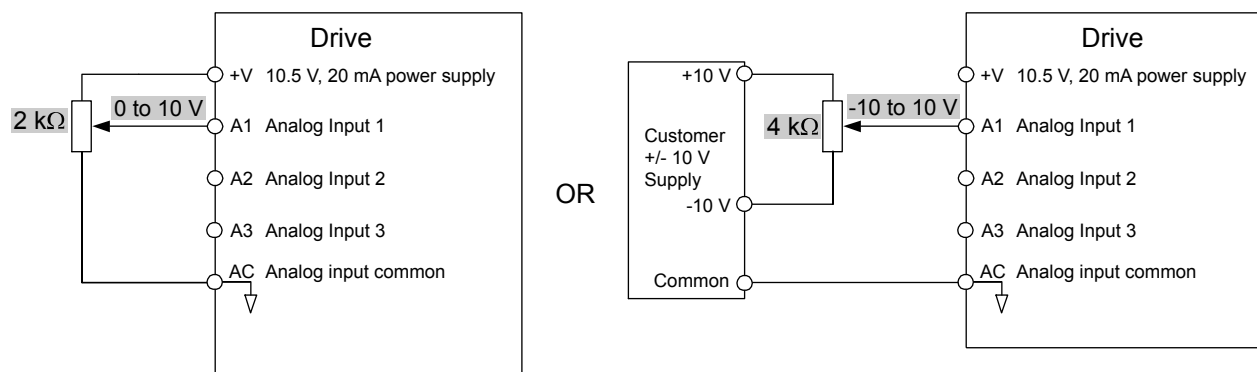


Figure 5.1 Setting the Frequency Reference as a Voltage Signal at Terminal A1

Current Input

Input terminals, A1, A2, and A3 can accept a current input signal. Refer to [Table 5.6](#) for an example to set terminal A2 for current input.

5.2 b: Application

Table 5.6 Analog Input Settings for Frequency Reference Using a Current Signal

| Terminal | Signal Level | Parameter Settings | | | | Notes |
|----------|--------------|------------------------|-------------------------------|-------|-------|--|
| | | Signal Level Selection | Function Selection | Gain | Bias | |
| A2 | 4 to 20 mA | H3-09 = 2 | H3-10 = 0 (Frequency Bias) | H3-11 | H3-12 | Make sure to set jumper S1 on the terminal board to "I" for current input. |
| | 0 to 20 mA | H3-09 = 3 | | | | |

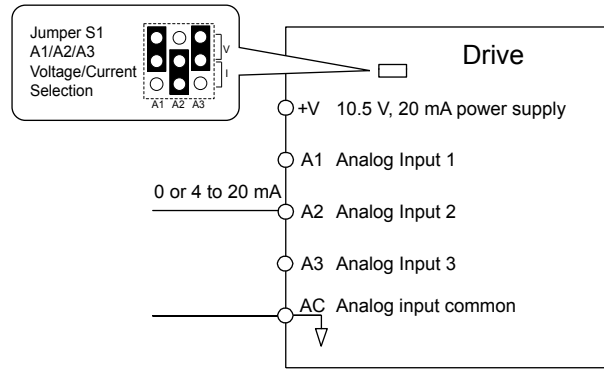


Figure 5.2 Setting the Frequency Reference as a Current Signal to Terminal A2

Switching between Main/Auxiliary Frequency References

The frequency reference input can be switched between the analog terminals A1, A2, and A3 using multi-speed inputs. [Refer to Multi-Step Speed Selection on page 182](#) for details on using this function.

Setting 2: MEMOBUS/Modbus Communications

This setting requires entering the frequency reference via the RS-485/RS-422 serial communications port (control terminals R+, R-, S+, S-). [Refer to MEMOBUS/Modbus Configuration on page 506](#) for instructions.

Setting 3: Option card

This setting requires entering the frequency reference via an option board plugged into connector CN5-A on the drive control board. Consult the option board manual for instructions on integrating the drive with the communication system.

Note: If the frequency reference source is set for Option PCB (b1-01 = 3), but an option board is not installed, an oPE05 operation error will be displayed on the digital operator and the drive will not run.

Setting 4: Pulse Train Input

This setting requires a pulse train signal to terminal RP to provide the frequency reference. Follow the directions below to verify that the pulse signal is working properly.

Verifying the Pulse Train is Working Properly

- Set b1-01 to 4 and set H6-01 to 0.
- Set the H6-02 to the pulse train frequency value that equals 100% of the frequency reference.
- Enter a pulse train signal to terminal RP and check for the correct frequency reference on the display.

■ b1-02: Run Command Selection 1

Determines the Run command source 1 in the REMOTE mode.

| No. | Parameter Name | Setting Range | Default |
|-------|-------------------------|---------------|---------|
| b1-02 | Run Command Selection 1 | 0 to 3 | 1 |

Setting 0: Operator

This setting will illuminate the LO/RE light to indicate that the Run command source is assigned to the digital operator. Use the digital operator RUN and STOP keys to start and stop operation.

Setting 1: Control Circuit Terminal

This setting requires entering the Run command via the digital input terminals using one of following sequences:

- 2-Wire sequence 1:

Setting A1-03 to 2220 initializes the drive and presets terminals S1 and S2 to FWD/Stop and REV/Stop. These are the default settings of the drive. [Refer to Setting 40, 41: Forward Run, Reverse Run Command for 2-Wire Sequence on page 212.](#)

- 2-Wire sequence 2:

Two inputs (Start/Stop-FWD/REV). *Refer to Setting 42, 43: Run and Direction Command for 2-Wire Sequence 2 on page 212.*

- 3-Wire sequence:

Setting A1-03 to 3330 initializes the drive and presets terminals S1, S2, and S5 to Start, Stop, and FWD/REV. *Refer to Setting 0: 3-Wire Sequence on page 206.*

Setting 2: MEMOBUS/Modbus Communications

This setting requires entering the Run command via serial communications by connecting the RS-485/RS-422 serial communication cable to control terminals R+, R-, S+, and S- on the removable terminal block. *Refer to MEMOBUS/Modbus Configuration on page 506* for instructions.

Setting 3: Option Card

This setting requires entering the Run command via the communication option board by plugging a communication option board into the CN5-A port on the control PCB. Refer to the option board manual for instructions on integrating the drive into the communication system.

Note: If b1-02 is set to 3, but an option board is not installed in CN5-A, an oPE05 operation error will be displayed on the digital operator and the drive will not run.

■ b1-03: Stopping Method Selection

Selects how the drive stops the motor when the Run command is removed or when a Stop command is entered.

| No. | Parameter Name | Setting Range | Default |
|-------|---------------------------|---------------|---------|
| b1-03 | Stopping Method Selection | 0 to 3 | 0 |

Setting 0: Ramp to Stop

When the Run command is removed, the drive will decelerate the motor to stop. The deceleration rate is determined by the active deceleration time. The default deceleration time is set to parameter C1-02.

When the output frequency falls below the level set in parameter b2-01, the drive will start DC injection, Zero Speed Control, or Short Circuit Braking. *Refer to b2-01: DC Injection Braking Start Frequency on page 153* for details.

Setting 1: Coast to Stop

When the Run command is removed, the drive will shut off its output and the motor will coast (uncontrolled deceleration) to stop. The stopping time is determined by the inertia and the friction in the driven system.

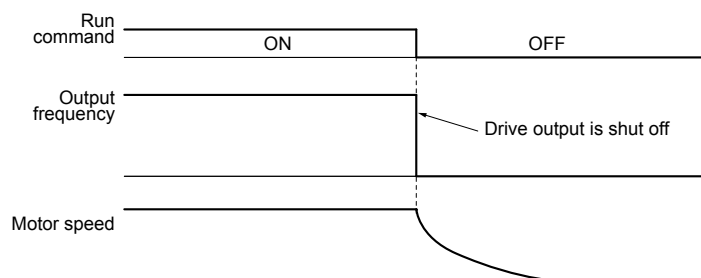


Figure 5.3 Coast to Stop

Note: After a stop is initiated, any subsequent Run command entered will be ignored until the minimum baseblock time (L2-03) has expired. Do not enter Run command until it has come to a complete stop. Use DC Injection at Start (*Refer to b2-03: DC Injection Braking Time at Start on page 153*) or Speed Search (*Refer to b3: Speed Search on page 153*) to restart the motor before it has completely stopped.

Setting 2: DC Injection Braking to Stop

When the Run command is removed, the drive will enter baseblock (turn off its output) for the minimum baseblock time (L2-03). When the minimum baseblock time has expired, the drive will inject the amount DC Injection Braking is set in parameter b2-02 into the motor windings to brake the motor. The stopping time in DC Injection Braking to Stop is significantly faster compared to Coast to Stop.

5.2 b: Application

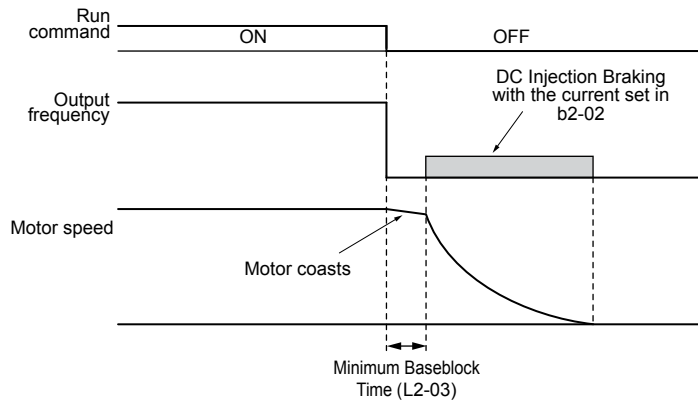


Figure 5.4 DC Injection Braking to Stop

DC Injection Braking time is determined by the value set to b2-04 and the output frequency at the time the Run command is removed. It can be calculated by:

$$\text{DC Injection brake time} = \frac{(\text{b2-04}) \times 10 \times \text{Output frequency}}{\text{Maximum output frequency (E1-04)}}$$

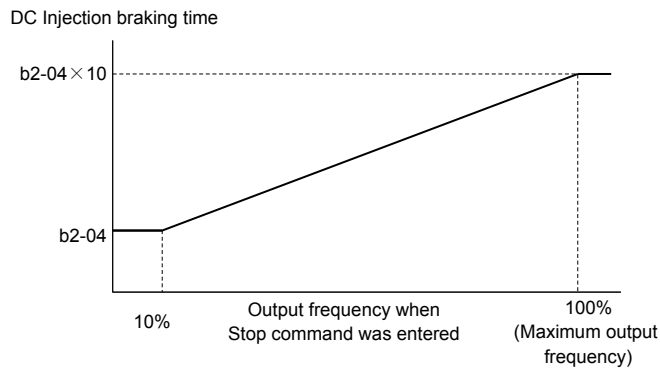


Figure 5.5 DC Injection Braking Time Depending on Output Frequency

Note: If an overcurrent (oC) fault occurs during DC Injection Braking to Stop, lengthen the minimum baseblock time (L2-03) until the fault no longer occurs.

Setting 3: Coast to Stop with Timer

When the Run command is removed, the drive will turn off its output and the motor will coast to stop. The drive will not start if a Run command is input before the time t (C1-02) has expired. Cycle the Run command that was activated during time t after t has expired to start the drive.

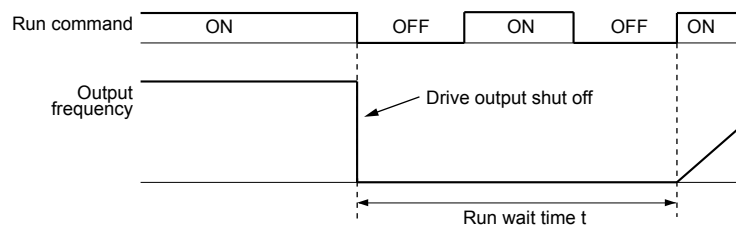


Figure 5.6 Coast to Stop with Timer

The wait time t is determined by the output frequency when the Run command is removed and by the active deceleration time.

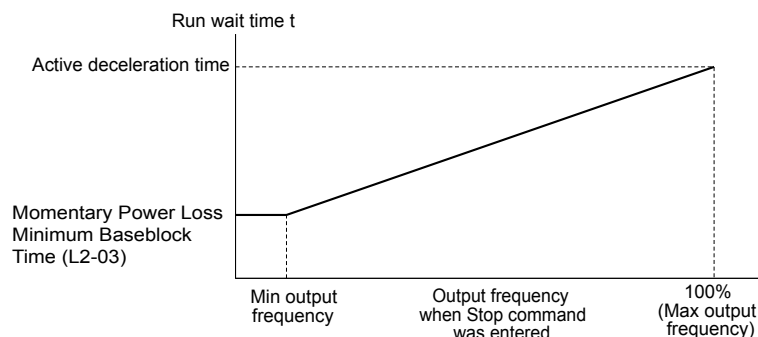


Figure 5.7 Run Wait Time Depending on Output Frequency

■ b1-04: Reverse Operation Selection

Enables and disables Reverse operation. For some applications, reverse motor rotation is not appropriate and may cause problems (e.g., air handling units, pumps, etc.).

| No. | Parameter Name | Setting Range | Default |
|-------|-----------------------------|---------------|---------|
| b1-04 | Reverse Operation Selection | 0, 1 | 0 |

Setting 0: Reverse operation enabled

Possible to operate the motor in both forward and reverse directions.

Setting 1: Reverse operation disabled

Drive disregards a Reverse run command or a negative frequency reference.

■ b1-07: LOCAL/REMOTE Run Selection

The drive has three separate control sources that can be switched using digital inputs (H1-□□ = 1 (LOCAL/REMOTE Selection) or 2 (External reference 1/2)) or the LO/RE key on the digital operator. [Refer to Setting 1: LOCAL/REMOTE Selection on page 206](#), [Refer to Setting 2: External Reference 1/2 Selection on page 207](#) and [Refer to o2-01: LO/RE \(LOCAL/REMOTE\) Key Function Selection on page 270](#) for details.

- LOCAL: Digital operator. The digital operator sets the frequency reference and Run command.
- REMOTE: External reference 1. The frequency reference and Run command source are set by b1-01 and b1-02.
- REMOTE: External reference 2. The frequency reference and Run command source are set by b1-15 and b1-16.

When switching from LOCAL to REMOTE, or between External reference 1 and External reference 2, the Run command may already be present at the location at which the source is being switched. In this case, use parameter b1-07 to determine how the Run command is treated.

| No. | Parameter Name | Setting Range | Default |
|-------|----------------------------|---------------|---------|
| b1-07 | LOCAL/REMOTE Run Selection | 0, 1 | 0 |

Setting 0: Run command must be cycled

When the Run command source differs between the old source and the new source (e.g., the old source was the terminals and the new source is serial communication), and the Run command is active at the new source as the switchover occurs, the drive will not start or the drive will stop operation if it was previously running. The Run command must be cycled at the new source to restart the drive.

Setting 1: Accept Run command at the new source

When the Run command is active at the new source, the drive starts or continues operation if it was previously running.

WARNING! Sudden Movement Hazard. The drive may start unexpectedly if switching control sources when b1-07 = 1. Clear all personnel from rotating machinery and electrical connections prior to switching control sources. Failure to comply may cause death or serious injury.

■ b1-08: Run Command Selection while in Programming Mode

As a safety precaution, the drive will not normally respond to a Run command input when the digital operator is being used to adjust parameters in Programming Mode (Verify Menu, Setup Mode, Parameter Settings Mode, and Auto-Tuning Mode). If required by the application, set b1-08 to allow the drive to run while in Programming Mode.

| No. | Parameter Name | Setting Range | Default |
|-------|---|---------------|---------|
| b1-08 | Run Command Selection while in Programming Mode | 0 to 2 | 0 |

5.2 b: Application

Setting 0: Disabled

A Run command is not accepted while the digital operator is in Programming Mode.

Setting 1: Enabled

A Run command is accepted in any digital operator mode.

Setting 2: Prohibit programming during run

It is not possible to enter the Programming Mode as long as the drive output is active. The Programming Mode cannot be displayed during Run.

■ b1-11: Drive Delay Time Setting

If a time is set to b1-11, the drive will delay executing a Run command until the set time has expired. During Drive Delay Time execution, the digital operator keypad will display “WrUn”. Both Alarm and Run indicators will blink while the drive waits to execute the Run command.

| No. | Parameter Name | Setting Range | Default |
|-------|--------------------------|---------------|---------|
| b1-11 | Drive Delay Time Setting | 0 to 600 s | 0 |

■ b1-14: Phase Order Selection

Sets the phase order for drive output terminals U/T1, V/T2, and W/T3.

Switching motor phases will reverse the direction of the motor.

| No. | Parameter Name | Setting Range | Default |
|-------|-----------------------|---------------|---------|
| b1-14 | Phase Order Selection | 0, 1 | 0 |

■ b1-15: Frequency Reference Selection 2

Enabled when H1-□□ = 2 and the terminal is closed. [Refer to Setting 2: External Reference 1/2 Selection on page 207](#) and [Refer to b1-02: Run Command Selection 1 on page 148](#) for details.

| No. | Parameter Name | Setting Range | Default |
|-------|---------------------------------|---------------|---------|
| b1-15 | Frequency Reference Selection 2 | 0 to 4 | 0 |

■ b1-16: Run Command Selection 2

Enabled when H1-□□ = 2 and the terminal is closed. [Refer to Setting 2: External Reference 1/2 Selection on page 207](#) and [Refer to b1-01: Frequency Reference Selection 1 on page 147](#) for details.

| No. | Parameter Name | Setting Range | Default |
|-------|-------------------------|---------------|---------|
| b1-16 | Run Command Selection 2 | 0 to 3 | 0 |

■ b1-17: Run Command at Power Up

Determines whether an external Run command that is active during power up will start the drive.

| No. | Parameter Name | Setting Range | Default |
|-------|-------------------------|---------------|---------|
| b1-17 | Run Command at Power Up | 0, 1 | 1 |

Setting 0: Disregarded

A new Run command must be issued after power up. Cycle the Run command to start the drive.

Note: For safety reasons, the drive is initially programmed not to accept a Run command at power up (b1-17 = 0). If a Run command is issued at power up, the RUN indicator LED will flash quickly.

Setting 1: Allowed

The motor will start immediately after a power up if a Run command is already enabled.

WARNING! Sudden Movement Hazard. If b1-17 is set to 1 and an external Run command is active during power up, the motor will begin rotating as soon as the power is switched on. Proper precautions must be taken to ensure that the area around the motor is safe prior to powering up the drive. Failure to comply may cause serious injury.

◆ b2: DC Injection Braking and Short Circuit Braking

These parameters determine operation of the DC Injection Braking, Zero Speed Control, and Short Circuit Braking features.

■ b2-01: DC Injection Braking Start Frequency

Active when “Ramp to Stop” is selected as the stopping method (b1-03 = 0).

| No. | Name | Setting Range | Default |
|-------|--------------------------------------|----------------|---------|
| b2-01 | DC Injection Braking Start Frequency | 0.0 to 10.0 Hz | 0.5 Hz |

V/f Control

Sets the starting frequency for DC Injection Braking at Stop. When the output frequency falls below the setting of b2-01, DC Injection Braking is enabled for the time set in parameter b2-04.

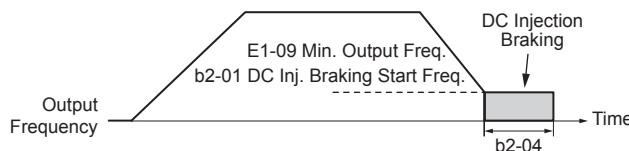


Figure 5.8 DC Injection Braking at Stop for V/f

Note: If b2-01 is set to a smaller value than E1-09 (Minimum Frequency), then DC Injection Braking will begin when the frequency falls to the E1-09 value.

■ b2-02: DC Injection Braking Current

Sets the DC Injection Braking current as a percentage of the drive rated current. The carrier frequency is automatically reduced to 1 kHz when this parameter is set to more than 50%.

| No. | Name | Setting Range | Default |
|-------|------------------------------|---------------|---------|
| b2-02 | DC Injection Braking Current | 0 to 100% | 50% |

■ b2-03: DC Injection Braking Time at Start

Sets DC Injection Braking time at start. Disabled when set to 0.00 s.

| No. | Name | Setting Range | Default |
|-------|------------------------------------|-----------------|---------|
| b2-03 | DC Injection Braking Time at Start | 0.00 to 10.00 s | 0.00 s |

■ b2-04: DC Injection Braking Time at Stop

Sets DC Injection Braking time at stop.

| No. | Name | Setting Range | Default |
|-------|-----------------------------------|-----------------|---------|
| b2-04 | DC Injection Braking Time at Stop | 0.00 to 10.00 s | 0.50 s |

◆ b3: Speed Search

The Speed Search function allows the drive to detect the speed of a rotating motor shaft that is driven by external forces and start the motor operation directly from the detected speed without first stopping the machine.

Example: When a momentary loss of power occurs, the drive output shuts off and the motor coasts. When power returns, the drive can find the speed of the coasting motor and restart it directly.

For induction motors, the drive offers two types of Speed Search that can be selected by parameter b3-24 (Speed Estimation and Current Detection). Both methods are explained below and followed by a description of all relevant parameters.

■ Current Detection Speed Search (b3-24 = 0)

Current Detection Speed Search detects the motor speed by looking at motor current in IM motors. When Speed Search is started it reduces the output frequency starting from either the maximum output frequency or the frequency reference while increasing the output voltage using the time set in parameter L2-04. As long as the current is higher than the level set to b3-02, the output frequency is lowered using the time constant set to b3-03. If the current falls below b3-02, the drive assumes that the output frequency and motor speed are the same and accelerates or decelerates to the frequency reference.

Be aware that sudden acceleration may occur when using this method of Speed Search with relatively light loads.

Figure 5.9 illustrates Current Detection Speed Search operation after a momentary power loss (L2-01 must be set to 1 or 2):

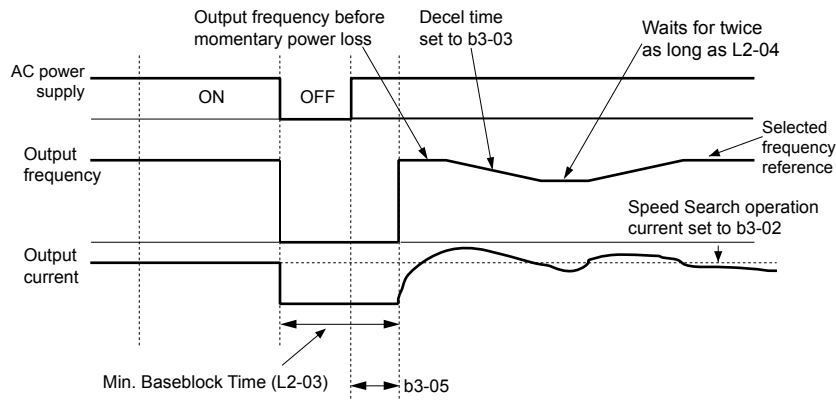


Figure 5.9 Current Detection Speed Search after Power Loss

Note: After power is restored, the drive waits until the time set to b3-05 has passed before performing Speed Search. Thereby the Speed Search may start not at the end of L2-03 but even later.

When Speed Search is applied automatically with the Run command, the drive waits for the minimum baseblock time set to L2-03 before starting Speed Search. If L2-03 is lower than the time set to parameter b3-05, then b3-05 is used as the wait time.

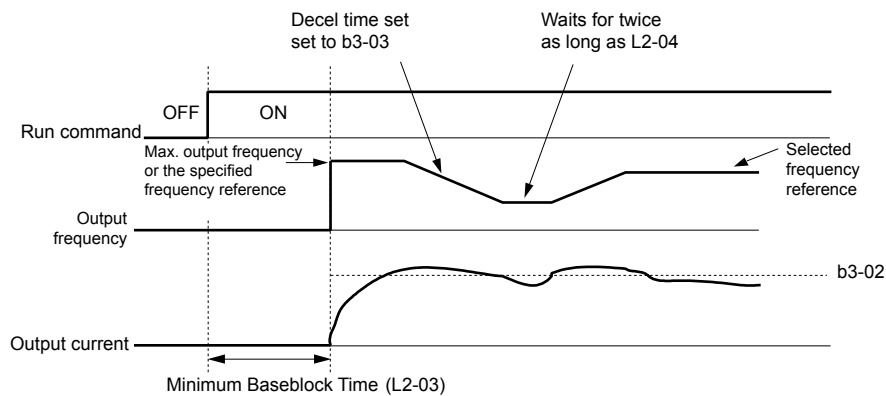


Figure 5.10 Current Detection Speed Search at Start or Speed Search Command by Digital Input

Notes on Using Current Detection Type Speed Search

- Shorten the Speed Search deceleration time set to b3-03 if an oL1 fault occurs while performing Current Detection Speed Search.
- Increase the minimum baseblock time set to L2-03 if an overcurrent or overvoltage fault occurs when performing Speed Search after power is restored following a momentary power loss.

■ Speed Estimation Type Speed Search (b3-24 = 1)

This method can be used for a single induction motor connected to a drive. Do not use this method if the motor is one or more frame size smaller than the drive, at motor speeds above 200 Hz, or when using a single drive to operate more than one motor.

Speed Estimation is executed in the two steps described below:

Step 1: Back EMF Voltage Estimation

This method is used by Speed Search after baseblock (e.g., a power loss where the drive CPU continued to run and the Run command was kept active). Here, the drive estimates the motor speed by analyzing the back EMF voltage and outputs the estimated frequency and increases the voltage using the time constant set in parameter L2-04. After that, the motor is accelerated or decelerated to the frequency reference starting from the detected speed. If there is not enough residual voltage in the motor windings to perform the calculations described above, the drive will automatically proceed to step 2.

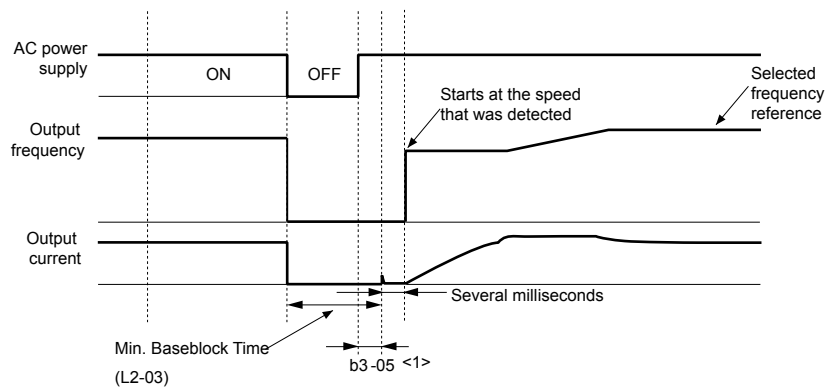


Figure 5.11 Speed Search after Baseblock

<1> After AC power is restored, the drive will wait for at least the time set to b3-05. If the power interruption is longer than the minimum baseblock time set to L2-03, the drive will wait until the time set to b3-05 has passed after power is restored before starting Speed Search.

Step 2: Current Injection

Current Injection is performed when there is insufficient residual voltage in the motor after extended power losses, when Speed Search is applied with the Run command (b3-01 = 1), or when an External search command is used.

This feature injects the amount of DC current set to b3-06 to the motor and detects the speed by measuring the current feedback. The drive then outputs the detected frequency and increases the voltage using the time constant set to parameter L2-04 while looking at the motor current.

The output frequency is reduced if the current is higher than the level in b3-02. When the current falls below b3-02, the motor speed is assumed to be found and the drive starts to accelerate or decelerate to the frequency reference.

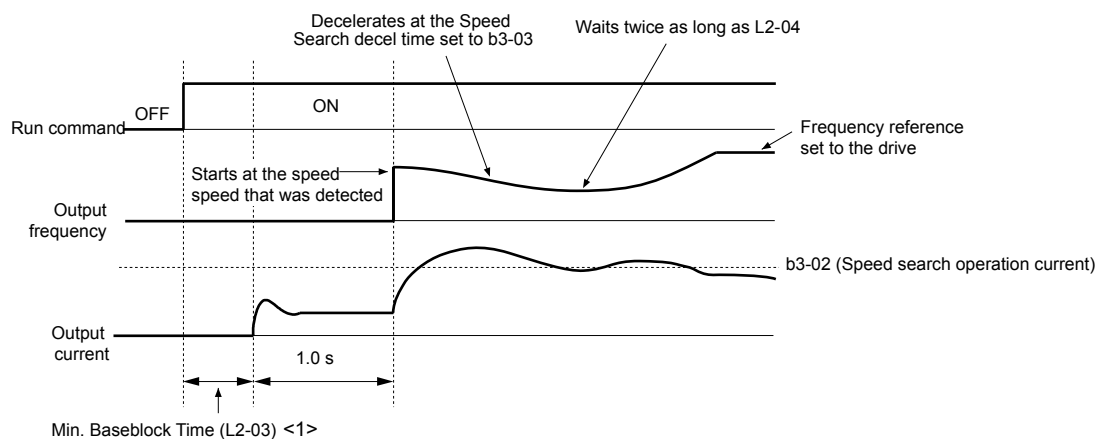


Figure 5.12 Speed Search at Start

<1> The wait time for Speed Search (b3-05) determines the lower limit.

Notes on Using Speed Estimation Speed Search

- Perform Rotational Auto-Tuning for V/f Control (T1-01 = 3) prior to using Speed Estimation in V/f Control and perform Stationary Auto-Tuning for Line-to-Line Resistance (T1-01 = 2) again if there is a change in the cable length between the drive and motor.
- Use Current Detection to search for speeds beyond 200 Hz if the application is running multiple motors from the same drive or if the motor is considerably smaller than the capacity of the drive.
- Speed Estimation may have trouble finding the actual speed if the motor cable is very long. Use Current Detection in these instances.
- Use Current Detection instead of Speed Estimation when operating motors smaller than 1.5 kW because Speed Estimation might not be able to detect the speed or rotation of these smaller motors, in which case Speed Estimation would stop the motor.

■ Speed Search Activation

Speed Search can be activated using any of the methods 1 through 5 described below. Select the Speed Search type in parameter b3-24 independent of the activation method.

Method 1. Automatically activate Speed Search with every Run command. Set b3-01, Speed Search Selection at Start, to 1 (Enabled). External Speed Search commands are ignored.

Method 2. Activate Speed Search using the multi-function input terminal.

Use the input functions for H1-□□ in [Table 5.7](#).

Table 5.7 Speed Search Activation by Multi-Function Input Terminal

| Setting | Description | b3-24 = 1 (Current Injection Method of Speed Estimation) | b3-24 = 0 (Current Detection Speed Search) |
|---------|------------------------------|---|---|
| 61 | External Search Command 1 | Activate Speed Estimation Speed Search | Closed: Activate Current Detection Speed Search from the maximum output frequency (E1-04). |
| 62 | External Search Command 2 | Activate Speed Estimation Speed Search | Closed: Activate Current Detection Speed Search from the frequency reference. |

To activate Speed Search by the multi-function input terminal, the input must be set together with the Run command or the Run command must be entered after giving the Speed Search command.

Method 3. After automatic fault restart.

When the number of maximum fault restarts in parameter L5-01 is set higher than 0, the drive will automatically perform Speed Search as specified by b3-24 following a fault.

Method 4. After momentary power loss.

This mode requires that the Power Loss Ride-Thru function is enabled during CPU operation (L2-01 = 1 or 2). *Refer to L2-01: Momentary Power Loss Operation Selection on page 240* for details.

Method 5. After external baseblock is released.

The drive will resume the operation starting with Speed Search if the Run command is present and the output frequency is above the minimum frequency when the Baseblock command (H1-□□ = 8 or 9) is released.

■ b3-01: Speed Search Selection at Start

Determines if Speed Search is automatically performed when a Run command is issued.

| No. | Parameter Name | Setting Range | Default |
|-------|---------------------------------|---------------|---------|
| b3-01 | Speed Search Selection at Start | 0, 1 | 0 |

Setting 0: Disabled

This setting starts operating the drive at the minimum output frequency when the Run command is entered. If external Speed Search 1 or 2 is already enabled by a digital input, the drive will start operating with Speed Search.

Setting 1: Enabled

This setting performs Speed Search when the Run command is entered. The drive begins running the motor after Speed Search is complete.

■ b3-02: Speed Search Deactivation Current

Sets the operating current for Speed Search as a percentage of the drive rated current. Normally there is no need to change this setting. Lower this value if the drive has trouble restarting.

| No. | Name | Setting Range | Default |
|-------|-----------------------------------|---------------|---------|
| b3-02 | Speed Search Deactivation Current | 0 to 200% | 120% |

■ b3-03: Speed Search Deceleration Time

Sets the output frequency reduction ramp used by the Current Injection Method of Speed Estimation (b3-24 = 1). The time entered into b3-03 will be the time to decelerate from maximum frequency (E1-04) to minimum frequency (E1-09).

| No. | Name | Setting Range | Default |
|-------|--------------------------------|---------------|---------|
| b3-03 | Speed Search Deceleration Time | 0.1 to 10.0 s | 2.0 s |

■ b3-04: V/f Gain During Speed Search

During Speed Search, the output voltage calculated from the V/f pattern is multiplied with this value. Changing this value can help reduce the output current during Speed Search.

| No. | Name | Setting Range | Default |
|-------|------------------------------|---------------|---------------------|
| b3-04 | V/f Gain During Speed Search | 10 to 100% | Determined by o2-04 |

■ b3-05: Speed Search Delay Time

In cases where an output contactor is used between the drive and the motor, the contactor must be closed before Speed Search can be performed. This parameter can be used to delay the Speed Search operation, giving the contactor enough time to close completely.

| No. | Name | Setting Range | Default |
|-------|-------------------------|----------------|---------|
| b3-05 | Speed Search Delay Time | 0.0 to 100.0 s | 0.2 s |

■ b3-06: Output Current 1 During Speed Search

Sets the current injected to the motor at the beginning of Speed Estimation Speed Search as a coefficient for the motor rated current.

5.2 b: Application

| No. | Name | Setting Range | Default |
|-------|--------------------------------------|---------------|---------------------|
| b3-06 | Output Current 1 during Speed Search | 0.0 to 2.0 | Determined by o2-04 |

■ b3-07: Output Current 2 during Speed Search (Speed Estimation Type)

Sets the amount of output current during Speed Estimation Speed Search as a coefficient for the no-load current. Output current during Speed Search is automatically limited by the drive rated current. Increase this setting value in increments of 0.1 if the drive fails to perform Speed Estimation

Note: This parameter is only available in models 4A0930 and 4A1200.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------------------|
| b3-07 | Output Current 2 during Speed Search (Speed Estimation Type) | 0.0 to 5.0 | Determined by o2-04 |

■ b3-08: Current Control Gain during Speed Search (Speed Estimation Type)

Sets the proportional gain for the current controller during Speed Search.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| b3-08 | Current Control Gain during Speed Search (Speed Estimation Type) | 0.00 to 6.00 | 0.8 |

■ b3-09: ACR Integral Time for Speed Search (Speed Estimation Type)

Sets the integral time for the current controller to adjust the responsiveness during a Speed Estimation Speed Search. There is normally no need to change this parameter from the default value.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| b3-09 | ACR Integral Time for Speed Search (Speed Estimation Type) | 0.0 to 1000.0 | 0.0 ms |

Note: This parameter is available in drive software versions PRG: 8504 and later.

■ b3-10: Speed Search Detection Compensation Gain (Speed Estimation Type)

Sets the gain for the detected motor speed of the Speed Estimation Speed Search. Increase the setting only if an overvoltage fault occurs when the drive restarts the motor.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| b3-10 | Speed Search Detection Compensation Gain | 1.00 to 1.20 | 1.05 |

■ b3-12: Minimum Current Detection Level during Speed Search

Sets the minimum current detection level during Speed Search. Increase this setting value in increments of 0.1 if the drive fails to perform Speed Estimation.

Note: This parameter is only available in models 4A0930 and 4A1200.

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------|
| b3-12 | Minimum Current Detection Level during Speed Search | 2.0 to 10.0 | 6.0 |

■ b3-14: Bi-Directional Speed Search Selection

Sets how the drive determines the motor rotation direction when performing Speed Estimation Speed Search.

| No. | Parameter Name | Setting Range | Default |
|-------|---------------------------------------|---------------|---------|
| b3-14 | Bi-Directional Speed Search Selection | 0, 1 | 1 |

Setting 0: Disabled

The drive uses the frequency reference to determine the direction of motor rotation to restart the motor.

Setting 1: Enabled

The drive detects the motor rotation direction to restart the motor.

■ b3-17: Speed Search Restart Current Level (Speed Estimation Type)

Sets the current level at which Speed Estimation is restarted as a percentage of drive rated current to avoid overcurrent and overvoltage problems since a large current can flow into the drive if the difference between the estimated frequency and the actual motor speed is too big when performing Speed Estimation.

| No. | Name | Setting Range | Default |
|-------|------------------------------------|---------------|---------|
| b3-17 | Speed Search Restart Current Level | 0 to 200% | 150% |

■ b3-18: Speed Search Restart Detection Time (Speed Estimation Type)

Sets the time for which the current must be above the level set in b3-17 before restarting Speed Search.

| No. | Name | Setting Range | Default |
|-------|-------------------------------------|----------------|---------|
| b3-18 | Speed Search Restart Detection Time | 0.00 to 1.00 s | 0.10 s |

■ b3-19: Number of Speed Search Restarts (Speed Estimation Type)

Sets the number of times the drive should attempt to find the speed and restart the motor. If the number of restart attempts exceeds the value set to b3-19, the SEr fault will occur and the drive will stop.

| No. | Name | Setting Range | Default |
|-------|---------------------------------|---------------|---------|
| b3-19 | Number of Speed Search Restarts | 0 to 10 | 3 |

■ b3-24: Speed Search Method Selection

Sets the Speed Search method.

| No. | Parameter Name | Setting Range | Default |
|-------|-------------------------------|---------------|---------|
| b3-24 | Speed Search Method Selection | 0, 1 | 0 |

Setting 0: Current Detection

Setting 1: Speed Estimation

Note: Refer to *Current Detection Speed Search (b3-24 = 0)* on page 153 and *Refer to Speed Estimation Type Speed Search (b3-24 = 1)* on page 154 for explanations of the Speed Search methods.

■ b3-25: Speed Search Wait Time

Sets the wait time between Speed Search restarts. Increase the wait time if problems occur with overcurrent, overvoltage, or if the SEr fault occurs.

| No. | Name | Setting Range | Default |
|-------|------------------------|---------------|---------|
| b3-25 | Speed Search Wait Time | 0.0 to 30.0 s | 0.5 s |

■ b3-26: Direction Determining Level

Sets the level that determines the direction of motor rotation. Increase this value if the drive fails to detect the direction of the motor correctly.

Note: This parameter is only available in models 4A0930 and 4A1200.

| No. | Name | Setting Range | Default |
|-------|-----------------------------|---------------|---------------------|
| b3-26 | Direction Determining Level | 40 to 60000 | Determined by o2-04 |

■ b3-27: Start Speed Search Select

Selects a condition to activate Speed Search Selection at Start (b3-01) or External Speed Search Command 1 or 2 from the multi-function input.

| No. | Name | Setting Range | Default |
|-------|---------------------------|---------------|---------|
| b3-27 | Start Speed Search Select | 0, 1 | 0 |

5.2 b: Application

Setting 0: Triggered when a Run Command Is Issued (Normal)

Setting 1: Triggered when an External Baseblock Is Released

◆ b4: Timer Function

The timer function is independent of drive operation and can delay the switching of a digital output triggered by a digital input signal and help eliminate chattering switch noise from sensors. An on-delay and off-delay can be set separately.

To enable the timer function, set a multi-function input to “Timer Function Input” (H1-□□ = 18) and set a multi-function output to “Timer output” (H2-□□ = 12). Only one timer can be used.

■ b4-01, b4-02: Timer Function On-Delay, Off-Delay Time

b4-01 sets the on-delay time for switching the timer output. b4-02 sets the off-delay time for switching the timer output.

| No. | Name | Setting Range | Default |
|-------|-------------------------------|-----------------|---------|
| b4-01 | Timer Function On-Delay Time | 0.0 to 3000.0 s | 0.0 s |
| b4-02 | Timer Function Off-Delay Time | 0.0 to 3000.0 s | 0.0 s |

■ Timer Function Operation

The timer function switches on when the timer function input closes for longer than the value set to b4-01. The timer function switches off when the timer function input is open for longer than the value set to b4-02. *Figure 5.13* illustrates the timer function operation:

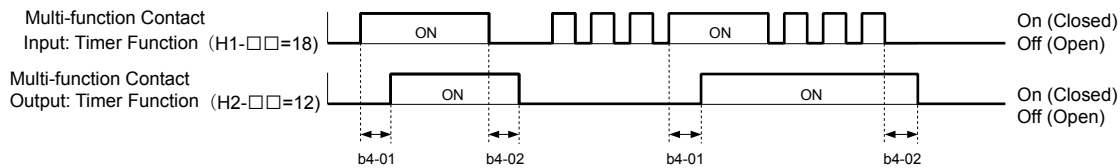


Figure 5.13 Timer Operation

◆ b5: PID Control

The drive has a built-in Proportional + Integral + Derivative (PID) controller that uses the difference between the target value and the feedback value to adjust the drive output frequency to minimize deviation and provide accurate closed loop control of system variables such as pressure or temperature.

■ P Control

The output of P control is the product of the deviation and the P gain so that it follows the deviation directly and linearly. With P control, only an offset between the target and feedback remains.

■ I Control

The output of I control is the integral of the deviation. It minimizes the offset between target and feedback value that typically remains when pure P control is used. The integral time (I time) constant determines how fast the offset is eliminated.

■ D Control

D control predicts the deviation signal by multiplying its derivative (slope of the deviation) with a time constant, then adds this value to the PID input. This way the D portion of a PID controller provides a braking action to the controller response and can reduce the tendency to oscillate and overshoot.

D control tends to amplify noise on the deviation signal, which can result in control instability. Only use D control when absolutely necessary.

■ PID Operation

To better demonstrate PID functionality, *Figure 5.14* illustrates the PID output when the PID input (deviation) is at a constant level.

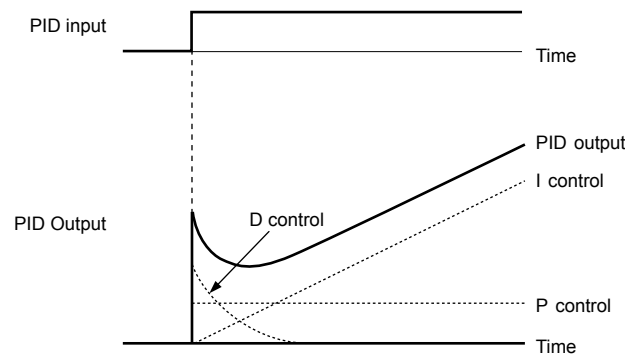


Figure 5.14 PID Operation

Using PID Control

Applications for PID control are listed in [Table 5.8](#).

Table 5.8 Using PID Control

| Application | Description | Sensors Used |
|---------------------|---|---------------------------|
| Speed Control | Machinery speed is fed back and adjusted to meet the target value. Synchronous control is performed using speed data from other machinery as the target value | Tachometer |
| Pressure | Maintains constant pressure using pressure feedback. | Pressure sensor |
| Fluid Control | Keeps flow at a constant level by feeding back flow data. | Flow rate sensor |
| Temperature Control | Maintains a constant temperature by controlling a fan with a thermostat. | Thermocoupler, Thermistor |

PID Setpoint Input Methods

The PID setpoint input can be input from one of the sources listed in [Table 5.9](#).

If none of the sources listed in [Table 5.9](#) are used, the frequency reference source in b1-01 (or b1-15) or one of the inputs listed in [Table 5.9](#) becomes the PID setpoint.

Table 5.9 PID Setpoint Sources

| PID Setpoint Source | Settings |
|--------------------------------|---|
| Analog Input A1 | Set H3-02 = C |
| Analog Input A2 | Set H3-10 = C |
| Analog Input A3 | Set H3-06 = C |
| MEMOBUS/Modbus Register 0006 H | Set bit 1 in register 000F H to 1 and input the setpoint to register 0006 H |
| Pulse Input RP | Set H6-01 = 2 |
| Parameter b5-19 | Set parameter b5-18 = 1 and input the PID setpoint to b5-19 |

Note: A duplicate allocation of the PID setpoint input will cause an oPE07 (Multi-Function Analog Input Selection Error) alarm.

PID Feedback Input Methods

Input one feedback signal for normal PID control or input two feedback signals can for controlling a differential process value.

Normal PID Feedback

Input the PID feedback signal from one of the sources listed in [Table 5.10](#):

Table 5.10 PID Feedback Sources

| PID Feedback Source | Settings |
|---------------------|---------------|
| Analog Input A1 | Set H3-02 = B |
| Analog Input A2 | Set H3-10 = B |
| Analog Input A3 | Set H3-06 = B |
| Pulse Input RP | Set H6-01 = 1 |

Note: A duplicate allocation of the PID feedback input will cause an oPE07 (Multi-Function Analog Input Selection Error) alarm.

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Differential Feedback

The second PID feedback signal for differential feedback can come from the sources listed in [Table 5.11](#). The differential feedback function is automatically enabled when a differential feedback input is assigned.

Table 5.11 PID Differential Feedback Sources

| PID Differential Feedback Source | Settings |
|----------------------------------|--|
| Analog Input A1 | Set H3-02 = 16 (Differential PID Feedback) |
| Analog Input A2 | Set H3-10 = 16 (Differential PID Feedback) |
| Analog Input A3 | Set H3-06 = 16 (Differential PID Feedback) |

Note: A duplicate allocation of the PID differential feedback input will cause an oPE07 (Multi-Function Analog Input Selection Error) alarm.

■ PID Block Diagram

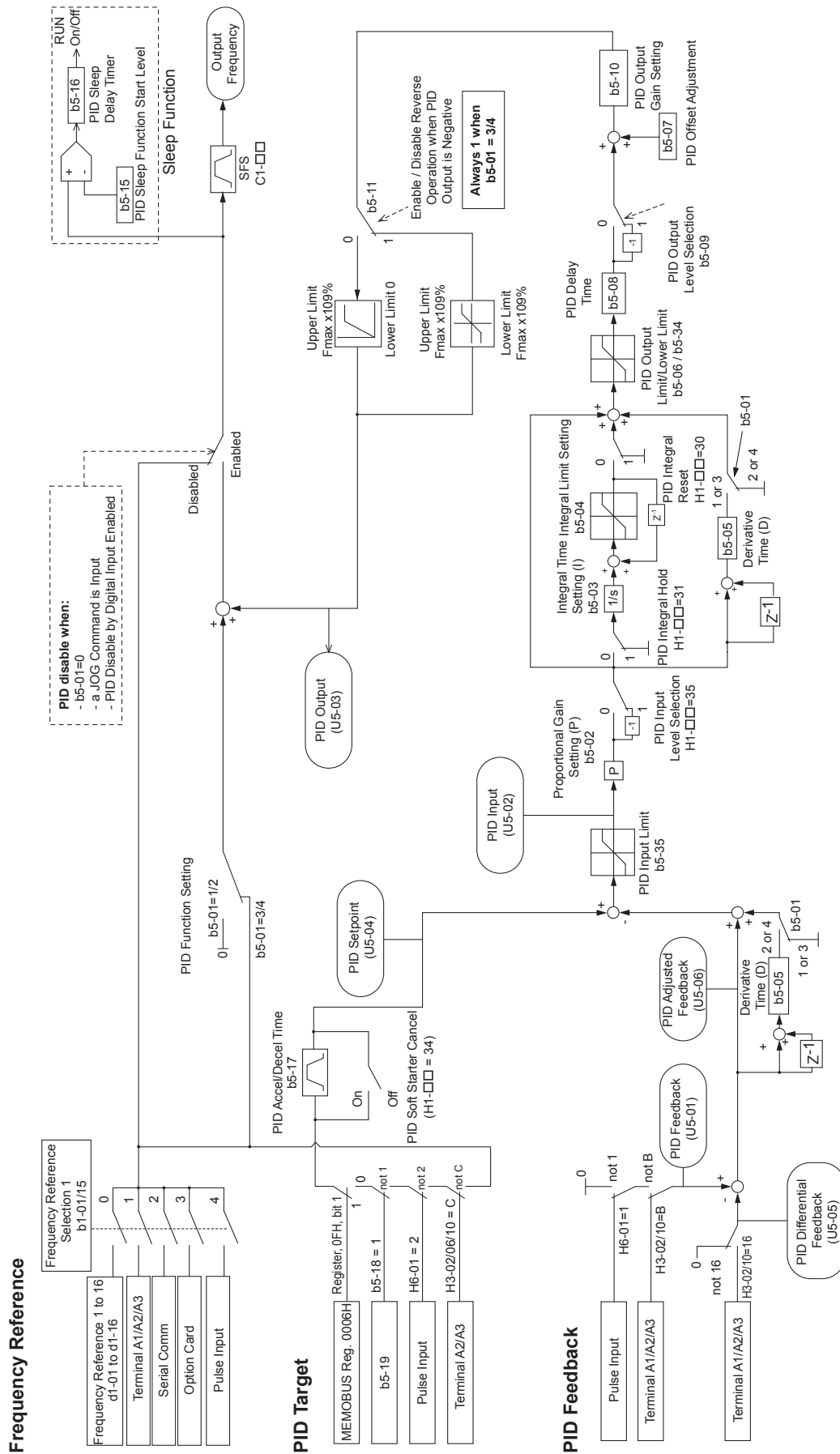


Figure 5.15 PID Block Diagram

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■ b5-01: PID Function Setting

Enables and disables the PID operation and selects the PID operation mode.

| No. | Parameter Name | Setting Range | Default |
|-------|----------------------|---------------|---------|
| b5-01 | PID Function Setting | 0, 1 | 0 |

Setting 0: PID disabled

Setting 1: Output frequency = PID output 1

The PID controller is enabled and the PID output builds the frequency reference. The PID input is D controlled.

■ b5-02: Proportional Gain Setting (P)

Sets the P gain applied to the PID input. Larger values will tend to reduce the error but may cause oscillations if set too high, while lower values may allow too much offset between the setpoint and feedback.

| No. | Name | Setting Range | Default |
|-------|-------------------------------|---------------|---------|
| b5-02 | Proportional Gain Setting (P) | 0.00 to 25.00 | 2.00 |

■ b5-03: Integral Time Setting (I)

Sets the time constant used to calculate the integral of the PID input. The shorter the integral time set to b5-03, the faster the offset will be eliminated. If the integral time is set too short, however, overshoot or oscillation may occur. To turn off the integral time, set b5-03 to 0.00.

| No. | Name | Setting Range | Default |
|-------|---------------------------|----------------|---------|
| b5-03 | Integral Time Setting (I) | 0.0 to 360.0 s | 1.0 s |

■ b5-04: Integral Limit Setting

Sets the maximum output possible from the integral block as a percentage of the maximum frequency (E1-04).

| No. | Name | Setting Range | Default |
|-------|------------------------|---------------|---------|
| b5-04 | Integral Limit Setting | 0.0 to 100.0% | 100.0% |

Note: On some applications, especially those with rapidly varying loads, the output of the PID function may show a fair amount of oscillation. Program b5-04 to apply a limit to the integral output and suppress this oscillation.

■ b5-05: Derivative Time (D)

Sets the time the drive predicts the PID input/PID feedback signal based on the derivative of the PID input/PID feedback. Longer time settings improve the response but can cause instability, while shorter time settings reduce the overshoot but reduce controller responsiveness. D control is disabled by setting b5-05 to zero seconds.

| No. | Name | Setting Range | Default |
|-------|---------------------|-----------------|---------|
| b5-05 | Derivative Time (D) | 0.00 to 10.00 s | 0.00 s |

■ b5-06: PID Output Limit

Sets the maximum output possible from the entire PID controller as a percentage of the maximum frequency (E1-04).

| No. | Name | Setting Range | Default |
|-------|------------------|---------------|---------|
| b5-06 | PID Output Limit | 0.0 to 100.0% | 100.0% |

■ b5-07: PID Offset Adjustment

Sets the offset added to the PID controller output as a percentage of the maximum frequency (E1-04).

| No. | Name | Setting Range | Default |
|-------|-----------------------|------------------|---------|
| b5-07 | PID Offset Adjustment | -100.0 to 100.0% | 0.0% |

■ b5-08: PID Primary Delay Time Constant

Sets the time constant for the filter applied to the output of the PID controller. Normally, change is not required.

| No. | Name | Setting Range | Default |
|-------|---------------------------------|-----------------|---------|
| b5-08 | PID Primary Delay Time Constant | 0.00 to 10.00 s | 0.00 s |

Note: Useful when there is a fair amount of oscillation or when rigidity is low. Set to a value larger than the cycle of the resonant frequency. Increasing this time constant may reduce the responsiveness of the drive.

■ b5-09: PID Output Level Selection

Reverses the sign of the PID controller output signal. Normally a positive PID input (feedback smaller than setpoint) leads to positive PID output.

| No. | Parameter Name | Setting Range | Default |
|-------|----------------------------|---------------|---------|
| b5-09 | PID Output Level Selection | 0, 1 | 0 |

Setting 0: Normal Output

A positive PID input causes an increase in the PID output (direct acting).

Setting 1: Reverse Output

A positive PID input causes a decrease in the PID output (reverse acting).

■ b5-10: PID Output Gain Setting

Applies a gain to the PID output and can be helpful when the PID function is used to trim the frequency reference (b5-01 = 3 or 4).

| No. | Name | Setting Range | Default |
|-------|-------------------------|---------------|---------|
| b5-10 | PID Output Gain Setting | 0.00 to 25.00 | 1.00 |

■ b5-11: PID Output Reverse Selection

Determines whether a negative PID output reverses the direction of drive operation. This parameter has no effect when the PID function trims the frequency reference (b5-01 = 3 or 4) and the PID output will not be limited (same as b5-11 = 1).

Note: When using setting 1, make sure reverse operation is permitted by b1-04.

| No. | Parameter Name | Setting Range | Default |
|-------|------------------------------|---------------|---------|
| b5-11 | PID Output Reverse Selection | 0, 1 | 0 |

Setting 0: Reverse Disabled

Negative PID output will be limited to 0 and the drive output will be stopped.

Setting 1: Reverse Enabled

Negative PID output will cause the drive to run in the opposite direction.

■ PID Feedback Loss Detection

The PID feedback loss detection function detects broken sensors or broken sensor wiring. It should be used when PID control is enabled to prevent critical machine conditions (e.g., acceleration to max. frequency) caused by a feedback loss.

Feedback loss can be detected in two ways:

- **Feedback Low Detection**

Detected when the feedback falls below a certain level for longer than the specified time. This function is set up using parameters b5-12 to b5-14.

- **Feedback High Detection**

Detected when the feedback rises above a certain level for longer than the specified time. This function is set up using parameters b5-12, b5-36, and b5-37.

The following figure illustrates the working principle of feedback loss detection when the feedback signal is too low. Feedback high detection works in the same way.

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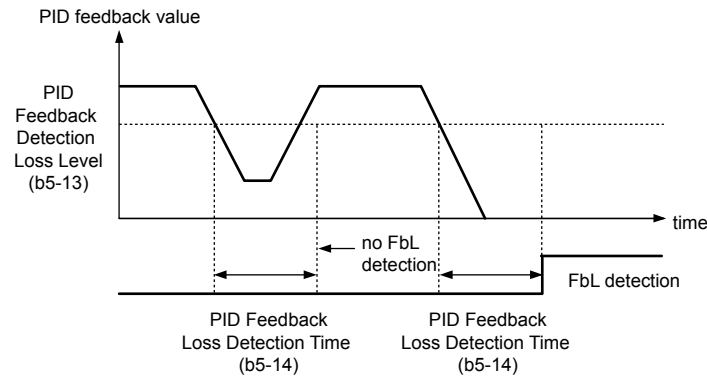


Figure 5.16 PID Feedback Loss Detection

■ b5-12: PID Feedback Loss Detection Selection

Enables or disables the feedback loss detection and sets the operation when a feedback loss is detected.

| No. | Parameter Name | Setting Range | Default |
|-------|---------------------------------------|---------------|---------|
| b5-12 | PID Feedback Loss Detection Selection | 0 to 5 | 0 |

Setting 0: Multi-Function Digital Outputs Only

Multi-function digital outputs set for “PID feedback low” (H2-□□ = 3E) will be triggered if the PID feedback value is below the detection level set to b5-13 for the time set to b5-14 or longer. Multi-function digital outputs set for “PID feedback high” (H2-□□ = 3F) will be triggered if the PID feedback value is beyond the detection level set to b5-36 for longer than the time set to b5-37. Neither a fault nor an alarm is displayed on the digital operator and the drive will continue operation. The multi-function digital outputs reset when the feedback value leaves the loss detection range.

Setting 1: Feedback Loss Alarm

If the PID feedback value falls below the level set to b5-13 for longer than the time set to b5-14, a “FbL - Feedback Low” alarm will be displayed and a digital output set for “PID feedback low” (H2-□□ = 3E) will be triggered. If the PID feedback value exceeds the level set to b5-36 for longer than the time set to b5-37, a “FbH - Feedback High” alarm will be displayed and a digital output set for “PID feedback high” (H2-□□ = 3F) will be triggered. Both events trigger an alarm output (H2-□□ = 10). The drive will continue operation. The alarm and multi-function digital outputs reset when the feedback value leaves the loss detection range.

Setting 2: Feedback Loss Fault

If the PID feedback value falls below the level set to b5-13 for longer than the time set to b5-14, a “FbL - Feedback Low” fault will be displayed. If the PID feedback value exceeds the level set to b5-36 for longer than the time set to b5-37, a “FbH - Feedback High” fault will be displayed. Both events trigger a fault output (H2-□□ = E) and cause the drive to stop the motor.

Setting 3: Digital Output Only, even if PID Is Disabled by Digital Input

Same as b5-12 = 0. Detection remains active when PID is disabled by a digital input (H1-□□ = 19).

Setting 4: Feedback Loss Alarm, even if PID Is Disabled by Digital Input

Same as b5-12 = 1. Detection remains active when PID is disabled by a digital input (H1-□□ = 19).

Setting 5: Feedback Loss fault, even if PID Is Disabled by Digital Input

Same as b5-12 = 2. Detection remains active when PID is disabled by a digital input (H1-□□ = 19).

■ b5-13: PID Feedback Low Detection Level

Sets the PID feedback detection low level as a percentage of E1-04 (Maximum Output Frequency). The PID feedback must fall below this level for longer than the time set to b5-14 before feedback loss is detected.

| No. | Name | Setting Range | Default |
|-------|----------------------------------|---------------|---------|
| b5-13 | PID Feedback Low Detection Level | 0 to 100% | 0% |

■ b5-14: PID Feedback Low Detection Time

Sets the time that the PID feedback has to fall below b5-13 before feedback loss is detected.

| No. | Name | Setting Range | Default |
|-------|----------------------------------|---------------|---------|
| b5-14 | PID Feedback Loss Detection Time | 0.0 to 25.5 s | 1.0 s |

■ b5-36: PID Feedback High Detection Level

Sets the excessive PID feedback detection high level as a percentage of E1-04 (Maximum Output Frequency). The PID feedback must exceed this level for longer than the time set to b5-37 before feedback loss is detected.

| No. | Name | Setting Range | Default |
|-------|-----------------------------------|---------------|---------|
| b5-36 | PID Feedback High Detection Level | 0 to 100% | 100% |

■ b5-37: PID Feedback High Detection Time

Sets the time that the PID feedback must exceed the value set to b5-36 before feedback loss is detected.

| No. | Name | Setting Range | Default |
|-------|----------------------------------|---------------|---------|
| b5-37 | PID Feedback High Detection Time | 0.0 to 25.5 s | 1.0 s |

■ PID Sleep

The PID Sleep function stops the drive when the PID output or the frequency reference falls below the PID Sleep operation level for a certain time. The drive will resume operating when the PID output or frequency reference rise above the PID Sleep operation level for the specified time. An example of PID Sleep operation appears in the figure below.

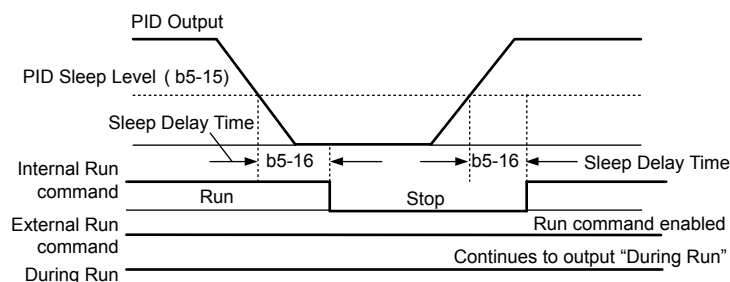


Figure 5.17 PID Sleep Operation

Notes on using the PID Sleep function

- The PID Sleep function is active even when PID control is disabled.
- The PID Sleep function stops the motor according to the stopping method set to b1-03.

The parameters necessary to control the PID Sleep function are explained below.

■ b5-15: PID Sleep Function Start Level

Sets the level that triggers PID Sleep.

The drive goes into Sleep mode if the PID output or frequency reference is smaller than b5-15 for longer than the time set to b5-16. The drive resumes operation when the PID output or frequency reference is above b5-15 for longer than the time set to b5-16.

| No. | Name | Setting Range | Default |
|-------|--------------------------------|-----------------|---------|
| b5-15 | PID Sleep Function Start Level | 0.0 to 400.0 Hz | 0.0 Hz |

■ b5-16: PID Sleep Delay Time

Sets the delay time to activate or deactivate the PID Sleep function.

| No. | Name | Setting Range | Default |
|-------|----------------------|---------------|---------|
| b5-16 | PID Sleep Delay Time | 0.0 to 25.5 s | 0.0 s |

■ b5-17: PID Accel/Decel Time

The PID acceleration/deceleration time is applied on the PID setpoint value.

When the setpoint changes quickly, the normal C1-□□ acceleration times reduce the responsiveness of the system as they are applied after the PID output. The PID accel/decel time helps avoid the hunting and overshoot and undershoot that can result from the reduced responsiveness.

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The PID acceleration/deceleration time can be canceled using a digital input programmed for “PID SFS cancel” (H1-□□ = 34).

| No. | Name | Setting Range | Default |
|-------|----------------------|-----------------|---------|
| b5-17 | PID Accel/Decel Time | 0.0 to 6000.0 s | 0.0 s |

■ b5-18: PID Setpoint Selection

Enables or disables parameter b5-19 for PID setpoint.

Refer to [Figure 5.18](#) for the digital operator home screen display when PID is enabled and b5-18 is set to 1, enabling PID Setpoint Selection.

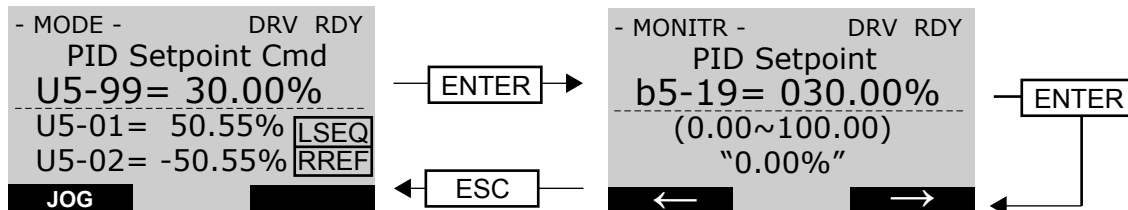


Figure 5.18 PID Setpoint Selection Display

| No. | Parameter Name | Setting Range | Default |
|-------|------------------------|---------------|---------|
| b5-18 | PID Setpoint Selection | 0, 1 | 0 |

Setting 0: Disabled

Parameter b5-19 is not used as the PID setpoint.

Setting 1: Enabled

Parameter b5-19 is used as PID setpoint.

■ b5-19: PID Setpoint Value

Used as the PID setpoint if parameter b5-18 = 1.

Note: Values set above b5-38 will be internally limited to b5-38.

| No. | Name | Setting Range | Default |
|-------|--------------------|-----------------|---------|
| b5-19 | PID Setpoint Value | 0.00 to 600.00% | 0.00% |

◆ EZ Sleep/Wake-up Function

To enable EZ Sleep/Wake-up functionality on the drive, first set parameter b5-89 to 1. The default setting for b5-89 is 0, which disables the EZ Sleep functionality and related parameters, except for parameter b5-91, EZ Sleep Minimum Speed.

Setting b5-89 to 1 disables the existing PID Sleep function (b5-15) and enables the EZ Sleep/Wake-up functionality.

EZ Sleep and Minimum Speed Units

Parameter b5-90, EZ Sleep Unit, determines the unit, range, and resolution of parameters b5-92 and b5-93. When set to Hz, the range is 0.1 to 400.0 Hz. When set to RPM, the range is 0 to 24000 RPM. Changing b5-90 will NOT automatically re-scale the values of b5-92 and b5-93.

Minimum Speed

Parameter b5-91, EZ Minimum Speed, acts as a lower limit on the PID output. This value is internally limited to the higher value between b5-34 or d2-02 and is active regardless of the b5-89 setting. When this limit is active, the PID integrator will be held to avoid integral wind-up. Parameter b5-90 determines whether the value is input in Hz or RPM.

Sleep

When the output frequency (or speed) is at or below the EZ Sleep Level (b5-92) for the time set in EZ Sleep Time (b5-93), the drive will sleep. The EZ Sleep Level is internally lower limited to the b5-92 setting.

Wake-up using Absolute Level (b5-95 = 0)

For Normal Acting PID, the PID Feedback must drop below the EZ Wake-up Level (b5-94) for the time set in EZ Wake-up Time (b5-96) in order for the drive to wake-up.

For Reverse Acting PID, the PID Feedback must rise above the b5-94 level for the time set in b5-96 in order for the drive to wake-up.

Wake-up using Setpoint Delta Level (b5-95 = 1)

For Normal Acting PID, the wake-up level is determined by the PID Setpoint minus the b5-94 level. The PID Feedback must drop below the wake-up level for the time set in b5-96 in order for the drive to wake-up

For Reverse Acting PID, the wake-up level is determined by the PID Setpoint plus the b5-94 level. The PID Feedback must rise above the wake-up level for the time set in b5-96 in order for the drive to wake-up.

Refer to *Figure 5.19* and *Figure 5.20* for detailed diagrams of EZ Sleep/Wake-up functions.

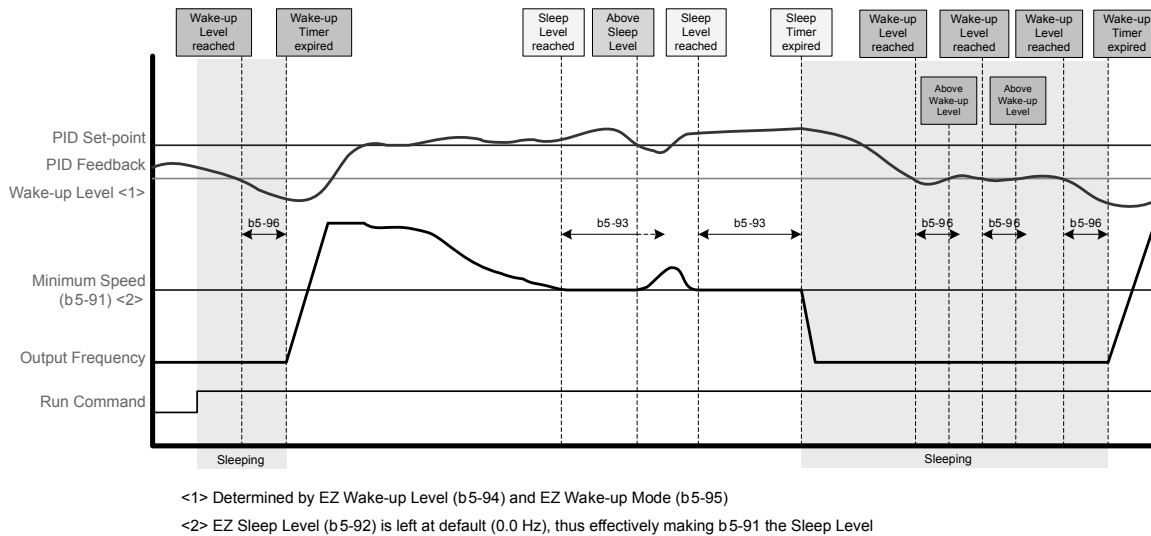


Figure 5.19 EZ Sleep/Wake-up with Normal Acting PID and b5-92 = 0.0 Hz

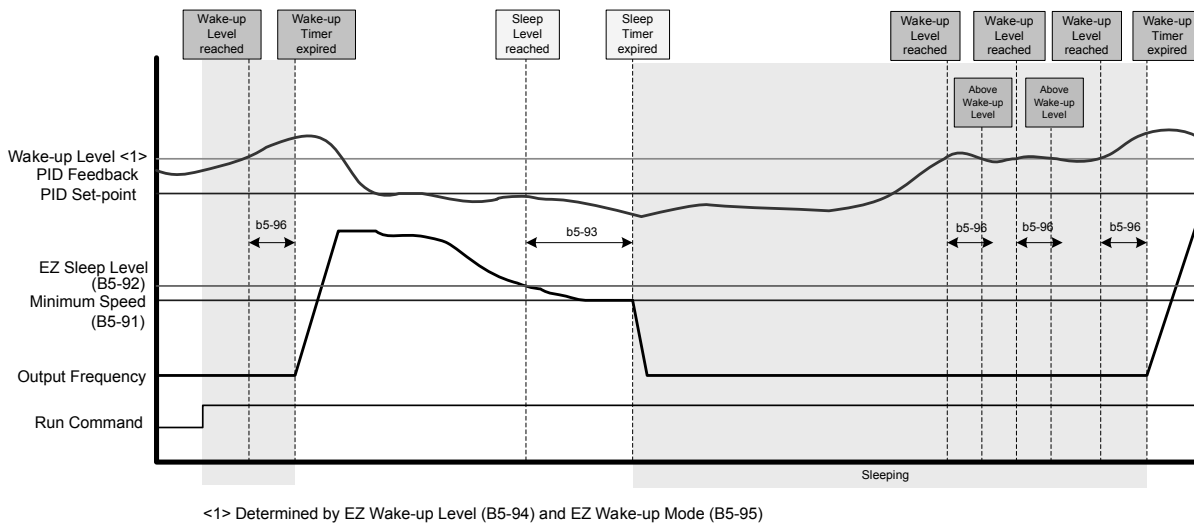


Figure 5.20 EZ Sleep/Wake-up with Reverse Acting PID and b5-92 > b5-91

■ b5-20: PID Setpoint Scaling

Determines the units for the PID Setpoint Value (b5-19) and monitors U5-01 and U5-04.

| No. | Parameter Name | Setting Range | Default |
|-------|----------------------|---------------|---------|
| b5-20 | PID Setpoint Scaling | 0 to 3 | 1 |

Setting 0: 0.01 Hz

The setpoint and PID monitors are displayed in Hz with a resolution of 0.01 Hz.

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Setting 1: 0.01% (100.00%: Maximum Frequency)

The setpoint and PID monitors are displayed as a percentage with a resolution of 0.01%.

Setting 2: r/min (Set the Motor Poles)

The setpoint and PID monitors are displayed in r/min with a resolution of 1 r/min.

Setting 3: User Defined (Determined by b5-38 and b5-39)

Parameters b5-38 and b5-39 determine the units based on b5-46 setting.

■ b5-38, b5-39: PID Setpoint User Display, PID Setpoint Display Digits

When parameter b5-20 is set to 3, parameters b5-38 and b5-39 set a user-defined display for the PID setpoint (b5-19) and PID feedback monitors (U5-01, U5-04).

Parameter b5-38 determines the display value when the maximum frequency is output and parameter b5-39 determines the number of digits. The setting value is equal to the number of decimal places.

| No. | Name | Setting Range | Default |
|-------|-----------------------------|---------------|---------|
| b5-38 | PID Setpoint User Display | 1 to 60000 | 10000 |
| b5-39 | PID Setpoint Display Digits | 0 to 3 | 2 |

Setting 0: No decimal places

Setting 1: One decimal place

Setting 2: Two decimal places

Setting 3: Three decimal places

■ b5-46: PID Setpoint Monitor Unit Selection

Sets the digital operator display units in U5-01 and U5-04 when b5-20 is set to 3.

| No. | Name | Setting Range | Default |
|-------|------------------------------------|---------------|---------|
| b5-46 | PI Setpoint Monitor Unit Selection | 0 to 15; 25 | 0 |

Setting 0: WC (Inch of Water)

Setting 1: PSI (Pounds per Square Inch)

Setting 2: GPM (Gallons per Minute)

Setting 3: F (Degrees Fahrenheit)

Setting 4: CFM (Cubic Feet per Minute)

Setting 5: CMH (Cubic Meters per Hour)

Setting 6: LPH (Liters per Hour)

Setting 7: LPS (Liters per Second)

Setting 8: Bar (Bar)

Setting 9: Pa (Pascal)

Setting 10: C (Degrees Celsius)

Setting 11: Mtr (Meters)

Setting 12: Ft (Feet)

Setting 13: LPN (Liters per Minute)

Setting 14: CMM (Cubic Meters per Minute)

Setting 15: "Hg (Inches of Mercury)

Setting 25: None

■ b5-89: Sleep Method Selection

Determines how the drive sleeps and wakes-up when using PID.

| No. | Name | Setting Range | Default |
|-------|------------------------|---------------|---------|
| b5-89 | Sleep Method Selection | 0, 1 | 0 |

Setting 0: Standard**Setting 1: EZ Sleep/Wake-up****■ b5-90: EZ Sleep Unit**

Sets the unit, range, and resolution of parameters b5-91 and b5-92.

| No. | Name | Setting Range | Default |
|-------|---------------|---------------|---------|
| b5-90 | EZ Sleep Unit | 0, 1 </> | 0 |

<1> Unit and resolution are determined by b5-20, b5-39, and b5-46. Internally limited to b5-38. Changing b5-20, b5-38 and b5-39 will not automatically update the value of this parameter.

Setting 0: Hz**Setting 1: RPM (number of motor poles must be entered)****■ b5-91: EZ Minimum Speed**

Sets the PID minimum speed and integral lower limit.

The lower limit of the internal value is the higher of b5-34 and d2-02.

| No. | Name | Setting Range | Default |
|-------|------------------|--|---------|
| b5-91 | EZ Minimum Speed | 0.0 to 400.0 Hz </> or 0 to 24000 RPM | 0.0 |

<1> Unit and resolution are determined by b5-20, b5-39, and b5-46. Internally limited to b5-38. Changing b5-20, b5-38 and b5-39 will not automatically update the value of this parameter.

■ b5-92: EZ Sleep Level

When the drive output frequency (or speed) is at or below this level for the time set in b5-93, the drive will go to sleep.

The internal lower limit of this parameter is b5-91 (EZ Min Speed) + 1 Hz.

| No. | Name | Setting Range | Default |
|-------|----------------|--|---------|
| b5-92 | EZ Sleep Level | 0.0 to 400.0 Hz </> or 0 to 24000 RPM | 0.0 |

<1> Unit and resolution are determined by b5-20, b5-39, and b5-46. Internally limited to b5-38. Changing b5-20, b5-38 and b5-39 will not automatically update the value of this parameter.

■ b5-93: EZ Sleep Time

The drive will go to sleep when the drive output frequency is at or below the level set to b5-92 for the time set in this parameter.

| No. | Name | Setting Range | Default |
|-------|--------------|--------------------|---------|
| b5-93 | EZ Sleep Tim | 0.0 to 10000.0 </> | 5.0 s |

<1> Unit and resolution are determined by b5-20, b5-39, and b5-46. Internally limited to b5-38. Changing b5-20, b5-38 and b5-39 will not automatically update the value of this parameter.

■ b5-94: EZ Wake-up Level

If b5-95 is set to 0 (Absolute), the drive wakes-up when the PID Feedback (H3-□□ = 20) drops below this level for the time set in b5-96. For reverse-acting, the PID Feedback has to be above this level for the time set in b5-96.

If b5-95 is set to 1 (Setpoint Delta), the drive wakes-up when the PID Feedback (H3-□□ = 20) drops below the PID Setpoint minus this level (for normal acting PID) for the time set in b5-96. For reverse-acting, Wake-up level is PID Setpoint plus this level. The PID Feedback has to be above the wake-up level for the time set in b5-96.

| No. | Name | Setting Range | Default |
|-------|------------------|---------------------|---------|
| b5-94 | EZ Wake-up Level | 0.00 to 600.00% </> | 0.00 |

<1> Unit and resolution are determined by b5-20, b5-39, and b5-46. Internally limited to b5-38. Changing b5-20, b5-38 and b5-39 will not automatically update the value of this parameter.

■ b5-95: EZ Wake-up Mode

Sets how the wake-up level is determined.

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| No. | Name | Setting Range | Default |
|-------|-----------------|---------------|---------|
| b5-95 | EZ Wake-up Mode | 0, 1 </> | 0 |

<1> Unit and resolution are determined by b5-20, b5-39, and b5-46. Internally limited to b5-38. Changing b5-20, b5-38 and b5-39 will not automatically update the value of this parameter.

Setting 0: Absolute

Setting 1: Setpoint Data

■ b5-96: EZ Wake-up Time

The drive will wake up when the PID Feedback drops below the b5-94, EZ Wake-up Level for the time set in this parameter.

| No. | Name | Setting Range | Default |
|-------|-----------------|-------------------|---------|
| b5-96 | EZ Wake-up Time | 0.0 to 1000.0 </> | 1.0 s |

<1> Unit and resolution are determined by b5-20, b5-39, and b5-46. Internally limited to b5-38. Changing b5-20, b5-38 and b5-39 will not automatically update the value of this parameter.

■ b5-34: PID Output Lower Limit

Sets the minimum possible PID controller output as a percentage of the maximum output frequency (E1-04). The lower limit is disabled when set to 0.00%

| No. | Name | Setting Range | Default |
|-------|------------------------|------------------|---------|
| b5-34 | PID Output Lower Limit | -100.0 to 100.0% | 0.00% |

■ b5-35: PID Input Limit

Sets the maximum allowed PID input as a percentage of the maximum output frequency (E1-04). Parameter b5-35 acts as a bipolar limit.

| No. | Name | Setting Range | Default |
|-------|-----------------|----------------|---------|
| b5-35 | PID Input Limit | 0.0 to 1000.0% | 1000.0% |

■ b5-40: Frequency Reference Monitor Content During PID

Sets the content of the frequency reference monitor display (U1-01) when PID control is active.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| b5-40 | Frequency Reference Monitor Content During PID | 0, 1 | 0 |

Setting 0: Frequency Reference after PID

Monitor U1-01 displays the frequency reference increased or reduced for the PID output.

Setting 1: Frequency Reference

Monitor U1-01 displays the frequency reference value.

■ b5-41: PI Unit Selection

Sets the display units in U5-14 and U5-15.

| No. | Name | Setting Range | Default |
|-------|----------------------------|---------------|---------|
| b5-41 | PI Output 2 Unit Selection | 0 to 15; 25 | 0 |

Setting 0: WC (Inch of Water)

Setting 1: PSI (Pounds per Square Inch)

Setting 2: GPM (Gallons per Minute)

Setting 3: F (Degrees Fahrenheit)

Setting 4: CFM (Cubic Feet per Minute)

Setting 5: CMH (Cubic Meters per Hour)

Setting 6: LPH (Liters per Hour)

Setting 7: LPS (Liters per Second)

Setting 8: Bar (Bar)

Setting 9: Pa (Pascal)

Setting 10: C (Degrees Celsius)

Setting 11: Mtr (Meters)

Setting 12: Ft (Feet)

Setting 13: LPM (Liters per Minute)

Setting 14: CMM (Cubic Meters per Minute)

Setting 15: Hg (Inches of Mercury)

Setting 25: None

■ b5-42: PI Output Monitor Calculation Method

| No. | Name | Setting Range | Default |
|-------|--------------------------------------|---------------|---------|
| b5-42 | PI Output Monitor Calculation Method | 0 to 3 | 0 |

Setting 0: Linear

The monitor displays PID output.

Setting 1: Square Root

The monitor displays square root PID output.

Setting 2: Quadratic

The monitor displays $1/(\text{PID output})^2$

Setting 3: Cubic

The monitor displays $1/(\text{PID output})^3$

Note: Used for U5-14 and U5-15 only.

■ b5-43/b5-44: PI Output 2 Monitor Max Upper/Lower 4 Digits

Set the maximum monitor value at maximum frequency. U5-14 and U5-15 show Custom PI output. U5-14 shows the upper 4 digits and U5-15 shows the lower 4 digits.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| b5-43 | PI Output 2 Monitor Max Upper 4 Digits | 0 to 9999 | 0 |
| b5-44 | PI Output 2 Monitor Max Lower 4 Digits | 0.00 to 99.99 | 0.00 |

Note: Used for U5-14 and U5-15 only.

■ b5-45: PI Output 2 Monitor Minimum

U5-14 and U5-15 show Custom PI Output. b5-45 sets the minimum display value at zero speed. This function is effective when b5-42 is set to 0 (Linear).

Note: Used for U5-14 and U5-15 only.

| No. | Name | Setting Range | Default |
|-------|-----------------------------|---------------|---------|
| b5-45 | PI Output 2 Monitor Minimum | 0.0 to 999.9 | 0.0 |

Note: Used for U5-14 and U5-15 only.

5.2 b: Application

■ b5-47: PID Output Reverse Selection 2

Determines whether a negative PID output reverses the direction of drive operation. When the PID function is used to trim the frequency reference (b5-01 = 3 or 4), this parameter has no effect and the PID output will not be limited (same as b5-11 = 1).

| No. | Name | Setting Range | Default |
|-------|--------------------------------|---------------|---------|
| b5-47 | PID Output Reverse Selection 2 | 0, 1 | 1 |

Setting 0: Reverse Disabled

Negative PID output will be limited to 0 and the drive output will be stopped.

Setting 1: Reverse Enabled

Negative PID output will cause the drive to run in the opposite direction.

■ Fine-Tuning PID

Follow the directions below to fine tune PID control parameters:

Table 5.12 PID Fine Tuning

| Goal | Tuning Procedure | Result |
|--|---|---|
| Suppress overshoot | <ul style="list-style-type: none"> Reduce the derivative time (b5-05) Increase the integral time (b5-03) | <p>The graph plots Response vs. Time. A horizontal dashed line represents the target. Two curves start from the origin: 'Before adjustment' has a higher peak and takes longer to settle; 'After adjustment' has a lower peak and settles faster.</p> |
| Achieve stability quickly while allowing some overshoot | <ul style="list-style-type: none"> Decrease the integral time (b5-03) Increase the derivative time (b5-05) | <p>The graph plots Response vs. Time. A horizontal dashed line represents the target. Two curves start from the origin: 'Before adjustment' has a lower peak and takes longer to settle; 'After adjustment' has a higher peak but settles faster.</p> |
| Suppress long cycle oscillations (longer than the integral time setting) | Increase the integral time (b5-03) | <p>The graph plots Response vs. Time. A horizontal dashed line represents the target. Two curves start from the origin: 'Before adjustment' shows large, sustained oscillations; 'After adjustment' shows a much smoother curve with minimal oscillations.</p> |
| Suppress short cycle oscillations | <ul style="list-style-type: none"> If oscillation cycle time is close to the derivative time, reduce the derivative time (b5-05). If the derivative time is set to 0.00 s and oscillations are still a problem, reduce the proportional gain (b5-02) or increase the PID primary delay time (b5-08) | <p>The graph plots Response vs. Time. A horizontal dashed line represents the target. Two curves start from the origin: 'Before adjustment' shows high-frequency oscillations; 'After adjustment' shows a much smoother curve with reduced high-frequency oscillations.</p> |

◆ b6: Dwell Function

The Dwell function temporarily holds the frequency reference at a predefined value for a set time then continues accelerating or decelerating.

The Dwell function helps prevent speed loss when starting and stopping a heavy load with induction motors.

Figure 5.21 illustrates how the Dwell function works.

Note: Set the stopping method to "Ramp to Stop" (b1-03 = 0) to use the Dwell function.

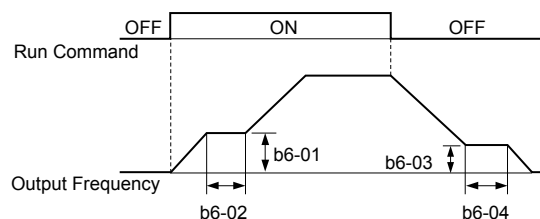


Figure 5.21 Dwell Function at Start and Stop

■ b6-01, b6-02: Dwell Reference, Dwell Time at Start

Parameter b6-01 determines the frequency that is held for the time set in b6-02 during acceleration.

| No. | Name | Setting Range | Default |
|-------|--------------------------|-----------------|---------|
| b6-01 | Dwell Reference at Start | 0.0 to 400.0 Hz | 0.0 Hz |
| b6-02 | Dwell Time at Start | 0.0 to 10.0 s | 0.0 s |

■ b6-03, b6-04: Dwell Reference, Dwell Time at Stop

Parameter b6-03 determines the frequency that is held for the time set in b6-04 during deceleration.

| No. | Name | Setting Range | Default |
|-------|-------------------------|-----------------|---------|
| b6-03 | Dwell Reference at Stop | 0.0 to 400.0 Hz | 0.0 Hz |
| b6-04 | Dwell Time at Stop | 0.0 to 10.0 s | 0.0 s |

◆ b8: Energy Saving

The Energy Saving feature improves overall system operating efficiency by operating the motor at its most efficient level.

- Note:**
1. Energy Saving is not designed for applications that experience instantaneous heavy loads or applications that rarely operate with light load conditions.
 2. Energy Saving is designed for applications with variable torque (Normal Duty) and is not appropriate for applications where the load may suddenly increase.
 3. The performance of the Energy Saving function depends on the accuracy of the motor data. Always perform Auto-Tuning and correctly enter the motor data before using this function.

■ b8-01: Energy Saving Control Selection

Enables or disables the Energy Saving function.

| No. | Parameter Name | Setting Range | Default |
|-------|---------------------------------|---------------|---------|
| b8-01 | Energy Saving Control Selection | 0, 1 | 0 |

Setting 0: Disabled

Setting 1: Enabled

■ b8-04: Energy Saving Coefficient Value

Determines the level of maximum motor efficiency. Setting range is 0.0 to 2000.0 for drives 3.7 kW and smaller. The display resolution depends on the rated output power of the drive.

| No. | Name | Setting Range | Default |
|-------|---------------------------------|----------------|--------------------------------|
| b8-04 | Energy Saving Coefficient Value | 0.00 to 655.00 | Determined by E2-11, and o2-04 |

Note: The default value changes if the motor rated capacity set to E2-11 is changed. The Energy Saving coefficient is set automatically when Auto-Tuning for Energy Saving is performed (*Refer to Auto-Tuning on page 129*).

5.2 b: Application

■ b8-05: Power Detection Filter Time

Determines how often in milliseconds the output power is measured. The Energy Saving function continuously searches out the lowest output voltage to achieve minimum output power.

Reducing this setting increases the response time. If the filter time is too short, the motor may become unstable with a lighter load.

| No. | Name | Setting Range | Default |
|-------|-----------------------------|---------------|---------|
| b8-05 | Power Detection Filter Time | 0 to 2000 ms | 20 ms |

■ b8-06: Search Operation Voltage Limit

Sets the voltage limit for the Speed Search optimal output voltage detection as a percentage of the maximum output voltage. The drive will keep the output voltage above this level during the search operation to prevent motor stalling.

| No. | Name | Setting Range | Default |
|-------|--------------------------------|---------------|---------|
| b8-06 | Search Operation Voltage Limit | 0 to 100% | 0% |

5.3 C: Tuning

C parameters set the characteristics for acceleration, deceleration, and S-curves. Other parameters in the C group cover settings for slip compensation, torque compensation, and carrier frequency.

◆ C1: Acceleration and Deceleration Times

■ C1-01 to C1-04: Accel, Decel Times 1 and 2

Two different sets of acceleration and deceleration times can be set in the drive by digital inputs, motor selection, or switched automatically.

Acceleration time parameters always set the time to accelerate from 0 Hz to the maximum output frequency (E1-04). Deceleration time parameters always set the time to decelerate from maximum output frequency to 0 Hz. C1-01 and C1-02 are the default active accel/decel settings.

| No. | Parameter Name | Setting Range | Default |
|-------|---------------------|--------------------------------------|---------|
| C1-01 | Acceleration Time 1 | 0.0 to 6000.0 s ^{<I>} | 10.0 s |
| C1-02 | Deceleration Time 1 | | |
| C1-03 | Acceleration Time 2 | | |
| C1-04 | Deceleration Time 2 | | |

<I> The setting range for the acceleration and deceleration times is determined by the accel/decel time setting units in C1-10. For example, if the time is set in units of 0.01 s (C1-10 = 0), the setting range becomes 0.00 to 600.00 s.

Switching Acceleration Times by Digital Input

Accel/decel time 1 is active by default if no input is set. Activate accel/decel times 2, 3, and 4 by digital inputs (H1-□□ = 7 and 1A) as explained in [Table 5.13](#).

Table 5.13 Accel/Decel Time Selection by Digital Input

| Accel/Decel Time Sel. 1 H1-□□ = 7 | Accel/Decel Time Sel. 2 H1-□□ = 1A | Active Times | |
|--------------------------------------|---------------------------------------|--------------|--------------|
| | | Acceleration | Deceleration |
| 0 | 0 | C1-01 | C1-02 |
| 1 | 0 | C1-03 | C1-04 |

[Figure 5.22](#) shows an operation example for changing accel/decel. times. The example below requires that the stopping method be set for “Ramp to stop” (b1-03 = 0).

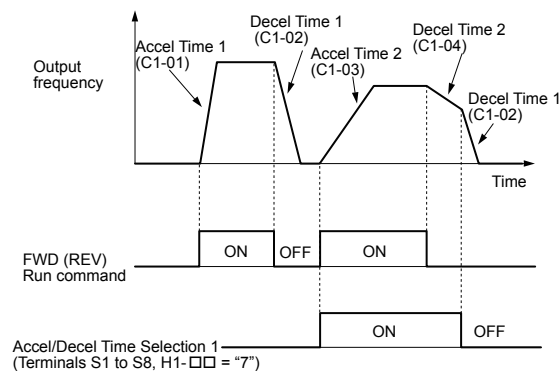


Figure 5.22 Timing Diagram of Accel/Decel Time Change

■ C1-11: Accel/Decel Time Switching Frequency

Sets the frequency at which the drive switches between accel/decel time settings.

| No. | Parameter Name | Setting Range | Default |
|-------|--------------------------------------|-----------------|---------|
| C1-11 | Accel/Decel Time Switching Frequency | 0.0 to 400.0 Hz | 0.0 Hz |

5.3 C: Tuning

■ C1-09: Fast Stop Time

Sets a special deceleration used when a select group of faults occur (e.g., L8-03 Overheat Pre-Alarm Operation Selection) or when closing a digital input configured as H1-□□ = 15 (N.O. input) or 17 (N.C. input). A momentary closure of the digital input will trigger the Fast Stop operation; it does not have to be closed continuously.

The drive cannot be restarted after initiating a Fast Stop operation until after completing deceleration, clearing the Fast Stop input, and cycling the Run command.

A digital output programmed for “During Fast Stop” (H2-□□ = 4C) will be closed as long as Fast Stop is active.

| No. | Parameter Name | Setting Range | Default |
|-------|----------------|---------------------|---------|
| C1-09 | Fast Stop Time | 0.0 to 6000.0 s </> | 10.0 s |

</> The setting range for the acceleration and deceleration times is determined by the accel/decel time setting units in C1-10. For example, if the time is set in units of 0.01 s (C1-10 = 0), the setting range becomes 0.00 to 600.00 s

NOTICE: Rapid deceleration can trigger an overvoltage fault. The drive output shuts off when faulted and the motor coasts. Set an appropriate Fast Stop time to C1-09 to avoid this uncontrolled motor state and to ensure that the motor stops quickly and safely.

■ C1-10: Accel/Decel Time Setting Units

Determines the units for the acceleration and deceleration times set to C1-01 through C1-09 using parameter C1-10.

| No. | Parameter Name | Setting Range | Default |
|-------|--------------------------------|---------------|---------|
| C1-10 | Accel/Decel Time Setting Units | 0, 1 | 1 |

Setting 0: 0.01 s units

The accel/decel times are set in 0.01 s units. The setting range is 0.00 to 600.00 s. C1-10 cannot be set to 0 if any of the parameters C1-01 to C1-09 is set to 600.1 s or longer.

Setting 1: 0.1 s units

The accel/decel times are set in 0.1 s units. The setting range is 0.0 to 6000.0 s.

◆ C2: S-Curve Characteristics

Use S-curve characteristics to smooth acceleration and deceleration and minimize abrupt shock to the load. Set S-curve characteristic time during acceleration/deceleration at start and acceleration/deceleration at stop.

■ C2-01 to C2-04: S-Curve Characteristics

C2-01 through C2-04 set separate S-curves for each section of the acceleration or deceleration.

| No. | Parameter Name | Setting Range | Default |
|-------|---------------------------------------|-----------------|---------|
| C2-01 | S-Curve Characteristic at Accel Start | 0.00 to 10.00 s | 0.20 s |
| C2-02 | S-Curve Characteristic at Accel End | | 0.20 s |
| C2-03 | S-Curve Characteristic at Decel Start | | 0.20 s |
| C2-04 | S-Curve Characteristic at Decel End | | 0.00 s |

Figure 5.23 illustrates S-curve application.

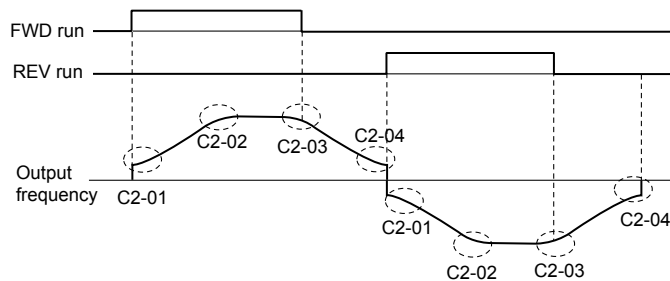


Figure 5.23 S-Curve Timing Diagram - FWD/REV Operation

Setting the S-curve will increase the acceleration and deceleration times.

- Actual accel time = accel time setting + (C2-01 + C2-02) / 2
- Actual decel time = decel time setting + (C2-03 + C2-04) / 2

◆ C3: Slip Compensation

The Slip Compensation function improves the speed accuracy of an induction motor. By adjusting the output frequency in accordance with the motor load, it compensates the slip and makes the motor speed equal to the frequency reference.

Note: Perform Auto-Tuning and make sure that the motor rated current (E2-01), the motor rated slip (E2-02), and the no-load current (E2-03) have all been set properly before making any adjustments to slip compensation parameters.

■ C3-01: Slip Compensation Gain

Sets the gain for the motor slip compensation function. Although this parameter rarely needs to be changed, adjustments may be necessary under the following circumstances:

- Increase the setting if the motor at constant speed is slower than the frequency reference.
- Decrease the setting if the motor at constant speed is faster than the frequency reference.

| No. | Parameter Name | Setting Range | Default |
|-------|------------------------|---------------|---------|
| C3-01 | Slip Compensation Gain | 0.0 to 2.5 | 0.0 |

■ C3-02: Slip Compensation Primary Delay Time

Adjusts the filter on the output side of the slip compensation function. Although this parameter rarely needs to be changed, adjustments may be necessary in the following situations:

- Decrease the setting when the slip compensation response is too slow.
- Increase this setting when speed is unstable.

| No. | Parameter Name | Setting Range | Default |
|-------|--------------------------------------|---------------|---------|
| C3-02 | Slip Compensation Primary Delay Time | 0 to 10000 ms | 2000 ms |

■ C3-03: Slip Compensation Limit

Sets the upper limit for the slip compensation function as a percentage of the motor rated slip (E2-02).

| No. | Parameter Name | Setting Range | Default |
|-------|-------------------------|---------------|---------|
| C3-03 | Slip Compensation Limit | 0 to 250% | 200% |

The slip compensation limit is constant throughout the constant torque range (frequency reference \leq E1-06). In the constant power range (frequency reference \geq E1-06), it is increased based on C3-03 and the output frequency as shown in the following diagram.

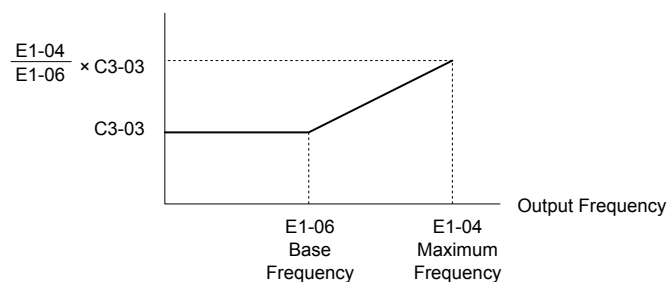


Figure 5.24 Slip Compensation Limit

■ C3-04: Slip Compensation Selection during Regeneration

Enables or disables slip compensation during regenerative operation. When slip compensation during regeneration has been activated and a regenerative load is applied, it might be necessary to use a dynamic braking option (braking resistor, braking resistor unit, or braking unit).

This function does not operate when the output frequency is too low, regardless of whether it has been enabled.

| No. | Parameter Name | Setting Range | Default |
|-------|---|---------------|---------|
| C3-04 | Slip Compensation Selection during Regeneration | 0 to 2 | 0 |

Setting 0: Disabled

Slip compensation is not provided. Depending on the load and mode of operation, the actual motor speed will be lower or higher than the frequency reference.

5.3 C: Tuning

Setting 1: Enabled (6 Hz and above)

Slip compensation is enabled during regenerative operation. It will not be active at output frequencies below 6 Hz.

Setting 2: Enabled (compensation provided wherever possible)

Slip compensation is enabled during regenerative operation and at frequencies as low as 2 Hz. The drive uses the motor rated slip set to E2-02 to automatically calculate the frequency range where compensation will be disabled.

◆ C4: Torque Compensation

The torque compensation function compensates for insufficient torque production at start-up or when a load is applied.

Note: Set the motor parameters and V/f pattern properly before setting torque compensation parameters.

■ C4-01: Torque Compensation Gain

Sets the gain for the torque compensation function.

| No. | Parameter Name | Setting Range | Default |
|-------|--------------------------|---------------|---------|
| C4-01 | Torque Compensation Gain | 0.00 to 2.50 | 1.00 |

■ C4-02: Torque Compensation Primary Delay Time 1

Sets the delay time used for applying torque compensation.

| No. | Parameter Name | Setting Range | Default |
|-------|--|---------------|---------|
| C4-02 | Torque Compensation Primary Delay Time 1 | 0 to 60000 ms | 200 ms |

◆ C6: Carrier Frequency

■ C6-02: Carrier Frequency Selection

Sets the switching frequency of the drive output transistors. Changes to the switching frequency lower audible noise and reduce leakage current.

| No. | Parameter Name | Setting Range | Default |
|-------|-----------------------------|------------------|---------|
| C6-02 | Carrier Frequency Selection | 1 to 9; A, F <1> | 7 |

<1> The setting range is 1, 2, and F for models 4A0930 and 4A1200

Settings:

| C6-02 | Carrier Frequency | C6-02 | Carrier Frequency | C6-02 | Carrier Frequency |
|-------|-------------------|-------|-------------------|---------|-------------------------------|
| 1 | 2.0 kHz | 5 | 12.5 kHz | 9 | Swing PWM 3 |
| 2 | 5.0 kHz | 6 | 15.0 kHz | A | Swing PWM 4 |
| 3 | 8.0 kHz | 7 | Swing PWM 1 | B to E: | No setting possible |
| 4 | 10.0 kHz | 8 | Swing PWM 2 | F | User defined (C6-03 to C6-05) |

Note: Swing PWM uses a carrier frequency of 2.0 kHz as a base, then applies a special PWM pattern to reduce the audible noise.

Guidelines for Carrier Frequency Parameter Setup

| Symptom | Remedy |
|--|--|
| Speed and torque are unstable at low speeds | Lower the carrier frequency. |
| Noise from the drive affects peripheral devices | |
| Excessive leakage current from the drive | |
| Wiring between the drive and motor is too long <1> | Increase the carrier frequency or use Swing PWM. <2> |
| Audible motor noise is too loud | |

<1> The carrier frequency may need to be lowered if the motor cable is too long. Refer to [Table 5.14](#).

<2> The default carrier frequency is Swing PWM (C6-02 = 7), using a 2 kHz base. Increasing the carrier frequency is permissible, however the drive rated current is reduced when the carrier frequency is increased.

Table 5.14 Wiring Distance and Carrier Frequency

| Wiring Distance | Up to 50 m | Up to 100 m | Greater than 100 m |
|-------------------------------------|-----------------------|--|--------------------------------|
| Recommended setting value for C6-02 | 1 to F (up to 15 kHz) | 1 to 2 (up to 5 kHz), 7 (Swing PWM) | 1 (up to 2 kHz), 7 (Swing PWM) |

■ C6-03, C6-04, C6-05: Carrier Frequency Upper Limit, Lower Limit, Proportional Gain

These parameters set a user-defined or a variable carrier frequency. Set C6-02 to F to set the upper and lower limits and the carrier frequency proportional gain.

| No. | Parameter Name | Setting Range | Default |
|-------|-------------------------------------|-----------------|---------------------|
| C6-03 | Carrier Frequency Upper Limit | 1.0 to 15.0 kHz | Determined by C6-02 |
| C6-04 | Carrier Frequency Lower Limit | 1.0 to 15.0 kHz | |
| C6-05 | Carrier Frequency Proportional Gain | 0 to 99 | |

Setting a Fixed User Defined Carrier Frequency

A carrier frequency between the fixed selectable values can be entered in parameter C6-03 when C6-02 is set to F. In V/f Control, adjust parameter C6-04 to the same value as C6-03.

Setting a Variable Carrier Frequency (V/f Control)

In V/f Control, the carrier frequency can be set up to change linearly with the output frequency by setting the upper and lower limits for the carrier frequency and the carrier frequency proportional gain (C6-03, C6-04, C6-05) as shown in [Figure 5.25](#).

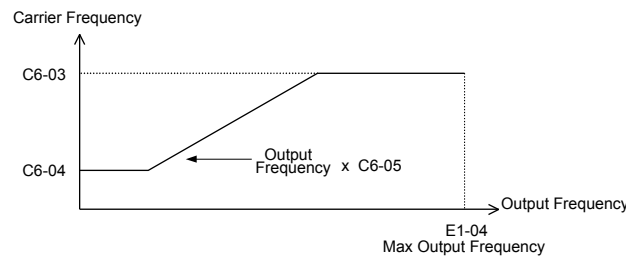


Figure 5.25 Carrier Frequency Changes Relative to Output Frequency

Note: When C6-05 is set lower than 7, C6-04 is disabled and the carrier frequency will be fixed to the value set in C6-03.

5.4 d: Reference Settings

The figure below gives an overview of the reference input, selections, and priorities.

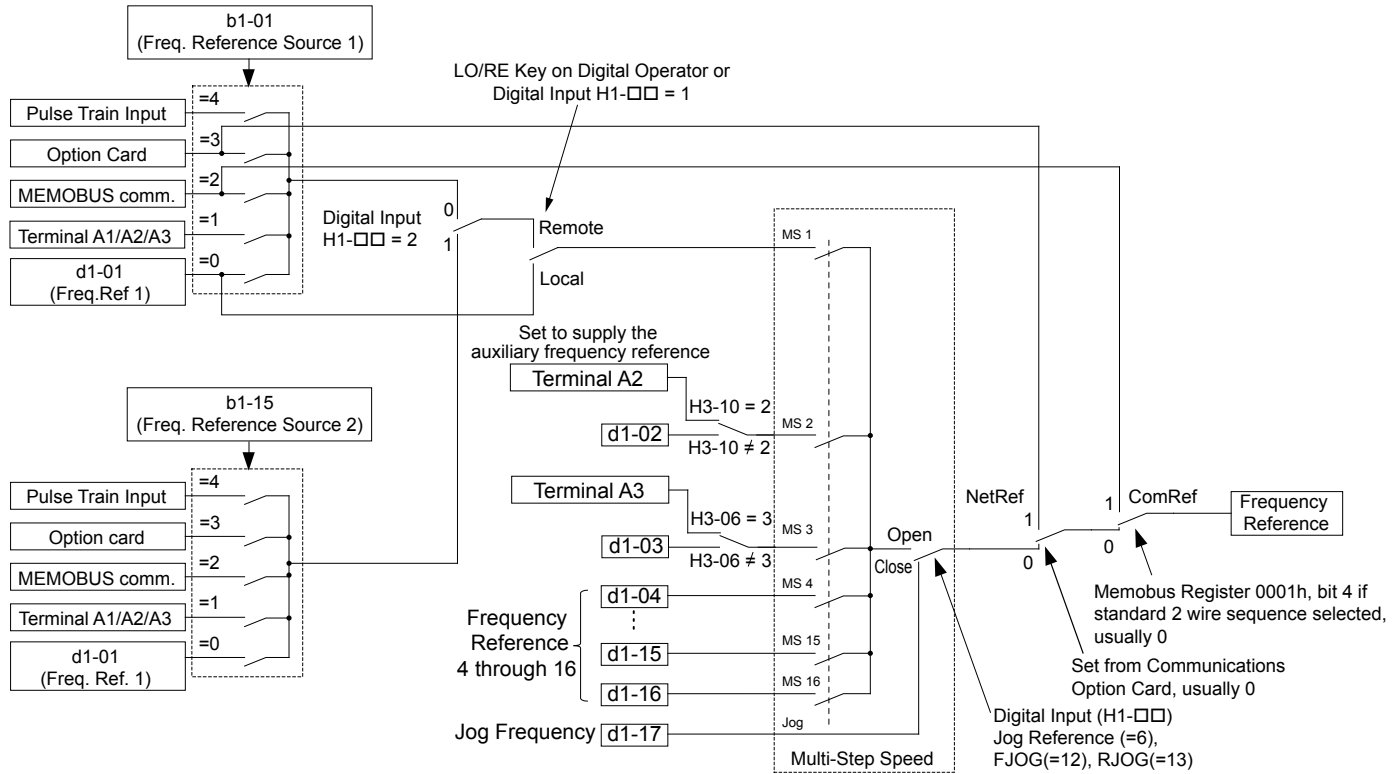


Figure 5.26 Frequency Reference Setting Hierarchy

◆ d1: Frequency Reference

■ d1-01 to d1-17: Frequency Reference 1 to 16 and Jog Frequency Reference

The drive lets the user switch between up to 17 preset frequency references during run (including the Jog reference) through the digital input terminals. The drive uses the acceleration and deceleration times that have been selected when switching between each frequency reference.

The Jog frequency overrides all other frequency references and must be selected by a separate digital input.

The multi-speed references 1, 2, and 3 can be provided by analog inputs.

| No. | Parameter Name | Setting Range | Default |
|----------------|-----------------------------|-----------------------|---------|
| d1-01 to d1-16 | Frequency Reference 1 to 16 | 0.00 to 400.00 Hz </> | 0.00 Hz |
| d1-17 | Jog Frequency Reference | 0.00 to 400.00 Hz </> | 6.00 Hz |

</> The upper limit is determined by the maximum output frequency (E1-04) and upper limit for the frequency reference (d2-01).

Multi-Step Speed Selection

To use several speed references for a multi-step speed sequence, set the H1-□□ parameters to 3, 4, 5, and 32. To assign the Jog reference to a digital input, set H1-□□ to 6.

Notes on using analog inputs as Multi-Speed 1, 2, and 3:

• Multi-Step Speed 1

Set b1-01 to 1 to set terminal A1 analog input to Multi-Step Speed 1.

Set b1-01 to 0 when setting d1-01, Frequency Reference 1, to Multi-Step Speed 1.

• Multi-Step Speed 2

Set H3-06, Terminal A3 Function Selection, to 2 (Auxiliary Frequency Reference 1) when setting terminal A3 analog input to Multi-Step Speed 2.

Set H3-06 to F (Through mode) when setting d1-02, Frequency Reference 2, to Multi-Step Speed 2.

• **Multi-Step Speed 3**

Set H3-10, Terminal A2 Function Selection, to 3 (Auxiliary Frequency Reference 2) when setting terminal A2 analog input to Multi-Step Speed 3.

Set H3-10 to F (Through mode) when setting d1-03, Frequency Reference 3, to Multi-Step Speed 3.

Set H3-09 to 0 and set jumper S1 on the control circuit terminal board to V (voltage) for A2 when inputting 0 to 10 V to terminal A2 analog input.

Select the different speed references as shown in *Table 5.15*. *Figure 5.27* illustrates the multi-step speed selection.

Table 5.15 Multi-Step Speed Reference and Terminal Switch Combinations

| Reference | Multi-Step Speed H1-□□ = 3 | Multi-Step Speed 2 H1-□□ = 4 | Multi-Step Speed 3 H1-□□ = 5 | Multi-Step Speed 4 H1-□□ = 32 | Jog Reference H1-□□ = 6 |
|---|-------------------------------|---------------------------------|---------------------------------|----------------------------------|----------------------------|
| Frequency Reference 1 (set in b1-01) | OFF | OFF | OFF | OFF | OFF |
| Frequency Reference 2 (d1-02 or input terminal A1, A2, A3) | ON | OFF | OFF | OFF | OFF |
| Frequency Reference 3 (d1-03 or input terminal A1, A2, A3) | OFF | ON | OFF | OFF | OFF |
| Frequency Reference 4 (d1-04) | ON | ON | OFF | OFF | OFF |
| Frequency Reference 5 (d1-05) | OFF | OFF | ON | OFF | OFF |
| Frequency Reference 6 (d1-06) | ON | OFF | ON | OFF | OFF |
| Frequency Reference 7 (d1-07) | OFF | ON | ON | OFF | OFF |
| Frequency Reference 8 (d1-08) | ON | ON | ON | OFF | OFF |
| Frequency Reference 9 (d1-09) | OFF | OFF | OFF | ON | OFF |
| Frequency Reference 10 (d1-10) | ON | OFF | OFF | ON | OFF |
| Frequency Reference 11 (d1-11) | OFF | ON | OFF | ON | OFF |
| Frequency Reference 12 (d1-12) | ON | ON | OFF | ON | OFF |
| Frequency Reference 13 (d1-13) | OFF | OFF | ON | ON | OFF |
| Frequency Reference 14 (d1-14) | ON | OFF | ON | ON | OFF |
| Frequency Reference 15 (d1-15) | OFF | ON | ON | ON | OFF |
| Frequency Reference 16 (d1-16) | ON | ON | ON | ON | OFF |
| Jog Frequency Reference (d1-17) <i><I></i> | – | – | – | – | ON |

<I> The Jog frequency overrides all other frequency references.

5.4 d: Reference Settings

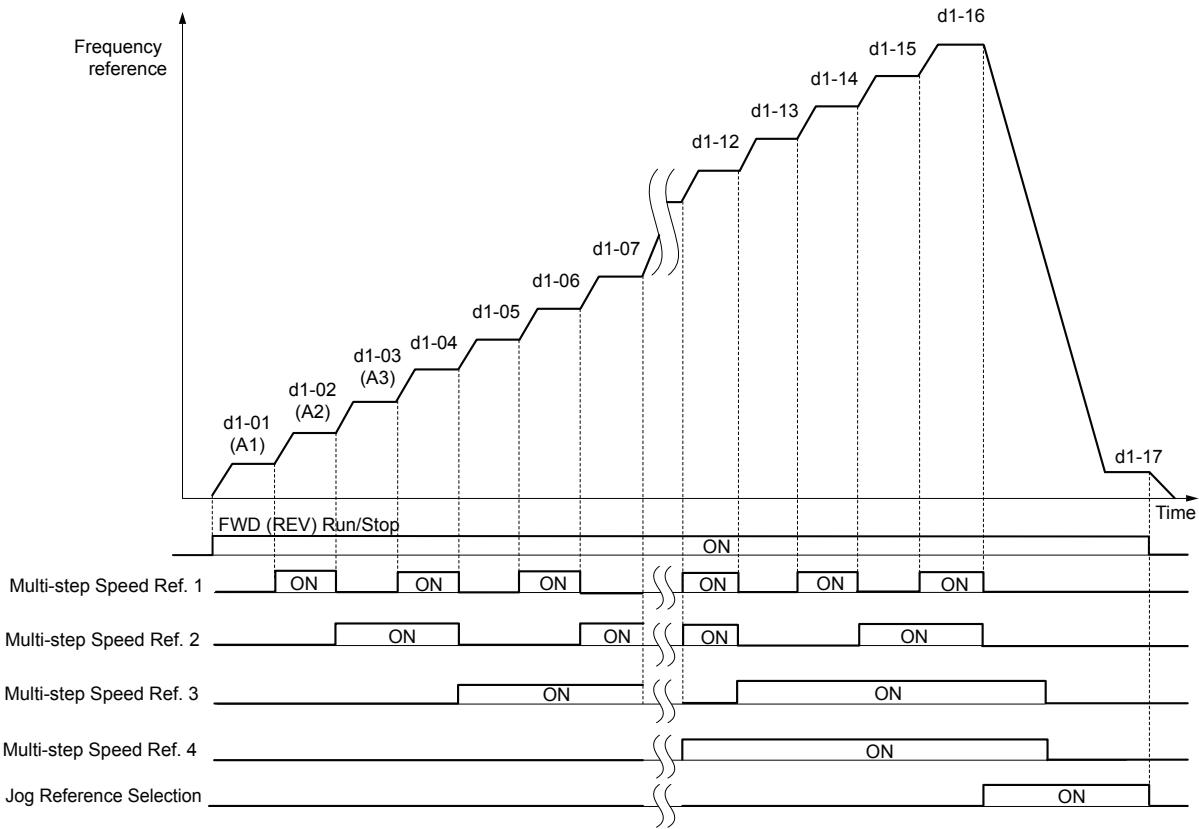


Figure 5.27 Preset Reference Timing Diagram

◆ d2: Frequency Upper/Lower Limits

Upper and lower frequency limits prevent motor speed from going above or below levels that may cause resonance or equipment damage.

■ d2-01: Frequency Reference Upper Limit

Sets the maximum frequency reference as a percentage of the maximum output frequency. This limit applies to all frequency references.

Even if the frequency reference is set to a higher value, the drive internal frequency reference will not exceed this value.

| No. | Parameter Name | Setting Range | Default |
|-------|---------------------------------|---------------|---------|
| d2-01 | Frequency Reference Upper Limit | 0.0 to 110.0% | 100.0% |

■ d2-02: Frequency Reference Lower Limit

Sets the minimum frequency reference as a percentage of the maximum output frequency. This limit applies to all frequency references.

If a lower reference than this value is entered, the drive will run at the limit set to d2-02. If the drive is started with a lower reference than d2-02, it will accelerate up to d2-02.

| No. | Parameter Name | Setting Range | Default |
|-------|---------------------------------|---------------|---------|
| d2-02 | Frequency Reference Lower Limit | 0.0 to 110.0% | 0.0% |

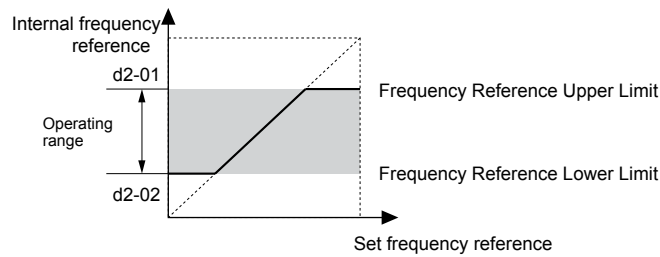


Figure 5.28 Frequency Reference: Upper and Lower Limits

■ d2-03: Master Speed Reference Lower Limit

Sets a lower limit as a percentage of the maximum output frequency that will only affect a frequency reference entered from the analog input terminals (A1, A2, or A3) as the master speed reference. This is unlike parameter d2-02, which affects all frequency references regardless of their source.

Note: When lower limits are set to both parameters d2-02 and d2-03, the drive uses the greater of those two values as the lower limit.

| No. | Parameter Name | Setting Range | Default |
|-------|------------------------------------|---------------|---------|
| d2-03 | Master Speed Reference Lower Limit | 0.0 to 110.0% | 0.0% |

◆ d3: Jump Frequency

■ d3-01 to d3-04: Jump Frequencies 1, 2, 3 and Jump Frequency Width

The Jump frequencies are frequency ranges at which the drive will not operate. The drive can be programmed with three separate Jump frequencies to avoid operating at speeds that cause resonance in driven machinery. If the speed reference falls within a Jump frequency dead band, the drive will clamp the frequency reference just below the dead band and only accelerate past it when the frequency reference rises above the upper end of the dead band.

Setting parameters d3-01 through d3-03 to 0.0 Hz disables the Jump frequency function.

| No. | Parameter Name | Setting Range | Default |
|-------|----------------------|-----------------|---------|
| d3-01 | Jump Frequency 1 | 0.0 to 400.0 Hz | 0.0 Hz |
| d3-02 | Jump Frequency 2 | 0.0 to 400.0 Hz | 0.0 Hz |
| d3-03 | Jump Frequency 3 | 0.0 to 400.0 Hz | 0.0 Hz |
| d3-04 | Jump Frequency Width | 0.0 to 20.0 Hz | 1.0 Hz |

Figure 5.29 shows the relationship between the Jump frequency and the output frequency.

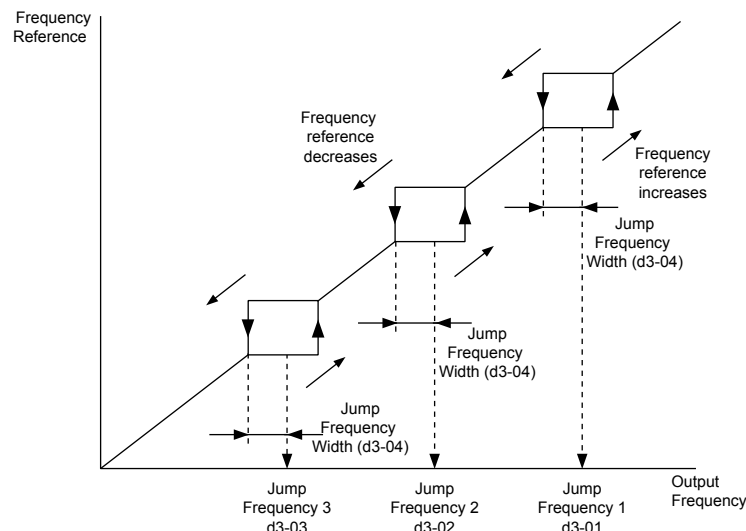


Figure 5.29 Jump Frequency Operation

Note: 1. The drive will use the active accel/decel time to pass through the specified dead band range, but will not allow continuous operation in that range.

5.4 d: Reference Settings

- When setting more than one Jump frequency, make sure that the parameters do not overlap.

◆ d4: Frequency Reference Hold and Up/Down 2 Function

■ d4-01: Frequency Reference Hold Function Selection

Determines whether the frequency reference or the frequency bias (Up/Down 2) value is saved when the Stop command is entered or the power supply is shut down. This parameter is effective when either of the digital input functions listed below are used:

- Accel/decel ramp hold function (H1-□□ = A)
- Up/Down function (H1-□□ = 10 and 11)
- Up/Down 2 function (H1-□□ = 75 and 76)

| No. | Parameter Name | Setting Range | Default |
|-------|---|---------------|---------|
| d4-01 | Frequency Reference Hold Function Selection | 0, 1 | 0 |

The operation depends on the function used with parameter d4-01.

Setting 0: Disabled

- Acceleration hold

The hold value will be reset to 0 Hz when the Stop command is entered or the drive power is switched off. The active frequency reference will be the value the drive uses when it restarts.

- Up/Down

The frequency reference value will be reset to 0 Hz when the Stop command is entered or the drive power is switched off. The drive will start from 0 Hz when it is restarted.

- Up/Down 2

The frequency bias is not saved when the Stop command is entered, or 5 s after the Up/Down 2 command has been released. The Up/Down 2 function will start with a bias of 0% when the drive is restarted.

Setting 1: Enabled

- Acceleration hold

The last hold value will be saved when the Run command or the drive power is switched off and the drive will use the saved value as the frequency reference when it restarts. Make sure to continuously enable the multi-function input terminal set for “Accel/decel ramp hold” (H1-□□ = A) or the hold value will be cleared when the power is switched on.

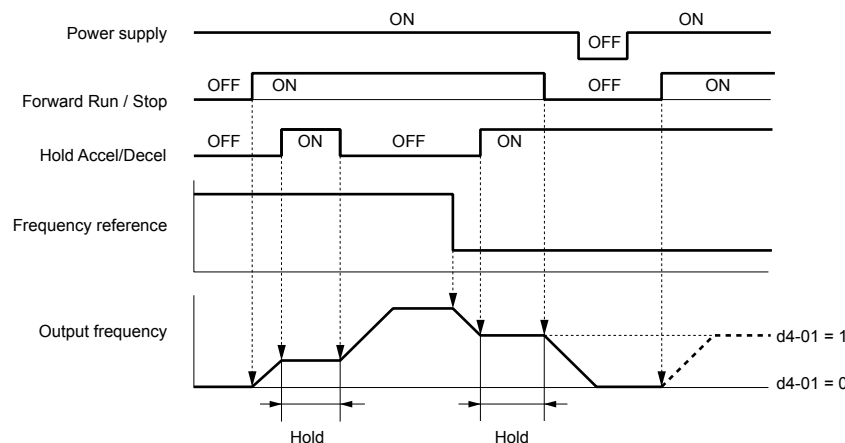


Figure 5.30 Frequency Reference Hold with Accel/Decel Hold Function

- Up/Down

The frequency reference value will be saved when the Run command or the drive power is switched off. The drive will use the frequency reference that was saved when it restarts.

- Up/Down 2 with frequency reference from digital operator

When a Run command is active and the Up/Down 2 command is released for longer than 5 s, the Up/Down 2 bias value is added to the frequency reference and then reset to 0. This new frequency reference is saved and will also be used to restart the drive after the power is cycled.

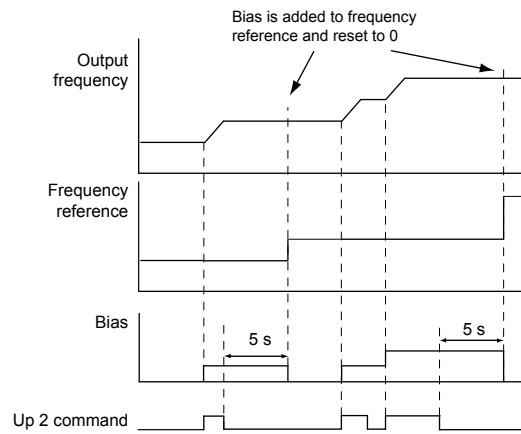


Figure 5.31 Up/Down 2 Example with Reference from Digital Operator and d4-01 = 1

- Up/Down 2 with frequency reference from input sources other than the digital operator

When a Run command is active and the Up/Down 2 command is released for longer than 5 s, the bias value will be saved in parameter d4-06. When restarting after the power is switched off, the drive will add the value saved in d4-06 as a bias to the frequency reference.

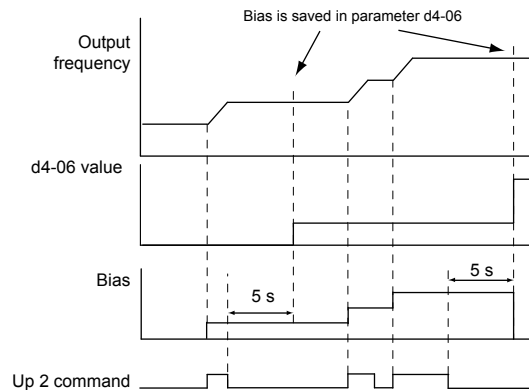


Figure 5.32 Up/Down 2 Example with Other Reference than Digital Operator and d4-01 = 1

Note: Set the limits for Up/Down 2 properly when using d4-01 = 1 in combination with the Up/Down 2 function. Refer to [d4-08: Frequency Reference Bias Upper Limit \(Up/Down 2\) on page 189](#) and [d4-09: Frequency Reference Bias Lower Limit \(Up/Down 2\) on page 189](#) for details on the limit settings.

Clearing the Saved Value

Depending on which function is used, it is possible to clear the saved frequency reference value by:

- Releasing the input programmed for Acceleration hold.
- Setting an Up or Down command while no Run command is active.
- Resetting parameter d4-06 to zero. Refer to [d4-06: Frequency Reference Bias \(Up/Down 2\) on page 189](#) for details.

■ d4-03: Frequency Reference Bias Step (Up/Down 2)

Sets the bias added to or subtracted from the frequency reference by the Up/Down 2 function.

| No. | Parameter Name | Setting Range | Default |
|-------|---|------------------|---------|
| d4-03 | Frequency Reference Bias Step (Up/Down 2) | 0.00 to 99.99 Hz | 0.00 Hz |

The operation depends on the set value:

Setting d4-03 = 0.00 Hz

While the Up 2 or Down 2 command is enabled, the bias value is increased or decreased using the accel/decel times determined by parameter d4-04.

5.4 d: Reference Settings

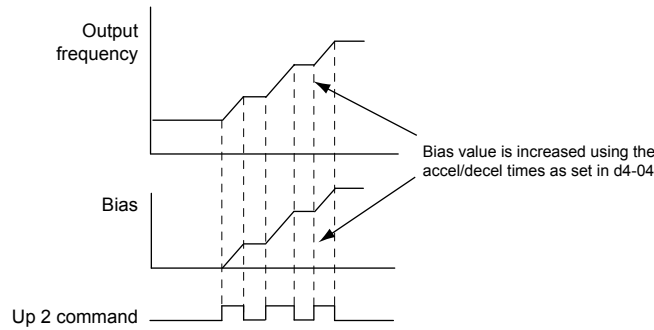


Figure 5.33 Up/Down 2 Bias when d4-03 = 0.00 Hz

Setting d4-03 ≠ 0.00 Hz

When an Up 2 or Down 2 command is enabled, the bias is increased or decreased in steps for the value set in d4-03. The frequency reference changes with the accel/decel times determined by parameter d4-04.

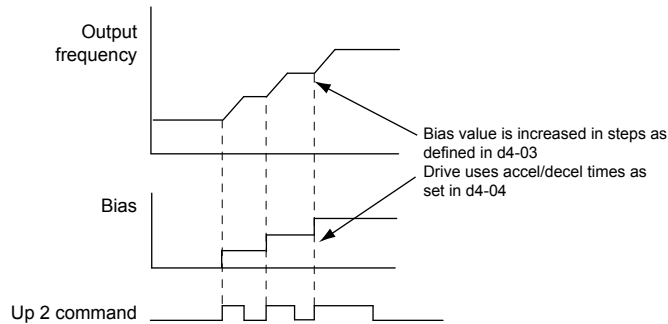


Figure 5.34 Up/Down 2 Bias when d4-03 ≠ 0.00 Hz

■ d4-04: Frequency Reference Bias Accel/Decel (Up/Down 2)

Determines the accel/decel times used to increase or decrease the frequency reference or bias when using the Up/Down 2 function.

| No. | Parameter Name | Setting Range | Default |
|-------|--|---------------|---------|
| d4-04 | Frequency Reference Bias Accel/Decel (Up/Down 2) | 0, 1 | 0 |

Setting 0: Current Accel/Decel Time

The drive uses the currently active accel/decel time.

Setting 1: Accel/Decel Time 4

The drive uses accel/decel time 4 set to parameters C1-07 and C1-08.

Note: The functionality of setting 1 is only accessible via MEMOBUS/Modbus communications.

■ d4-05: Frequency Reference Bias Operation Mode Selection (Up/Down 2)

Determines if the bias value is held when the Up/Down 2 inputs are both released or both enabled. The parameter is effective only when parameter d4-03 is set to 0.00.

| No. | Parameter Name | Setting Range | Default |
|-------|---|---------------|---------|
| d4-05 | Frequency Reference Bias Operation Mode Selection (Up/Down 2) | 0, 1 | 0 |

Setting 0: Hold Bias Value

The bias value will be held if no input Up 2 or Down 2 is active.

Setting 1: Reset Bias Value

The bias is reset to 0% when inputs Up 2 and Down 2 are both on or both off. The drive will use the accel/decel time as selected in d4-04 to accelerate or decelerate to the frequency reference value.

■ d4-06: Frequency Reference Bias (Up/Down 2)

Saves the frequency reference bias value set by the Up/Down 2 function as a percentage of the maximum output frequency. The function of this parameter depends on the Up/Down 2 function configuration. This parameter is not normally used when the digital operator sets the frequency reference.

- The value set to d4-06 will be applied during run, however the value is reset when the frequency reference changes (including multi-step references) and is disabled when d4-01 = 0 and the Run command is removed.
- When d4-01 = 0 and the frequency reference is set by a source other than the digital operator, the value set in d4-06 is added to or subtracted from the frequency reference.
- When d4-01 = 1 and the frequency reference is set by a source other than the digital operator, the bias value adjusted with the Up/Down 2 inputs is stored in d4-06 when 5 s have passed after releasing the Up 2 or Down 2 command. The frequency reference will return to the value without the Up/Down 2 command.

| No. | Parameter Name | Setting Range | Default |
|-------|--------------------------------------|-----------------|---------|
| d4-06 | Frequency Reference Bias (Up/Down 2) | -99.9 to 100.0% | 0.0% |

Conditions that Reset or Disable d4-06

- The Up/Down 2 function has not been assigned to the multi-function terminals.
- The frequency reference source has been changed (including LOCAL/REMOTE or External reference 1/2 switch over by digital inputs).
- d4-03 = 0.00 Hz, d4-05 = 1, and the Up/Down 2 commands are both open or both closed.
- Any changes to the maximum frequency set to E1-04.

■ d4-07: Analog Frequency Reference Fluctuation Limit (Up/Down 2)

Handles frequency reference changes while the Up 2 or Down 2 terminal is enabled. If the frequency reference changes for more than the level set to d4-07, then the bias value will be held, and the drive will accelerate or decelerate following the frequency reference. When the frequency reference is reached, the bias hold is released and the bias follows the Up/Down 2 input commands.

This parameter is applicable only if the frequency reference is set by an analog or pulse input.

| No. | Parameter Name | Setting Range | Default |
|-------|--|---------------|---------|
| d4-07 | Analog Frequency Reference Fluctuation Limit (Up/Down 2) | 0.1 to 100.0% | 0.01.% |

■ d4-08: Frequency Reference Bias Upper Limit (Up/Down 2)

Sets the upper limit of the Up/Down 2 bias (monitor U6-20) and the value that can be saved in parameter d4-06. Set this parameter to an appropriate value before using the Up/Down 2 function.

Note: When the frequency reference is set by the digital operator (b1-01 = 0) and d4-01 = 1, the bias value will be added to the frequency reference if no Up/Down 2 command is received for 5 s, and will be reset to 0 afterwards. From that point, the bias can be increased up to the limit set in d4-08 again.

| No. | Parameter Name | Setting Range | Default |
|-------|--|---------------|---------|
| d4-08 | Frequency Reference Bias Upper Limit (Up/Down 2) | 0.0 to 100.0% | 1.0% |

■ d4-09: Frequency Reference Bias Lower Limit (Up/Down 2)

Sets the lower limit of the Up/Down 2 bias (monitor U6-20) and the value that can be saved in parameter d4-06. Set this parameter to an appropriate value before using the Up/Down 2 function.

Note: When the frequency reference is set by the digital operator (b1-01 = 0) and d4-01 = 1, the bias value will be added to the frequency reference if no Up/Down 2 command is received for 5 s, and will be reset to 0 afterwards. If the bias is increased using the Up 2 command, it cannot be reduced with a Down 2 command when the limit set in d4-09 is 0. Set a negative lower limit in d4-09 to allow speed reduction in this situation.

| No. | Parameter Name | Setting Range | Default |
|-------|--|---------------|---------|
| d4-09 | Frequency Reference Bias Lower Limit (Up/Down 2) | -99.9 to 0.0% | 0.0% |

■ d4-10: Up/Down Frequency Reference Limit Selection

Selects how the lower frequency limit is set when using the Up/Down function. [Refer to Setting 10, 11: Up/Down Function on page 208](#) for details on the Up/Down function in combination with frequency reference limits.

5.4 d: Reference Settings

| No. | Parameter Name | Setting Range | Default |
|-------|---|---------------|---------|
| d4-10 | Up/Down Frequency Reference Limit Selection | 0, 1 | 0 |

Setting 0: Lower Limit is Determined by d2-02 or Analog Input

The higher value between d2-02 and an analog input programmed for Frequency bias (A1, A2, A3) determines the lower frequency reference limit.

Note: When using the External Reference 1/2 (H1-□□ = 2) to switch between the Up/Down function and an analog input as the reference source, the analog value becomes the lower reference limit when the Up/Down command is active. Set d4-10 to 1 to make the Up/Down function independent of the analog input value.

Setting 1: Lower Limit is Determined by d2-02

Only parameter d2-02 sets the lower frequency reference limit.

◆ d6: Field Weakening and Field Forcing

Field Weakening

The Field Weakening function reduces the output voltage to a predefined level to reduce the energy consumption of the motor. To activate the Field Weakening function, use a digital input programmed for H1-□□ = 63. Only use Field Weakening with a known and unchanging light load condition. Use the Energy Saving function (b8-□□ parameters) when Energy Saving for various different load conditions is required.

■ d6-01: Field Weakening Level

Sets the level to which the output voltage is reduced when Field Weakening is activated. Set as percentage of the maximum output voltage.

| No. | Parameter Name | Setting Range | Default |
|-------|-----------------------|---------------|---------|
| d6-01 | Field Weakening Level | 0 to 100% | 80% |

■ d6-02: Field Weakening Frequency Limit

Sets the minimum output frequency at which field weakening can be activated. Field Weakening cannot be activated for frequencies below d6-02.

| No. | Parameter Name | Setting Range | Default |
|-------|---------------------------------|---------------|---------|
| d6-02 | Field Weakening Frequency Limit | 0 to 400.0 Hz | 0.0 Hz |

5.5 E: Motor Parameters

E parameters cover V/f pattern and motor data settings.

◆ E1: V/f Pattern for Motor 1

■ E1-01: Input Voltage Setting

Adjusts the levels of some protective features of the drive (overvoltage, Stall Prevention, etc.). Set this parameter to the nominal voltage of the AC power supply.

NOTICE: Set parameter E1-01 to match the input voltage of the drive. Drive input voltage (not motor voltage) must be set in E1-01 for the protective features to function properly. Failure to set the correct drive input voltage will result in improper drive operation.

| No. | Parameter Name | Setting Range | Default |
|-------|-----------------------|------------------|-----------|
| E1-01 | Input Voltage Setting | 155 to 255 V <I> | 230 V <I> |

<I> Values shown are specific to 200 V class drives. Double the value for 400 V class drives. Multiply the value by 2.875 for 600 V class drives.

E1-01 Related Values

The input voltage setting determines the overvoltage and undervoltage detection levels, the operation levels of the braking transistor, the KEB function, and the overvoltage suppression function.

| Voltage | Setting Value of E1-01 | ov Detection Level/Dynamic Braking Transistor Detection Level <I> (rr Detection Level) | (Approximate Values) | | |
|-------------|------------------------|--|----------------------------|---|---|
| | | | Uv Detection Level (L2-05) | Desired DC Bus Voltage during KEB (L2-11) | ov Suppression / Stall Prevention Level (L3-17) |
| 200 V Class | All settings | 410 V / 394 V | 190 V | 260 V | 375 V |
| 400 V Class | setting ≥ 400 V | 820 V / 788 V | 380 V | 500 V | 750 V |
| | setting < 400 V | 820 V / 788 V | 350 V | 460 V | 750 V |
| 600 V Class | All settings | 1178 V / 1132 V | 475 V | 635 V | 930 V |

<I> The braking transistor operation levels are valid for the drive internal braking transistor. When using a CDBR braking unit, refer to instruction manual TOBPC72060000 or TOBPC72060001.

■ V/f Pattern Settings (E1-03)

The drive uses a V/f pattern to adjust the output voltage relative to the frequency reference. There are 15 different predefined V/f patterns (setting 0 to E) from which to select, each with varying voltage profiles, saturation levels (frequency at which maximum voltage is reached), and maximum frequencies. Additionally, one custom V/f pattern is available (setting F) that requires the user to create the pattern using parameters E1-04 through E1-10.

■ E1-03: V/f Pattern Selection

Selects the V/f pattern for the drive and motor from 15 predefined patterns or creates a custom V/f pattern.

| No. | Parameter Name | Setting Range | Default |
|-------|-----------------------|---------------|---------|
| E1-03 | V/f Pattern Selection | 0 to F | F <I> |

<I> Parameter is not reset to the default value when the drive is initialized using A1-03.

Setting a Predefined V/f Pattern (Setting 0 to E)

Choose the V/f pattern that best meets the application demands from [Table 5.16](#). These settings are available only in V/f Control modes. Set the correct value to E1-03. Parameters E1-04 to E1-13 can only be monitored, not changed.

- Note:**
1. Setting an improper V/f pattern may result in low motor torque or increased current due to overexcitation.
 2. Drive initialization does not reset parameter E1-03.

5.5 E: Motor Parameters

Table 5.16 Predefined V/f Patterns

| Setting | Specification | Characteristic | Application |
|----------|-----------------------------|----------------------|--|
| 0 | 50 Hz | Constant torque | For general purpose applications. Torque remains constant regardless of changes to speed. |
| 1 | 60 Hz | | |
| 2 | 60 Hz (with 50 Hz base) | | |
| 3 | 72 Hz (with 60 Hz base) | | |
| 4 | 50 Hz, Variable torque 1 | Variable torque | For fans, pumps, and other applications where the required torque changes as a function of the speed. |
| 5 | 50 Hz, Variable torque 2 | | |
| 6 | 60 Hz, Variable torque 1 | | |
| 7 | 60 Hz, Variable torque 2 | | |
| 8 | 50 Hz, mid starting torque | High starting torque | Select high starting torque when: <ul style="list-style-type: none"> • Wiring between the drive and motor exceeds 150 m. • A large amount of starting torque is required. • An AC reactor is installed. |
| 9 | 50 Hz, high starting torque | | |
| A | 60 Hz, mid starting torque | | |
| B | 60 Hz, high starting torque | | |
| C | 90 Hz (with 60 Hz base) | Constant output | Output voltage is constant when operating at greater than 60 Hz. |
| D | 120 Hz (with 60 Hz base) | | |
| E | 180 Hz (with 60 Hz base) | | |
| F </> | 60 Hz | | |

</> Setting F enables a custom V/f pattern by changing parameters E1-04 to E1-13. When the drive is shipped, the default values for parameters E1-04 to E1-13 are the same as those of setting 1.

The following tables show details on predefined V/f patterns.

Predefined V/f Patterns for Models 2A0004 to 2A0021, 4A0002 to 4A0011, and 5A0003 to 5A0009

The values in the following graphs are specific to 200 V class drives. Double the values for 400 V class drives. Multiply the values by 2.875 for 600 V drives.

Table 5.17 Constant Torque Characteristics, Settings 0 to 3

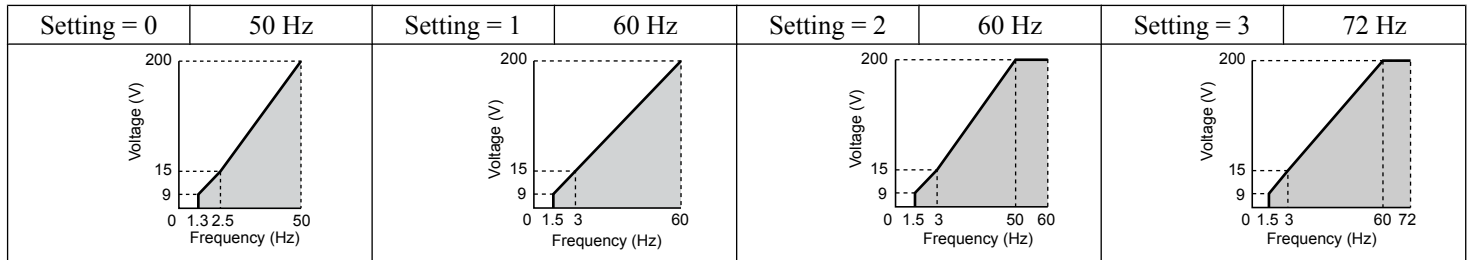


Table 5.18 Derated Torque Characteristics, Settings 4 to 7

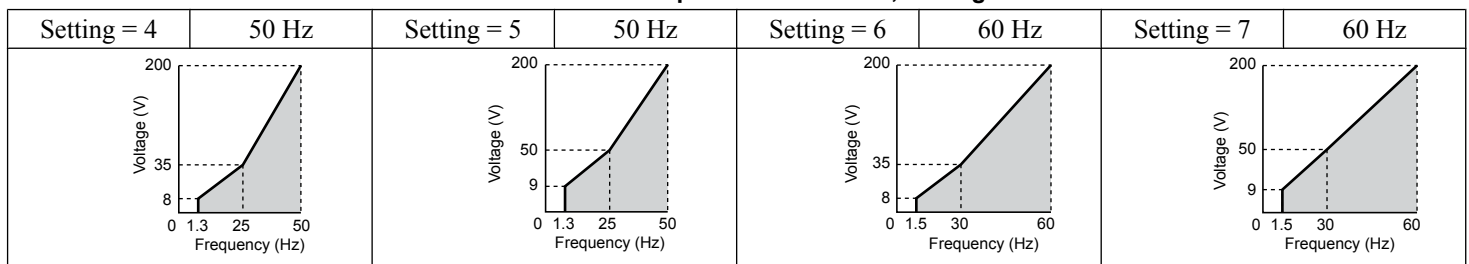


Table 5.19 High Starting Torque, Settings 8 to B

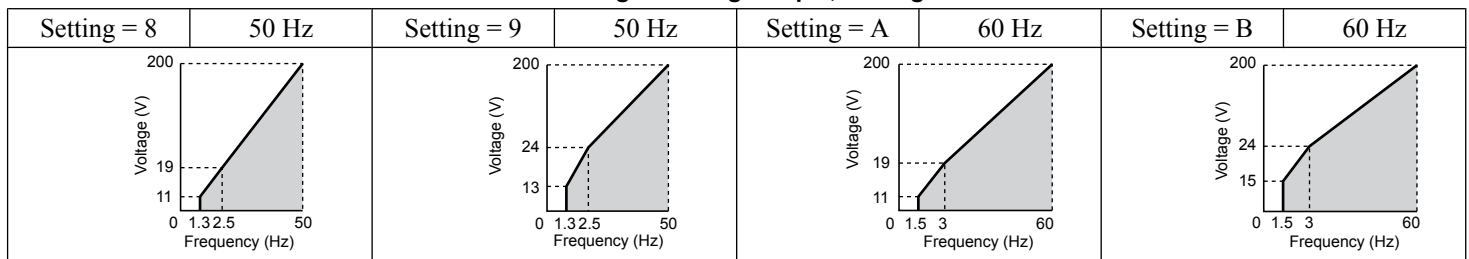
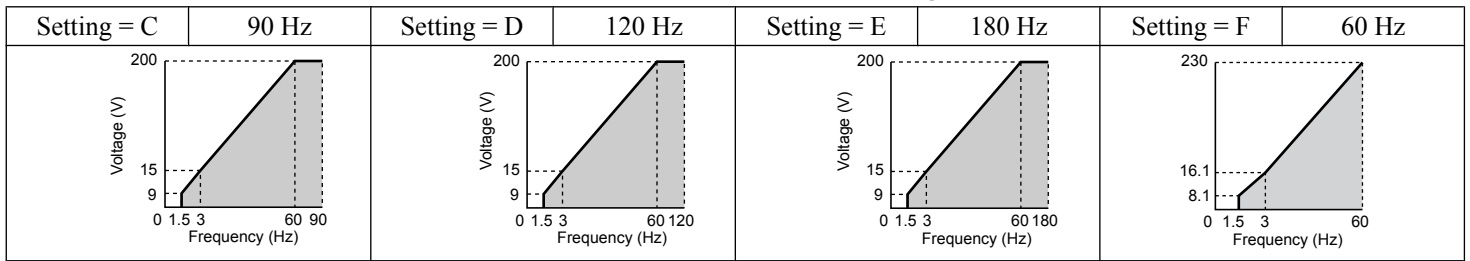


Table 5.20 Rated Output Operation, Settings C to F



Predefined V/f Patterns for Models 2A0030 to 2A0211, 4A0018 to 4A0103, and 5A0011 to 5A0077

The values in the following graphs are specific to 200 V class drives. Double the values for 400 V class drives. Multiply the values by 2.875 for 600 V class drives.

Table 5.21 Rated Torque Characteristics, Settings 0 to 3

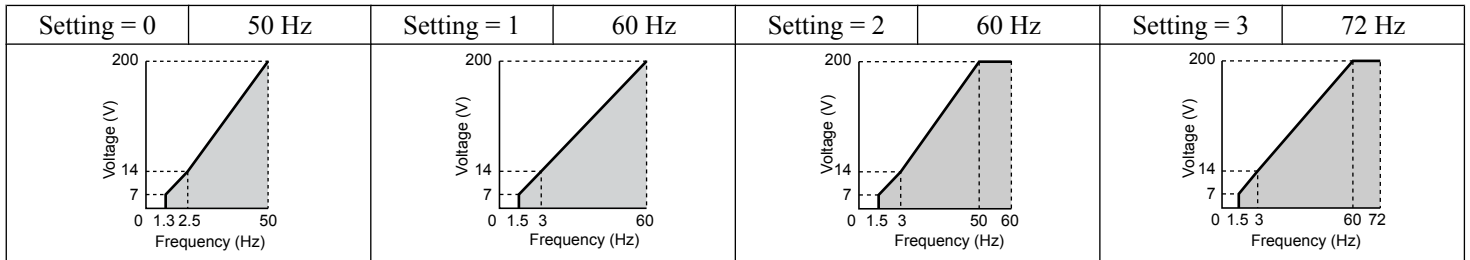


Table 5.22 Derated Torque Characteristics, Settings 4 to 7

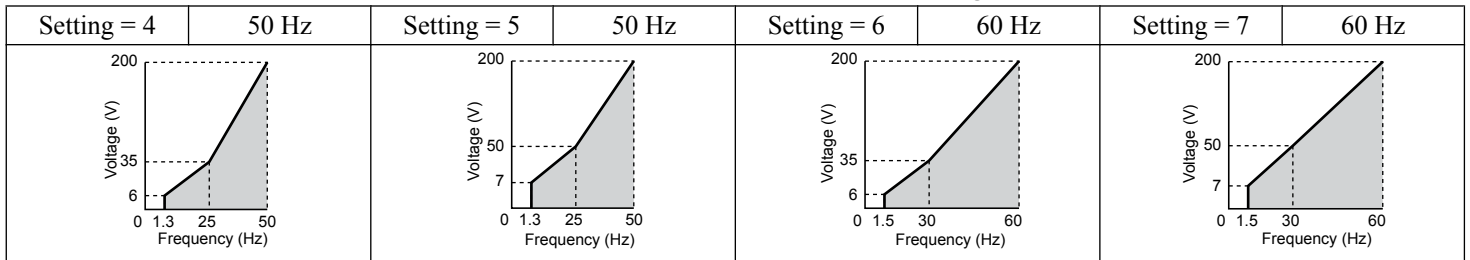


Table 5.23 High Starting Torque, Settings 8 to B

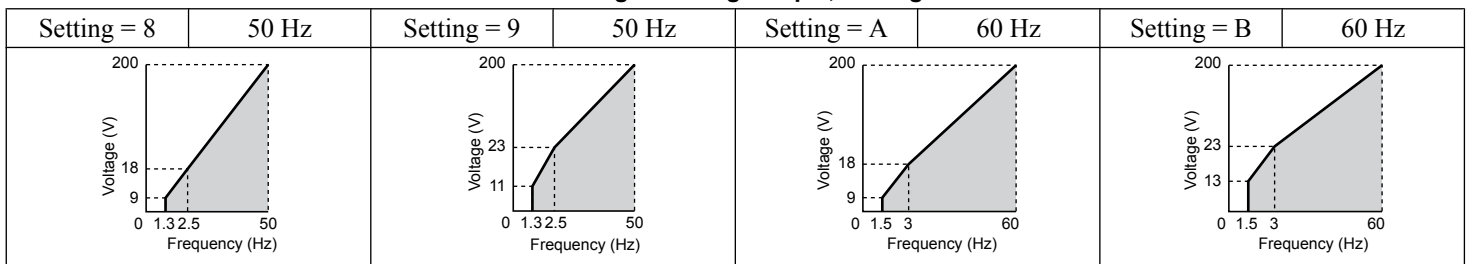
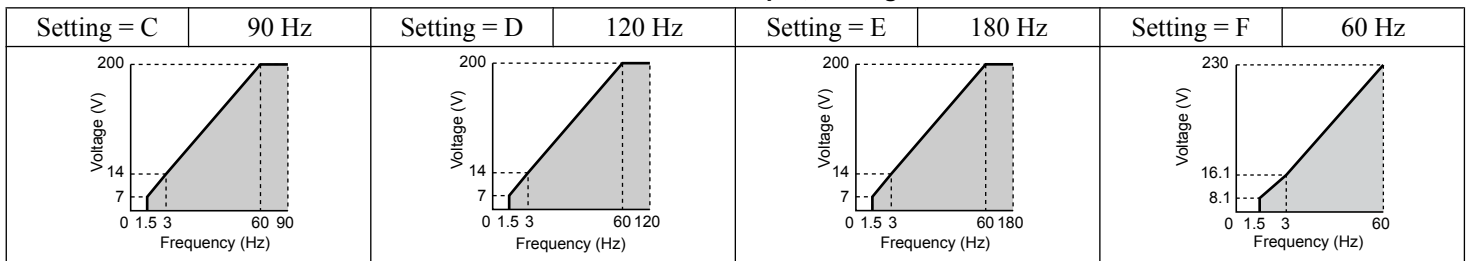


Table 5.24 Constant Output, Settings C to F



Predefined V/f Patterns for Models 2A0250 to 2A0415, 4A0139 to 4A1200, and 5A0099 to 5A0242

The values in the following graphs are specific to 200 V class drives. Double the values for 400 V class drives. Multiply the values by 2.875 for 600 V class drives.

5.5 E: Motor Parameters

Table 5.25 Rated Torque Characteristics, Settings 0 to 3

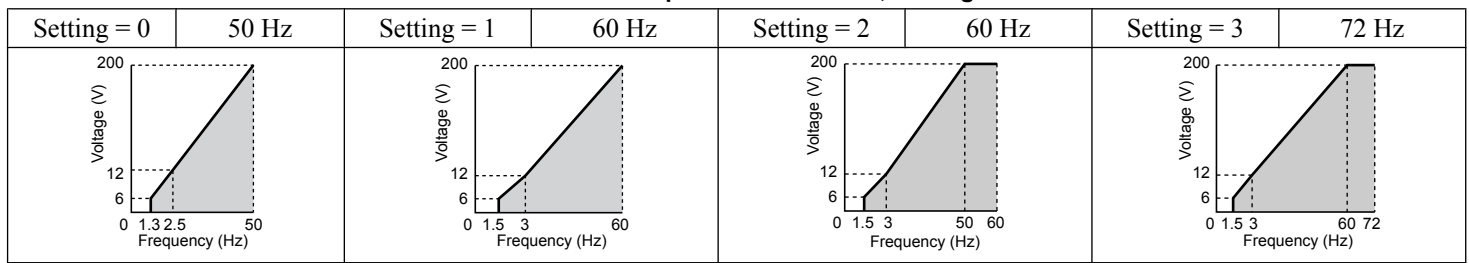


Table 5.26 Derated Torque Characteristics, Settings 4 to 7

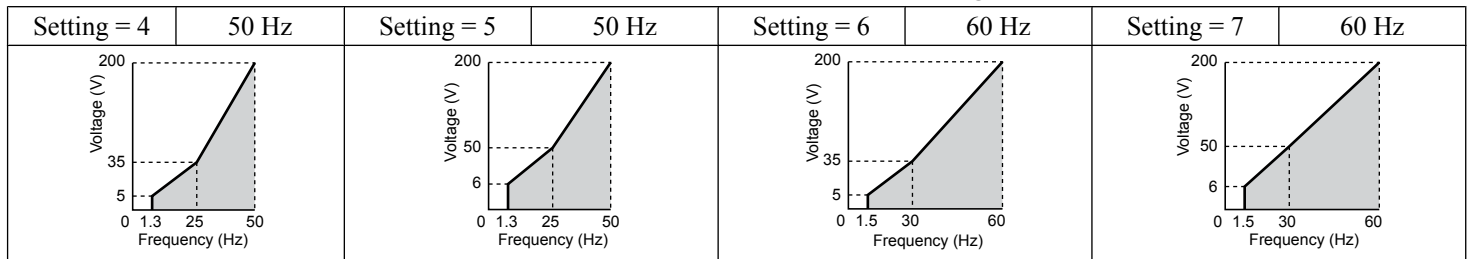


Table 5.27 High Starting Torque, Settings 8 to B

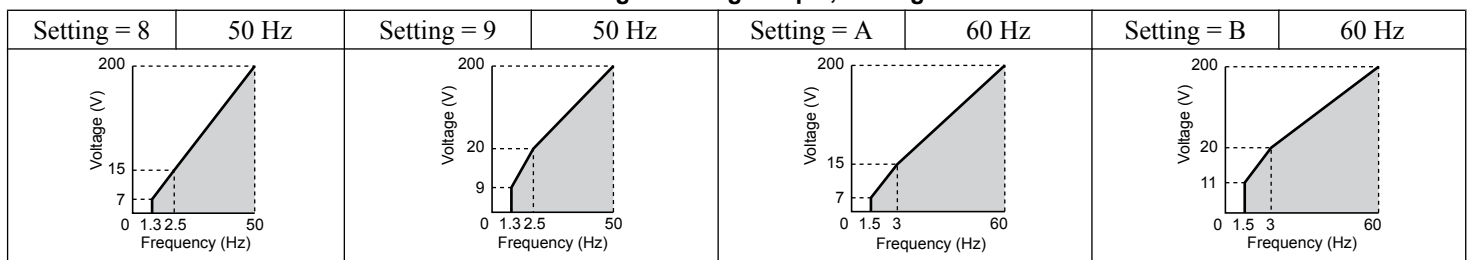
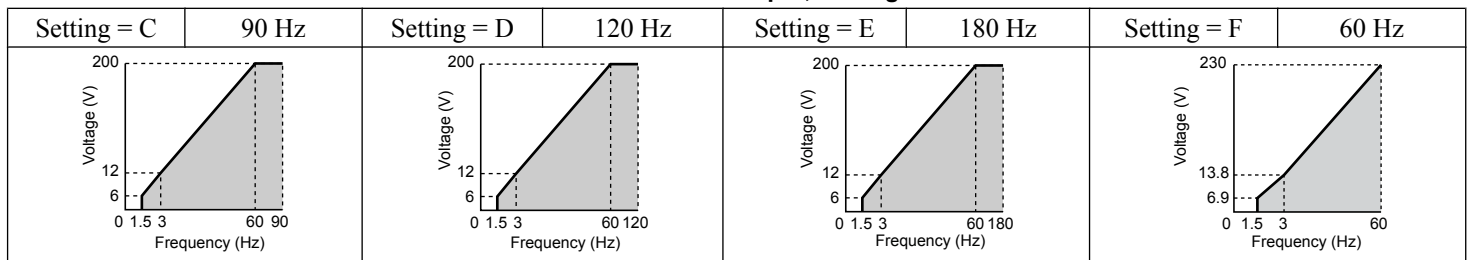


Table 5.28 Constant Output, Settings C to F



Setting a Custom V/f Pattern (Setting F: Default)

Setting parameter E1-03 to F allows the user to set up a custom V/f pattern by changing parameters E1-04 to E1-13.

■ V/f Pattern Settings E1-04 to E1-13

If E1-03 is set to a preset V/f pattern (i.e., a value other than F), the user can monitor the V/f pattern in parameters E1-04 through E1-13. To create a new V/f pattern, set E1-03 to F. [Refer to V/f Pattern on page 195](#) for an example custom V/f pattern.

| No. | Parameter Name | Setting Range | Default |
|-------|-----------------------------------|--------------------|---------------|
| E1-04 | Maximum Output Frequency | 40.0 to 400.0 Hz | 60.0 Hz |
| E1-05 | Maximum Voltage | 0.0 to 255.0 V <4> | 575.0 V |
| E1-06 | Base Frequency | 0.0 to [E1-04] | 60.0 Hz |
| E1-07 | Middle Output Frequency | 0.0 to [E1-04] | 3.0 Hz |
| E1-08 | Middle Output Frequency Voltage | 0.0 to 255.0 V <4> | 15.0 V |
| E1-09 | Minimum Output Frequency | 0.0 to [E1-04] | 1.5 Hz |
| E1-10 | Minimum Output Frequency Voltage | 0.0 to 255.0 V <4> | 9.0 V |
| E1-11 | Middle Output Frequency 2 | 0.0 to [E1-04] | 0.0 Hz <6> |
| E1-12 | Middle Output Frequency Voltage 2 | 0.0 to 255.0 V <4> | 0.0 V <5> <6> |

| No. | Parameter Name | Setting Range | Default |
|-------|----------------|-------------------|-------------|
| E1-13 | Base Voltage | 0.0 to 255.0 V <> | 0.0 V <> <> |

- <4> Values shown are specific to 200 V class drives. Double the value for 400 V class drives. Multiply the value by 2.875 for 600 V class drives.
- <5> The drive changes these settings when Auto-Tuning is performed (Rotational Auto-Tuning, Stationary Auto-Tuning 1, 2).
- <6> Parameter ignored when E1-11 and E1-12 are set to 0.0.
- <7> E1-13 and E1-05 are set to the same value when Auto-Tuning is performed.

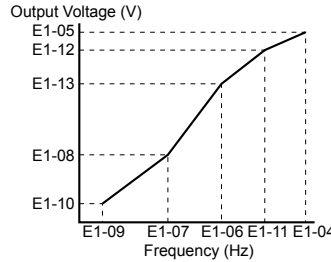


Figure 5.35 V/f Pattern

- Note:**
1. The following condition must be true when setting up the V/f pattern: $E1-09 \leq E1-07 < E1-06 \leq E1-11 \leq E1-04$
 2. To make the V/f pattern a straight line below E1-06, set E1-09 equal to E1-07. In this case the E1-08 setting is disregarded.
 3. E1-03 is unaffected when the drive is initialized, but E1-04 through E1-13 return to their default values.
 4. Only use E1-11, E1-12, and E1-13 to fine-tune the V/f pattern in the constant output range. These parameters rarely need to be changed.

◆ E2: Motor 1 Parameters

These parameters contain the motor data needed for motor 1. Performing Auto-Tuning (including Rotational Auto-Tuning and Stationary Auto-Tuning 1 and 2) automatically sets these parameters. *Refer to Auto-Tuning Fault Detection on page 322* for details if Auto-Tuning cannot be performed.

■ E2-01: Motor Rated Current

Provides motor control, protects the motor, and calculates torque limits. Set E2-01 to the full load amps (FLA) stamped on the motor nameplate. If Auto-Tuning completes successfully, the value entered to T1-04 will automatically be saved to E2-01.

| No. | Parameter Name | Setting Range | Default |
|-------|---------------------|---|---------------------|
| E2-01 | Motor Rated Current | 10% to 200% of the drive rated current <> | Determined by o2-04 |

- <1> Display is in the following units:
 2A0004 to 2A0040, 4A0002 to 4A0023, and 5A0007 to 5A0017: 0.01 A units.
 2A0056 to 2A0415, 4A0031 to 4A0675, and 5A0022 to 5A0242: 0.1 A units.
 4A0930 and 4A1200: 1 A units.

Note: An oPE02 error will occur if the motor rated current in E2-01 is set lower than the motor no-load current in E2-03. Set E2-03 correctly to prevent this error.

■ E2-02: Motor Rated Slip

Sets the motor rated slip in Hz to provide motor control, protect the motor, and calculate torque limits. This value is automatically set during Auto-Tuning (Rotational Auto-Tuning, Stationary Auto-Tuning 1 and 2).

| No. | Parameter Name | Setting Range | Default |
|-------|------------------|------------------|---------------------|
| E2-02 | Motor Rated Slip | 0.00 to 20.00 Hz | Determined by o2-04 |

If Auto-Tuning cannot be performed, calculate the motor rated slip using the information written on the motor nameplate and the formula below:

$$E2-02 = f - (n \times p) / 120$$

(f: rated frequency (Hz), n: rated motor speed (r/min), p: number of motor poles)

5.5 E: Motor Parameters

■ E2-03: Motor No-Load Current

Set the no-load current for the motor in amperes when operating at the rated frequency and the no-load voltage. The drive sets E2-03 during the Auto-Tuning process (Rotational Auto-Tuning and Stationary Auto-Tuning 1, 2). The motor no-load current listed in the motor test report can also be entered to E2-03 manually. Contact the motor manufacturer to receive a copy of the motor test report.

| No. | Parameter Name | Setting Range | Default |
|-------|-----------------------|--------------------------------|------------------------|
| E2-03 | Motor No-Load Current | 0 to [E2-01] (unit: 0.01 A) | Determined by o2-04 |

Note: The number of decimal places in the parameter value depends on the drive model 1. This value has two decimal places (0.01 A) if the drive is set for a maximum applicable motor capacity up to and including 11 kW, and one decimal place (0.1 A) if the maximum applicable motor capacity is higher than 11 kW. *Refer to Power Ratings on page 394* for details.

■ E2-04: Number of Motor Poles

Set the number of motor poles to E2-04. If Auto-Tuning completes successfully, the value entered to T1-06 will automatically be saved to E2-04.

| No. | Parameter Name | Setting Range | Default |
|-------|-----------------------|---------------|---------|
| E2-04 | Number of Motor Poles | 2 to 48 | 4 |

■ E2-05: Motor Line-to-Line Resistance

Sets the line-to-line resistance of the motor stator winding. If Auto-Tuning completes successfully, this value is automatically calculated. Enter this value as line-to-line and not for each motor phase.

If Auto-Tuning is not possible, contact the motor manufacturer to find out the line-to-line resistance or measure it manually. When using the manufacturer motor test report, calculate E2-05 by one of the formulas below:

- E-type insulation: Multiply 0.92 times the resistance value (Ω) listed on the test report at 75 °C.
- B-type insulation: Multiply 0.92 times the resistance value (Ω) listed on the test report at 75 °C.
- F-type insulation: Multiply 0.87 times the resistance value (Ω) listed on the test report at 115 °C.

| No. | Parameter Name | Setting Range | Default |
|-------|-------------------------------|--------------------------------|------------------------|
| E2-05 | Motor Line-to-Line Resistance | 0.000 to 65.000 m Ω <1> | Determined by o2-04 |

<1>

■ E2-06: Motor Leakage Inductance

Sets the voltage drop due to motor leakage inductance as a percentage of motor rated voltage. This value is automatically set during Auto-Tuning (Rotational Auto-Tuning, Stationary Auto-Tuning 1, 2).

| No. | Parameter Name | Setting Range | Default |
|-------|--------------------------|---------------|------------------------|
| E2-06 | Motor Leakage Inductance | 0.0 to 40.0% | Determined by o2-04 |

■ E2-10: Motor Iron Loss for Torque Compensation

Sets the motor iron loss in watts.

| No. | Parameter Name | Setting Range | Default |
|-------|---|---------------|------------------------|
| E2-10 | Motor Iron Loss for Torque Compensation | 0 to 65535 W | Determined by o2-04 |

■ E2-11: Motor Rated Power

Sets the motor rated power in kW. If Auto-Tuning completes successfully, the value entered to T1-02 will automatically be saved to E2-11.

| No. | Parameter Name | Setting Range | Default |
|-------|-------------------|-------------------|------------------------|
| E2-11 | Motor Rated Power | 0.00 to 650.00 kW | Determined by o2-04 |

■ Setting Motor Parameters Manually

Follow the instructions below when setting motor-related parameters manually instead of Auto-Tuning. Refer to the motor test report included with the motor to ensure the correct data is entered into the drive.

Set the Motor Rated Current

Enter the motor rated current listed on the nameplate of the motor to E2-01.

Set the Motor Rated Slip

Calculate the motor rated slip using the base speed listed on the motor nameplate. Refer to the formula below, then enter that value to E2-02.

$$\text{Motor rated slip} = \text{rated frequency [Hz]} - \text{base speed [r/min]} \times (\text{no. of motor poles}) / 120$$

Set the No-Load Current

Enter the no-load current at rated frequency and rated voltage to E2-03. This information is not usually listed on the nameplate. Contact the motor manufacturer if the data cannot be found.

The default setting of the no-load current is for performance with a 4-pole Yaskawa motor.

Set the Line-to-Line Resistance

E2-05 is normally set during Auto-Tuning. If Auto-Tuning cannot be performed, contact the motor manufacturer to determine the correct resistance between motor lines. The motor test report can also be used to calculate this value using the formulas below:

- E-type insulation: Multiply 0.92 times the resistance value (Ω) listed on the test report at 75 °C.
- B-type insulation: Multiply 0.92 times the resistance value (Ω) listed on the test report at 75 °C.
- F-type insulation: Multiply 0.87 times the resistance value (Ω) listed on the test report at 115 °C.

Set the Motor Leakage Inductance

The motor leakage inductance set to E2-06 determines the amount of voltage drop relative to the motor rated voltage. Enter this value for motors with a low degree of inductance, such as high-speed motors. This information is usually not listed on the motor nameplate. Contact the motor manufacturer if the data cannot be found.

Set the Motor Iron-Core Saturation Coefficient 1, 2

E2-07 and E2-08 are set when Auto-Tuning is performed.

Set the Motor Iron Loss for Torque Compensation

Enter this value in watts to E2-10. The drive uses this setting to improve the precision of torque compensation.

5.6 F: Option Settings

◆ F4: Analog Monitor Card Settings

These parameters set the drive for operation with the analog output option card AO-A3. Refer to the instruction manual packaged with the option card for specific details on installation, wiring, input signal level selection, and parameter setup.

■ F4-01, F4-03: Terminal V1, V2 Monitor Selection

Selects the data to output from analog terminal V1. Enter the final three digits of U□-□□ to determine which monitor data is output from the option card. Some monitors are only available in certain control modes.

| No. | Parameter Name | Setting Range | Default |
|-------|-------------------------------|---------------|---------|
| F4-01 | Terminal V1 Monitor Selection | 000 to 999 | 102 |
| F4-03 | Terminal V2 Monitor Selection | 000 to 999 | 103 |

Note: Set "000" or "031" when using the terminal in through mode. This setting can adjust the V1 and V2 terminal output from PLC via MEMOBUS/Modbus communications or a communications option.

■ F4-02, F4-04, F4-05, F4-06: Terminal V1, V2 Monitor Gain and Bias

Parameters F4-02 and F4-04 determine the gain, while parameters F4-05 and F4-06 set the bias. These parameters are set as a percentage of the output signal from V1 and V2 where 100% equals 10 V output. The terminal output voltage is limited to 10 V.

| No. | Parameter Name | Setting Range | Default |
|-------|--------------------------|------------------|---------|
| F4-02 | Terminal V1 Monitor Gain | -999.9 to 999.9% | 100.0% |
| F4-04 | Terminal V2 Monitor Gain | -999.9 to 999.9% | 50.0% |
| F4-05 | Terminal V1 Monitor Bias | -999.9 to 999.9% | 0.0% |
| F4-06 | Terminal V2 Monitor Bias | -999.9 to 999.9% | 0.0% |

Using Gain and Bias to Adjust Output Signal Level

The output signal is adjustable while the drive is stopped.

Terminal V1

1. View the value set to F4-02 (Terminal V1 Monitor Gain) on the digital operator. A voltage equal to 100% of the parameter being set in F4-01 will be output from terminal V1.
2. Adjust F4-02 viewing the monitor connected to the terminal V1.
3. View the value set to F4-05 on the digital operator, terminal V1 will output a voltage equal to 0% of the parameter being set in F4-01.
4. Adjust F4-05 viewing the output signal on the terminal V1.

Terminal V2

1. View the value set to F4-02 (Terminal V2 Monitor Gain) on the digital operator. A voltage equal to 100% of the parameter being viewed in F4-03 will be output from terminal V2.
2. Adjust F4-04 viewing the monitor connected to the terminal V2.
3. View the value set to F4-06 on the digital operator, terminal V2 will output a voltage equal to 0% of the parameter being set in F4-03.
4. Adjust F4-06 viewing the output signal on the terminal V2.

■ F4-07, F4-08: Terminal V1, V2 Signal Level

Sets the output signal level for terminals V1 and V2.

| No. | Parameter Name | Setting Range | Default |
|-------|--------------------------|---------------|---------|
| F4-07 | Terminal V1 Signal Level | 0, 1 | 0 |
| F4-08 | Terminal V2 Signal Level | 0, 1 | 0 |

Setting 0: 0 to 10 V

Setting 1: -10 to 10 V

◆ F6 and F7: Communication Option Card

These parameters configure communication option cards and communication fault detection methods.

Some parameters apply to all communication option cards and some parameters apply to certain network options only. The option cards are applicable to the parameter rows marked with an “O”.

| Comm. Protocol | Parameter Range | | | | | | | | | | | | | |
|-------------------|-----------------|-------|----------------|----------------|--------------|-------|----------------|----------------|--------------|----------------|----------------|----------------|-------|----------------|
| | F6-01 to F6-03 | F6-04 | F6-06 to F6-08 | F6-10 to F6-14 | F6-20, F6-21 | F6-22 | F6-23 to F6-26 | F6-30 to F6-32 | F6-35, F6-36 | F6-45 to F6-49 | F6-50 to F6-63 | F7-01 to F7-15 | F7-16 | F7-17 to F7-42 |
| CC-Link | O | O | O | O | - | - | - | - | - | - | - | - | - | - |
| MECHA-TROLINK-II | O | - | O | - | O | O | O | - | - | - | - | - | - | - |
| MECHA-TROLINK-III | O | - | O | - | O | - | O | - | - | - | - | - | - | - |
| PROFIBUS-DP | O | - | O | - | - | - | - | O | - | - | - | - | - | - |
| CANopen | O | - | O | - | - | - | - | - | O | - | - | - | - | - |
| EtherCAT | O | - | O | - | - | - | - | - | - | - | - | - | - | - |
| BACnet | O | - | - | - | - | - | - | - | - | O | - | - | - | - |
| DeviceNet | O | - | O | - | - | - | - | - | - | - | O | - | - | - |
| LonWorks | O | - | O | - | - | - | - | - | - | - | - | - | - | - |
| Modbus TCP/IP | O | - | O | - | - | - | - | - | - | - | - | O | O | - |
| PROFINET | O | - | O | - | - | - | - | - | - | - | - | O | - | O |
| EtherNet/IP | O | - | O | - | - | - | - | - | - | - | - | O | - | O |

■ F6-01: Communications Error Operation Selection

Determines drive operation when a communication error occurs.

| No. | Parameter Name | Setting Range | Default |
|-------|--|---------------|---------|
| F6-01 | Communications Error Operation Selection | 0 to 5 | 1 |

Setting 0: Ramp to Stop (Use the Deceleration Time Set to C1-02)

Setting 1: Coast to Stop

Setting 2: Fast Stop (Use the Fast Stop Time Set to C1-09)

Setting 3: Alarm Only (Continue Operation)

Setting 4: Alarm Only (Continue Operation Using the Frequency Reference Set in d1-04)

Setting 5: Alarm and Ramp to Stop

Note: Settings 4 and 5 available in drive software versions PRG: 8503 and later.

■ F6-02: External Fault from Comm. Option Detection Selection

Determines the detection method of an external fault initiated by a communication option (EF0).

| No. | Parameter Name | Setting Range | Default |
|-------|--|---------------|---------|
| F6-02 | External Fault from Comm. Option Detection Selection | 0, 1 | 0 |

Setting 0: Always Detected

Setting 1: Detection during Run Only

5.6 F: Option Settings

■ F6-03: External Fault from Comm. Option Operation Selection

Determines drive operation when an external fault is initiated by a communication option (EF0).

| No. | Parameter Name | Setting Range | Default |
|-------|--|---------------|---------|
| F6-03 | External Fault from Comm. Option Operation Selection | 0 to 3 | 1 |

Setting 0: Ramp to Stop

Setting 1: Coast to Stop

Setting 2: Fast Stop

Setting 3: Alarm Only (Continue Operation)

■ F6-07: NetRef/ComRef Function Selection

Selects the treatment of multi-step speed inputs when the NetRef command is set.

| No. | Parameter Name | Setting Range | Default |
|-------|----------------------------------|---------------|---------|
| F6-07 | NetRef/ComRef Function Selection | 0, 1 | 0 |

Setting 0: Multi-step Speed Operation Disabled

Multi-step speed input frequency references are disabled when the NetRef command is selected.

Setting 1: Multi-step Speed Operation Enabled

Multi-step speed inputs are still active and can override the frequency reference from the communications option even when the NetRef command is selected.

■ F6-08: Reset Communication Parameters

Determines whether F6-□□/□□/□□ communication-related parameters are reset after initialization.

| No. | Parameter Name | Setting Range | Default |
|-------|--------------------------------|---------------|---------|
| F6-08 | Reset Communication Parameters | 0, 1 | 0 |

Setting 0: Do Not Reset F6-□□/□□/□□ Parameters after Initialization Using A1-03

Setting 1: Reset F6-□□/□□/□□ Parameters after Initialization Using A1-03

Note: F6-08 is not reset when the drive is initialized.

◆ CC-Link Parameters

Parameters F6-04, F6-10, F6-11, and F6-14 set the drive to operate on a CC-Link network.

■ F6-04: bUS Error Detection Time

Sets the delay time for bUS error detection.

| No. | Parameter Name | Setting Range | Default |
|-------|--------------------------|---------------|---------|
| F6-04 | bUS Error Detection Time | 0.0 to 5.0 s | 2.0 s |

■ F6-10: CC-Link Node Address

Sets the node address of a CC-Link option board.

| No. | Parameter Name | Setting Range | Default |
|-------|----------------------|---------------|---------|
| F6-10 | CC-Link Node Address | 0 to 64 | 0 |

■ F6-11: CC-Link Communication Speed

Sets the communication speed for a CC-Link option card.

| No. | Parameter Name | Setting Range | Default |
|-------|-----------------------------|---------------|---------|
| F6-11 | CC-Link Communication Speed | 0 to 4 | 0 |

Setting 0: 156 kbps

Setting 1: 625 kbps

Setting 2: 2.5 Mbps

Setting 3: 5 Mbps

Setting 4: 10 Mbps

■ F6-14: bUS Error Auto Reset

Selects whether a bUS error can be automatically reset if automatic fault retry is enabled.

| No. | Parameter Name | Setting Range | Default |
|-------|----------------------|---------------|---------|
| F6-14 | bUS Error Auto Reset | 0, 1 | 0 |

Setting 0: Disabled, Auto Reset Not Possible

Setting 1: Enabled, Auto Reset Possible

◆ MECHATROLINK Parameters

Parameters F6-20 through F6-26 run the MECHATROLINK options.

■ F6-20: MECHATROLINK Station Address

| No. | Parameter Name | Setting Range | Default |
|-------|------------------------------|---------------|---------|
| F6-20 | MECHATROLINK Station Address | 20, 3F | 21 |

■ F6-21: MECHATROLINK Frame Size

| No. | Parameter Name | Setting Range | Default |
|-------|-------------------------|---------------|---------|
| F6-21 | MECHATROLINK Frame Size | 0, 1 | 0 |

Setting 0: 32 byte

Setting 1: 17 byte

■ F6-22: MECHATROLINK Link Speed

| No. | Parameter Name | Setting Range | Default |
|-------|-------------------------|---------------|---------|
| F6-22 | MECHATROLINK Link Speed | 0, 1 | 0 |

Setting 0: 10 Mbps

Setting 1: 4 Mbps

■ F6-23 and F6-24: MECHATROLINK Monitor Selection

Sets the output signal level for terminals V1 and V2.

| No. | Parameter Name | Setting Range | Default |
|-------|--|---------------|---------|
| F6-23 | MECHATROLINK-II Monitor Selection (E) | 0, FFFF | 0 |
| F6-24 | MECHATROLINK -II Monitor Selection (F) | 0, FFFF | 0 |

■ F6-25: Operation Selection at Watchdog Timer Error

| No. | Parameter Name | Setting Range | Default |
|-------|--|---------------|---------|
| F6-25 | Operation Selection at Watchdog Timer Error (E5) | 0 to 3 | 1 |

Setting 0: Ramp to stop. Decelerate using the deceleration time in C1-02.

Setting 1: Coast to stop.

Setting 2: Fast stop. Decelerate using the deceleration time in C1-09.

Setting 3: Alarm only

■ F6-26: MECHATROLINK bUS Errors Detected

Sets the number of option communication errors (bUS).

| No. | Parameter Name | Setting Range | Default |
|-------|----------------------------------|---------------|---------|
| F6-26 | MECHATROLINK bUS Errors Detected | 2 to 10 | 2 |

5.6 F: Option Settings

◆ PROFIBUS-DP Parameters

Parameters F6-30 through F6-32 set the drive to run on a PROFIBUS-DP network.

■ F6-30: PROFIBUS-DP Node Address

Sets the node address of a PROFIBUS-DP option card.

| No. | Parameter Name | Setting Range | Default |
|-------|--------------------------|---------------|---------|
| F6-30 | PROFIBUS-DP Node Address | 0 to 125 | 0 |

■ F6-31: PROFIBUS-DP Clear Mode Selection

Determines the operation when a Clear Mode command is received.

| No. | Parameter Name | Setting Range | Default |
|-------|----------------------------------|---------------|---------|
| F6-31 | PROFIBUS-DP Clear Mode Selection | 0, 1 | 0 |

Setting 0: Reset

Resets the drive operation (frequency reference, inputs, outputs etc.).

Setting 1: Maintain the Previous State

Returns the drive status to the state prior to receiving the command.

■ F6-32: PROFIBUS-DP Data Format Selection

Selects the data format used for PROFIBUS-DP communication.

| No. | Parameter Name | Setting Range | Default |
|-------|-----------------------------------|---------------|---------|
| F6-32 | PROFIBUS-DP Data Format Selection | 0 to 5 | 0 |

Setting 0: PPO-type Data Format

Setting 1: Conventional Data Format

Setting 2: PPO (w/bit 0)

Setting 3: PPO Type (Auto Enter)

Setting 4: Conventional (Auto Enter)

Setting 5: PPO (w/bit0, Auto Enter)

Note: Settings 2 to 5 are available in drive software versions PRG: 8503 and later.

◆ CANopen Parameters

Parameters F6-35 and F6-36 set the drive to operate on a CANopen network.

■ F6-35: CANopen Node ID Selection

Selects the node ID of a CANopen option board.

| No. | Parameter Name | Setting Range | Default |
|-------|---------------------------|---------------|---------|
| F6-35 | CANopen Node ID Selection | 0 to 126 | 0 |

■ F6-36: CANopen Communication Speed

Sets the communication speed for a CANopen option card.

| No. | Parameter Name | Setting Range | Default |
|-------|-----------------------------|---------------|---------|
| F6-36 | CANopen Communication Speed | 0 to 8 | 6 |

Setting 0: Auto detection

Setting 1: 10 kbps

Setting 2: 20 kbps

Setting 3: 50 kbps

Setting 4: 125 kbps

Setting 5: 250 kbps

Setting 6: 500 kbps

Setting 7: 800 kbps

Setting 8: 1 Mbps

◆ DeviceNet Parameters

Parameters F6-50 through F6-63 set the drive to operate on a DeviceNet network.

■ F6-50: DeviceNet MAC Address

Sets the MAC address for a DeviceNet option card.

| No. | Parameter Name | Setting Range | Default |
|-------|-----------------------|---------------|---------|
| F6-50 | DeviceNet MAC Address | 0 to 64 | 64 |

■ F6-51: DeviceNet Communication Speed

Sets the communication speed for a DeviceNet option card.

To assign the baud rate for the drive from the upper controller, set F6-51 = 3.

To make the drive detect the network speed, set F6-51 = 4. The drive will automatically adjust itself after detecting the network speed.

| No. | Parameter Name | Setting Range | Default |
|-------|-------------------------------|---------------|---------|
| F6-51 | DeviceNet Communication Speed | 0 to 4 | 4 |

Setting 0: 125 kbps

Setting 1: 250 kbps

Setting 2: 500 kbps

Setting 3: Adjustable from network

Setting 4: Auto detection

■ F6-52: DeviceNet PCA Setting

Defines the format for data the drive receives from the DeviceNet master.

| No. | Parameter Name | Setting Range | Default |
|-------|-----------------------|---------------|---------|
| F6-52 | DeviceNet PCA Setting | 0 to 255 | 21 |

■ F6-53: DeviceNet PPA Setting

Defines the format for data sent from the drive to the DeviceNet master.

| No. | Parameter Name | Setting Range | Default |
|-------|-----------------------|---------------|---------|
| F6-53 | DeviceNet PPA Setting | 0 to 255 | 71 |

■ F6-54: DeviceNet Idle Mode Fault Detection

Determines whether the drive triggers an EF0 fault when no data is received from the master (e.g., when the master is idling).

| No. | Parameter Name | Setting Range | Default |
|-------|-------------------------------------|---------------|---------|
| F6-54 | DeviceNet Idle Mode Fault Detection | 0 to 4 | 0 |

Setting 0: Enabled

Setting 1: Disabled, No Fault Detection

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Setting 2: Vendor Specific

Setting 3: Forward

Setting 4: Reverse

Note: Settings 2 to 4 are available in drive software versions PRG: 8503 and later.

■ F6-55: DeviceNet Baud Rate Monitor

Displays the baud rate currently being used for network communications. F6-55 is used only as a monitor.

| No. | Parameter Name | Setting Range | Default |
|-------|-----------------------------|--------------------|---------|
| F6-55 | DeviceNet Baud Rate Monitor | 0 to 2 (read only) | 0 |

Setting 0: 125 kbps

Setting 1: 250 kbps

Setting 2: 500 kbps

■ F6-56 to F6-61: DeviceNet Scaling Factors

These parameters define scaling factors for drive monitors in the DeviceNet Class ID 2AH - AC/DC Drive Object.

| No. | Parameter Name | Setting Range | Default |
|-------|---------------------------|---------------|---------|
| F6-56 | DeviceNet Speed Scaling | -15 to 15 | 0 |
| F6-57 | DeviceNet Current Scaling | -15 to 15 | 0 |
| F6-58 | DeviceNet Torque Scaling | -15 to 15 | 0 |
| F6-59 | DeviceNet Power Scaling | -15 to 15 | 0 |
| F6-60 | DeviceNet Voltage Scaling | -15 to 15 | 0 |
| F6-61 | DeviceNet Time Scaling | -15 to 15 | 0 |

Setting

The monitor value in the AC/DC Drive Object 2AH is calculated by:

$$\text{AC/DC Drive Object 2AH Monitor} = \text{Drive Value} \times 2^{\text{Scaling}}$$

Example:

If the drive output frequency monitor (U1-02) is 5.00 and the scaling is set to F6-56 = 6, then the value in the AC/DC Drive Object 2AH, Instance 1, Attribute 7 would be $500 \times 2^6 = 32000$.

■ F6-62: DeviceNet Heartbeat Interval

Sets the heartbeat interval for DeviceNet communications. A setting of 0 disables the heartbeat function.

| No. | Parameter Name | Setting Range | Default |
|-------|------------------------------|---------------|---------|
| F6-62 | DeviceNet Heartbeat Interval | 0 to 10 | 0 |

■ F6-63: DeviceNet Network MAC ID

Displays the MAC ID assigned to the drive. F6-63 is used only as a monitor.

| No. | Parameter Name | Setting Range | Default |
|-------|--------------------------|---------------------|---------|
| F6-63 | DeviceNet Network MAC ID | 0 to 63 (read only) | 63 |

■ F6-64 to F6-71: Dynamic Assembly Parameters (Reserved)

5.7 H: Terminal Functions

H parameters assign functions to the external terminals.

◆ H1: Multi-Function Digital Inputs

■ H1-01 to H1-08: Functions for Terminals S1 to S8

These parameters assign functions to the multi-function digital inputs. The various functions and settings are listed in [Table 5.29](#).

| No. | Parameter Name | Setting Range | Default |
|-------|---|---------------|--|
| H1-01 | Multi-Function Digital Input Terminal S1 Function Selection | 1 to 9F | 40 (F) <I> : Forward Run Command (2-Wire sequence) |
| H1-02 | Multi-Function Digital Input Terminal S2 Function Selection | 1 to 9F | 41 (F) <I> : Reverse Run Command (2-Wire sequence) |
| H1-03 | Multi-Function Digital Input Terminal S3 Function Selection | 0 to 9F | 24: External Fault |
| H1-04 | Multi-Function Digital Input Terminal S4 Function Selection | 0 to 9F | 14: Fault Reset |
| H1-05 | Multi-Function Digital Input Terminal S5 Function Selection | 0 to 9F | 3 (0) <I> : Multi-Step Speed Reference 1 |
| H1-06 | Multi-Function Digital Input Terminal S6 Function Selection | 0 to 9F | 4 (3) <I> : Multi-Step Speed Reference 2 |
| H1-07 | Multi-Function Digital Input Terminal S7 Function Selection | 0 to 9F | 6 (4) <I> : Jog Reference Selection |
| H1-08 | Multi-Function Digital Input Terminal S8 Function Selection | 0 to 9F | 8: (6) <I> : External Baseblock Command |

<I> Number appearing in parenthesis is the default value after performing a 3-Wire initialization (A1-03 = 3330).

Table 5.29 Multi-Function Digital Input Terminal Settings

| Setting | Function | Page | Setting | Function | Page |
|----------|----------------------------------|---------------------|---------|---------------------------------------|---------------------|
| 0 | 3-Wire Sequence | 206 | 32 | Multi-Step Speed Reference 4 | 211 |
| 1 | LOCAL/REMOTE Selection | 206 | 34 | PID Soft Starter Cancel | 211 |
| 2 | External Reference 1/2 Selection | 207 | 35 | PID Input Level Selection | 211 |
| 3 | Multi-Step Speed Reference 1 | 207 | 40 | Forward Run Command (2-Wire sequence) | 212 |
| 4 | Multi-Step Speed Reference 2 | | 41 | Reverse Run Command (2-Wire sequence) | |
| 5 | Multi-Step Speed Reference 3 | | 42 | Run Command (2-Wire sequence 2) | 212 |
| 6 | Jog reference Selection | 207 | 43 | FWD/REV Command (2-Wire sequence 2) | |
| 7 | Accel/Decel Time Selection 1 | 207 | 47 | Node Setup | 212 |
| 8 | Baseblock Command (N.O.) | 207 | 51 | Disable Sequence Timers | 212 |
| 9 | Baseblock Command (N.C.) | | 52 | Cancel Active Sequence Timer | 212 |
| A | Accel/Decel Ramp Hold | 207 | 60 | DC Injection Braking Command | 212 |
| B | Drive Overheat Alarm (oH2) | 208 | 61 | External Speed Search Command 1 | 212 |
| C | Analog Terminal Input Selection | 208 | 62 | External Speed Search Command 2 | 212 |
| F | Through Mode | 208 | 63 | Field Weakening | 213 |
| 10 | Up Command | 208 | 65 | KEB Ride-Thru 1 (N.C.) | 213 |
| 11 | Down Command | | 66 | KEB Ride-Thru 1 (N.O.) | |
| 12 | Forward Jog | 209 | 67 | Communications Test Mode | 213 |
| 13 | Reverse Jog | | 68 | High Slip Braking (HSB) | 213 |
| 14 | Fault Reset | 209 | 6A | Drive Enabled | 213 |
| 15 | Fast Stop (N.O.) | 209 | 75 | Up 2 Command | 213 |
| 17 | Fast Stop (N.C.) | 209 | 76 | Down 2 Command | |
| 18 | Timer Function Input | 210 | 7A | KEB Ride-Thru 2 (N.C.) | 214 |
| 19 | PID Disable | 210 | 7B | KEB Ride-Thru 2 (N.O.) | |
| 1A | Accel/Decel Time Selection 2 | 210 | A8 | Secondary PI Disable (N.O.) | 214 |
| 1B | Program Lockout | 210 | A9 | Secondary PI Disable (N.C.) | 214 |
| 1E | Reference Sample Hold | 210 | AA | Secondary PI Inverse Operation | 214 |
| 20 to 2F | External Fault | 211 | AB | Secondary PI Integral Reset | 214 |
| 30 | PID Integral Reset | 211 | AC | Secondary PI Integral Hold | 214 |
| 31 | PID Integral Hold | 211 | AD | Select Secondary PI Parameters | 215 |

5.7 H: Terminal Functions

| Setting | Function | Page | Setting | Function | Page |
|---------|--------------------------------|------|---------|--------------------------------|------|
| AF | Emergency Override Forward Run | 215 | B0 | Emergency Override Reverse Run | 215 |

Setting 0: 3-Wire Sequence

The digital input programmed for 3-Wire control becomes the forward/reverse directional input, S1 becomes the Run command input, and S2 becomes the Stop command input.

The drive starts the motor when the input S1 set for the Run command closes for longer than 2 ms. The drive stops the operation when the Stop input S2 is released. When the digital input programmed for a forward/reverse operation is open, the drive is set for forward operation. When the digital input is closed, the drive is set for reverse operation.

Note: Input the Run and Stop commands via S1 and S2 when selecting a 3-Wire sequence.

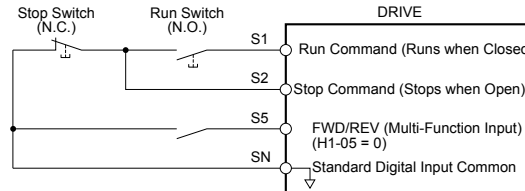


Figure 5.36 3-Wire Sequence Wiring Diagram

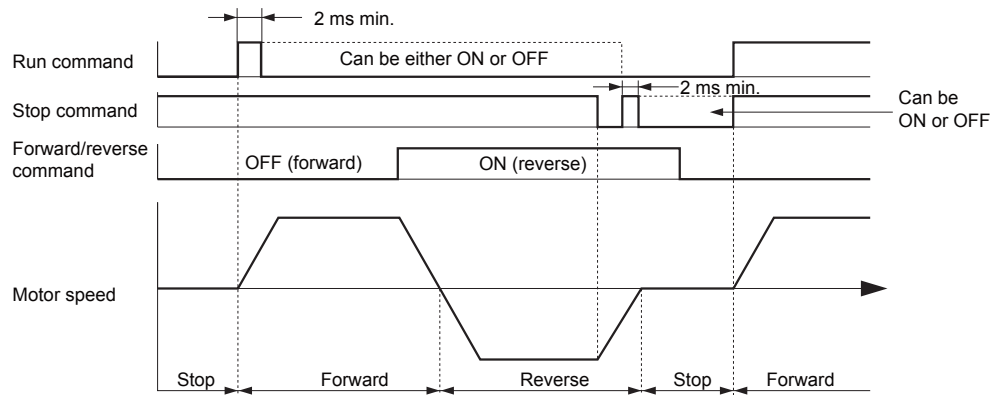


Figure 5.37 3-Wire Sequence

- Note:**
1. The Run command must be closed for more than 2 ms.
 2. If the Run command is active at power up and b1-17 = 0 (Run command at power up not accepted), the Run LED will flash to indicate that protective functions are operating. If required by the application, set b1-17 to 1 to automatically issue the Run command upon drive power up.

WARNING! Sudden Movement Hazard. Ensure start/stop and safety circuits are wired properly and in the correct state before applying power to the drive. Failure to comply could result in death or serious injury from moving equipment.

WARNING! Sudden Movement Hazard. The drive may start unexpectedly in reverse direction after power up if it is wired for 3-Wire sequence but set up for 2-Wire sequence (default). Make sure b1-17 is set to "0" (drive does not accept a Run command active at power up). When initializing the drive use 3-Wire initialization. Failure to comply could result in death or serious injury from moving equipment.

Setting 1: LOCAL/REMOTE Selection

This setting allows the input terminal to determine if the drive will run in LOCAL mode or REMOTE mode.

| Status | Description |
|--------|---|
| Closed | LOCAL: Frequency reference and Run command are input from the digital operator. |
| Open | REMOTE: Frequency reference and Run command are input from the selected external reference. If a digital input set to H1-□□ = 2 is active, they will be read from external reference source 2 (b1-15 and b1-16). In all other cases they will be read from external reference source 1 (b1-01 and b1-02). |

- Note:**
1. The LO/RE key on the digital operator is disabled when one of the multi-function input terminals is set to for LOCAL/REMOTE.
 2. When the drive is set to LOCAL, the LO/RE LED will light.
 3. The default setting of the drive does not allow switching between LOCAL and REMOTE during run. To allow the drive to switch between LOCAL and REMOTE during run, [Refer to b1-07: LOCAL/REMOTE Run Selection on page 151.](#)

Setting 2: External Reference 1/2 Selection

This function switches the Run command and frequency reference source between External reference 1 and 2 if the drive is in the REMOTE mode.

| Status | Description |
|--------|--|
| Open | External reference 1 is used (defined by parameters b1-01 and b1-02) |
| Closed | External reference 2 is used (defined by parameters b1-15 and b1-16) |

Note: Default drive settings do not allow switching between External reference 1 and 2 during run. *Refer to b1-07: LOCAL/REMOTE Run Selection on page 151* if this feature is required by the application.

Setting 3 to 5: Multi-Step Speed Reference 1 to 3

Switches multi-step speed frequency references d1-01 to d1-08 by digital inputs. *Refer to d1: Frequency Reference on page 182* for details.

Setting 6: Jog Reference Selection

The Jog frequency set in parameter d1-17 becomes the frequency reference when the input terminal closes. *Refer to d1: Frequency Reference on page 182* for details.

Setting 7: Accel/Decel Time Selection 1

Switches between accel/decel times 1 (C1-01 and C1-02) and 2 (C1-03 and C1-04). *Refer to C1-01 to C1-04: Accel, Decel Times 1 and 2 on page 177* for details.

Setting 8, 9: Baseblock Command (N.O., N.C.)

When the drive receives a baseblock command, the output transistors stop switching, the motor coasts to stop, and a bb alarm flashes on the digital operator to indicate baseblock. When baseblock ends while a Run command is active, the drive performs Speed Search to restart the motor.

| Digital Input Function | Drive Operation | |
|------------------------|------------------------------|------------------------------|
| | Input Open | Input Closed |
| Setting 8 (N.O.) | Normal operation | Baseblock (Interrupt output) |
| Setting 9 (N.C.) | Baseblock (Interrupt output) | Normal operation |

WARNING! Sudden Movement Hazard. When using a mechanical holding brake with the drive in a lifting application, close the brake when the drive output is cut off by a baseblock command triggered by one of the input terminals. Failure to comply will result in a slipping load from the motor suddenly coasting when the baseblock command is entered and may cause serious injury or death.

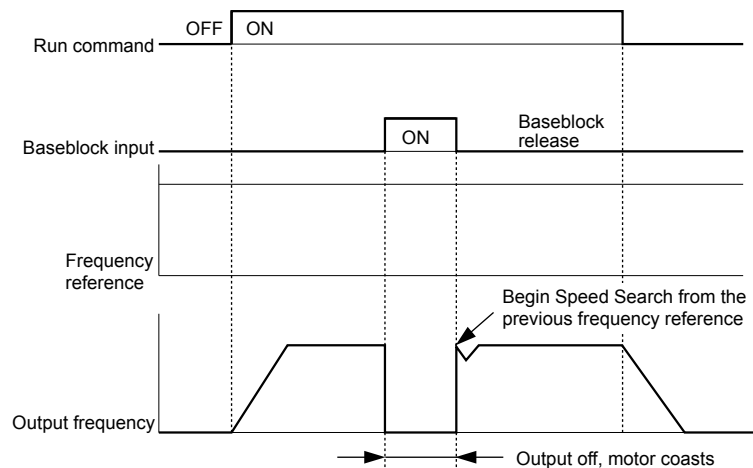


Figure 5.38 Baseblock Operation During Run

Setting A: Accel/Decel Ramp Hold

When the digital input programmed for the Accel/decel ramp hold function closes, the drive locks (holds) the output frequency. Acceleration or deceleration resumes when the input is reopened.

If the Accel/decel ramp hold function is enabled (d4-01 = 1), the drive saves the output frequency to memory when the Ramp Hold input is closed. When the drive is restarted after stop or after power supply interruption, the saved output frequency becomes the frequency reference (provided that the Accel/decel ramp hold input is still closed). *Refer to d4-01: Frequency Reference Hold Function Selection on page 186* for details.

5.7 H: Terminal Functions

Setting B: Drive Overheat Alarm (oH2)

Closed: An external device has triggered an oH2 alarm. Sets Drive Overheat Pre-alarm Multi-Function Digital Output 20h.

Setting C: Analog Terminal Input Selection (Terminal A1, A2, A3)

When closed, the terminals specified in H3-14 are enabled. When open, the drive disregards the input signal to the analog terminals.

Setting F: Through Mode

Select this setting when using the terminal in a pass-through mode. When set to F, an input does not trigger any function in the drive. Setting F, however, still allows the input status to be read out by a PLC via a communication option or MEMOBUS/Modbus communications.

Setting 10, 11: Up/Down Function

The Up/Down function allows the frequency reference to be set by two push buttons when one digital input is programmed as the Up input (H1-□□= 10) to increase the frequency reference and the other digital input is programmed as the Down input (H1-□□= 11) to decrease the frequency reference.

The Up/Down function takes priority over the frequency references from the digital operator, the analog inputs, and the pulse input (b1-01 = 0, 1, 4). When using the Up/Down function, references provided by these sources will be disregarded.

The inputs operate as shown in [Table 5.30](#):

Table 5.30 Up, Down Command

| Status | | Drive Operation |
|---------|-----------|----------------------------------|
| Up (10) | Down (11) | |
| Open | Open | Hold current frequency reference |
| Closed | Open | Increase frequency reference |
| Open | Closed | Decrease frequency reference |
| Closed | Closed | Hold current frequency reference |

- Note:**
1. An oPE03 alarm occurs when only one of the Up/Down functions is programmed to a digital input.
 2. An oPE03 alarm occurs when the Up/Down function is assigned to the terminals and a different digital input is programmed for the Accel/decel ramp hold function. For more information on alarms, [Refer to Drive Alarms, Faults, and Errors on page 291](#).
 3. The Up/Down function can only be used for External reference 1. Consider this when using Up/Down and the external reference switching command (H1-□□ = 2).

Using the Up/Down Function with Frequency Reference Hold (d4-01)

- If the frequency reference hold function is disabled (d4-01 = 0), the Up/Down frequency reference will be reset to 0 when the Run command is cleared or the power is cycled.
- When d4-01 = 1, the drive will save the frequency reference set by the Up/Down function. When the Run command or the power is cycled, the drive will restart with the saved reference value. Close the Up or Down input without an active Run command to reset the saved value. [Refer to d4-01: Frequency Reference Hold Function Selection on page 186](#).

Using the Up/Down Function with Frequency Reference Limits

Parameter d2-01 determines the upper frequency reference limit.

The value for the lower frequency reference limit depends on the parameter d4-10 setting. This value can be set by an analog input or parameter d2-02. [Refer to d4-10: Up/Down Frequency Reference Limit Selection on page 189](#) for details. When a Run command is applied, the lower limits function as follows:

- If the lower limit is set by d2-02 only, the drive accelerates to this limit as soon as a Run command is entered.
- If the lower limit is determined by an analog input only, the drive accelerates to the limit when both the Run command and an Up or Down command are active. The drive will not start running if only the Run command is active.
- If the lower limit is set by both an analog input and d2-02, and the analog limit is higher than the d2-02 value, the drive accelerates to the d2-02 value when a Run command is input. When the d2-02 value is reached, the drive accelerates to the analog limit only if an Up or Down command is set.

[Figure 5.39](#) shows an Up/Down function example with a lower frequency reference limit set by d2-02, and the frequency reference hold function both enabled and disabled.

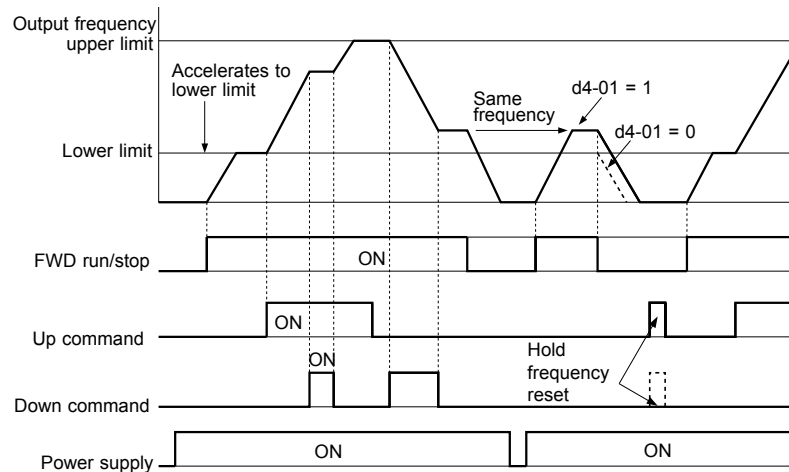


Figure 5.39 Up/Down Command Operation

Setting 12, 13: Forward Jog, Reverse Jog

Digital inputs programmed as Forward Jog (H1-□□ = 12) and Reverse Jog (H1-□□ = 13) will be Jog inputs that do not require a Run command. Closing the terminal set for Forward Jog input will cause the drive to ramp to the Jog frequency reference (d1-17) in the forward direction. The Reverse Jog will cause the same action in the reverse direction. The Forward Jog and Reverse Jog command can be set independently.

Note: The Forward Jog and Reverse Jog commands override all other frequency references. However, if the drive is set to prohibit reverse rotation (b1-04 = 1), activating Reverse Jog will have no effect. Inputting both the Forward Jog and Reverse Jog are simultaneously for 500 ms or longer will trigger an alarm will and the drive will ramp to stop.

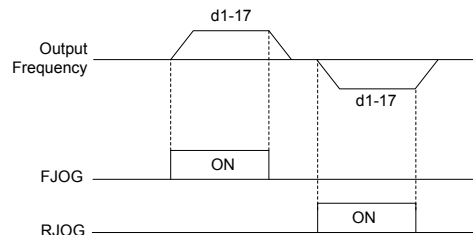


Figure 5.40 FJOG/RJOG Operation

Setting 14: Fault Reset

When the drive detects a fault condition, the fault output contact closes, the drive output shuts off, and the motor coasts to stop (specific stopping methods can be selected for some faults such as L1-04 for motor overheating). After removing the Run command, clear the fault either by pressing the RESET key on the digital operator or closing a digital input configured as a Fault Reset (H1-□□ = 14).

Note: Remove the Run command prior to resetting a fault. Fault Reset commands are ignored while the Run command is present.

Setting 15, 17: Fast Stop (N.O., N.C.)

The Fast Stop function operates similar to an emergency stop input to the drive. If a Fast Stop command is input while the drive is running, the drive decelerates to a stop in the deceleration time set to C1-09 (*Refer to C1-09: Fast Stop Time on page 178*). The drive can only be restarted after bringing the drive to a complete stop, turning off the Fast Stop input, and switching off the Run command.

- To trigger the Fast Stop function with an N.O. switch, set H1-□□ = 15.
- To trigger the Fast Stop function with an N.C. switch, set H1-□□ = 17.

Figure 5.41 shows an operation example of Fast Stop.

5.7 H: Terminal Functions

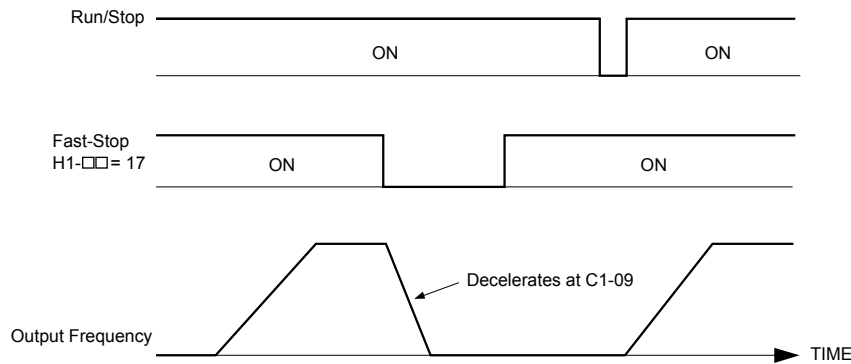


Figure 5.41 Fast Stop Sequence

NOTICE: Rapid deceleration can trigger an overvoltage fault. When faulted, the drive output shuts off, and the motor coasts. To avoid this uncontrolled motor state and to ensure that the motor stops quickly and safely, set an appropriate Fast Stop time to C1-09.

Setting 18: Timer Function Input

This setting configures a digital input terminal as the input for the timer function. Use this setting combination with the timer function output (H2-□□ = 12). [Refer to b4: Timer Function on page 160](#) for details.

Setting 19: PID Disable

Close a digital input to indefinitely disable the PID function. When the input is released, the drive resumes PID operation. [Refer to PID Block Diagram on page 163](#).

Setting 1A: Accel/Decel Time Selection 2

Selects accel/decel times 1 to 4 in combination with the Accel/decel time selection 1 command. [Refer to C1-01 to C1-04: Accel, Decel Times 1 and 2 on page 177](#) for details.

Note: Setting is available in drive software versions PRG: 8502 and earlier.

Setting 1B: Program Lockout

Parameter values cannot be changed when an input is programmed for Program Lockout and the input is open. It is still possible, however, to view and monitor parameter settings.

Setting 1E: Reference Sample Hold

This function allows the user to sample an analog frequency reference signal being input to terminal A1, A2, or A3 and hold the frequency reference at the sampled level. When the Analog Frequency Reference Sample/Hold function is held for at least 100 ms, the drive reads the analog input and changes the frequency reference to the newly sampled speed as illustrated in [Figure 5.42](#).

When the power is shut off and the sampled analog frequency reference is cleared, the frequency reference is reset to 0.

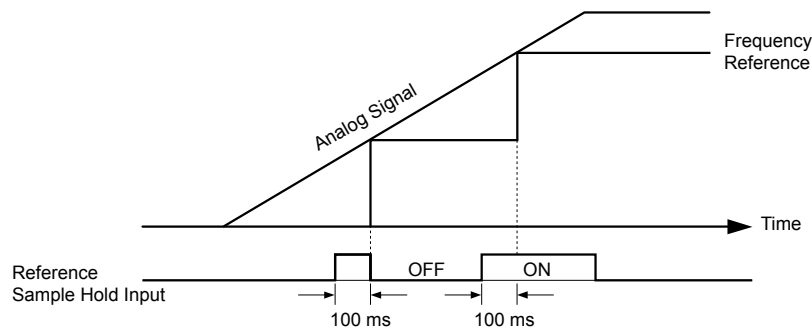


Figure 5.42 Analog Frequency Reference Sample/Hold

An oPE03 error will occur when one of the following functions is used simultaneously with the Analog frequency reference sample/hold command:

- Hold accel/decel stop (setting: A)
- Up command, Down command (setting: 10, 11)
- Offset frequency (setting: 44 to 46)

- Up or Down functions (setting: 75, 76)

Setting 20 to 2F: External Fault

The External fault command stops the drive when problems occur with external devices.

To use the External fault command, set one of the multi-function digital inputs to a value between 20 and 2F. The digital operator will display EF□ where □ is the number of the terminal to which the external fault signal is assigned.

For example, if an external fault signal is input to terminal S3, “EF3” will be displayed.

Select the value to be set in H1-□□ from a combination of any of the following three conditions:

- Signal input level from peripheral devices (N.O., N.C.)
- External fault detection method
- Operation after external fault detection

Table 5.31 shows the relationship between the conditions and the value set to H1-□□:

Terminal statuses, detection conditions, and stopping methods marked with an “O” are applicable to the corresponding settings.

Table 5.31 Stopping Method for External Fault

| Setting | Terminal Status <1> | | Detection Conditions <2> | | Stopping Method | | | |
|---------|---------------------|------|--------------------------|--------------------------|----------------------|-----------------------|-------------------|-------------------------------|
| | N.O. | N.C. | Always Detected | Detected during Run only | Ramp to Stop (fault) | Coast to Stop (fault) | Fast Stop (fault) | Alarm Only (continue running) |
| 20 | O | | O | | O | | | |
| 21 | | O | O | | O | | | |
| 22 | O | | | O | O | | | |
| 23 | | O | | O | O | | | |
| 24 | O | | O | | | O | | |
| 25 | | O | O | | | O | | |
| 26 | O | | | O | | O | | |
| 27 | | O | | O | | O | | |
| 28 | O | | O | | | | O | |
| 29 | | O | O | | | | O | |
| 2A | O | | | O | | | O | |
| 2B | | O | | O | | | O | |
| 2C | O | | O | | | | | O |
| 2D | | O | O | | | | | O |
| 2E | O | | | O | | | | O |
| 2F | | O | | O | | | | O |

<1> Determine the terminal status for each fault, i.e., whether the terminal is normally open or normally closed.

<2> Determine whether detection for each fault should be enabled only during run or always detected.

Setting 30: PID Integral Reset

Configuring one of the digital inputs for PID integral reset (H1-□□ = 30) resets the value of the integral component in PID control to 0 when the terminal is closed. *Refer to PID Block Diagram on page 163* for more details.

Setting 31: PID Integral Hold

Configuring a digital input for Integral Hold (H1-0□ = 31) locks the value of the integral component of the PID control as long as the input is active. The PID controller resumes integral operation from the hold value as soon as the integral hold input is released. *Refer to PID Block Diagram on page 163* for more information on this function.

Setting 32: Multi-Step Speed Reference 4

Selects the multi-step speeds d1-09 to d1-16 in combination with the input terminal set for Multi-Step Speed 1, 2 and 3. *Refer to d1-01 to d1-17: Frequency Reference 1 to 16 and Jog Frequency Reference on page 182.*

Setting 34: PID Soft Starter Cancel

A digital input configured as a PID soft starter cancel input (H1-0□ = 34) enables or disables the PID soft starter and cancels the PID accel/decel time (b5-17). *Refer to PID Block Diagram on page 163.*

Setting 35: PID Input Level Selection

Allows an input terminal to switch the sign of the PID input. *Refer to PID Block Diagram on page 163* for details.

5.7 H: Terminal Functions

Setting 40, 41: Forward Run, Reverse Run Command for 2-Wire Sequence

Configures the drive for a 2-Wire sequence.

When an input terminal set to 40 closes, the drive operates in the forward direction. When an input set for 41 closes, the drive operates in reverse. Closing both inputs simultaneously will result in an external fault.

- Note:**
1. This function cannot be used simultaneously with settings 42 and 43.
 2. The same functions are assigned to terminals S1 and S2 when the drive is initialized for 2-Wire sequence.

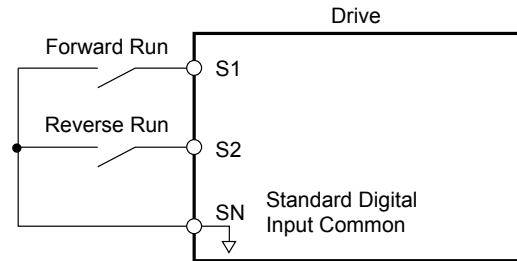


Figure 5.43 Example Wiring Diagram for 2-Wire Sequence

Setting 42, 43: Run and Direction Command for 2-Wire Sequence 2

Sets the drive for 2-Wire sequence 2.

When an input terminal programmed for 42 closes, the drive will operate in the selected direction. The drive will stop when the input opens.

The input programmed for 43 selects the direction. If the input is open, forward direction is selected. If the input is closed, reverse direction is selected.

- Note:** This function cannot be used simultaneously with settings 40 and 41.

Setting 47: Node Setup

If the SI-S3 option card is connected, closing this terminal sets a node address for operation on a CANopen network.

Setting 51: Sequence Timer Disable

Drive ignores sequence timers and runs normally (based on b1-02/b1-16 source).

Setting 52: Sequence Timer Cancel

The sequence timers are canceled.

Setting 60: DC Injection Braking Command

DC Injection Braking is activated when a DC Injection Braking command is input while the drive is stopped. DC Injection Braking is released when a Run command or a Jog command is input. [Refer to b2: DC Injection Braking and Short Circuit Braking on page 152](#) for details on setting up the DC Injection Braking function.

The diagram below illustrates DC Injection Braking:

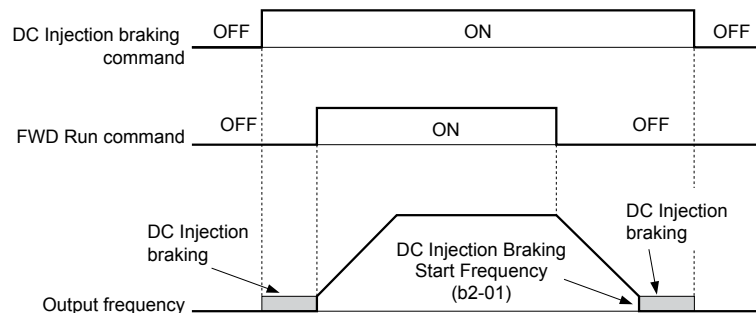


Figure 5.44 DC Injection Braking Input Timing Diagram

Setting 61, 62: External Speed Search Command 1, 2

These input functions enable Speed Search even if parameter b3-01 = 0 (no Speed Search at start). [Refer to Speed Search Activation on page 156](#) for details on how to use the input signals. [Refer to b3: Speed Search on page 153](#) for more about Speed Search.

- Note:** Simultaneously assigning Speed Search 1 and Speed Search 2 to the input terminals will trigger an oPE03 error.

Setting 63: Field Weakening

Enabled in V/f Control. When this input is closed, Field Weakening is performed. For details, see [d6: Field Weakening and Field Forcing](#).

Setting 65, 66: KEB Ride-Thru 1 (N.C.), 2 (N.O.)

Enables the KEB Ride-Thru function selected in parameter L2-29. [Refer to KEB Ride-Thru Function on page 241](#) for more information on this function.

| Digital Input Function | Drive Operation | |
|------------------------|----------------------------|----------------------------|
| | Input Open | Input Closed |
| Setting 65 (N.C.) | KEB Ride-Thru Deceleration | Normal operation |
| Setting 66 (N.O.) | Normal operation | KEB Ride-Thru Deceleration |

Note: Simultaneously assigning KEB Ride-Thru 1 and KEB Ride-Thru 2 to the input terminals will trigger an oPE03 error.

Setting 67: Communication Test Mode

The drive has a built-in function to self-diagnose serial communications operation. The test involves wiring the send and receive terminals of the RS-422/RS-485 port together. The drive transmits data and then confirms that the communications are received normally. [Refer to Self-Diagnostics on page 538](#) for details on how to use this function.

Setting 68: High Slip Braking (HSB)

Closing an input programmed for this function triggers High Slip Braking. After starting HSB, bring the drive to a complete stop and remove the HSB command before restarting. [Refer to n3: High Slip Braking \(HSB\) and Overexcitation Braking on page 264](#).

Setting 6A: Drive Enable

A digital input configured as a “Drive enable” (H1-□□ = 6A) will prevent the drive from executing a Run command until the input is closed. When the input is open, the digital operator will display “dnE” to indicate that the drive is disabled.

If a Run command is enabled before the terminal set for “Drive enable” closes, then the drive will not run until the Run command is cycled (i.e., a new Run command is required). If the input is opened while the drive is running, the drive will stop according to the stop method set to b1-03 ([Refer to b1-03: Stopping Method Selection on page 149](#)).

Setting 75, 76: Up 2/Down 2 Function

The Up/Down 2 function adds a bias to the frequency reference. The input programmed for 75 will increase the bias and the input programmed for 76 will decrease the bias. [Table 5.32](#) explains how the Up/Down 2 function works depending on the frequency reference source and parameters d4-01, d5-03, and d4-05. [Refer to d4: Frequency Reference Hold and Up/Down 2 Function on page 186](#) for detailed explanations of these and other Up/Down 2 related parameters.

- Note:**
1. The Up/Down 2 functions must be set as a pair.
 2. When using the Up/Down 2 function, set appropriate bias limit values to parameters d4-08 and d4-09.

Table 5.32 Up/Down 2 Operations

| Condition | Freq. Ref. Source | d4-03 | d4-05 | d4-01 | Operation | Frequency Saved |
|-----------|----------------------------|-------|-------|-------|---|---|
| 1 | Multi-Step Speed Reference | 0 | 0 | 0 | <ul style="list-style-type: none"> Accelerates (increases the bias) while the Up 2 terminal is closed. Decelerates (decreases the bias) while Down 2 is closed. | Not saved |
| 2 | | | | 1 | | <ul style="list-style-type: none"> Holds output frequency (holds the bias) when no Up 2 or Down 2 input or both active. Resets the bias when the reference changes. Operates with the frequency reference in all other situations. |
| 3 | | | | 1 | -- | <ul style="list-style-type: none"> Accelerates (increases the bias) while the Up 2 terminal is closed. Decelerates (decreases the bias) while Down 2 is closed. Otherwise operates at the frequency reference. |

5.7 H: Terminal Functions

| Condition | Freq. Ref. Source | d4-03 | d4-05 | d4-01 | Operation | Frequency Saved |
|-----------|----------------------------|--------------------|-------|-------|---|--|
| 4 | Multi-Step Speed Reference | Value other than 0 | -- | 0 | <ul style="list-style-type: none"> When the Up 2 is enabled, the drive accelerates to the frequency reference plus d4-03 (bias is increased for d4-03). When Down 2 is enabled, the drive decelerates to the frequency reference minus d4-03 (bias is decreased for d4-03). Holds output frequency (holds the bias) when neither Up/Down 2 inputs are active or both inputs are active. Resets the bias when the reference changes. Operates with the frequency reference in all other situations. | Not saved |
| 5 | | | | 1 | | If the bias and frequency reference are constant for 5 s, the bias is added to the active frequency reference and reset afterwards. |
| 6 | Other (analog comm., etc.) | 0 | 0 | 0 | <ul style="list-style-type: none"> Accelerates (increases the bias) while the Up 2 terminal is closed. Decelerates (decreases the bias) while Down 2 is closed. Holds output frequency (holds the bias) when neither Up/Down 2 inputs are active or both inputs are active. If the frequency reference changes for more than the time set to d4-07 during accel/decel, bias value is held until the output frequency meets the reference (speed agree). | Not saved |
| 7 | | | | 1 | | If the bias is constant for 5 s, it is saved to parameter d4-06. The frequency reference cannot be overwritten, so only the bias is saved. |
| 8 | Other (analog comm., etc.) | 0 | 1 | -- | <ul style="list-style-type: none"> Accelerates (increases the bias) while the Up 2 terminal is closed. Decelerates (decreases the bias) while Down 2 is closed. Otherwise operates at the frequency reference | Not saved |
| 9 | | | | 0 | | Not saved |
| 10 | | | | 1 | | If the bias is constant for 5 s, it is saved to parameter d4-06. The frequency reference cannot be overwritten, so only the bias is saved. |

Setting 7A, 7B: KEB Ride-Thru 2 (N.C., N.O.)

An input terminal set to 7A or 7B can trigger Single Drive KEB Ride-Thru during deceleration. L2-29 is disregarded if this is enabled. [Refer to KEB Ride-Thru Function on page 241](#) for details.

| Digital Input Function | Drive Operation | |
|------------------------|------------------------------|------------------------------|
| | Input Open | Input Closed |
| Setting 7A (N.C.) | Single Drive KEB Ride-Thru 2 | Normal operation |
| Setting 7B (N.O.) | Normal operation | Single Drive KEB Ride-Thru 2 |

Note: Simultaneously assigning KEB Ride-Thru 1 and KEB Ride-Thru 2 to the input terminals will trigger an oPE03 error.

Setting A8: PI2 Disable (N.O.)

Disables the secondary PI controller. Output behavior depends on the setting of S3-12

Setting A9: PI2 Disable (N.C.)

Enables the secondary PI controller (when open, output behavior depends on the setting of S3-12).

Setting AA: PI2 Inverse Operation

Changes the sign of the secondary PI controller input (reverse acting PI control).

Setting AB: PI2 Integral Reset

Resets the secondary PI controller integral value.

Setting AC: PI2 Integral Hold

Locks the value of the secondary PI controller integral value.

Setting AD: Select PI2 Parameters

Uses the secondary PI controller Proportional and Integral adjustments (S3-06 and S3-07) instead of the primary PI controller Proportional and Integral adjustments (b5-02 and b5-03). Only valid when S3-01 = 0 (secondary PI controller disabled).

Note: This multi-function input has no effect on the secondary PI controller. It is only used for the primary PI controller (b5-□□).

Emergency Override Function

The Emergency Override function is activated by closing the digital input programmed for Emergency Override Forward Run (H1-□□ = AF) or Emergency Override Reverse Run (H1-□□ = B0).

If H1-□□ = 6A (Drive Enable) is programmed, it must be opened to disable the drive for Emergency Override to take effect. Closing both Emergency Override digital inputs at the same time will trigger an External Fault (EF) error.

When the drive is in Emergency Override, the frequency reference source is dependent on parameter S6-02, Emergency Override Reference Selection. When S6-02 is set to 0 (Use S6-01 Reference), the drive will run at the S6-01 setting. When S6-02 is set to 1 (Use Frequency Ref), the drive will use the currently selected frequency reference (based on b1-01 and LOCAL/REMOTE) as the run speed.

An alarm will flash during Emergency Override indicating that the function is active and the direction the drive is commanded to run.

Resettable faults occurring when Emergency Override is activated will be cleared.

The drive will perform unlimited speed search retries during Emergency Override.

When Emergency Stop is active and Emergency Override is activated, the drive will run in Emergency Override mode.

The CALL (Serial Communication Error) mechanism is deactivated when Emergency Override is activated.

The Emergency Override function has priority over the PID Sleep feature (b5-15/b5-16).

Setting AF: Emergency Override Forward Run

Enables Emergency Override Forward Run (Enabled when S6-01 = 1).

Setting B0: Emergency Override Reverse Run

Enables Emergency Override Reverse Run (Enabled when S6-01 = 1).

◆ **H2: Multi-Function Digital Outputs**

■ **H2-01 to H2-03: Terminal M1-M2, M3-M4, and MD-ME-MF Function Selection**

The drive has three multi-function output terminals. [Table 5.33](#) lists the functions available for these terminals using H2-01, H2-02, and H2-03.

| No. | Parameter Name | Setting Range | Default |
|-------|--|---------------|------------------|
| H2-01 | Terminal M1-M2 Function Selection (relay) | 0 to 192 | 0: During Run |
| H2-02 | Terminal M3-M4 Function Selection (relay) | 0 to 192 | 1: Zero Speed |
| H2-03 | Terminal MD-ME-MF Function Selection (relay) | 0 to 192 | 2: Speed agree 1 |

Table 5.33 Multi-Function Digital Output Terminal Settings

| Setting | Function | Setting | Function |
|---------|--|---------|--|
| 0 | During Run 216 | E | Fault 219 |
| 1 | Zero Speed 216 | F | Through Mode 219 |
| 2 | Speed Agree 1 216 | 10 | Minor Fault 219 |
| 3 | User-Set Speed Agree 1 217 | 11 | Fault Reset Command Active 219 |
| 4 | Frequency Detection 1 217 | 12 | Timer Output 220 |
| 5 | Frequency Detection 2 218 | 13 | Speed Agree 2 220 |
| 6 | Drive Ready 218 | 14 | User-Set Speed Agree 2 220 |
| 7 | DC Bus Undervoltage 218 | 15 | Frequency Detection 3 221 |
| 8 | During Baseblock (N.O.) 219 | 16 | Frequency Detection 4 221 |
| 9 | Frequency Reference Source 219 | 17 | Torque Detection 1 (N.C.) 219 |
| A | Run Command Source 219 | 18 | Torque Detection 2 (N.O.) 219 |
| B | Torque Detection 1 (N.O.) 219 | 19 | Torque Detection 2 (N.C.) 219 |
| C | Frequency Reference Loss 219 | 1A | During Reverse 221 |
| D | Braking Resistor Fault 219 | 1B | During Baseblock (N.C.) 222 |

5.7 H: Terminal Functions

| Setting | Function | | Setting | Function | |
|---------|--------------------------------|-----|------------|---------------------------------------|-----|
| 1E | Restart Enabled | 222 | 4D | oH Pre-Alarm Time Limit | 223 |
| 1F | Motor Overload Alarm (oL1) | 222 | 4E <2> | Braking Transistor Fault (rr) | 223 |
| 20 | Drive Overheat Pre-Alarm (oH) | 222 | 4F <2> | Braking Resistor Overheat (rH) | 223 |
| 22 | Mechanical Weakening Detection | 222 | 50 | Waiting to Run | 223 |
| 2F | Maintenance Period | 222 | 51 | Sequence timer 1 | 224 |
| 37 | During Frequency Output | 222 | 52 | Sequence timer 2 | 224 |
| 38 | Drive Enabled | 223 | 53 | Sequence timer 3 | 224 |
| 39 | Watt Hour Pulse Output | 223 | 54 | Sequence timer 4 | 224 |
| 3C | LOCAL/REMOTE Status | 223 | 58 | UL6 Detected | 224 |
| 3D | During Speed Search | 223 | 60 | Internal Cooling Fan Alarm | 223 |
| 3E | PID Feedback Low | 223 | 71 | Secondary PI Feedback Low | 224 |
| 3F | PID Feedback High | 223 | 72 | Secondary PI Feedback High | 224 |
| 4A | During KEB Operation | 223 | 100 to 192 | Functions 0 to 92 with Inverse Output | 224 |
| 4C | During Fast Stop | 223 | | | |

<2> Not available in models 2A0169 to 2A0415 and 4A0088 to 4A1200.

Setting 0: During Run

Output closes when the drive is outputting a voltage.

| Status | Description |
|--------|---|
| Open | Drive is stopped. |
| Closed | A Run command is input or the drive is in deceleration or DC injection. |

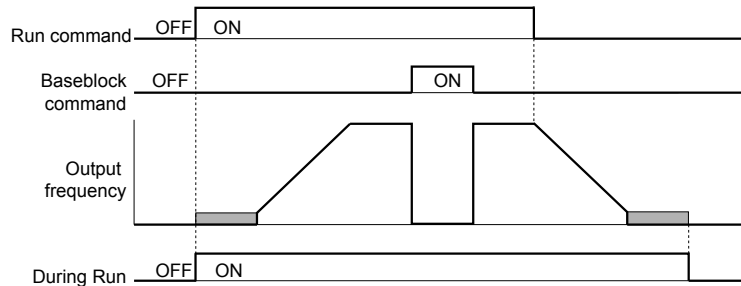


Figure 5.45 During Run Time Chart

Setting 1: Zero Speed

Terminal closes when the output frequency falls below the minimum output frequency set to E1-09 or b2-01.

| Status | Description |
|--------|--|
| Open | Output frequency is above the minimum output frequency set to E1-09 or b2-01 |
| Closed | Output frequency is less than the minimum output frequency set to E1-09 or b2-01 |

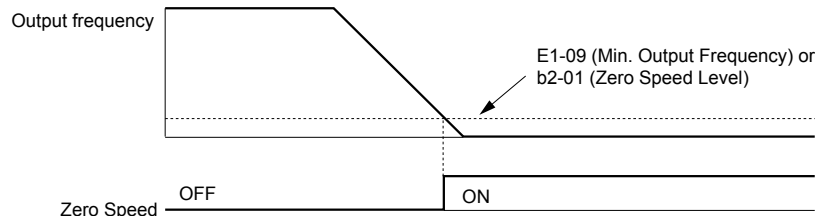


Figure 5.46 Zero-Speed Time Chart

Setting 2: Speed Agree 1 (f_{ref}/f_{out} Agree 1)

Closes when the actual output frequency is within the Speed Agree Width (L4-02) of the current frequency reference regardless of the direction.

| Status | Description |
|--------|--|
| Open | Output frequency or motor speed does not match the frequency reference while the drive is running. |
| Closed | Output frequency or motor speed is within the range of frequency reference $\pm L4-02$. |

Note: Detection works in forward and reverse.

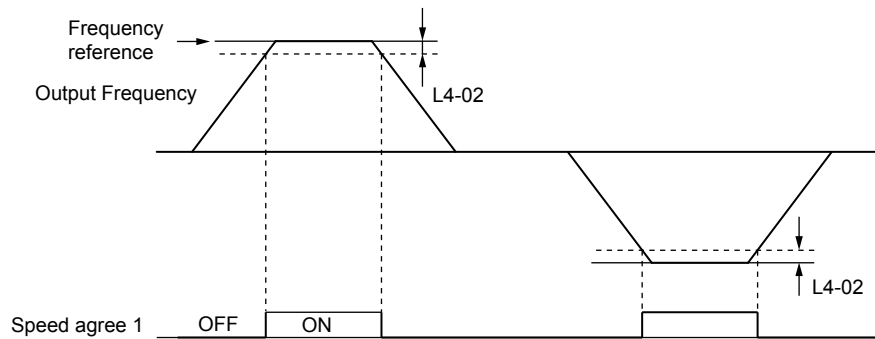


Figure 5.47 Speed Agree 1 Time Chart

Refer to L4-01, L4-02: Speed Agreement Detection Level and Detection Width on page 253 for more details.

Setting 3: User-Set Speed Agree 1 (f_{ref}/f_{set} Agree 1)

Closes when the actual output frequency and the frequency reference are within the speed agree width (L4-02) of the programmed speed agree level (L4-01).

| Status | Description |
|--------|--|
| Open | Output frequency or motor speed and frequency reference are not both within the range of L4-01 $\pm L4-02$. |
| Closed | Output frequency or motor speed and the frequency reference are both within the range of L4-01 $\pm L4-02$. |

Note: Frequency detection works in forward and reverse. The value of L4-01 is used as the detection level for both directions.

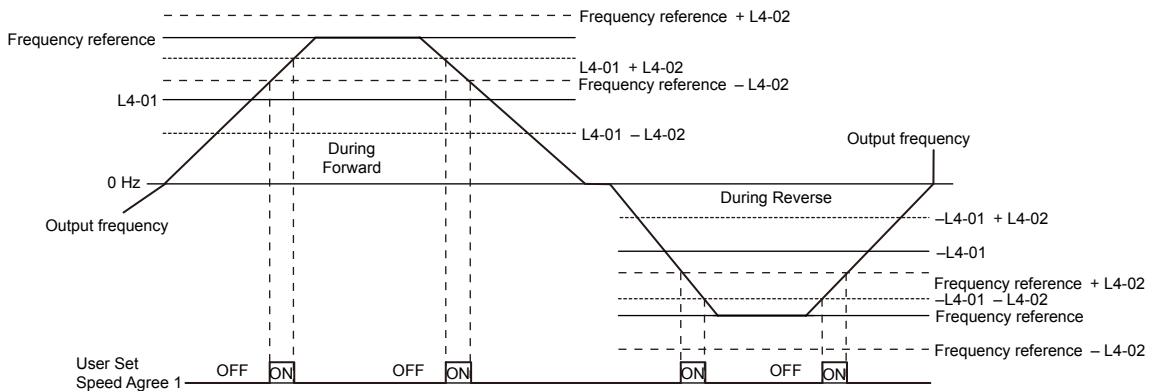


Figure 5.48 User Set Speed Agree 1 Time Chart

Refer to L4-01, L4-02: Speed Agreement Detection Level and Detection Width on page 253 for more instructions.

Setting 4: Frequency Detection 1

The output opens when the output frequency rises above the detection level set in L4-01 plus the detection width set in L4-02. The terminal remains open until the output frequency or motor speed fall below the level set in L4-01.

| Status | Description |
|--------|---|
| Open | Output frequency or motor speed exceeded L4-01 + L4-02. |
| Closed | Output frequency or motor speed is below L4-01 or has not exceeded L4-01 + L4-02. |

Note: Frequency detection works in forward and reverse. The value of L4-01 is used as the detection level for both directions.

5.7 H: Terminal Functions

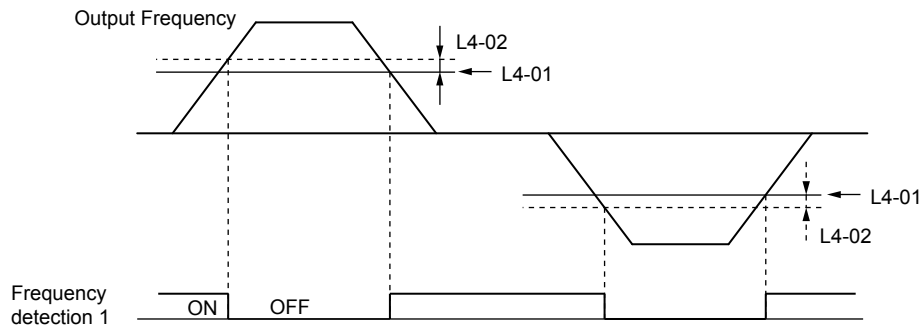


Figure 5.49 Frequency Detection 1 Time Chart

Refer to L4-01, L4-02: Speed Agreement Detection Level and Detection Width on page 253 for more details.

Setting 5: Frequency Detection 2

The output closes when the output frequency is above the detection level set in L4-01. The terminal remains closed until the output frequency or motor speed fall below L4-01 minus the setting of L4-02.

| Status | Description |
|--------|---|
| Open | Output frequency or motor speed is below L4-01 minus L4-02 or has not exceeded L4-01. |
| Closed | Output frequency or motor speed exceeded L4-01. |

Note: Frequency detection works in forward and reverse. The value of L4-01 is used as the detection level for both directions.

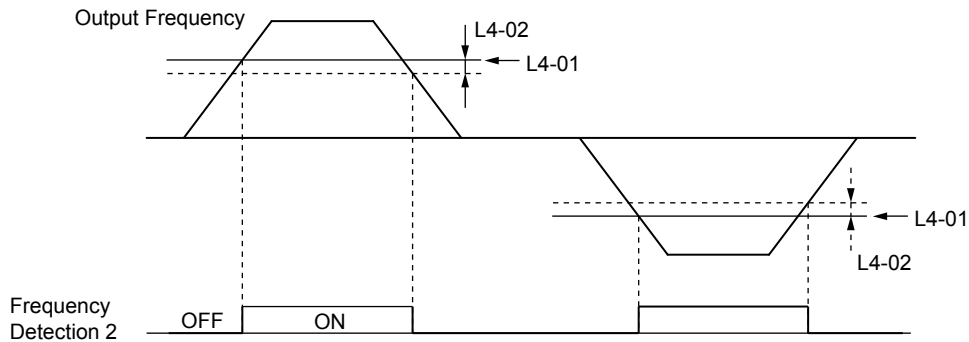


Figure 5.50 Frequency Detection 2 Time Chart

Refer to L4-01, L4-02: Speed Agreement Detection Level and Detection Width on page 253 for more details.

Setting 6: Drive Ready

The output closes when the drive is ready to operate the motor. The terminal will not close under the conditions listed below, and any Run commands will be disregarded.

- When the power is shut off
- During a fault
- When the internal power supply of the drive has malfunctioned
- When a parameter setting error makes it impossible to run
- Although stopped, an overvoltage or undervoltage situation occurs
- While editing a parameter in the Programming Mode (when b1-08 = 0)

Setting 7: DC Bus Undervoltage

The output closes when the DC bus voltage or control circuit power supply drops below the trip level set in L2-05. A fault in the DC bus circuit will also cause the terminal set for “DC bus undervoltage” to close.

| Status | Description |
|--------|--|
| Open | DC bus voltage is above the level set to L2-05. |
| Closed | DC bus voltage has fallen below the trip level set to L2-05. |

Setting 8: During Baseblock (N.O.)

The output closes to indicate that the drive is in a baseblock state. While in baseblock, output transistors do not switch and no main circuit voltage is output.

| Status | Description |
|--------|------------------------------------|
| Open | Drive is not in a baseblock state. |
| Closed | Baseblock is being executed. |

Setting 9: Frequency Reference Source

Displays the currently selected frequency reference source.

| Status | Description |
|--------|--|
| Open | Frequency reference is provided from External reference 1 (b1-01) or External reference 2 (b1-15). |
| Closed | Frequency reference is being sourced from the digital operator. |

Setting A: Run Command Source

Displays the currently selected Run command source.

| Status | Description |
|--------|---|
| Open | Run command is provided from External reference 1 (b1-02) or 2 (b1-16). |
| Closed | Run command is being sourced from the digital operator. |

Setting B, 17, 18, 19: Torque Detection 1 (N.O., N.C.), Torque Detection 2 (N.O., N.C.)

These digital output functions signal an overtorque or undertorque situation to an external device.

Set up the torque detection levels and select the output function from the table below. [Refer to L6: Torque Detection on page 255](#) for details.

| Setting | Status | Description |
|---------|--------|---|
| B | Closed | Torque detection 1 (N.O.): Output current/torque exceeds (overtorque detection) or is below (undertorque detection) the torque value set in parameter L6-02 for longer than the time specified in parameter L6-03. |
| 17 | Open | Torque detection 1 (N.C.): Output current/torque exceeds (overtorque detection) or is below (undertorque detection) the torque value set in parameter L6-02 for longer than the time specified in parameter L6-03. |
| 18 | Closed | Torque detection 2 (N.O.): Output current/torque exceeds (overtorque detection) or is below (undertorque detection) the torque value set in parameter L6-05 for longer than the time specified in parameter L6-06. |
| 19 | Open | Torque detection 2 (N.C.): Output current/torque exceeds (overtorque detection) or is below (undertorque detection) the torque value set in parameter L6-05 for longer than the time specified in parameter L6-06. |

Setting C: Frequency Reference Loss

An output set for this function closes when frequency reference loss is detected. [Refer to L4-05: Frequency Reference Loss Detection Selection on page 253](#) for details.

Setting D: Braking Resistor Fault

An output programmed for this function closes when the dynamic braking resistor (DB) overheats or the braking transistor is in a fault condition.

Setting E: Fault

The output closes when the drive faults (excluding CPF00 and CPF01 faults).

Setting F: Through Mode

Select this setting when using the terminal in a pass-through mode. When set to F, an output does not trigger any function in the drive. Setting F, however, still allows the output status to be read by a PLC via a communication option or MEMOBUS/Modbus communications.

Setting 10: Minor Fault

The output closes when a minor fault condition is present.

Setting 11: Fault Reset Command Active

The output closes when there is an attempt to reset a fault situation from the control circuit terminals, via serial communications, or using a communications option card.

5.7 H: Terminal Functions

Setting 12: Timer Output

This setting configures a digital output terminal as the output for the timer function. *Refer to b4: Timer Function on page 160* for details.

Setting 13: Speed Agree 2 (f_{ref} / f_{out} Agree 2)

The output closes when the actual output frequency is within the speed agree width (L4-04) of the current frequency reference, regardless of the direction.

| Status | Description |
|--------|--|
| Open | Output frequency or motor speed does not match the frequency reference while the drive is running. |
| Closed | Output frequency or motor speed is within the range of frequency reference \pm L4-04. |

Note: Detection works in forward and reverse.

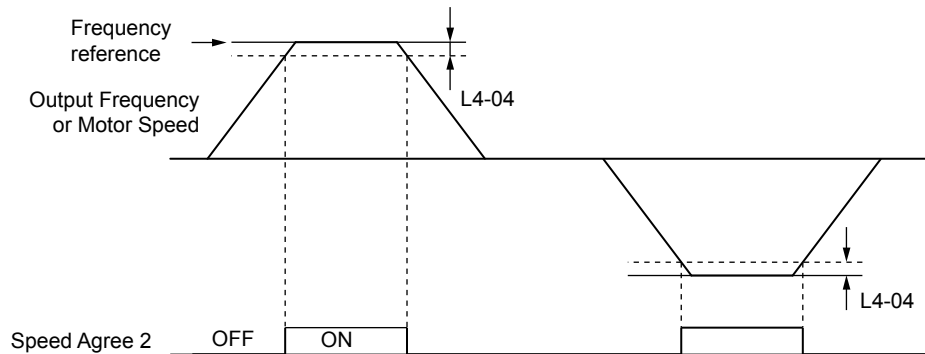


Figure 5.51 Speed Agree 2 Time Chart

Refer to L4-03, L4-04: Speed Agreement Detection Level and Detection Width (+/-) on page 253 for more details.

Setting 14: User-Set Speed Agree 2 (f_{ref} / f_{set} Agree 2)

The output closes when the actual output frequency and the frequency reference are within the speed agree width (L4-04) of the programmed speed agree level (L4-03).

| Status | Description |
|--------|---|
| Open | Output frequency or motor speed and frequency reference are both outside the range of L4-03 \pm L4-04. |
| Closed | Output frequency or motor speed and the frequency reference are both within the range of L4-03 \pm L4-04. |

Note: The detection level L4-03 is a signed value; detection works in the specified direction only.

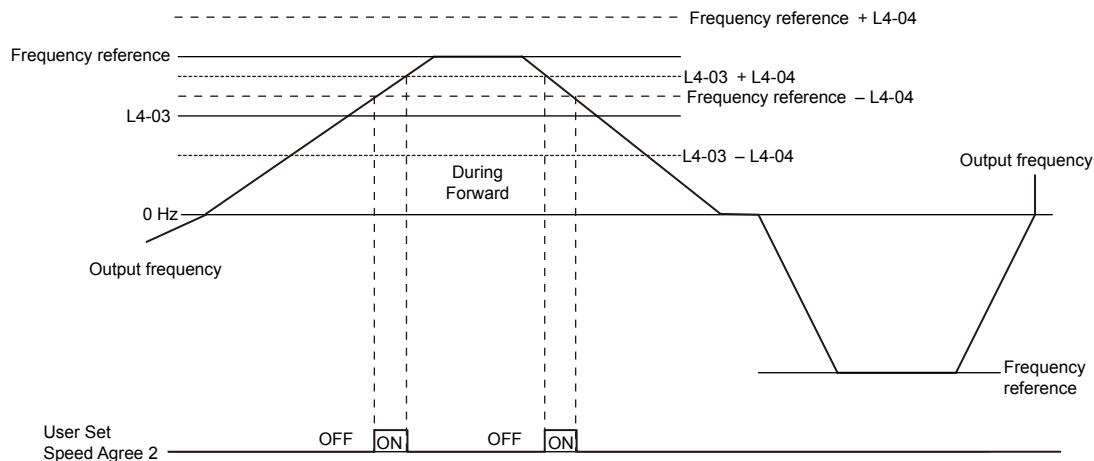


Figure 5.52 User-Set Speed Agree 2 Example with a Positive L3-04 Value

Refer to L4-03, L4-04: Speed Agreement Detection Level and Detection Width (+/-) on page 253 for more details.

Setting 15: Frequency Detection 3

The output opens when the output frequency rises above the detection level set in L4-03 plus the detection with set in L4-04. The terminal remains open until the output frequency or motor speed falls below the level set in L4-03. The detection level L4-03 is a signed value; detection works in the specified direction only.

| Status | Description |
|--------|--|
| Open | Output frequency or motor speed exceeded L4-03 plus L4-04. |
| Closed | Output frequency or motor speed is below L4-03 or has not exceeded L4-03 plus L4-04. |

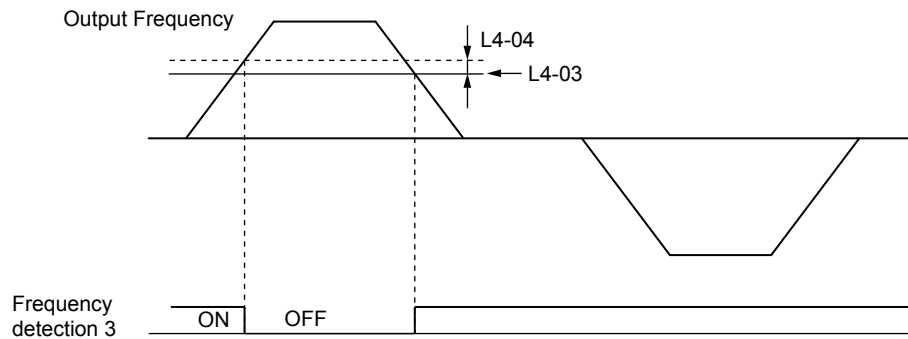


Figure 5.53 Frequency Detection 3 Example with a Positive L3-04 Value

Refer to L4-03, L4-04: Speed Agreement Detection Level and Detection Width (+/-) on page 253 for more details.

Setting 16: Frequency Detection 4

The output closes when the output frequency is above the detection level set in L4-03. The terminal remains closed until the output frequency or motor speed falls below L4-03 minus the setting of L4-04.

| Status | Description |
|--------|---|
| Open | Output frequency or motor speed is below L4-03 minus L4-04 or has not exceeded L4-03. |
| Closed | Output frequency or motor speed exceeded L4-03. |

Note: The detection level L4-03 is a signed value; detection works in the specified direction only.

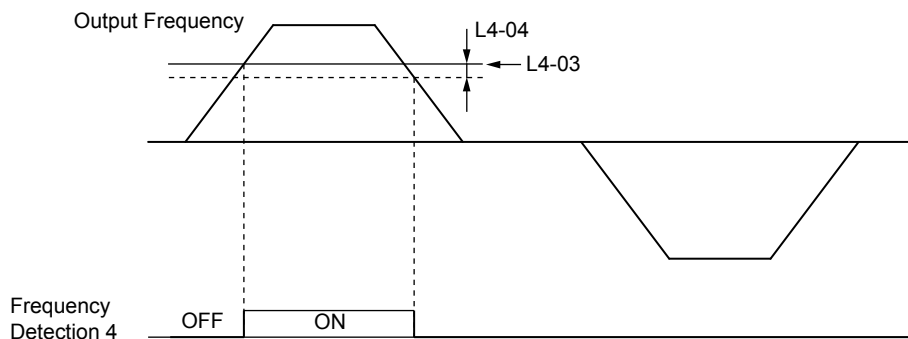


Figure 5.54 Frequency Detection 4 Example with Positive L3-04 Value

Refer to L4-03, L4-04: Speed Agreement Detection Level and Detection Width (+/-) on page 253 for more details.

Setting 1A: During Reverse

A digital output set for “During reverse” closes when the drive is running the motor in the reverse direction.

| Status | Description |
|--------|--|
| Open | Motor is being driven in the forward direction or stopped. |
| Closed | Motor is being driven in reverse. |

5.7 H: Terminal Functions

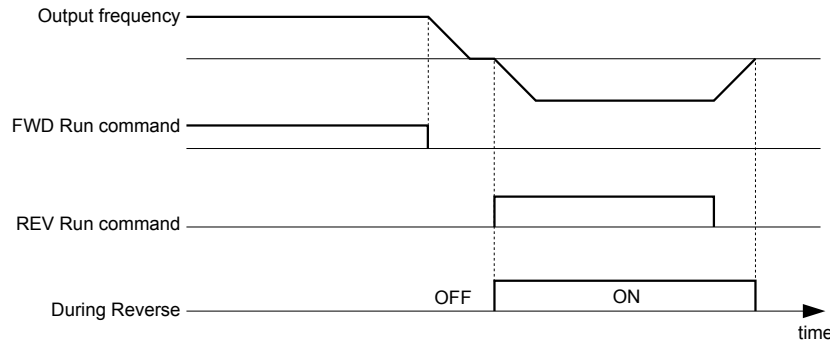


Figure 5.55 Reverse Direction Output Example Time Chart

Setting 1B: During Baseblock (N.C.)

The output opens to indicate that the drive is in a baseblock state. While Baseblock is executed, output transistors do not switch and no main circuit voltage is output.

| Status | Description |
|--------|------------------------------------|
| Open | Baseblock is being executed. |
| Closed | Drive is not in a baseblock state. |

Setting 1E: Restart Enabled

An output set for “Restart enabled” closes when the drive attempts to restart after a fault has occurred.

The fault restart function allows the drive to automatically clear a fault. The terminal set to 1E will close after the fault is cleared and the drive has attempted to restart. If the drive cannot successfully restart within the number of attempts permitted by L5-01, a fault will be triggered and the terminal set to 1E will open. [Refer to L5: Fault Restart on page 254](#) for details on automatic restart.

Setting 1F: Motor Overload Alarm (oL1)

The output closes when the motor overload level estimated by the oL1 fault detection exceeds 90% of the oL1 detection level. [Refer to L1-01: Motor Overload Protection Selection on page 234](#).

Setting 20: Drive Overheat Pre-Alarm (oH)

Closed: The heatsink temperature exceeds the L8-02 level (while L8-03 = 3 or 4), or an external device has triggered an oH2 alarm via multi-function input H1-□□ = B.

Setting 22: Mechanical Weakening Detection

The output closes when a mechanical weakening situation is detected.

Setting 2F: Maintenance Period

The output closes when the cooling fan, DC bus capacitors, or DC bus pre-charge relay may require maintenance as determined by the estimated performance life span of those components. Components performance life is displayed as a percentage on the digital operator screen. [Refer to Periodic Maintenance on page 343](#).

Setting 37: During Frequency Output

The output closes when the drive is outputting a frequency.

| Status | Description |
|--------|--|
| Open | Drive is stopped or one of the following functions is being performed: baseblock, DC Injection Braking, Short Circuit Braking. |
| Closed | Drive is outputting frequency. |

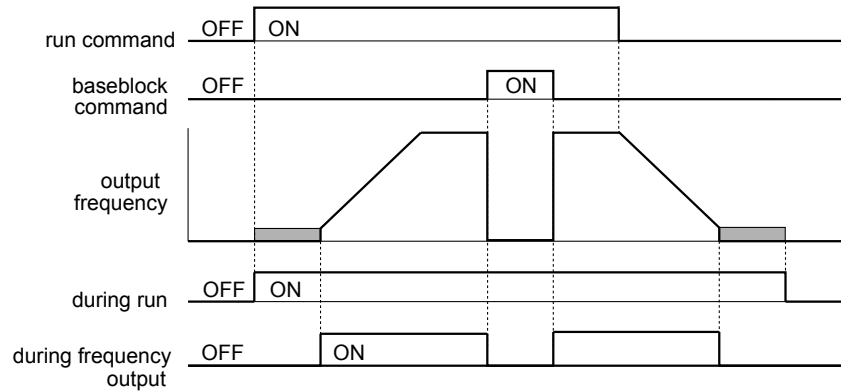


Figure 5.56 During Frequency Output Time Chart

Setting 38: Drive Enable

Reflects the status of a digital input configured as a “Drive enable” input (H1-□□ = 6A). If that digital input closes, then the digital output set for “Drive enable” will also close.

Setting 39: Watt Hour Pulse Output

Outputs a pulse to indicate the watt hours. [Refer to H2-06: Watt Hour Output Unit Selection on page 224](#) for details.

Setting 3C: LOCAL/REMOTE Status

The output terminal closes while the drive is set for LOCAL and opens when in REMOTE.

| Status | Description |
|--------|--|
| Open | REMOTE: The external reference that has been selected (either b1-01 and b1-02 or b1-15 and b1-16) is used as frequency reference and Run command source. |
| Closed | LOCAL: The digital operator is used as frequency reference and Run command source. |

Setting 3D: During Speed Search

The output terminal closes while Speed Search is being performed. [Refer to b3: Speed Search on page 153](#) for details.

Setting 3E: PID Feedback Low

Output terminal closes when a PID feedback loss (FbL) is detected. The feedback is considered to be lost if it falls below the level set to b5-13 for longer than the time set to b5-14. [Refer to PID Feedback Loss Detection on page 165](#) for details.

Setting 3F: PID Feedback High

Output terminal closes when a PID feedback loss (FbH) is detected. The feedback is considered to be lost if it rises beyond the level set to b5-36 for longer than the time set to b5-37. [Refer to PID Feedback Loss Detection on page 165](#) for details.

Setting 4A: During KEB Operation

The output terminal closes while KEB is being performed. [Refer to KEB Ride-Thru Function on page 241](#) for a KEB function description.

Setting 4C: During Fast Stop

The output terminal closes when a Fast Stop is being executed. [Refer to Setting 15, 17: Fast Stop \(N.O., N.C.\) on page 209](#).

Setting 4D: oH Pre-Alarm Time Limit

Closed: An oH pre-alarm is present after 10 output frequency reduction cycles have passed (L8-03 = 4).

Setting 4E: Braking Transistor Fault (rr)

The output closes if the internal braking transistor reaches the overheat level.

Setting 4F: Braking Resistor Overheat (rH)

The output closes when the braking resistor exceeds the overheat level. The braking resistor may overheat due to motor regeneration or short deceleration time setting.

Setting 50: Waiting to Run (WrUn)

The drive will delay executing a Run command until the time set to b1-11 has expired.

5.7 H: Terminal Functions

Setting 51: Sequence Timer 1 Active

Sequence Timer 1 is active.

Setting 52: Sequence Timer 2 Active

Sequence Timer 2 is active.

Setting 53: Sequence Timer 3 Active

Sequence Timer 3 is active.

Setting 54: Sequence Timer 4 Active

Sequence Timer 4 is active.

Setting 58: Underload Detection

Underload is detected when the output current falls below the underload detection level defined by L6-14 and L6-02.

Setting 60: Internal Cooling Fan Alarm

The output closes when the drive internal cooling fan has failed.

Setting 71: Secondary PI Feedback Low

The PI2 feedback level is too low.

Setting 72: Secondary PI Feedback High

The PI2 feedback level is too high.

Setting 89: Secondary PI Feedback High

Drive output speed is being limited due to the output current limit or due the single-phase foldback regulator.

Note: Available in drive software versions PRG: 8503 and later.

Setting 100 to 189: Functions 0 to 89 with Inverse Output

These settings have the same function as settings 0 to 89 but with inverse output. Set as 1□□, where the “1” indicates inverse output and the last two digits specify the setting number of the function.

Examples:

- For inverse output of “8: During baseblock”, set 108.
- For inverse output of “4A: During KEB” set 14A.

■ H2-06: Watt Hour Output Unit Selection

When one of the multi-function terminals is set to output the number of watt hours (H2-01, H2-02, or H2-03 = 39), parameter H2-06 determines the units for the output signal.

This output function provides a watt hour meter or a PLC input by a 200 ms pulse signal. H2-06 determines the frequency that pulses are issued to keep track of the kWh for the drive.

| No. | Parameter Name | Setting Range | Default |
|-------|---------------------------------|--|---------|
| H2-06 | Watt Hour Output Unit Selection | 0: 0.1 kWh units 1: 1 kWh units 2: 10 kWh units 3: 100 kWh units 4: 1000 kWh units | 0 |

- Note:**
1. A negative power output (i.e., regeneration) does not subtract from the total watt hours.
 2. The drive keeps track of the watt hours as long as the control circuit has power. The value is reset when the power supply is shut off.

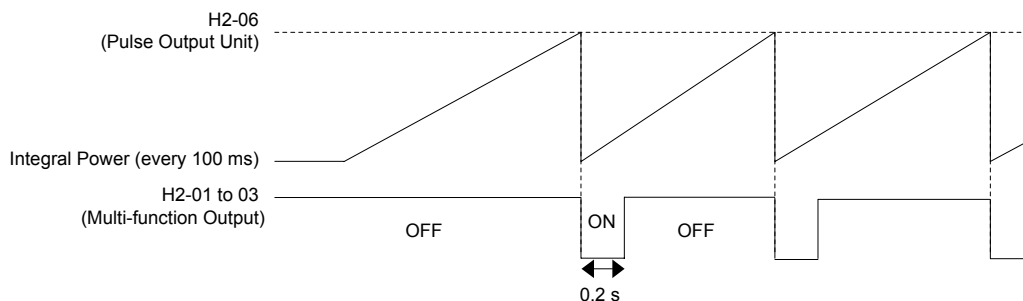


Figure 5.57 Watt Hour Output Example

◆ H3: Multi-Function Analog Inputs

The drive is equipped with three multi-function analog input terminals: A1, A2, and A3. *Refer to Multi-Function Analog Input Terminal Settings on page 228* for a listing of the functions that can be set to these terminals.

■ H3-01: Terminal A1 Signal Level Selection

Selects the input signal level for analog input A1.

| No. | Name | Setting Range | Default |
|-------|------------------------------------|---------------|---------|
| H3-01 | Terminal A1 Signal Level Selection | 0 to 3 | 0 |

Setting 0: 0 to 10 Vdc

The input level is 0 to 10 Vdc. The minimum input level is limited to 0%, so that a negative input signal due to gain and bias settings will be read as 0%.

Setting 1: 0 to 10 Vdc Bipolar

The input level is -10 to 10 Vdc. If the resulting voltage is negative after being adjusted by gain and bias settings, then the motor will rotate in reverse.

Setting 2: 4 to 20 mA

Setting 3: 0 to 20 mA

■ H3-02: Terminal A1 Function Selection

Selects the input signal level for analog input A1. *Refer to Multi-Function Analog Input Terminal Settings on page 228* for instructions on adjusting the signal level.

| No. | Name | Setting Range | Default |
|-------|--------------------------------|---------------|---------|
| H3-02 | Terminal A1 Function Selection | 0 to 26 | 0 |

■ H3-03, H3-04: Terminal A1 Gain and Bias Settings

Parameter H3-03 sets the level of the selected input value that is equal to 10 Vdc input at terminal A1 (gain).

Parameter H3-04 sets the level of the selected input value that is equal to 0 V input at terminal A1 (bias).

Use both parameters to adjust the characteristics of the analog input signal to terminal A1.

| No. | Name | Setting Range | Default |
|-------|--------------------------|------------------|---------|
| H3-03 | Terminal A1 Gain Setting | -999.9 to 999.9% | 100.0% |
| H3-04 | Terminal A1 Bias Setting | -999.9 to 999.9% | 0.0% |

Setting Examples

- Gain H3-03 = 200%, bias H3-04 = 0, terminal A1 as frequency reference input (H3-02 = 0):

A 10 Vdc input is equivalent to a 200% frequency reference and 5 Vdc is equivalent to a 100% frequency reference. Since the drive output is limited by the maximum frequency parameter (E1-04), the frequency reference will be equal to E1-04 above 5 Vdc.

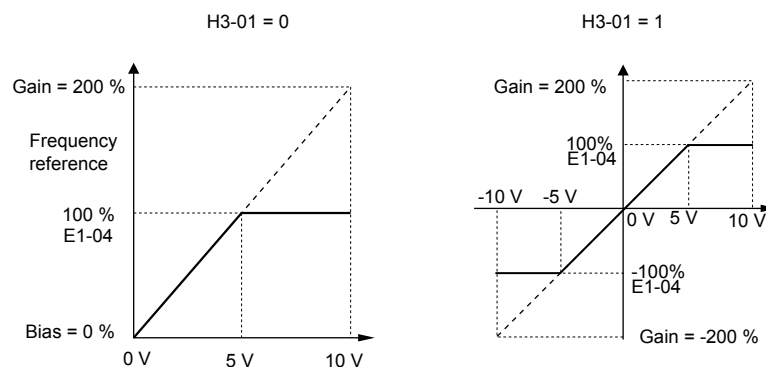


Figure 5.58 Frequency Reference Setting by Analog Input with Increased Gain

- Gain H3-03 = 100%, bias H3-04 = -25%, terminal A1 as frequency reference input:

An input of 0 Vdc will be equivalent to a -25% frequency reference.

5.7 H: Terminal Functions

When parameter H3-01 = 0, the frequency reference is 0% between 0 and 2 Vdc input.

When parameter H3-01 = 1, the motor will rotate in reverse between -10 and 2 Vdc input.

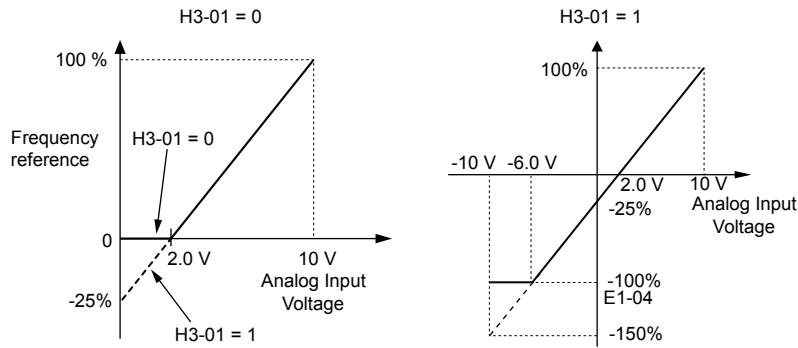


Figure 5.59 Frequency Reference Setting by Analog Input with Negative Bias

■ H3-05: Terminal A3 Signal Level Selection

Determines the function assigned to analog input terminal A3. [Refer to Multi-Function Analog Input Terminal Settings on page 228](#) for a list of functions and descriptions.

| No. | Name | Setting Range | Default |
|-------|------------------------------------|---------------|---------|
| H3-05 | Terminal A3 Signal Level Selection | 0 to 3 | 0 |

Setting 0: 0 to 10 Vdc

The input level is 0 to 10 Vdc. See the explanation provided for H3-01. [Refer to Setting 0: 0 to 10 Vdc on page 225.](#)

Setting 1: 0 to 10 Vdc Bipolar

The input level is -10 to 10 Vdc. See the explanation provided for H3-01. [Refer to Setting 1: 0 to 10 Vdc Bipolar on page 225.](#)

Setting 2: 4 to 20 mA

Setting 3: 0 to 20 mA

■ H3-06: Terminal A3 Function Selection

Determines the function assigned to analog input terminal A3. [Refer to Multi-Function Analog Input Terminal Settings on page 228](#) for a list of functions and descriptions.

| No. | Name | Setting Range | Default |
|-------|--------------------------------|---------------|---------|
| H3-06 | Terminal A3 Function Selection | 0 to 26 | 2 |

■ H3-07, H3-08: Terminal A3 Gain and Bias Setting

Parameter H3-07 sets the level of the selected input value that is equal to 10 Vdc input at terminal A3 (gain).

Parameter H3-08 sets the level of the selected input value that is equal to 0 V input at terminal A3 (bias).

| No. | Name | Setting Range | Default |
|-------|--------------------------|------------------|---------|
| H3-07 | Terminal A3 Gain Setting | -999.9 to 999.9% | 100.0% |
| H3-08 | Terminal A3 Bias Setting | -999.9 to 999.9% | 0.0% |

■ H3-09: Terminal A2 Signal Level Selection

Selects the input signal level for analog input A2. Set jumper S1 on the terminal board accordingly for a voltage input or current input.

| No. | Name | Setting Range | Default |
|-------|------------------------------------|---------------|---------|
| H3-09 | Terminal A2 Signal Level Selection | 0 to 3 | 2 |

Setting 0: 0 to 10 Vdc

The input level is 0 to 10 Vdc. [Refer to Setting 0: 0 to 10 Vdc on page 225.](#)

Setting 1: -10 to 10 Vdc

The input level is -10 to 10 Vdc. *Refer to Setting 1: 0 to 10 Vdc Bipolar on page 225.*

Setting 2: 4 to 20 mA

The input level is 4 to 20 mA. Negative input values by negative bias or gain settings will be limited to 0%.

Setting 3: 0 to 20 mA

The input level is 0 to 20 mA. Negative input values by negative bias or gain settings will be limited to 0%.

■ H3-10: Terminal A2 Function Selection

Determines the function assigned to analog input terminal A2. *Refer to Multi-Function Analog Input Terminal Settings on page 228* for a list of functions and descriptions.

| No. | Name | Setting Range | Default |
|-------|--------------------------------|---------------|---------|
| H3-10 | Terminal A2 Function Selection | 0 to 26 | 0 |

■ H3-11, H3-12: Terminal A2 Gain and Bias Setting

Parameter H3-11 sets the level of the input value selected that is equal to 10 Vdc input or 20 mA input to terminal A2.

Parameter H3-12 sets the level of the input value selected that is equal to 0 V, 4 mA or 0 mA input at terminal A2.

Use both parameters to adjust the characteristics of the analog input signal to terminal A2. The setting works in the same way as parameters H3-03 and H3-04 for analog input A1.

| No. | Name | Setting Range | Default |
|-------|--------------------------|------------------|---------|
| H3-11 | Terminal A2 Gain Setting | -999.9 to 999.9% | 100.0% |
| H3-12 | Terminal A2 Bias Setting | -999.9 to 999.9% | 0.0% |

■ H3-13: Analog Input Filter Time Constant

Parameter H3-13 sets the time constant for a first order filter that will be applied to the analog inputs.

An analog input filter prevents erratic drive control when using a “noisy” analog reference. Drive operation becomes more stable as the programmed time becomes longer, but it also becomes less responsive to rapidly changing analog signals.

| No. | Name | Setting Range | Default |
|-------|-----------------------------------|----------------|---------|
| H3-13 | Analog Input Filter Time Constant | 0.00 to 2.00 s | 0.03 s |

■ H3-14: Analog Input Terminal Enable Selection

When one of the multi-function digital input parameters is set for “Analog input enable” (H1-□□ = C), the value set to H3-14 determines which analog input terminals are enabled when the input is closed. All of the analog input terminals will be enabled all of the time when H1-□□ ≠ C. The terminals not set as the target are not influenced by input signals.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| H3-14 | Analog Input Terminal Enable Selection | 1 to 7 | 7 |

Setting 1: A1 Only Enabled

Setting 2: A2 Only Enabled

Setting 3: A1 and A2 Only Enabled

Setting 4: A3 Only Enabled

Setting 5: A1 and A3 Only Enabled

Setting 6: A2 and A3 Only Enabled

Setting 7: All Analog Input Terminals Enabled

■ H3-16 to H3-18: Terminal A1/A2/A3 Offset

Set the offset level of the selected input value to terminals A1, A2, or A3 that is equal to 0 Vdc input. These parameters rarely require adjustment.

5.7 H: Terminal Functions

| No. | Name | Setting Range | Default |
|-------|--------------------|---------------|---------|
| H3-16 | Terminal A1 Offset | -500 to 500 | 0 |
| H3-17 | Terminal A2 Offset | -500 to 500 | 0 |
| H3-18 | Terminal A3 Offset | -500 to 500 | 0 |

Multi-Function Analog Input Terminal Settings

See [Table 5.34](#) for information on how H3-02, H3-10, and H3-06 determine functions for terminals A1, A2, and A3.

Note: The scaling of all input functions depends on the gain and bias settings for the analog inputs. Set these to appropriate values when selecting and adjusting analog input functions.

Table 5.34 Multi-Function Analog Input Terminal Settings

| Setting | Function | Page | Setting | Function | Page |
|---------|------------------------------------|---------------------|---------|-------------------------------|---------------------|
| 0 | Frequency Bias | 228 | B | PID Feedback | 229 |
| 1 | Frequency Gain | 228 | C | PID Setpoint | 229 |
| 2 | Auxiliary Frequency Reference 1 | 228 | D | Frequency Bias | 229 |
| 3 | Auxiliary Frequency Reference 2 | 228 | E | Motor Temperature (PTC Input) | 230 |
| 4 | Output Voltage Bias | 228 | 16 | Differential PID Feedback | 230 |
| 5 | Accel/Decel Time Gain | 228 | 17 <1> | Motor Thermistor (NTC) | 230 |
| 6 | DC Injection Braking Current | 229 | 1F | Through Mode | 230 |
| 7 | Torque Detection Level | 229 | 25 | Secondary PI Setpoint | 230 |
| 8 | Stall Prevention Level During Run | 229 | 26 | Secondary PI Feedback | 230 |
| 9 | Output Frequency Lower Limit Level | 229 | | | |

<1> This function is only available in models 4A0930 and 4A1200.

Setting 0: Frequency Bias

The input value of an analog input set to this function will be added to the analog frequency reference value. When the frequency reference is supplied by a different source other than the analog inputs, this function will have no effect. Use this setting also when only one of the analog inputs is used to supply the frequency reference.

By default, analog inputs A1 and A2 are set for this function. Simultaneously using A1 and A2 increases the frequency reference by the total of all inputs.

Example: If the analog frequency reference from analog input terminal A1 is 50% and a bias of 20% is applied by analog input terminal A2, the resulting frequency reference will be 70% of the maximum output frequency.

Setting 1: Frequency Gain

The input value of an analog input set to this function will be multiplied with the analog frequency reference value.

Example: If the analog frequency reference from analog input terminal A1 is 80% and a gain of 50% is applied from analog input terminal A2, the resulting frequency reference will be 40% of the maximum output frequency.

Setting 2: Auxiliary Reference 1

Sets the auxiliary frequency reference 1 when multi-step speed operation is selected. [Refer to Multi-Step Speed Selection on page 182](#) for details.

Setting 3: Auxiliary Reference 2

Sets the auxiliary frequency reference 2 when multi-step speed operation is selected. [Refer to Multi-Step Speed Selection on page 182](#) for details.

Setting 4: Output Voltage Bias

Voltage bias boosts the output voltage of the V/f curve as a percentage of the maximum output voltage (E1-05). Available only when using V/f Control.

Setting 5: Accel/Decel Time Gain

Adjusts the gain level for the acceleration and deceleration times set to parameters C1-01 through C1-04.

The drive acceleration time is calculated by multiplying the gain level to C1-□□ as follows:

$$C1-□□ \times \text{Accel/decel time gain} = \text{Drive accel/decel time}$$

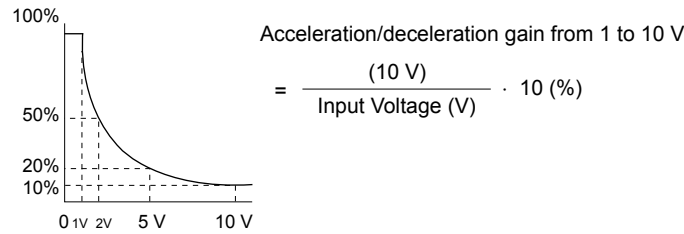


Figure 5.60 Accel/Decel Time Gain with Analog Input Terminal

Setting 6: DC Injection Braking Current

The current level used for DC Injection Braking is set as a percentage of the drive rated current.

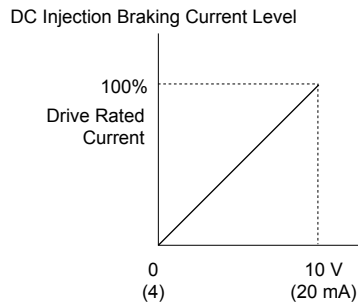


Figure 5.61 DC Injection Braking Current Using an Analog Input Terminal

Setting 7: Torque Detection Level

Using this setting, the overtorque/undertorque detection level for torque detection 1 (L6-01) can be set by an analog input. The analog input replaces the level set to L6-02. An analog input of 100% (10 V or 20 mA) sets a torque detection level equal to 100% drive rated current/motor rated torque. Adjust the analog input gain if higher detection level settings are required. [Refer to L6: Torque Detection on page 255](#) for details on torque detection.

Setting 8: Stall Prevention Level

Allows an analog input signal to adjust the Stall Prevention level. [Figure 5.62](#) shows the setting characteristics. The drive will use the lower value of the Stall Prevention level set to L3-06 or the level coming from the selected analog input terminal.

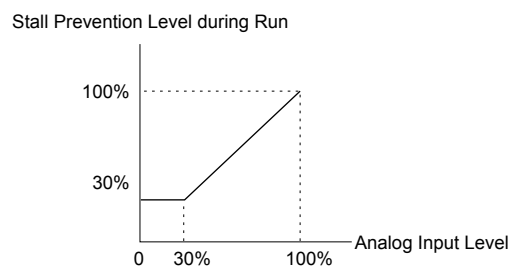


Figure 5.62 Stall Prevention During Run Using an Analog Input Terminal

Setting 9: Output Frequency Lower Limit Level

The user can adjust the lower limit of the output frequency using an analog input signal.

Setting B: PID Feedback

Supplies the PID feedback value. This setting requires PID operation to be enabled in b5-01. [Refer to PID Feedback Input Methods on page 161](#).

Setting C: PID Setpoint

Supplies the PID setpoint value and makes the frequency reference selected in parameter b1-01 no longer the PID setpoint. PID operation to be enabled in b5-01 to use this setting. [Refer to PID Setpoint Input Methods on page 161](#).

Setting D: Frequency Bias

The input value of an analog input set to this function will be added to the frequency reference. This function can be used with any frequency reference source.

5.7 H: Terminal Functions

Setting E: Motor Temperature

In addition to motor overload fault detection oL1, it is possible to use a Positive Temperature Coefficient (PTC) thermistor for motor insulation protection. [Refer to Motor Protection Using a Positive Temperature Coefficient \(PTC\) Thermistor on page 236](#) for a detailed explanation.

Setting 16: Differential PID Feedback

If an analog value is set for this function, the PID controller is set for differential feedback. The difference of the PID feedback input value and the differential feedback input value builds the feedback value used to calculate the PID input. [Refer to PID Feedback Input Methods on page 161](#).

Setting 17: Motor Thermistor (NTC)

Used as a complement or a substitution for oL1. [Refer to Motor Protection Using an NTC Thermistor Input on page 238](#) for details.

Setting 1F: Through Mode

An input does not affect any drive function, but the input level can still be read out by a PLC via a communication option or MEMOBUS/Modbus communications.

Setting 25: Secondary PI Setpoint

10 V = S3-02 (maximum output frequency)

Setting 26: Secondary PI Feedback

10 V = S3-02 (maximum output frequency)

◆ H4: Multi-Function Analog Outputs

These parameters assign functions to analog output terminals FM and AM for monitoring a specific aspect of drive performance.

■ H4-01, H4-04: Multi-Function Analog Output Terminal FM, AM Monitor Selection

Sets the desired drive monitor parameter $U\Box-\Box\Box$ to output as an analog value via terminal FM and AM. [Refer to U: Monitor Parameters on page 286](#) for a list of all monitors. The “Analog Output Level” column indicates whether a monitor can be used for analog output.

Example: Enter “103” for U1-03.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| H4-01 | Multi-Function Analog Output Terminal FM Monitor Selection | 000 to 999 | 102 |
| H4-04 | Multi-Function Analog Output Terminal AM Monitor Selection | 000 to 999 | 103 |

A setting of 031 or 000 applies no drive monitor to the analog output. With either of these settings, the output level of the terminals FM and AM can be set by a PLC via a communication option or MEMOBUS/Modbus (through mode).

■ H4-02, H4-03: Multi-Function Analog Output Terminal FM Gain and Bias H4-05, H4-06: Multi-Function Analog Output Terminal AM Gain and Bias

Parameters H4-02 and H4-05 set the terminal FM and AM output signal level when the value of the selected monitor is at 100%. Parameters H4-03 and H4-06 set the terminal FM and AM output signal level when the value of the selected monitor is at 0%. Both are set as a percentage, where 100% equals 10 Vdc or 20 mA analog output and 0% equals 0 V or 4 mA. The output voltage of both terminals is limited to +/-10 Vdc.

The output signal range can be selected between 0 to +10 Vdc or -10 to +10 Vdc, or 4 to 20 mA using parameter H4-07 and H4-08. [Figure 5.63](#) illustrates how gain and bias settings work.

| No. | Name | Setting Range | Default |
|-------|---|------------------|---------|
| H4-02 | Multi-Function Analog Output Terminal FM Gain | -999.9 to 999.9% | 100.0% |
| H4-03 | Multi-Function Analog Output Terminal FM Bias | -999.9 to 999.9% | 0.0% |
| H4-05 | Multi-Function Analog Output Terminal AM Gain | -999.9 to 999.9% | 50.0% |
| H4-06 | Multi-Function Analog Output Terminal AM Bias | -999.9 to 999.9% | 0.0% |

Using Gain and Bias to Adjust Output Signal Level

The output signal is adjustable while the drive is stopped.

Terminal FM

1. View the value set to H4-02 (Terminal FM Monitor Gain) on the digital operator. A voltage equal to 100% of the parameter being set in H4-01 will be output from terminal FM.
2. Adjust H4-02 viewing the monitor connected to the terminal FM.
3. View the value set to H4-03 on the digital operator; terminal FM will output a voltage equal to 0% of the parameter being set in H4-01.
4. Adjust H4-03 viewing the output signal on the terminal FM.

Terminal AM

1. View the value set to H4-05 (Terminal AM Monitor Gain) on the digital operator. A voltage equal to 100% of the parameter being set in H4-04 will be output from terminal AM.
2. Adjust H4-05 viewing the monitor connected to the terminal AM.
3. View the value set to H4-06 on the digital operator; terminal AM will output a voltage equal to 0% of the parameter being set in H4-04.
4. Adjust H4-06 viewing the output signal on the terminal AM.

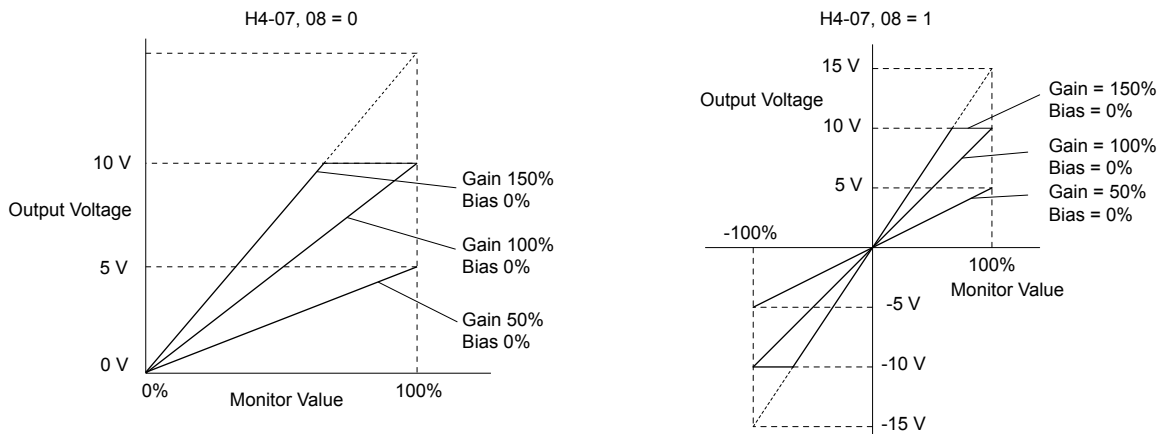


Figure 5.63 Analog Output Gain and Bias Setting Example 1 and 2

Set H4-03 to 30% for an output signal of 3 V at terminal FM when the monitored value is at 0%.

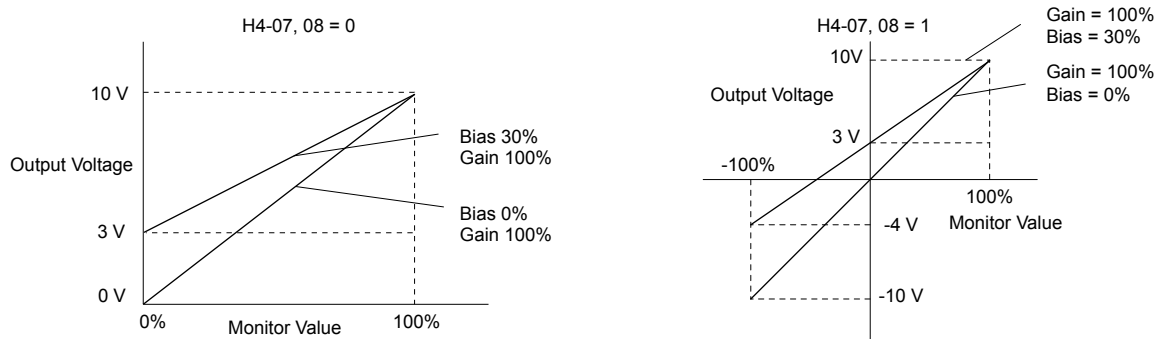


Figure 5.64 Analog Output Gain and Bias Setting Example 3

■ H4-07, H4-08: Multi-Function Analog Output Terminal FM, AM Signal Level Selection

Sets the voltage output level of U parameter (monitor parameter) data to terminal FM and terminal AM using parameters H4-07 and H4-08.

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------|
| H4-07 | Multi-Function Analog Output Terminal FM Signal Level Selection | 0 to 2 | 0 |
| H4-08 | Multi-Function Analog Output Terminal AM Signal Level Selection | 0 to 2 | 0 |

5.7 H: Terminal Functions

Setting 0: 0 to 10 V

Setting 1: -10 V to 10 V

Setting 2: 4 to 20 mA

◆ H5: MEMOBUS/Modbus Serial Communication

Serial communication is possible in the drive using the built-in RS-422/485 port (terminals R+, R-, S+, S-) and programmable logic controllers (PLCs) or similar devices running the MEMOBUS/Modbus protocol.

The H5-□□ parameters set the drive for MEMOBUS/Modbus Communications. [Refer to MEMOBUS/Modbus Serial Communication on page 511](#) for detailed descriptions of the H5-□□ parameters.

◆ H6: Pulse Train Input

A one-track pulse train signal with a maximum frequency of 32 kHz can be input to the drive at terminal RP. This pulse train signal can be used as the frequency reference or for PID functions.

Use parameters H6-□□ to set the scale and other aspects of the pulse input terminal RP.

■ H6-01: Pulse Train Input Terminal RP Function Selection

Selects the function of pulse train input terminal RP.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| H6-01 | Pulse Train Input Terminal RP Function Selection | 0 to 2 | 0 |

Setting 0: Frequency reference

If the pulse input is set for this function and the frequency reference source is set to pulse input (b1-01, b1-15 = 4), the drive reads the frequency value from terminal RP.

Setting 1: PID feedback value

Using this setting, the feedback value for PID control can be supplied as a pulse signal at terminal RP. [Refer to b5: PID Control on page 160](#) for details on PID control.

Setting 2: PID setpoint value

Using this setting, the setpoint value for PID control can be supplied as a pulse signal at terminal RP. [Refer to b5: PID Control on page 160](#) for details on PID control.

■ H6-02: Pulse Train Input Scaling

Sets the pulse signal frequency that is equal to 100% of the input value selected in parameter H6-01.

| No. | Name | Setting Range | Default |
|-------|---------------------------|-----------------|---------|
| H6-02 | Pulse Train Input Scaling | 100 to 32000 Hz | 1440 Hz |

■ H6-03: Pulse Train Input Gain

Sets the level of the input value selected in H6-01 when a pulse train signal with the frequency set in H6-02 is input to terminal RP.

| No. | Name | Setting Range | Default |
|-------|------------------------|----------------|---------|
| H6-03 | Pulse Train Input Gain | 0.0 to 1000.0% | 100.0% |

■ H6-04: Pulse Train Input Bias

Sets the level of the input value selected in H6-01 when no signal (0 Hz) is input to terminal RP.

| No. | Name | Setting Range | Default |
|-------|------------------------|------------------|---------|
| H6-04 | Pulse Train Input Bias | -100.0 to 100.0% | 0.0% |

■ H6-05: Pulse Train Input Filter Time

Sets the pulse train input filter time constant in seconds.

| No. | Name | Setting Range | Default |
|-------|-------------------------------|----------------|---------|
| H6-05 | Pulse Train Input Filter Time | 0.00 to 2.00 s | 0.10 s |

■ H6-08: Pulse Train Input Minimum Frequency

Sets the minimum output frequency detected by the pulse train input. Increasing this setting reduces the time the drive needs to react to changes in the input signal.

- The pulse input value becomes 0 when the pulse input frequency falls below this level.
- Enabled when H6-01 = 0, 1, or 2.
- When simple speed feedback in V/f Control is set as the function for terminal RP (H6-01 = 3), the minimum frequency becomes the detection time for PG disconnect (F1-14).

| No. | Name | Setting Range | Default |
|-------|-------------------------------------|------------------|---------|
| H6-08 | Pulse Train Input Minimum Frequency | 0.1 to 1000.0 Hz | 0.5 Hz |

5.8 L: Protection Functions

◆ L1: Motor Protection

■ L1-01: Motor Overload Protection Selection

The drive has an electronic overload protection function that estimates the motor overload level based on output current, output frequency, thermal motor characteristics, and time. When the drive detects a motor overload an oL1 fault is triggered and the drive output shuts off.

L1-01 sets the overload protection function characteristics according to the motor being used.

| No. | Name | Setting Range | Default |
|-------|-------------------------------------|---------------|---------|
| L1-01 | Motor Overload Protection Selection | 0 to 6 | 1 |

- Note:**
- When the motor protection function is enabled (L1-01 ≠ 0), an oL1 alarm can be output through one of the multi-function outputs by setting H2-01 to 1F. The output closes when the motor overload level reaches 90% of the oL1 detection level.
 - Set L1-01 to a value between 1 and 6 when running a single motor from the drive to select a method to protect the motor from overheat. An external thermal relay is not necessary.

Setting 0: Disabled (motor overload protection is not provided)

Use this setting if no motor overheat protection is desired or if multiple motors are connected to a single drive. If multiple motors are connected to a single drive, install a thermal relay for each motor as shown in [Figure 5.65](#).

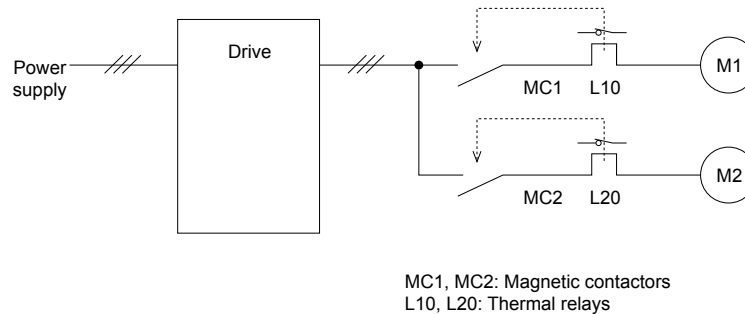


Figure 5.65 Example of Protection Circuit Design for Multiple Motors

NOTICE: Thermal protection cannot be provided when running multi-motors simultaneously with the same drive, or when using motors with a relatively high current rating compared to other standard motors (such as a submersible motor). Failure to comply could result in motor damage. Disable the electronic overload protection of the drive (L1-01 = "0: Disabled") and protect each motor with individual motor thermal overloads.

Note: Close MC1 and MC2 before operating the drive. MC1 and MC2 cannot be switched off during run.

Setting 1: General-purpose motor (standard self-cooled)

Because the motor is self-cooled, the overload tolerance drops when the motor speed is lowered. The drive appropriately adjusts the electrothermal trigger point according to the motor overload characteristics, protecting the motor from overheat throughout the entire speed range.

| Overload Tolerance | Cooling Ability | Overload Characteristics |
|---|---|---|
| <p>Rated Speed=100% Speed 60 s A: Max. speed for 200LJ and above B: Max. speed for 160MJ to 180 LJ C: Max. speed for 132MJ and below</p> <p>Torque (%) 150 90 60 50 Continuous</p> <p>05 33 100 120 167 200 Speed (%)</p> | <p>Motor designed to operate from line power. Motor cooling is most effective when running at rated base frequency (check the motor nameplate or specifications).</p> | <p>Continuous operation at less than line power frequency with 100% load can trigger motor overload protection (oL1). A fault is output and the motor will coast to stop.</p> |

Setting 2: Drive dedicated motor (speed range for constant torque: 1:10)

Use this setting when operating a drive duty motor that allows constant torque in a speed range of 1:10. The drive will allow the motor to run with 100% load from 10% up to 100% speed. Running at slower speeds with full load can trigger an overload fault.

| Overload Tolerance | Cooling Ability | Overload Characteristics |
|--|---|--|
| <p>Rated Speed=100% Speed 60 s A: Max. speed for 200LJ and above B: Max. speed for 160MJ to 180 LJ C: Max. speed for 132MJ and below Continuous</p> | <p>Motor is designed to effectively cool itself even at low speeds.</p> | <p>Continuous operation with 100% load from 6 Hz to E1-06, Motor Base Frequency.</p> |

Setting 3: Vector motor (speed range for constant torque: 1:100)

Use this setting when operating a drive-dedicated motor that allows constant torque in a speed range of 1:100. This motor type is allowed to run with 100% load from 1% up to 100% speed. Running slower speeds with full load can trigger an overload fault.

| Overload Tolerance | Cooling Ability | Overload Characteristics |
|--|--|--|
| <p>Rated Speed=100% Speed 60 s A: Max. speed for 200LJ and above B: Max. speed for 160MJ to 180 LJ C: Max. speed for 132MJ and below Continuous</p> | <p>Motor is designed to effectively cool itself at speeds near 0.6 Hz.</p> | <p>Continuous operation with 100% load from 0.6 Hz to E1-06, Motor Base Frequency. Continuous operation below 0.6 Hz may cause an oL1 or oL2 fault.</p> |

Setting 6: General-purpose Motor

Note: General-purpose motors are designed with a base speed that operates at line frequency (50/60 Hz depending on geographic region).

Because the motor is self-cooled, the overload tolerance drops when the motor speed is lowered. The drive appropriately adjusts the electrothermal trigger point according to the motor overload characteristics and protects the motor from overheat throughout the entire speed range.

| Overload Tolerance | Cooling Ability | Overload Characteristics |
|--|--|--|
| <p>Rated Speed=100% Speed 60 s A: Max. speed for 200LJ and above B: Max. speed for 160MJ to 180 LJ C: Max. speed for 132MJ and below Continuous</p> | <p>Motor designed to operate from line power. Motor cooling is most effective when running at rated base frequency (check the motor nameplate or specifications)</p> | <p>Continuous operation at less than line power frequency with 100% load can trigger a motor overload fault (oL1). A fault is output and the motor will coast to stop.</p> |

■ L1-02: Motor Overload Protection Time

Sets the time for the drive to shut down on motor overload (oL1) when the motor is running with excessive current. Enter the time the motor can withstand operating at 150% current after previously running at 100% current (hot motor overload condition). There is normally no need to change this parameter from the default value.

| No. | Name | Setting Range | Default |
|-------|--------------------------------|--------------------|-------------|
| L1-02 | Motor Overload Protection Time | 0.1 to 5.0 minutes | 1.0 minutes |

Defaulted to operate with an allowance of 150% overload operation for one minute in a hot start after continuous operation at 100%.

Figure 5.66 illustrates an example of the electrothermal protection operation time using a general-purpose motor operating at the value of E1-06, Motor Base Speed, with L1-02 set to one minute.

Motor overload protection operates in the area between a cold start and a hot start.

- Cold start: Characteristics of motor protection operation time in response to an overload situation that was suddenly reached when starting a stationary motor.
- Hot start: Characteristics of motor protection operation time in response to an overload situation that occurred while the motor was operating continuously at or below its rated current.

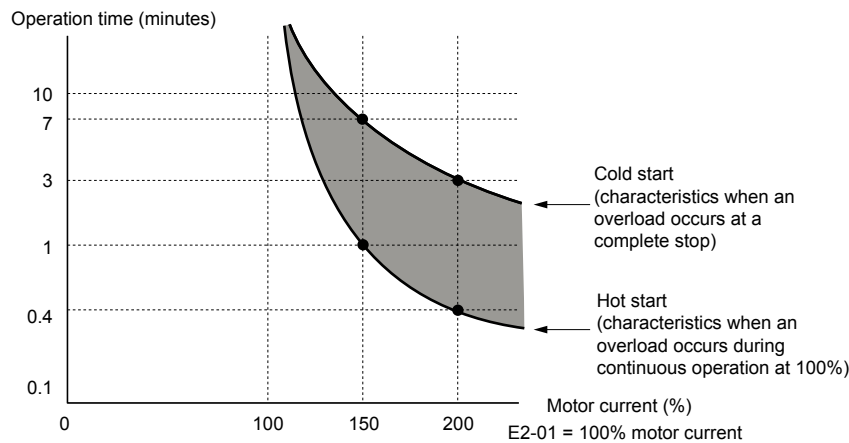


Figure 5.66 Protection Operation Time for General Purpose Motors at the Rated Output Frequency

■ Motor Protection Using a Positive Temperature Coefficient (PTC) Thermistor

Connect a motor PTC can to an analog input of the drive for motor overheat protection.

The motor overheat alarm level triggers an oH3 alarm and the drive continues the operation selected in L1-03. The overheat fault level triggers an oH4 fault, outputs a fault signal, and the drive stops the motor using the stop method selected in L1-04.

Connect the PTC between terminals AC and A3 and install a 12 kOhm resistor between terminals V+ and A3 as shown in **Figure 5.67**. Set H3-05 to 0 and H3-06 to E.

Note: A 12 kOhm resistor must be connected between one of the terminals A1, A2, or A3 and V+ for PTC functionality. Connect the 12 kOhm resistor to the same terminal as the PTC input. Do not connect terminals V+ to AC, or damage to the drive may result.

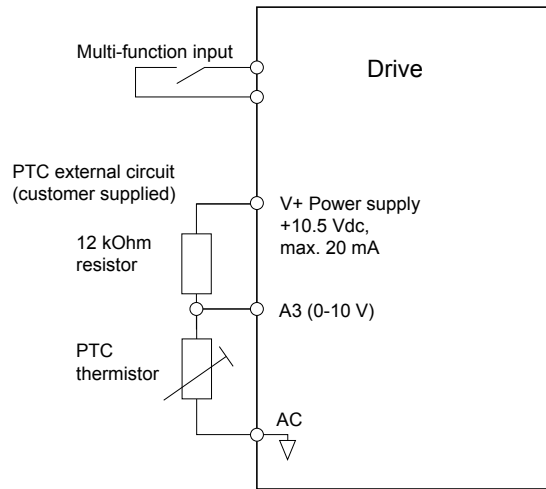


Figure 5.67 Connection of a Motor PTC

The PTC must exhibit the characteristics shown in **Figure 5.68** in one motor phase. The motor overload protection of the drive expects 3 of these PTCs to be connected in a series.

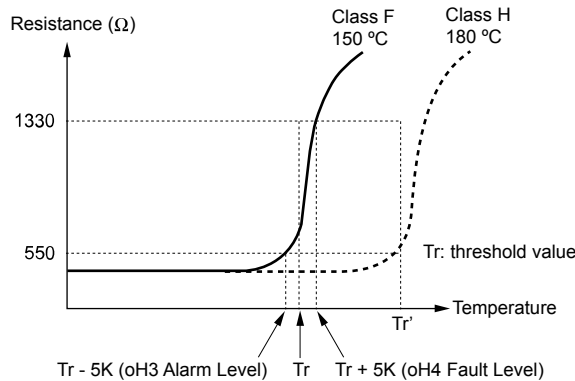


Figure 5.68 Motor PTC Characteristics

Set up overheat detection using a PTC using parameters L1-03, L1-04, and L1-05 as explained in the following sections.

■ **L1-03: Motor Overheat Alarm Operation Selection (PTC input)**

Sets the drive operation when the PTC input signal reaches the motor overheat alarm level (oH3).

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| L1-03 | Motor Overheat Alarm Operation Selection (PTC input) | 0 to 3 | 3 |

Setting 0: Ramp to Stop

The drive stops the motor using the deceleration time 1 set in parameter C1-02.

Setting 1: Coast to Stop

The drive output is switched off and the motor coasts to stop.

Setting 2: Fast Stop

The drive stops the motor using the Fast Stop time set in parameter C1-09.

Setting 3: Alarm Only

The operation is continued and an oH3 alarm is displayed on the digital operator.

■ **L1-04: Motor Overheat Fault Operation Selection (PTC input)**

Sets the drive operation when the PTC input signal reaches the motor overheat fault level (oH4).

5.8 L: Protection Functions

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| L1-04 | Motor Overheat Fault Operation Selection (PTC input) | 0 to 2 | 1 |

Setting 0: Ramp to Stop

The drive stops the motor using the deceleration time 1 set in parameter C1-02.

Setting 1: Coast to Stop

The drive output is switched off and the motor coasts to stop.

Setting 2: Fast Stop

The drive stops the motor using the Fast Stop time set in parameter C1-09.

■ L1-05: Motor Temperature Input Filter Time (PTC input)

Sets a filter on the PTC input signal to prevent erroneous detection of a motor overheat fault.

| No. | Name | Setting Range | Default |
|-------|---|-----------------|---------|
| L1-05 | Motor Temperature Input Filter Time (PTC input) | 0.00 to 10.00 s | 0.20 s |

■ L1-13: Continuous Electrothermal Operation Selection

Determines whether to hold the current value of the electrothermal motor protection (L1-01) when the power supply is interrupted.

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------|
| L1-13 | Continuous Electrothermal Operation Selection | 0 to 2 | 1 |

Setting 0: Disabled

Setting 1: Enabled

Setting 2: Enabled (RTC)

■ Motor Protection Using an NTC Thermistor Input

Motor protection is possible for models 4A0930 and 4A1200 by connecting the NTC thermistor input in the motor windings to one of the drive analog input terminals.

This enables the drive to provide torque compensation in response to changes in motor temperature and protect the motor from overheating.

If the NTC input signal using the drive multi-function analog input terminal exceeds the overheat alarm level set to L1-16, then “oH5” will flash on the digital operator screen. The drive will respond to the alarm according to the setting of L1-20 (default setting is to continue operation when an oH5 alarm occurs).

Figure 5.69 shows a circuit using the NTC thermistor and the terminal resistance values. Set jumper S1 on the drive to for voltage input when wiring the NTC thermistor input to terminal A2 on the drive.

Note: This example assumes that H3-10 = 17, H3-09 = 0, and that jumper S1 has been set for voltage input.

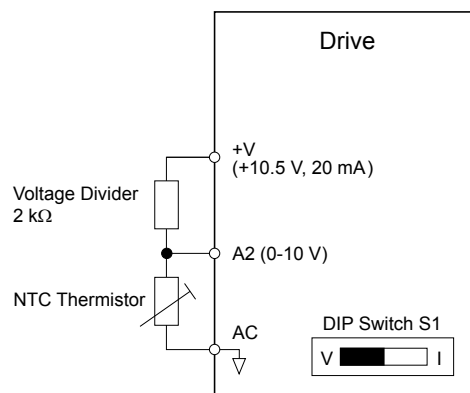


Figure 5.69 Motor Protection Circuit Using NTC Input

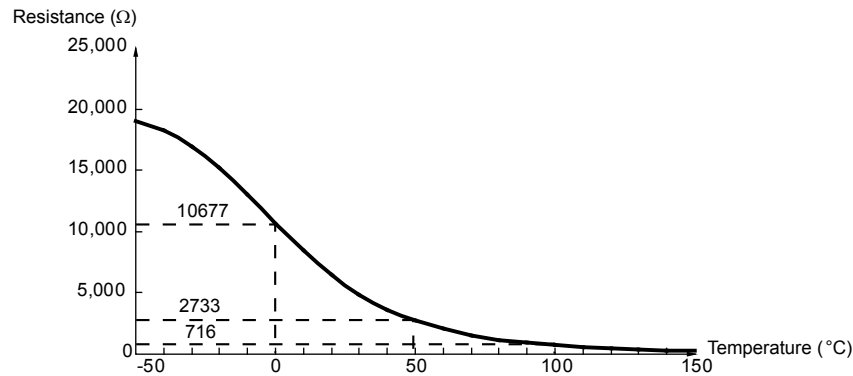


Figure 5.70 Temperature and Resistance of NTC Thermistor

L1-15 to L1-20 can determine the overheat protection settings using the NTC thermistor input. Parameter descriptions are listed below.

■ L1-15: Motor 1 Thermistor Selection (NTC)

Note: This parameter is only available in models 4A0930 and 4A1200.

| No. | Name | Setting Range | Default |
|-------|------------------------------------|---------------|---------|
| L1-15 | Motor 1 Thermistor Selection (NTC) | 0 to 2 | 0 |

Setting 0: Disabled

Setting 1: Thermistor Input by Analog Input

Setting 2: Thermistor Input by Special Thermistor Input

■ L1-16: Motor 1 Overheat Temperature

Note: This parameter is only available in models 4A0930 and 4A1200.

Sets the temperature that will trigger an overheat fault (oH5) for motor 1.

| No. | Name | Setting Range | Default |
|-------|------------------------------|---------------|---------|
| L1-16 | Motor 1 Overheat Temperature | 50 to 200 °C | 120 °C |

■ L1-17: Motor 2 Thermistor Selection (NTC)

Note: This parameter is only available in models 4A0930 and 4A1200.

| No. | Name | Setting Range | Default |
|-------|------------------------------------|---------------|---------|
| L1-17 | Motor 2 Thermistor Selection (NTC) | 0 to 2 | 0 |

Setting 0: Disabled

Setting 1: Thermistor Input by Analog Input

Setting 2: Thermistor Input by Special Thermistor Input

■ L1-18: Motor 2 Overheat Temperature

Note: This parameter is only available in models 4A0930 and 4A1200.

Sets the temperature that will trigger an overheat fault (oH5) for motor 2.

| No. | Name | Setting Range | Default |
|-------|------------------------------|---------------|---------|
| L1-18 | Motor 2 Overheat Temperature | 50 to 200 °C | 120 °C |

■ L1-19: Operation Time at Thermistor Disconnect (NTC)

Note: This parameter is only available in models 4A0930 and 4A1200.

Determines drive operation when a thermistor disconnect fault (THo) occurs.

5.8 L: Protection Functions

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------|
| L1-19 | Operation Time at Thermistor Disconnect (NTC) | 0 to 3 | 3 |

Setting 0: Ramp to Stop

The drive stops the motor using the deceleration time set in parameter C1-02.

Setting 1: Coast to Stop

The drive output is switched off and the motor coasts to a stop.

Setting 2: Fast Stop

The drive stops the motor using the Fast stop time set in parameter C1-09.

Setting 3: Alarm Only

The operation is continued and a THo alarm is displayed on the digital operator.

■ L1-20: Operation at Motor Overheat

Note: This parameter is only available in models 4A0930 and 4A1200.

Determines drive operation when a motor overheat fault (oH5) occurs.

| No. | Name | Setting Range | Default |
|-------|-----------------------------|---------------|---------|
| L1-20 | Operation at Motor Overheat | 0 to 3 | 1 |

Setting 0: Ramp to Stop

The drive stops the motor using the deceleration time set in parameter C1-02.

Setting 1: Coast to Stop

The drive output is switched off and the motor coasts to a stop.

Setting 2: Fast Stop

The drive stops the motor using the Fast stop time set in parameter C1-09.

Setting 3: Alarm Only

The operation is continued and an oH5 alarm is displayed on the digital operator.

◆ L2: Momentary Power Loss Ride-Thru

■ L2-01: Momentary Power Loss Operation Selection

When a momentary power loss occurs (DC bus voltage falls below the level set in L2-05), the drive can automatically return to the operation it was performing prior to the power loss based on certain conditions.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| L2-01 | Momentary Power Loss Operation Selection | 0 to 5 | 2 |

Setting 0: Disabled

If power is not restored within 15 ms, a Uv1 fault will result and the motor coasts to stop.

Setting 1: Recover within L2-02

When a momentary power loss occurs, the drive output will be shut off. If the power returns within the time set to parameter L2-02, the drive will perform Speed Search and attempt to resume operation. If power is not restored within this time (i.e., DC bus voltage level remains below Uv1 detection level L2-05), then a Uv1 fault is triggered and the drive will stop.

Setting 2: Recover as long as CPU Has Power

When a momentary power loss occurs, the drive output will be shut off. If the power returns and the drive control circuit has power, the drive will attempt to perform Speed Search and resume the operation. This will not trigger a Uv1 fault.

Setting 3: Kinetic Energy Backup (KEB) Ride-Thru Operation within L2-02

The drive decelerates using regenerative energy from the motor until the time set in L2-02 has expired. It then tries to accelerate back to the frequency reference. If the power does not return within the time set to L2-02, it will trigger a Uv1 fault and the drive output will shut off. The type of KEB operation is determined by the L2-29 setting.

Setting 4: KEB Ride-Thru as long as CPU Has Power

The drive decelerates using regenerative energy from the motor until the power returns and then restarts. If the motor comes to a stop before the power returns, the drive loses control power and the drive output shuts off. A Uv1 fault is not triggered. The type of KEB operation is determined by the L2-29 setting.

Setting 5: Ramp to Stop with KEB Deceleration

The drive ramps to stop using the regenerative energy from the motor. Even if the power is restored, the drive will continue to decelerate until the motor comes to a complete stop. The type of KEB operation is determined by the L2-29 setting.

Notes on Settings 1 through 5

- “Uv” will flash on the operator while the drive is attempting to recover from a momentary power loss. A fault signal is not output at this time.
- A Momentary Power Loss Unit is available to allow for a longer momentary power loss ride through time in models 2A0004 to 2A0056 and 4A0002 to 4A0031. This option makes it possible to continue running the drive after up to two seconds of power loss.
- When using a magnetic contactor between the motor and the drive, keep the magnetic contactor closed as long as the drive performs KEB operation or attempts to restart with Speed Search.
- Keep the Run command active during KEB operation or the drive cannot accelerate back to the frequency reference when the power returns.
- When L2-01 is set to 3, 4, or 5, KEB Ride-Thru will be executed as specified in L2-29.

■ KEB Ride-Thru Function

When the drive detects a power loss, KEB Ride-Thru decelerates the motor and uses regenerative energy to keep the main circuit operating. Despite power loss, the drive output is not interrupted.

Choose between Single Drive KEB Ride-Thru 1 and 2 (L2-29 = 0 or 1) for applications driven by a single drive.

Choose between System KEB Ride-Thru 1 and 2, (L2-29 = 2 or 3) for applications where multiple drives have to perform KEB operation while keeping a certain speed ratio.

Single Drive KEB Ride-Thru 1 (L2-29 = 0)

After KEB Ride-Thru begins, the drive uses regenerative energy from the motor to keep the DC bus voltage at the level set to L2-11 while adjusting the rate of deceleration based on the time set to L2-06. The user must set L2-06 properly to prevent Uv1 and ov faults.

Note: Shorten the KEB deceleration time (L2-06) if undervoltage (Uv1) occurs in the DC bus. Increase the KEB deceleration time if overvoltage (ov) occurs.

Single Drive KEB Ride-Thru 2 (L2-29 = 1)

The drive uses information about the inertia of the connected machinery to determine the deceleration rate necessary to keep the DC bus voltage at the level set in parameter L2-11. The resulting deceleration time is calculated based on the system inertia and cannot be adjusted.

System KEB Ride-Thru 1 (L2-29 = 2)

The drive decelerates at the KEB deceleration time set to L2-06. L2-06 is the time required to decelerate from the current frequency reference to 0. Using this setting, multiple drives can decelerate while keeping the speed ratio constant between those drives. This function requires a braking resistor and disregards the voltage level in the DC bus.

System KEB Ride-Thru 2 (L2-29 = 3)

The drive decelerates based on the KEB deceleration time set to L2-06 while monitoring the DC bus voltage. If the voltage level rises, the drive briefly holds the frequency before continuing to decelerate.

■ KEB Ride-Thru Start

KEB operation is triggered independently of the selected KEB operation mode. When the KEB function is selected as the function to be executed when power loss operation occurs (L2-01 = 3, 4, or 5), then KEB Ride-Thru will be activated if one of the following conditions becomes true:

- A digital input programmed for H1-□□ = 65 or 66 is activated. This will start KEB operation using the mode selected in parameter L2-29.
- A digital input programmed for H1-□□ = 7A or 7B is activated. This will automatically select Single KEB Ride-Thru 2, disregarding the setting of L2-29.
- The DC bus voltage fell below the level specified in L2-05. The KEB operation will start as specified in L2-29.

Note: Attempting to simultaneously assign KEB Ride-Thru 1 and 2 to input terminals will trigger an oPE3 error.

5.8 L: Protection Functions

When using a digital input to trigger KEB operation and the device controlling the input acts relatively slow, set a minimum KEB operation time in parameter L2-10. In the example below, the DC bus voltage triggers KEB operation and a digital input triggers the Hold command.

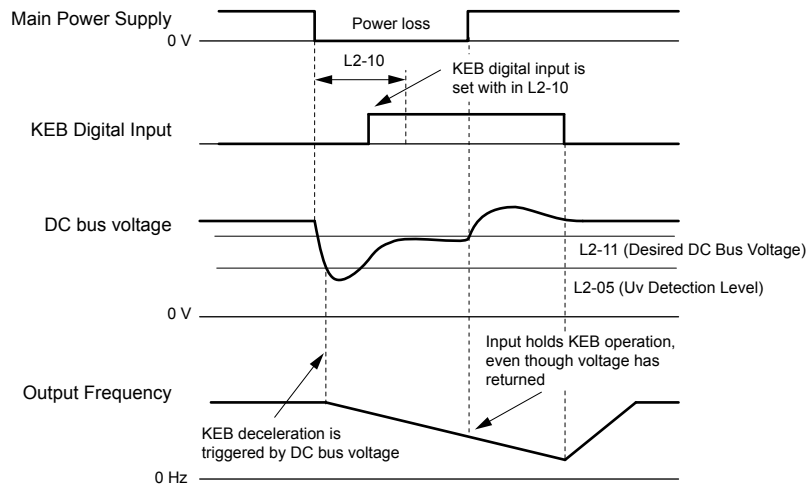


Figure 5.71 KEB Operation Using a KEB Input

■ KEB Ride-Through End Detection

The KEB function end detection depends on the setting of parameter L2-01 and whether a digital input programmed for KEB (H1-□□ = 65, 66, 7A, 7B) is used.

KEB Ride-Through Operation in L2-02, Input Terminals Not Used

Here, L2-01 = 3 and the input terminals have not been set for KEB Ride-Through (H1-□□ does not equal 65, 66, 7A, 7B). After decelerating for the time set in parameter L2-02, the drive ends KEB operation and attempts to accelerate back to the frequency reference. A Uv1 fault occurs and the drive output shuts off if the power does not return within the time set to L2-02.

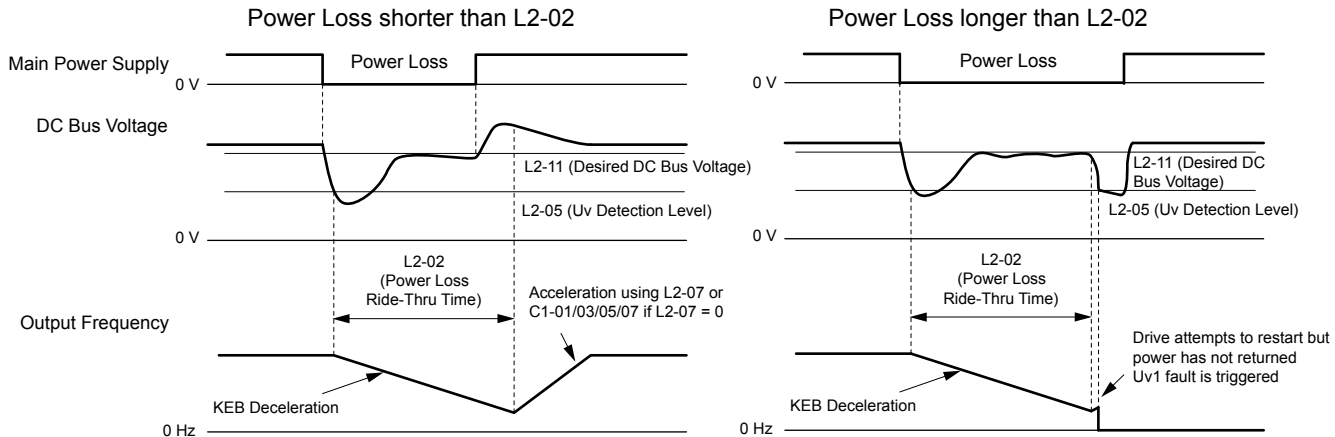


Figure 5.72 KEB Operation Using L2-02, Without KEB Input

KEB Ride-Through Operation Within L2-02, Input Terminals Used

Here, L2-01 = 3 and an input terminal is set to issue KEB Ride-Through (H1-□□ = 65, 66, 7A, 7B). After decelerating for the time set in parameter L2-02, the drive checks the DC bus voltage and the status of the digital input. If the DC bus voltage is still below the level set in L2-11 or if the KEB digital input is still active, KEB deceleration continues. If the voltage level has risen above the value set to L2-11, then normal operation is resumed.

Note: If L2-10 is set to a longer time than L2-02, the drive checks the DC bus voltage level and the status of the terminal assigned to KEB Ride-Through after the time set to L2-02 passes. The drive will then try to restart.

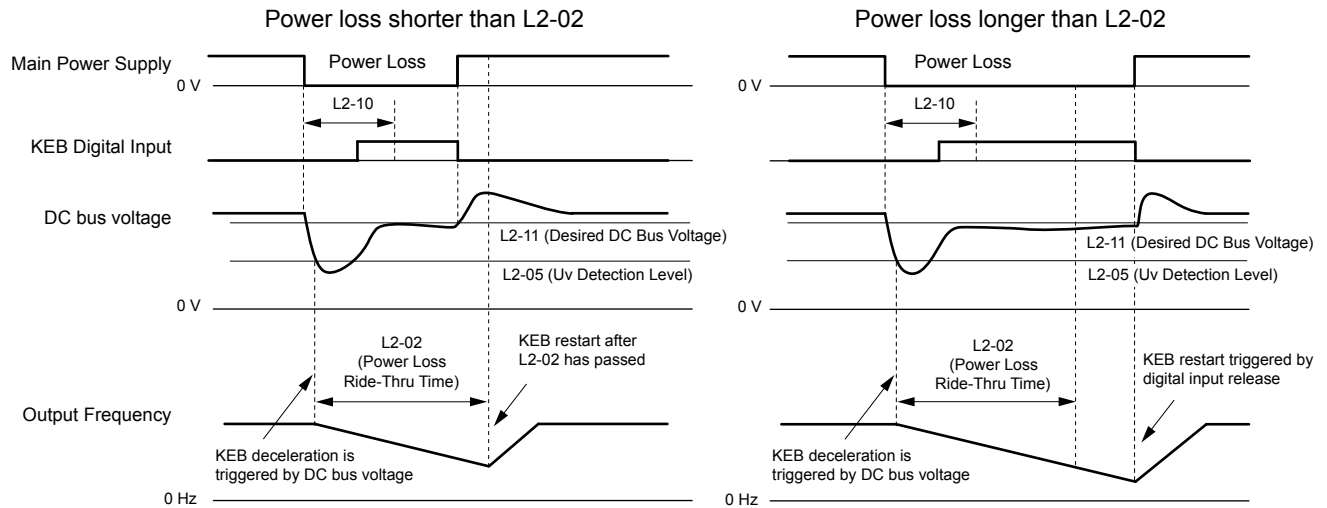


Figure 5.73 KEB Operation Using L2-02 and KEB Input

KEB Ride-Thru Operation as Long as CPU Has Power, KEB Input Not Used

Here, L2-01 = 4 and the input terminals have not been set for KEB Ride-Thru (H1-□□ does not equal 65, 66, 7A, 7B). After decelerating for the time set to parameter L2-10, the drive checks the DC bus voltage level. Deceleration continues if the DC bus voltage is lower than the level set in L2-11. Normal operation resumes when the DC bus voltage rises above the value of L2-11.

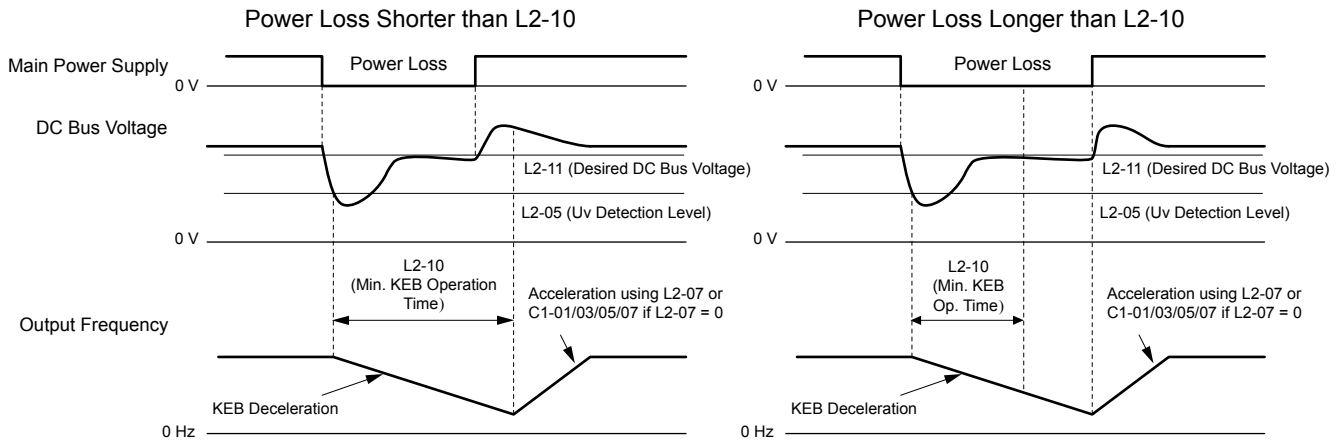


Figure 5.74 KEB Operation Using L2-10, Without KEB Input

KEB Ride-Thru Operation as Long as CPU Has Power, KEB Input Used

Here, L2-01 = 3 and an input terminal is set to issue KEB Ride-Thru (H1-□□ = 65, 66, 7A, 7B). After decelerating for the time set to parameter L2-10, the drive checks the DC bus voltage and the status of the digital input. Deceleration continues if the DC bus voltage is still below the level set in L2-11 or if the digital input assigned to KEB Ride-Thru is still active. Normal operation resumes when the DC bus voltage rises above the value of L2-11 and the terminal that initiated KEB Ride-Thru is released.

5.8 L: Protection Functions

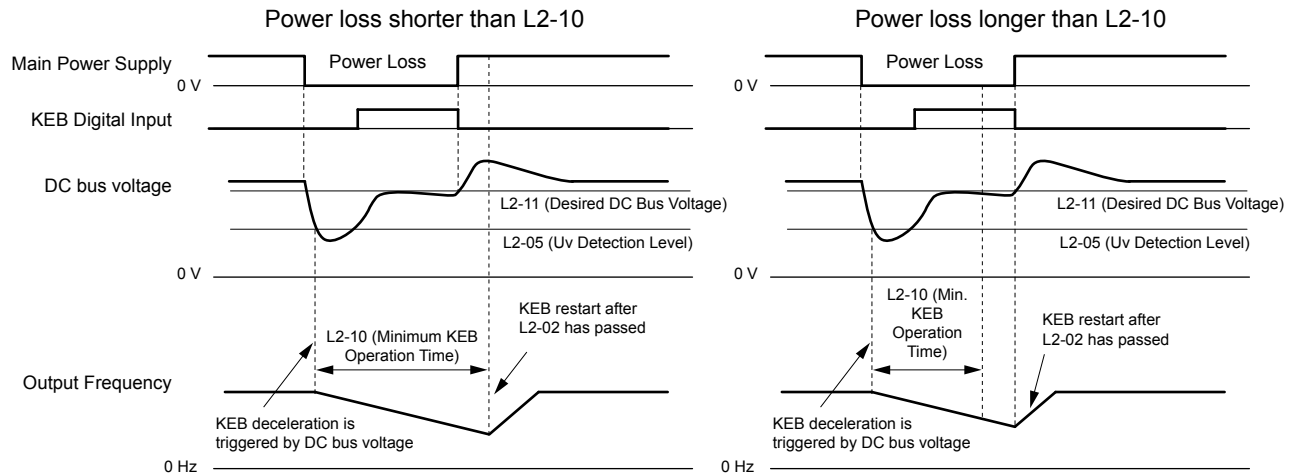


Figure 5.75 KEB Operation Using L2-10 and KEB Input

L2-01 = 5

KEB operation ends when the motor has come to a stop, even if the power returns and the digital input terminal that initiated KEB Ride-Thru is cleared.

■ KEB Operation Wiring Example

Figure 5.76 shows a wiring example to trigger the KEB Ride-Thru at power loss using an undervoltage relay. When a power loss occurs, the undervoltage relay triggers KEB Ride-Thru at terminal S6 (H1-06 = 65, 66, 7A, 7B). Note that using System KEB Ride-Thru requires an additional dynamic braking option.

- Note:**
1. Do not switch off the Run command during momentary power loss. If the Run command is shut off, the drive will not accelerate back to speed when the power is restored.
 2. A dynamic braking option is required to use System KEB 1 (L2-29 = 2).

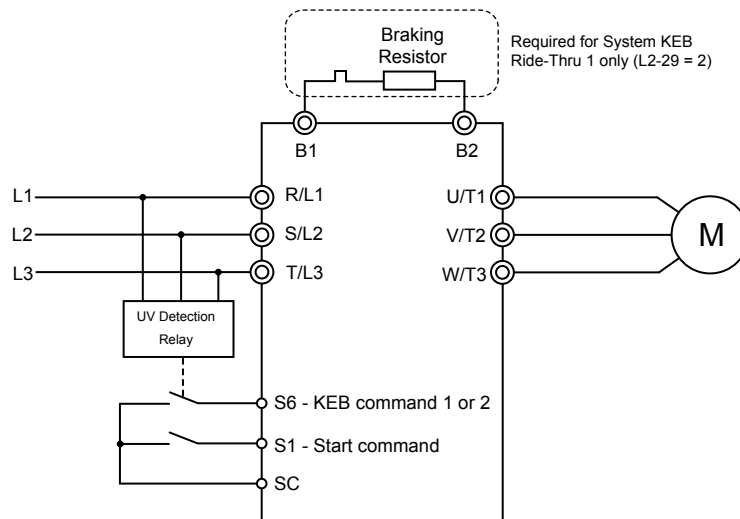


Figure 5.76 KEB Function Wiring Example

■ Parameters for KEB Ride-Thru

Table 5.35 lists parameters needed to set up KEB Ride-Thru depending on the type of KEB Ride-Thru selected in L2-29.

Table 5.35 KEB Function Related Adjustments

| Parameter | Name | Setting Instructions | KEB Mode (L2-29) | | | |
|-----------|-----------------------------------|---|------------------|-----|-----|-----|
| | | | 0 | 1 | 2 | 3 |
| C1-09 | Fast Stop Time | <ul style="list-style-type: none"> Increase if an overvoltage fault occurs during KEB deceleration. Decrease if an undervoltage fault occurs during KEB deceleration. | YES | NO | NO | NO |
| C2-03 | S-Curve at Deceleration Start | <ul style="list-style-type: none"> Shorten if undervoltage occurs immediately after KEB Ride-Thru is triggered. Lengthen this setting if overvoltage occurs immediately after KEB operation starts. | YES | NO | YES | YES |
| L2-05 | Undervoltage Detection Level | Increase if an undervoltage fault occurs at KEB operation start to let the drive detect power loss more quickly. | YES | YES | YES | YES |
| L2-06 | KEB Deceleration Time | <ul style="list-style-type: none"> Increase if an overvoltage fault occurs during KEB deceleration Decrease if an undervoltage fault occurs during KEB deceleration | NO | NO | YES | YES |
| L2-07 | KEB Acceleration Time | Adjust to the desired acceleration time. If set to 0, standard acceleration times are used (C1-01, C1-03, C1-05, C1-07). | YES | YES | YES | YES |
| L2-08 | Frequency Gain at KEB Start | <ul style="list-style-type: none"> Increase if an undervoltage fault occurs immediately after KEB operation starts. Decrease if an overvoltage fault occurs immediately after KEB operation starts. | YES | NO | YES | YES |
| L2-10 | KEB Detection Time | <ul style="list-style-type: none"> Increase when a digital input is set for KEB Ride-Thru and an undervoltage fault occurs after power was lost because the device controlling the input does not react quickly enough. If the DC bus voltage overshoots after KEB Ride-Thru begins (and no input terminal is set to KEB Ride-Thru), increase L2-10 to longer than the overshoot. | YES | YES | YES | YES |
| L2-11 | Desired DC Bus Voltage during KEB | <ul style="list-style-type: none"> Set to approximately 1.22 times the input voltage for Single Drive KEB Ride-Thru 2. Set to approximately 1.4 times the input voltage for Single Drive KEB Ride-Thru 1 and System KEB Ride-Thru modes. | YES | YES | YES | YES |
| L3-20 | Main Circuit Adjustment Gain | <ul style="list-style-type: none"> Increase this setting in steps of 0.1 if overvoltage or undervoltage occurs at the beginning of deceleration Reduce if torque ripple occurs during deceleration while executing KEB Ride-Thru. | NO | YES | NO | NO |
| L3-21 | Accel/Decel Rate Calculation Gain | <ul style="list-style-type: none"> Reduce L3-21 in steps of 0.05 if there is a fairly large speed or current ripple. Decreasing this setting too much can cause a slow DC bus voltage control response, and may lead to problems with overvoltage or undervoltage. | NO | YES | NO | NO |
| L3-24 | Motor Acceleration Time | Set the motor acceleration time as described on page 252. | NO | YES | NO | NO |
| L3-25 | Load Inertia Ratio | Set the load/inertia ratio as described on page 252. | NO | YES | NO | NO |

■ L2-02: Momentary Power Loss Ride-Thru Time

Sets the maximum time allowed to ride through a power loss. If power loss operation exceeds this time, the drive will attempt to accelerate back to the frequency reference. This parameter is valid if L2-01 = 1 or 3.

Note: The amount of time the drive is capable of recovering after a power loss is determined by the capacity of the drive. Drive capacity determines the upper limit for L2-02.

| No. | Name | Setting Range | Default |
|-------|-------------------------------------|---------------|---------------------|
| L2-02 | Momentary Power Loss Ride-Thru Time | 0.0 to 25.5 s | Determined by o2-04 |

■ L2-03: Momentary Power Loss Minimum Baseblock Time

Sets the minimum baseblock time when power is restored following a momentary power loss. This determines the time the drive waits for the residual voltage in the motor to dissipate. Increase this setting if overcurrent or overvoltage occurs at the beginning of Speed Search, after a power loss, or during DC Injection Braking.

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------------------|
| L2-03 | Momentary Power Loss Minimum Baseblock Time | 0.1 to 5.0 s | Determined by o2-04 |

5.8 L: Protection Functions

■ L2-04: Momentary Power Loss Voltage Recovery Ramp Time

Sets the time for the drive to restore the output voltage to the level specified by the V/f pattern after Speed Search. The setting value determines the time for the voltage to go from 0 V to the maximum voltage.

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------------------|
| L2-04 | Momentary Power Loss Voltage Recovery Ramp Time | 0.0 to 5.0 s | Determined by o2-04 |

■ L2-05: Undervoltage Detection Level (Uv)

Determines the voltage at which a Uv1 fault is triggered or at which the KEB function is activated. This setting rarely needs to be changed.

| No. | Name | Setting Range | Default |
|-------|------------------------------|--------------------|-------------------------|
| L2-05 | Undervoltage Detection Level | 150 to 210 Vdc <1> | Determined by E1-01 <2> |

<1> Values are specific to 200 V class drives. Double the value for 400 V class drives. Multiply the value by 2.875 for 600 V class drives.

<2> The default setting for 400 V class drives depends on whether the drive input voltage is over 400 V or under 400 V.

- Note:**
1. Install an AC reactor option on the input side of the power supply when setting L2-05 below the default value to prevent damage to drive circuitry.
 2. If using KEB Ride-Thru and L2-05 is set too low, then undervoltage in the DC bus (Uv1) will be triggered before KEB Ride-Thru can be executed. Take caution not to set this value too low.

■ L2-06: KEB Deceleration Time

Sets the time to decelerate from the frequency reference at the time KEB Ride-Thru was initiated to zero speed. This setting can be used only when L2-29 = 2 (System KEB Ride-Thru 1).

| No. | Name | Setting Range | Default |
|-------|-----------------------|----------------------|---------|
| L2-06 | KEB Deceleration Time | 0.00 to 6000.0 s <1> | 0.00 s |

<1> Setting range is determined by the accel/decel time units set in C1-10. If the time is set in units of 0.01 s (C1-10 = 0), the setting range becomes 0.00 to 600.00 s.

■ L2-07: KEB Acceleration Time

Sets the time to reaccelerate from the speed when KEB was deactivated to the frequency reference.

When set to 0.0 s, the drive will accelerate to speed according to the active acceleration time set in C1-01 or C1-03.

| No. | Name | Setting Range | Default |
|-------|-----------------------|----------------------|---------|
| L2-07 | KEB Acceleration Time | 0.00 to 6000.0 s <1> | 0.00 s |

<1> Setting range is determined by the accel/decel time units set in C1-10. If the time is set in units of 0.01 s (C1-10 = 0), the setting range becomes 0.00 to 600.00 s.

■ L2-08: Frequency Gain at KEB Start

When the KEB Ride-Thru command is input, the output frequency is reduced in a single step to quickly get the motor into a regenerative state. Calculate the amount of this frequency reduction using the formula below. L2-08 can only be used with induction motors.

Amount of reduction = Slip frequency prior to KEB \times (L2-08/100) \times 2

| No. | Name | Setting Range | Default |
|-------|-----------------------------|---------------|---------|
| L2-08 | Frequency Gain at KEB Start | 0 to 300% | 100% |

■ L2-10: KEB Detection Time (Minimum KEB Time)

| No. | Name | Setting Range | Default |
|-------|--------------------|---------------|---------|
| L2-10 | KEB Detection Time | 0 to 2000 ms | 50 ms |

■ L2-11: DC Bus Voltage Setpoint during KEB

Determines the setpoint (target value) for the DC bus voltage during Single KEB Ride-Thru 2. For Single KEB Ride-Thru 1 and System KEB Ride-Thru, parameter L2-11 defines the voltage level to end KEB Ride-Thru.

| No. | Name | Setting Range | Default |
|-------|------------------------------------|--------------------|----------------|
| L2-11 | DC Bus Voltage Setpoint during KEB | 150 to 400 Vdc </> | [E1-01] × 1.22 |

<1> Values are specific to 200 V class drives. Double the value for 400 V class drives. Multiply the value by 2.875 for 600 V class drives, but set the value below 1040 Vdc (overvoltage protection level).

■ L2-29: KEB Method Selection

Selects the way the Kinetic Energy Buffering function operates.

Note: If a multi-function input is set for Single KEB Ride-Thru 2 (H1-□□ = 7A, 7B), the setting of L2-29 is disregarded and the KEB mode equal to L2-29 = 1 is automatically selected.

| No. | Name | Setting Range | Default |
|-------|----------------------|---------------|---------|
| L2-29 | KEB Method Selection | 0 to 3 | 0 |

Setting 0: Single Drive KEB Ride-Thru 1

Setting 1: Single Drive KEB Ride-Thru 2

Setting 2: System KEB Ride-Thru 1

Setting 3: System KEB Ride-Thru 2

Refer to KEB Ride-Thru Function on page 241 for detailed explanations.

◆ L3: Stall Prevention

The motor may experience excessive slip because it cannot keep up with the frequency reference when the load is too high or acceleration and deceleration times are too short. If the motor slips during acceleration, it usually causes an overcurrent fault (oC), drive overload (oL2), or motor overload (oL1). If the motor slips during deceleration, it can cause excessive regenerative power to flow back into the DC bus capacitors, and eventually cause the drive to fault out from overvoltage (ov). The Stall Prevention Function prevents the motor from stalling and while allowing the motor to reach the desired speed without requiring the user to change the acceleration or deceleration time settings. The Stall Prevention function can be set separately for acceleration, operating at constant speeds, and deceleration.

■ L3-01: Stall Prevention Selection during Acceleration

Stall Prevention during acceleration prevents tripping with overcurrent (oC), motor overload (oL1), or drive overload (oL2) faults common when accelerating with heavy loads.

L3-01 determines the type of Stall prevention the drive should use during acceleration.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| L3-01 | Stall Prevention Selection during Acceleration | 0 to 2 | 1 |

Setting 0: Disabled

No Stall Prevention is provided. If the acceleration time is too short, the drive may not be able to get the motor up to speed fast enough, causing an overload fault.

Setting 1: Enabled

Enables Stall Prevention during acceleration.

Acceleration is reduced when the output current value exceeds 85% of the level set to parameter L3-02 for a longer than the time set to L3-27. The acceleration stops when the current exceeds L3-02. Acceleration continues when the current falls below L3-02 for longer than the time set to L3-27.

The Stall Prevention level is automatically reduced in the constant power range. *Refer to L3-03: Stall Prevention Limit during Acceleration on page 248.*

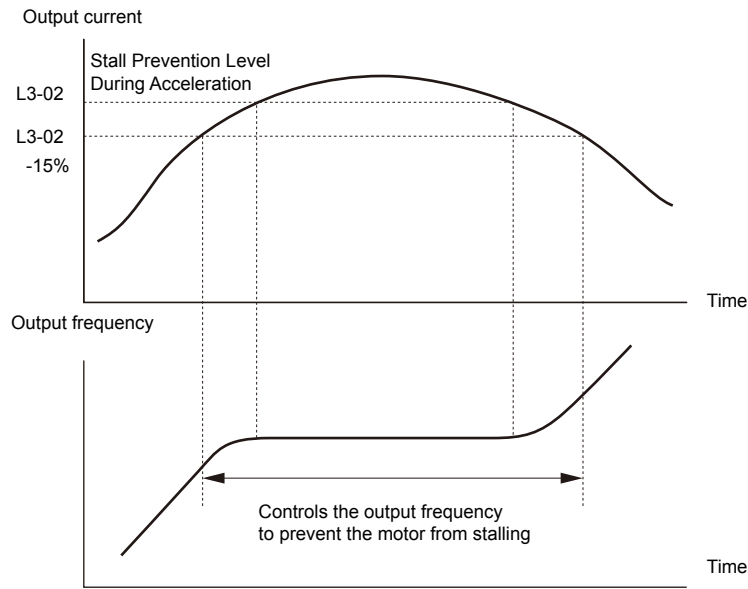


Figure 5.77 Stall Prevention During Acceleration for Induction Motors

Setting 2: Intelligent Stall Prevention

The drive disregards the selected acceleration time and attempts to accelerate in the minimum time. The acceleration rate is adjusted so the current does not exceed the value set to parameter L3-02.

■ L3-02: Stall Prevention Level during Acceleration

Sets the output current level at which the Stall Prevention during acceleration is activated.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| L3-02 | Stall Prevention Level during Acceleration | 0 to 150% </> | </> |

<1> The upper limit and default value is determined by parameter L8-38, Carrier Frequency Reduction.

- Lower L3-02 if stalling occurs when using a motor that is relatively small compared to the drive.
- Also set parameter L3-03 when operating the motor in the constant power range.

■ L3-03: Stall Prevention Limit during Acceleration

The Stall Prevention level is automatically reduced when the motor is operated in the constant power range. L3-03 sets the lower limit for this reduction as a percentage of the drive rated current.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| L3-03 | Stall Prevention Limit during Acceleration | 0 to 100% | 50% |

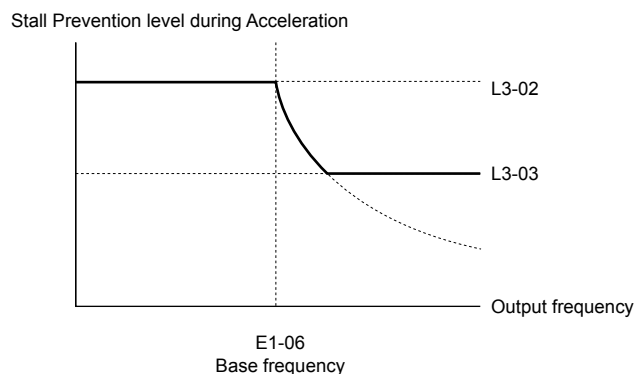


Figure 5.78 Stall Prevention Level and Limit During Acceleration

■ L3-04: Stall Prevention Selection during Deceleration

Stall Prevention during deceleration controls the deceleration based on the DC bus voltage and prevents an overvoltage fault caused by high inertia or rapid deceleration.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| L3-04 | Stall Prevention Selection During Deceleration | 0 to 5 <I> | 1 |

<I> Setting 3 is not available in models 4A0930 or 4A1200.

Setting 0: Disabled

The drive decelerates according to the set deceleration time. With high inertia loads or rapid deceleration, an overvoltage fault may occur. If an overvoltage fault occurs, use dynamic braking options or switch to another L3-04 selection.

Setting 1: General-purpose Stall Prevention

The drive tries to decelerate within the set deceleration time. The drive pauses deceleration when the DC bus voltage exceeds the Stall Prevention level and then continues deceleration when the DC bus voltage drops below that level. Stall Prevention may be triggered repeatedly to avoid an overvoltage fault. The DC bus voltage level for Stall Prevention depends on the input voltage setting E1-01.

| Drive Input Voltage | Stall Prevention Level during Deceleration |
|---------------------|--|
| 200 V Class | 377 Vdc |
| 400 V Class | 754 Vdc |
| 600 V Class | 1084 Vdc |

- Note:**
1. Do not use this setting in combination with a Dynamic Braking Resistor or other dynamic braking options. If Stall Prevention during deceleration is enabled, it will be triggered before the braking resistor option can operate.
 2. This method may lengthen the total deceleration time compared to the set value. If this is not appropriate for the application consider using a dynamic braking option.

Figure 5.79 illustrates the function of Stall Prevention during deceleration.

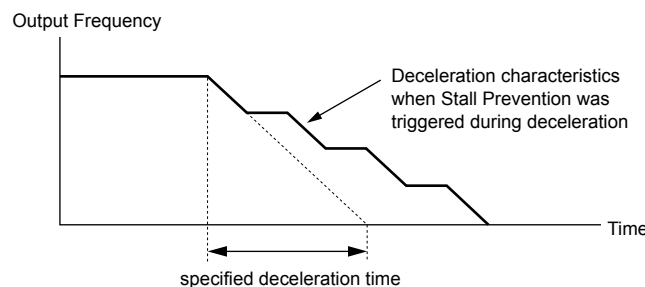


Figure 5.79 Stall Prevention During Deceleration

Setting 2: Intelligent Stall Prevention

The drive adjusts the deceleration rate so the DC bus voltage is kept at the level set to parameter L3-17. This produces the shortest possible deceleration time while protecting the motor from stalling. The selected deceleration time is disregarded and the achievable deceleration time cannot be smaller than 1/10 of the set deceleration time.

This function uses the following parameters for adjusting the deceleration rate:

- DC bus voltage gain (L3-20)
- Deceleration rate calculations gain (L3-21)
- Inertia calculations for motor acceleration time (L3-24)
- Load inertia ratio (L3-25)

Note: The deceleration time is not constant. Do not use Intelligent Stall Prevention in applications where stopping accuracy is a concern. Use dynamic braking options instead.

Setting 3: Stall Prevention with dynamic braking option

Enables the Stall Prevention function while using a dynamic braking resistor.

Setting 4: Overexcitation Deceleration 1

Overexcitation Deceleration 1 (increasing the motor flux) is faster than deceleration with no Stall Prevention (L3-04 = 0). Setting 4 changes the selected decel time and functions to provide protection from an overvoltage trip. *Refer to Overexcitation Deceleration (Induction Motors) on page 265* for details.

5.8 L: Protection Functions

Setting 5: Overexcitation Deceleration 2

Overexcitation Deceleration 2 slows down the motor while trying to maintain the DC bus voltage at the level set to parameter L3-17. This function shortens the achievable deceleration time more than by using Overexcitation Deceleration 1. Setting 5 will shorten/lengthen the decel time to maintain the L3-17 bus level. *Refer to Overexcitation Deceleration (Induction Motors) on page 265* for details.

■ L3-05: Stall Prevention Selection during Run

Determines how Stall Prevention works during Run. Stall Prevention during run prevents the motor from stalling by automatically reducing the speed when a transient overload occurs while the motor is running at constant speed.

| No. | Name | Setting Range | Default |
|-------|---------------------------------------|---------------|---------|
| L3-05 | Stall Prevention Selection During Run | 0 to 2 | 1 |

Note: Stall Prevention during run is disabled when the output frequency is 6 Hz or lower regardless of the L3-05 and L3-06 settings.

Setting 0: Disabled

Drive runs at the set frequency reference. A heavy load may cause the motor to stall and trip the drive with an oC or oL fault.

Setting 1: Decelerate using C1-02

If the current exceeds the Stall Prevention level set in parameter L3-06, the drive will decelerate at decel time 1 (C1-02). When the current level drops below the value of L3-06 minus 2% for 100 ms, the drive accelerates back to the frequency reference at the active acceleration time.

Setting 2: Decelerate using C1-04

Same as setting 1 except the drive decelerates at decel time 2 (C1-04).

■ L3-06: Stall Prevention Level during Run

Sets the current level to trigger Stall Prevention during run. Depending on the setting of parameter L3-23, the level is automatically reduced in the constant power range (speed beyond base speed). A setting of 100% is equal to the drive rated current.

The Stall Prevention level can be adjusted using an analog input. *Refer to Multi-Function Analog Input Terminal Settings on page 228* for details.

| No. | Name | Setting Range | Default |
|-------|-----------------------------------|----------------|---------|
| L3-06 | Stall Prevention Level During Run | 30 to 150% </> | </> |

<1> The upper limit and default for this setting is determined by L8-38.

■ Overvoltage Suppression Function

Suppresses overvoltage faults by decreasing the regenerative torque limit and slightly increasing the output frequency when the DC bus voltage rises. This function can drive loads with cyclic regenerative operation, such as a punch press or other applications that involve repetitive crank movements.

The regenerative torque limit and the output frequency are adjusted during ov suppression so that the DC bus voltage does not exceed the level set to parameter L3-17. In addition to the parameters explained below, ov suppression also uses these settings for frequency adjustment:

- DC bus voltage gain (L3-20)
- Deceleration rate calculations gain (L3-21)
- Inertia calculations for motor acceleration time (L3-24)
- Load inertia ratio (L3-25)

- Note:**
1. The motor speed will exceed the frequency reference when overvoltage suppression is triggered. Consequently, overvoltage suppression is not appropriate in applications that require a perfect match between the frequency reference and the motor speed.
 2. Disable overvoltage suppression when using a braking resistor.
 3. Overvoltage may still occur if there is a sudden increase to a regenerative load.
 4. This function is enabled only when operating just below the maximum frequency. Overvoltage suppression does not increase the output frequency beyond the maximum frequency. If the application requires this, increase the maximum frequency and change the base frequency setting.

■ L3-11: Overvoltage Suppression Function Selection

Enables or disables the overvoltage suppression function.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| L3-11 | Overvoltage Suppression Function Selection | 0, 1 | 0 |

Setting 0: Disabled

The regenerative torque limit and the output frequency are not adjusted. A regenerative load may trip the drive with an overvoltage fault. Use this setting if dynamic braking options are installed.

Setting 1: Enabled

When the DC bus voltage rises due to regenerative load, an overvoltage fault is prevented by decreasing the regenerative torque limit and increasing the output frequency.

■ L3-17: Target DC Bus Voltage for Overvoltage Suppression and Stall Prevention

Sets the target DC bus voltage level used by the overvoltage suppression function (L3-11 = 1), Intelligent Stall Prevention during deceleration (L3-04 = 2).

| No. | Name | Setting Range | Default |
|-------|--|--------------------|-----------------|
| L3-17 | Target DC Bus Voltage for Overvoltage Suppression and Stall Prevention | 150 to 400 Vdc <1> | 375 Vdc <1> <2> |

<1> Values are specific to 200 V class drives. Double the value for 400 V class drives. Multiply the value by 2.875 for 600 V class drives, but set the value below 1040 Vdc (overvoltage protection level).

<2> This value is initialized when E1-01 is changed.

■ L3-20: DC Bus Voltage Adjustment Gain

Determines the proportional gain used by overvoltage suppression (L3-11 = 1), Single Drive KEB 2 (L2-29 = 1), KEB Ride-Thru 2 (H1-□□ = 7A or 7B), and Intelligent Stall Prevention during deceleration (L3-04 = 2) to control the DC bus voltage.

| No. | Name | Setting Range | Default |
|-------|--------------------------------|---------------|---------|
| L3-20 | DC Bus Voltage Adjustment Gain | 0.00 to 5.00 | 1.00 |

Adjustment for Single Drive KEB 2 (L2-29 = 1) and Intelligent Stall Prevention During Deceleration

- Increase this setting slowly in steps of 0.1 if overvoltage or undervoltage occurs at the beginning of deceleration.
- Decrease this setting if there is a fair amount of speed or torque ripple.

Adjustment for Overvoltage Suppression

- Increase this setting slowly in steps of 0.1 if overvoltage suppression is enabled (L3-11 = 1) and a sudden increase in a regenerative load causes an overvoltage fault.
- Decrease this setting if there is a fair amount of speed or torque ripple.

■ L3-21: Accel/Decel Rate Calculation Gain

Determines the proportional gain used by overvoltage suppression (L3-11 = 1), Single Drive KEB 2 (L2-29 = 1), and Intelligent Stall Prevention during deceleration (L3-04 = 2) to calculate acceleration and deceleration rates.

| No. | Name | Setting Range | Default |
|-------|-----------------------------------|---------------|---------|
| L3-21 | Accel/Decel Rate Calculation Gain | 0.10 to 10.00 | 1.00 |

Adjustment for Single Drive KEB 2 (L2-29 = 1) and Intelligent Stall Prevention During Deceleration

- Reduce L3-21 in steps of 0.05 if there is a fairly large speed or current ripple.
- Small reductions of L3-21 can help solve problems with overvoltage and overcurrent.
- Decreasing this setting too much can cause slow DC bus voltage control response and may also lengthen deceleration times beyond optimal levels.

Adjustment for Overvoltage Suppression

- Increase this setting in steps of 0.1 if overvoltage occurs as a result of a regenerative load when overvoltage suppression is enabled (L3-11 = 1).
- Decrease L3-21 in steps of 0.05 if there is a fairly large speed ripple when overvoltage suppression is enabled.

■ L3-23: Automatic Reduction Selection for Stall Prevention during Run

Reduces the Stall Prevention during run level in the constant power range.

5.8 L: Protection Functions

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------|
| L3-23 | Automatic Reduction Selection for Stall Prevention During Run | 0, 1 | 0 |

Setting 0: Disabled

The level set in L3-06 is used throughout the entire speed range.

Setting 1: Enabled

The Stall Prevention level during run is reduced in the constant power range. The lower limit will be 40% of L3-06.

■ L3-24: Motor Acceleration Time for Inertia Calculations

Sets the time to accelerate the motor from stop to the maximum speed at motor rated torque. Set this parameter when using Single Drive KEB 2 (L2-29 = 1), Intelligent Stall Prevention during Deceleration (L3-04 = 2), or the Overvoltage Suppression function (L3-11 = 1).

| No. | Name | Setting Range | Default |
|-------|--|-------------------|-------------------------|
| L3-24 | Motor Acceleration Time for Inertia Calculations | 0.001 to 10.000 s | Determined by o2-04 </> |

<1> Parameter L3-24 is defaulted for a Yaskawa standard 4-pole motor. During Auto-Tuning, L3-24 will be initialized to a Yaskawa standard 4-pole motor if parameter E2-11 is changed.

Manual Parameter Setup

Make the calculations in the formula below:

$$L3-24 = \frac{2 \cdot \pi \cdot J [\text{kgm}^2] \cdot n_{\text{rated}} [\text{r/min}]}{60 \cdot T_{\text{rated}} [\text{Nm}]}$$

Calculate the rated torque in the formula below:

$$T_{\text{rated}} [\text{Nm}] = \frac{60 \cdot P_{\text{Motor}} [\text{kW}] \cdot 10^3}{2 \cdot \pi \cdot n_{\text{rated}} [\text{r/min}]}$$

■ L3-25: Load Inertia Ratio

Determines the ratio between the rotor inertia and the load. Set this parameter when using Single Drive KEB 2 (L2-29 = 1), Intelligent Stall Prevention during deceleration (L3-04 = 2), or the overvoltage suppression function (L3-11 = 1).

| No. | Name | Setting Range | Default |
|-------|--------------------|---------------|---------|
| L3-25 | Load Inertia Ratio | 1.0 to 1000.0 | 1.0 |

When set incorrectly, a fairly large current ripple can result during Single Drive KEB 2 (L2-29 = 1). This may cause overvoltage suppression (L3-11 = 1) or other faults such as ov, Uv1, and oC.

Manual Parameter Setup

Calculate parameter L3-25 in the formula below:

$$L3-25 = \frac{\text{Machine Inertia}}{\text{Motor Inertia}}$$

■ L3-26: Additional DC Bus Capacitors

Sets the capacity of any additionally installed DC bus capacitors. This data is used in calculations for Single Drive KEB Ride-Thru 2. Adjust this setting only if external capacity is connected to the DC bus and Single Drive KEB 2 is used.

| No. | Name | Setting Range | Default |
|-------|------------------------------|---------------|---------|
| L3-26 | Additional DC Bus Capacitors | 0 to 65000 μF | 0 μF |

■ L3-27: Stall Prevention Detection Time

Sets a delay time from when the Stall Prevention level is reached and the actual Stall Prevention function is activated.

| No. | Name | Setting Range | Default |
|-------|---------------------------------|---------------|---------|
| L3-27 | Stall Prevention Detection Time | 0 to 5000 ms | 50 ms |

◆ L4: Speed Detection

These parameters set up the speed agree and speed detection functions that can be assigned to the multi-function output terminals.

■ L4-01, L4-02: Speed Agreement Detection Level and Detection Width

Parameter L4-01 sets the detection level for the digital output functions Speed agree 1, User-set speed agree 1, Frequency detection 1, and Frequency detection 2.

Parameter L4-02 sets the hysteresis level for these functions.

| No. | Name | Setting Range | Default |
|-------|---------------------------------|-----------------|---------|
| L4-01 | Speed Agreement Detection Level | 0.0 to 400.0 Hz | 0.0 Hz |
| L4-02 | Speed Agreement Detection Width | 0.0 to 20.0 Hz | 2.0 Hz |

Refer to H2-01 to H2-03: Terminal M1-M2, M3-M4, and MD-ME-MF Function Selection on page 215, Settings 2, 3, 4, and 5.

■ L4-03, L4-04: Speed Agreement Detection Level and Detection Width (+/-)

Parameter L4-03 sets the detection level for the digital output functions Speed agree 2, User-set speed agree 2, Frequency detection 3, and Frequency detection 4.

Parameter L4-04 sets the hysteresis level for these functions.

| No. | Name | Setting Range | Default |
|-------|---------------------------------------|--------------------|---------|
| L4-03 | Speed Agreement Detection Level (+/-) | -400.0 to 400.0 Hz | 0.0 Hz |
| L4-04 | Speed Agreement Detection Width (+/-) | 0.0 to 20.0 Hz | 2.0 Hz |

Refer to H2-01 to H2-03: Terminal M1-M2, M3-M4, and MD-ME-MF Function Selection on page 215, Settings 13, 14, 15, and 16.

■ L4-05: Frequency Reference Loss Detection Selection

The drive can detect a loss of an analog frequency reference from input A1, A2, or A3. Frequency reference loss is detected when the frequency reference drops below 10% of the reference or below 5% of the maximum output frequency within 400 ms. Restoring the analog frequency reference to the L4-06 value or higher before loss occurs will clear the frequency reference loss status.

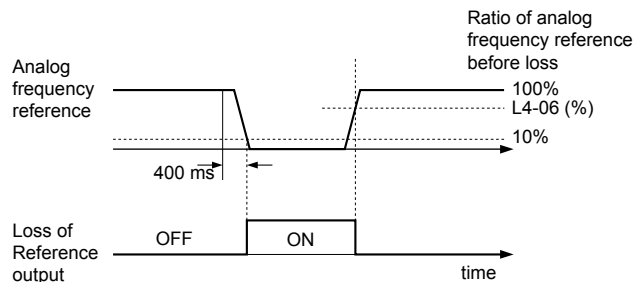


Figure 5.80 Loss of Reference Function

Set H2-01, H2-02, or H2-03 to C for a digital output to trigger when frequency reference loss occurs. Refer to Setting C: Frequency Reference Loss on page 219 for details on setting the output function.

Parameter L4-05 selects the operation when a frequency reference loss is detected.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| L4-05 | Frequency Reference Loss Detection Selection | 0, 1 | 0 |

Setting 0: Operate following the frequency reference

Setting 1: Continue operation with reduced frequency reference

The drive will continue operation at the frequency reference value set to parameter L4-06. When the external frequency reference value is restored, the operation is continued with the frequency reference.

5.8 L: Protection Functions

■ L4-06: Frequency Reference at Reference Loss

Sets the frequency reference level at which the drive runs when L4-05 = 1 and when detecting a reference loss. The value is set as a percentage of the frequency reference before the loss was detected.

| No. | Name | Setting Range | Default |
|-------|---------------------------------------|---------------|---------|
| L4-06 | Frequency Reference at Reference Loss | 0.0 to 100.0% | 80.0% |

■ L4-07: Speed Agree Detection Selection

Determines when frequency detection is active using parameters L4-01 through L4-04.

| No. | Name | Setting Range | Default |
|-------|---------------------------------|---------------|---------|
| L4-07 | Speed Agree Detection Selection | 0, 1 | 0 |

Setting 0: No Detection during baseblock

Setting 1: Detection always enabled

◆ L5: Fault Restart

After a fault has occurred, Fault Restart attempts to automatically restart the motor and continue operation instead of stopping. The drive can perform a self-diagnostic check and resume the operation after a fault has occurred. If the self-check is successful and the cause of the fault has disappeared, the drive restarts by first performing Speed Search (*Refer to b3: Speed Search on page 153* for details).

- Note:**
1. The wiring sequence should remove the Forward/Reverse command when a fault is triggered and output is shut off.
 2. When the Forward/Reverse command is removed, the drive can perform a self-diagnostic check and attempt to restart the fault automatically.

WARNING! *Sudden Movement Hazard. Do not use the fault restart function in lifting applications. Fault restart may cause the machine to drop the load, which could result in death or serious injury.*

The drive can attempt to restart itself following the faults listed below.

| Fault | Name | Fault | Name |
|-------|-------------------|-------|--------------------------|
| GF | Ground Fault | oL4 | Overtorque 2 |
| LF | Output Open Phase | ov | DC Bus Overvoltage |
| oC | Overcurrent | PF | Input Phase Loss |
| oH1 | Drive Overheat | rH | Braking Resistor Fault |
| oL1 | Motor Overload | rr | Braking Transistor Fault |
| oL2 | Drive Overload | Uv1 | DC Bus Undervoltage <1> |
| oL3 | Overtorque 1 | | |

<1> When L2-01 is set to 1 through 4 (continue operation during momentary power loss)

Use parameters L5-01 to L5-05 to set up automatic fault restart.

Set H2-01, H2-02, or H2-03 to 1E. to output a signal during fault restart.

■ L5-01: Number of Auto Restart Attempts

Sets the number of times that the drive may attempt to restart itself.

Parameter L5-05 determines the method of incrementing the restart counter. When the counter reaches the number set to L5-01, the operation stops and the fault must be manually cleared and reset.

The restart counter is incremented at each restart attempt, regardless of whether the attempt was successful. When the counter reaches the number set to L5-01, the operation stops and the fault must be manually cleared and reset.

The number of fault restarts is reset to zero when:

- The drive operates normally for 10 minutes following a fault restart.
- A fault is cleared manually after protective functions are triggered.
- The power supply is cycled.

| No. | Name | Setting Range | Default |
|-------|---------------------------------|---------------|---------|
| L5-01 | Number of Auto Restart Attempts | 0 to 10 Times | 0 Times |

■ L5-02: Auto Restart Fault Output Operation Selection

Determines if a fault output is triggered ($H2-\square\square = E$) when the drive attempts to restart.

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------|
| L5-02 | Auto Restart Fault Output Operation Selection | 0, 1 | 0 |

Setting 0: No Fault Output

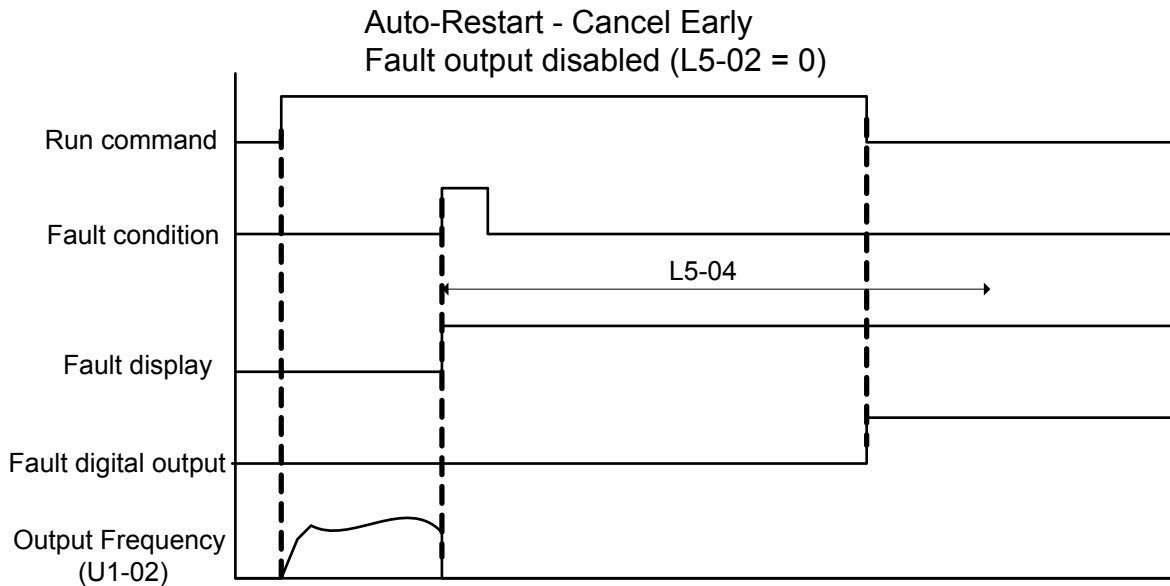


Figure 5.81 Auto Restart Cancel Early

Setting 1: Fault Output Is Set

■ L5-04: Fault Reset Interval Time

Determines the amount of time to wait between restart attempts when parameter L5-05 is set to 1.

| No. | Name | Setting Range | Default |
|-------|---------------------------|----------------|---------|
| L5-04 | Fault Reset Interval Time | 0.5 to 600.0 s | 10.0 s |

■ L5-05: Fault Reset Operation Selection

| No. | Name | Setting Range | Default |
|-------|---------------------------------|---------------|---------|
| L5-05 | Fault Reset Operation Selection | 0, 1 | 0 |

Setting 0: Count Successful Restarts

The drive will continuously attempt to restart. If it restarts successfully, the restart counter is increased. This operation is repeated each time a fault occurs until the counter reaches the value set to L5-01.

Setting 1: Count Restart Attempts

The drive will attempt to restart using the time interval set to parameter L5-04. A record is kept of the number of attempts to restart to the drive, regardless of whether those attempts were successful. When the number of attempted restarts exceeds the value set to L5-01, the drive stops attempting to restart.

◆ L6: Torque Detection

The drive provides two independent torque detection functions that trigger an alarm or fault signal when the load is too heavy (oL), or suddenly drops (UL). These functions are set up using the L6- $\square\square$ parameters. Program the digital outputs as shown below to indicate the underload or overload condition to an external device:

Note: When overtorque occurs in the application, the drive may stop due to overcurrent (oC) or overload (oL1). To prevent the drive from stopping, use torque detection to indicate an overload situation to the controller before oC or oL1 occur. Use undertorque detection to discover application problems like a torn belt, a pump shutting off, or other similar trouble.

5.8 L: Protection Functions

| H2-01, H2-02, H2-03 Setting | Description |
|-----------------------------|---|
| B | Torque detection 1, N.O. (output closes when overload or underload is detected) |
| 17 | Torque detection 1, N.C. (output opens when overload or underload is detected) |
| 18 | Torque detection 2, N.O. (output closes when overload or underload is detected) |
| 19 | Torque detection 2, N.C. (output opens when overload or underload is detected) |

Figure 5.82 and Figure 5.83 illustrate the functions of overtorque and undertorque detection.

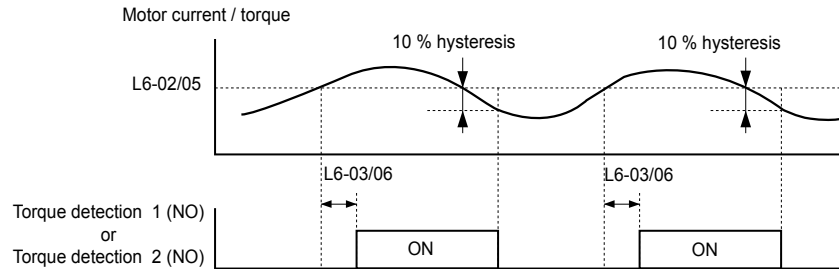


Figure 5.82 Overtorque Detection Operation

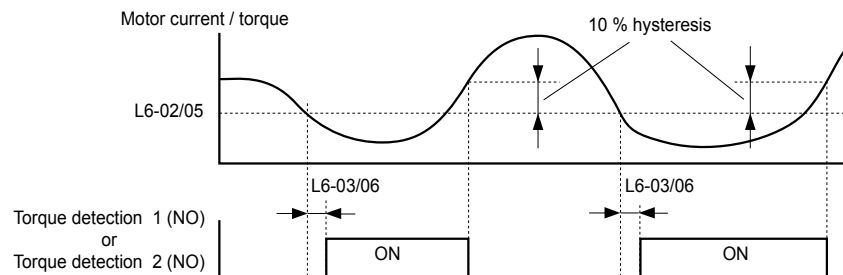


Figure 5.83 Undertorque Detection Operation

- Note:**
1. The torque detection function uses a hysteresis of 10% of the drive rated output current and motor rated torque.
 2. The level is set as a percentage of the drive rated output current.

■ L6-01, L6-04: Torque Detection Selection 1, 2

The torque detection function is triggered when the current or torque exceed the levels set to L6-02 and L6-05 for longer than the times set to L6-03 and L6-06. L6-01 and L6-04 select the conditions for detection and the operation that follows.

| No. | Name | Setting Range | Default |
|-------|------------------------------|---------------|---------|
| L6-01 | Torque Detection Selection 1 | 0 to 12 | 0 |
| L6-04 | Torque Detection Selection 2 | 0 to 8 | 0 |

Setting 0: Disabled

Setting 1: oL3, oL4 at speed agree (Alarm)

Overtorque detection is active only when the output speed is equal to the frequency reference (i.e., no detection during acceleration and deceleration). The operation continues after detecting overtorque and triggering an oL3/oL4 alarm.

Setting 2: oL3, oL4 at run (Alarm)

Overtorque detection works as long as the Run command is active. The operation continues after detecting overtorque and triggering an oL3/oL4 alarm.

Setting 3: oL3, oL4 at speed agree (Fault)

Overtorque detection is active only when the output speed is equal to the frequency reference, i.e., no detection during acceleration and deceleration. The operation stops and triggers an oL3/oL4 fault.

Setting 4: oL3, oL4 at run (Fault)

Overtorque detection works as long as a Run command is active. The operation stops and triggers an oL3/oL4 fault.

Setting 5: UL3, UL4 at speed agree (Alarm)

Undertorque detection is active only when the output speed is equal to the frequency reference, i.e., no detection during acceleration and deceleration. The operation continues after detecting overtorque and triggering a UL3/UL4 alarm.

Setting 6: UL3, UL4 at Run (Alarm)

Undertorque detection works as long as the Run command is active. The operation continues after detecting overtorque and triggering a UL3/UL4 alarm.

Setting 7: UL3, UL4 at Speed Agree (Fault)

Undertorque detection is active only when the output speed is equal to the frequency reference, i.e., no detection during acceleration and deceleration. The operation stops and triggers a UL3/UL4 fault.

Setting 8: UL3, UL4 at run (Fault)

Undertorque detection works as long as a Run command is active. The operation stops and triggers a UL3/UL4 fault.

Setting 9: UL6 at speed agree (Alarm)**Setting 10: UL6 during run (Alarm)****Setting 11: UL6 at speed agree (Fault)****Setting 12: UL6 during run (Fault)****■ L6-02, L6-05: Torque Detection Level 1, 2**

These parameters set the detection levels for torque detection functions 1 and 2 as a percentage of the drive rated output current.

| No. | Name | Setting Range | Default |
|-------|--------------------------|---------------|---------|
| L6-02 | Torque Detection Level 1 | 0 to 300% | 15% |
| L6-05 | Torque Detection Level 2 | 0 to 300% | 150% |

Note: The torque detection level 1 (L6-02) can also be supplied by an analog input terminal set to H3-□□ = 7. Here, the analog value has priority and the setting in L6-02 is disregarded. Torque detection level 2 (L6-05) cannot be set by an analog input.

■ L6-03, L6-06: Torque Detection Time 1, 2

These parameters determine the time required to trigger an alarm or fault after exceeding the levels in L6-02 and L6-05.

| No. | Name | Setting Range | Default |
|-------|-------------------------|---------------|---------|
| L6-03 | Torque Detection Time 1 | 0.0 to 10.0 s | 10.0 s |
| L6-06 | Torque Detection Time 2 | 0.0 to 10.0 s | 0.1 s |

■ L6-13: Motor Underload Protection Selection

Sets the motor underload protection (UL6) based on motor load.

| No. | Name | Setting Range | Default |
|-------|--------------------------------------|---------------|---------|
| L6-13 | Motor Underload Protection Selection | 0, 1 | 0 |

Setting 0: Base frequency enable**Setting 1: Max frequency enable****■ L6-14: Motor Underload Protection Level at Minimum Frequency**

Sets the motor underload protection (UL6) based on motor load.

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------|
| L6-14 | Motor Underload Protection Level at Minimum Frequency | 0 to 300% | 15% |

◆ L8: Drive Protection**■ L8-01: Internal Dynamic Braking Resistor Protection Selection (ERF type)**

Selects the dynamic braking resistor protection when using an optional heatsink mounted braking resistor (ERF type, 3% ED).

Note:

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------|
| L8-01 | Internal Dynamic Braking Resistor Protection Selection (ERF type) | 0, 1 | 0 |

5.8 L: Protection Functions

Setting 0: Disabled

Disables braking resistor protection. Use this setting for any dynamic braking option other than the Yaskawa ERF-type resistor.

Setting 1: Enabled

Enables protection for Yaskawa ERF-type resistors.

■ L8-02: Overheat Alarm Level

Sets the overheat alarm (oH) detection level.

The drive outputs an alarm when the heatsink temperature exceeds the overheat alarm level. If the drive is set to continue operation after this alarm occurs (L8-03 = 4) and the temperature reaches the overheat fault level, the drive will trigger an oH1 fault and stop operation.

When an output terminal is set for the oH pre-alarm (H2-□□ = 20), the switch will close when the heatsink temperature rises above L8-02.

| No. | Name | Setting Range | Default |
|-------|----------------------|---------------|---------------------|
| L8-02 | Overheat Alarm Level | 50 to 150 °C | Determined by o2-04 |

■ L8-03: Overheat Pre-Alarm Operation Selection

Sets the operation when an overheat pre-alarm is detected.

Note: Change L8-03 setting only when necessary.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| L8-03 | Overheat Pre-Alarm Operation Selection | 0 to 4 | 3 |

Setting 0: Ramp to Stop

If an overheat alarm occurs, the drive decelerates to stop using the currently selected deceleration time. If a digital output is programmed for “fault” (H2-□□ = E), this output will be triggered.

Setting 1: Coast to Stop

If an overheat alarm occurs, the drive switches off the output and the motor coasts to stop. If a digital output is programmed for “fault” (H2-□□ = E), this output will be triggered.

Setting 2: Fast Stop

If an overheat alarm occurs, the drive decelerates to stop using the Fast Stop time (C1-09). If a digital output is programmed for “fault” (H2-□□ = E), this output will be triggered.

Setting 3: Alarm Only

If an overheat alarm occurs, an alarm is output and the drive continues operation.

Setting 4: Operation with Reduced Speed

If an overheat alarm occurs, the operation continues with the speed reduced to the level set to parameter L8-19. If the oH alarm is still present after 10 s, the speed is reduced again. The amount of speed reduction depends on how often the alarm repeats. If the oH alarm disappears while the drive is operating at a reduced speed, the drive will switch to the previous speed in 10 s increments until reaching base frequency. *Figure 5.84* explains the operation with reduced speed during an oH alarm. A digital output programmed for 4D is switched when the oH alarm is still active after ten reduction cycles.

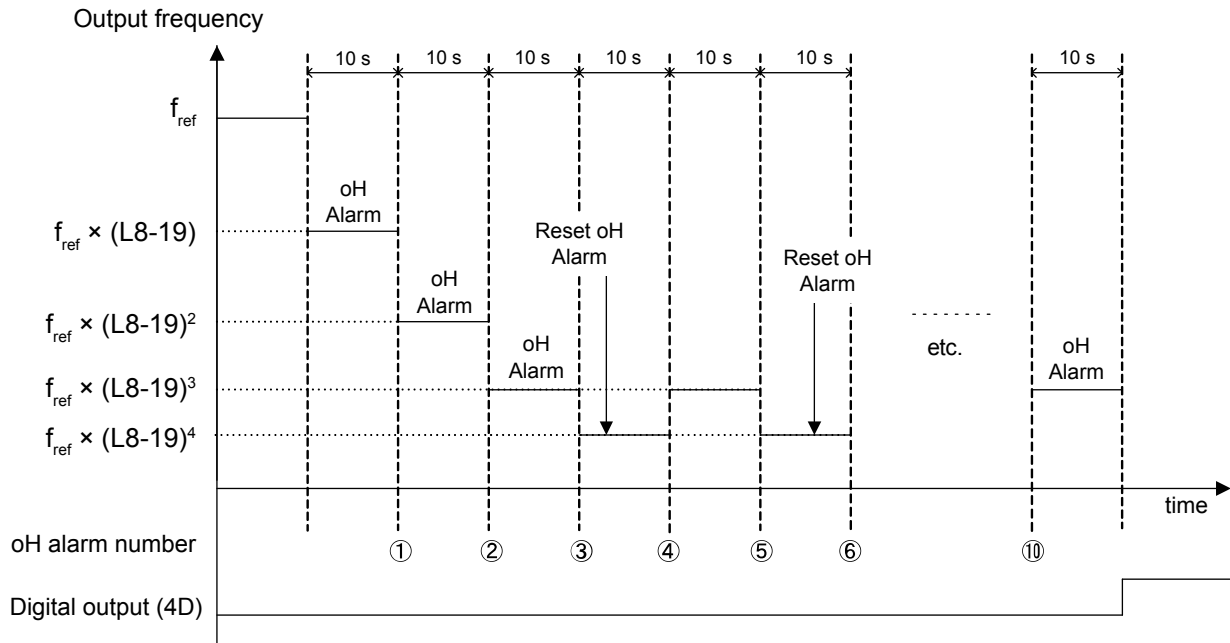


Figure 5.84 Output Frequency Reduction During Overheat Alarm

■ **L8-19: Frequency Reduction Rate during Overheat Pre-Alarm**

Specifies the output frequency reduction when L8-03 is set to 4 and an oH alarm is present.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| L8-19 | Frequency Reduction Rate During Overheat Pre-Alarm | 0.1 to 0.9 | 0.8 |

■ **L8-05: Input Phase Loss Protection Selection**

Enables or disables the input phase loss detection.

| No. | Name | Setting Range | Default |
|-------|---------------------------------------|---------------|---------|
| L8-05 | Input Phase Loss Protection Selection | 0, 1 | 1 |

Setting 0: Disabled

Setting 1: Enabled

Enables input phase loss detection. Since measuring the DC bus ripple detects input phase loss, a power supply voltage imbalance or main circuit capacitor deterioration may also trigger a phase loss fault (PF).

Detection is disabled if:

- The drive is decelerating.
- No Run command is active.
- Output current is less than or equal to 30% of the drive rated current.

■ **L8-07: Output Phase Loss Protection Selection**

Enables or disables the output phase loss detection triggered when the output current falls below 5% of the drive rated current.

Note: Output phase loss detection can mistakenly be triggered if the motor rated current is very small compared to the drive rating. Disable this parameter in such cases.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| L8-07 | Output Phase Loss Protection Selection | 0 to 2 | 1 |

Setting 0: Disabled

Setting 1: Fault when One Phase Is Lost

An output phase loss fault (LF) is triggered when one output phase is lost. The output shuts off and the motor coasts to stop.

5.8 L: Protection Functions

Setting 2: Fault when Two Phases Are Lost

An output phase loss fault (LF) is triggered when two or more output phases are lost. The output shuts off and the motor coasts to stop.

■ L8-09: Output Ground Fault Detection Selection

Enables or disables the output ground fault detection.

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------|
| L8-09 | Output Ground Fault Detection Selection | 0, 1 | 1 |

Setting 0: Disabled

Ground faults are not detected.

Setting 1: Enabled

A ground fault (GF) is triggered when high leakage current or a ground short circuit occurs in one or two output phases.

■ L8-10: Heatsink Cooling Fan Operation Selection

Selects the heatsink cooling fan operation.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| L8-10 | Heatsink Cooling Fan Operation Selection | 0, 1 | 0 |

Setting 0: Run with Timer

The fan is switched on when a Run command is active and switched off with the delay set to parameter L8-11 after releasing the Run command. This setting extends the fan lifetime.

Setting 1: Run Always

The fan runs when power is supplied to the drive.

■ L8-11: Heatsink Cooling Fan Off-Delay Time

Sets the cooling fan switch off-delay time if parameter L8-10 is set to 0.

| No. | Name | Setting Range | Default |
|-------|-------------------------------------|---------------|---------|
| L8-11 | Heatsink Cooling Fan Off-Delay Time | 0 to 300 s | 60 s |

■ L8-12: Ambient Temperature Setting

Automatically adapts the drive rated current to safe values when used with parameter L8-35. This eliminates the need to reduce the drive rated current when the temperature where the drive is mounted is above the specified values. [Refer to Temperature Derating on page 428](#) for details.

| No. | Name | Setting Range | Default |
|-------|-----------------------------|---------------|---------|
| L8-12 | Ambient Temperature Setting | -10 to +50 °C | 40 °C |

■ L8-15: oL2 Characteristics Selection at Low Speeds

Selects whether the drive overload capability (oL fault detection level) is reduced at low speeds to prevent premature output transistor failures. Set this parameter to 0 (Protection disabled at low speed) when protection is activated for an oL2 fault for a light load at low speed.

- Note:**
1. Contact Yaskawa before using the drive for applications for which the setting is 0 (disabled).
 2. Do not set this parameter to 0 (disabled) in V/f or OLV control.
 3. Do not set this parameter to 0 (disabled) in models 4□0302 to 4□0930.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| L8-15 | oL2 Characteristics Selection at Low Speed | 0, 1 | 1 |

Setting 0: oL2 (Drive Overload) Characteristics Disabled at Low Speed

The overload protection level is not reduced. Frequently operating the drive with high output current at low speed can lead to premature drive faults.

Setting 1: oL2 (Drive Overload) Characteristics Enabled at Low Speed

The overload protection level (oL2 fault detection level) is automatically reduced at speeds below 6 Hz. At zero speed, the overload is derated by 50%.

■ L8-18: Software Current Limit Selection

Enables and disables the Software Current Limit (CLA) protection function to prevent main circuit transistor failures caused by high current.

Note: Do not change this setting unless absolutely necessary.

| No. | Name | Setting Range | Default |
|-------|----------------------------------|---------------|---------------------|
| L8-18 | Software Current Limit Selection | 0, 1 | Determined by A1-02 |

Setting 0: Software CLA Disabled

The drive may trip on an oC fault if the load is too heavy or the acceleration is too short.

Setting 1: Software CLA Enabled

When the Software CLA current level is reached, the drive reduces the output voltage to reduce the current. Normal operation continues when the current level drops below the Software CLA level.

■ L8-32: Cooling Fan Failure Selection

Determines drive operation when a FAn fault occurs.

| No. | Name | Setting Range | Default |
|-------|-------------------------------|---------------|---------|
| L8-32 | Cooling Fan Failure Selection | 0 to 4 | 1 |

Setting 0: Ramp to Stop

The drive stops the motor using the deceleration time set in parameter C1-02.

Setting 1: Coast to Stop

The drive output is switched off and the motor coasts to a stop.

Setting 2: Fast Stop

The drive stops the motor using the Fast stop time set in parameter C1-09.

Setting 3: Alarm Only

The operation is continued and a FAn alarm is displayed on the digital operator.

Setting 4: Operation with Reduced Speed

The operation is continued, but the speed is reduced to the level set in parameter L8-19.

Note: "FAn" is detected as an error when Settings 0 or 2 are selected; it is detected as an alarm when Settings 3 or 4 are selected.

■ L8-35: Installation Method Selection

Selects the type of installation for the drive and changes the drive overload (oL2) limits accordingly. *Refer to Temperature Derating on page 428* for details.

- Note:**
1. Initialization does not reset this parameter.
 2. The value is preset to the appropriate value when the drive is shipped. Change the value only when using Side-by-Side installation or when mounting a standard drive with the heatsink outside the cabinet.

| No. | Name | Setting Range | Default |
|-------|-------------------------------|---------------|---------|
| L8-35 | Installation Method Selection | 0 to 3 | <I> |

<I> Default setting is determined by drive model.

Setting 2: Model code 2A0004 to 2A0211, 4A0002 to 4A0165, and 5A0003 to 5A0242

Setting 0: Model code 2A0250 to 2A0415 and 4A0208 to 4A1200.

Setting 0: IP00/Open-Chassis Enclosure

For an Open Type enclosure drive installed with at a minimum of 30 mm space to the next drive or a cabinet wall.

Setting 1: Side-by-Side Mounting

For drives mounted according to Yaskawa Side-by-Side specifications (requires 2 mm between drives).

5.8 L: Protection Functions

Setting 2: IP20/NEMA 1, UL Type 1 Enclosure

For drives compliant with IP20/NEMA 1, UL Type 1 enclosure specifications.

Setting 3: External Heatsink Installation

For a standard drive mounted with the heatsink outside the cabinet or enclosure panel.

■ L8-38: Carrier Frequency Reduction Selection

Selects the operation of the carrier frequency reduction function. Reduces the carrier frequency when the output current exceeds a certain level. This temporarily increases the overload capability (oL2 detection), allowing the drive to run through transient load peaks without tripping.

| No. | Name | Setting Range | Default |
|-------|---------------------------------------|---------------|---------|
| L8-38 | Carrier Frequency Reduction Selection | 0 to 2 | 2 |

Setting 0: Disabled

No carrier frequency reduction at high current.

Setting 1: Enabled for output frequencies below 6 Hz

The carrier frequency is reduced at speeds below 6 Hz when the current exceeds 100% of the drive rated current. The drive returns to the normal carrier frequency when the current falls below 88% or the output frequency exceeds 7 Hz.

Setting 2: Enabled for entire frequency range

The carrier frequency is reduced at the following speeds:

- Below 6 Hz when the current exceeds 100% of the drive rated current.
- Above 7 Hz when the current exceeds 112% of the drive rated current.

The drive uses the delay time set in parameter L8-40 and a hysteresis of 12% when switching the carrier frequency back to the set value.

■ L8-40: Carrier Frequency Reduction Off-Delay Time

Sets a hold time before returning to the original carrier frequency setting after the carrier frequency has been temporarily derated as determined by L8-38. The carrier frequency reduction function is disabled when this value is 0.00 s.

| No. | Name | Setting Range | Default |
|-------|--|----------------|---------|
| L8-40 | Carrier Frequency Reduction Off-Delay Time | 0.00 to 2.00 s | 0.50 s |

■ L8-41: High Current Alarm Selection

Triggers a high current alarm (HCA) when the output current exceeds 150% of the drive rated current.

| No. | Name | Setting Range | Default |
|-------|------------------------------|---------------|---------|
| L8-41 | High Current Alarm Selection | 0, 1 | 0 |

Setting 0: Disabled

No alarm is detected.

Setting 1: Enabled

An alarm is triggered when the output current exceeds 150% of the drive rated current. A digital output set for an alarm (H2-□□ = 10) will close.

■ L8-55: Internal Braking Transistor Protection

Enables or disables protection for the internal braking transistor.

Note: This parameter is not available in models 4A0930 and 4A1200.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| L8-55 | Internal Braking Transistor Protection | 0, 1 | 1 |

Setting 0: Disabled

Disable braking transistor protection when not using the internal braking transistor, including the following instances:

- When using a regen converter such as DC.
- When using a regen unit such as RC5.
- When using external braking transistor options like CDBR units.

- When using the drive in common DC bus applications and the internal braking unit is not installed. Enabling L8-55 under such conditions can incorrectly trigger a braking resistor fault (rF).

Setting 1: Enabled

Enable L8-55 when connecting a braking resistor or a braking resistor unit to the drive built-in braking transistor. Models 2A0004 to 2A0138, 4A0002 to 4A0072, and 5A0003 to 5A0052 come with a built-in braking transistor.

■ L8-78: Power Unit Output Phase Loss Protection

Protects the power unit from phase loss.

Note: This parameter is only available in models 4A0930 and 4A1200.

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------|
| L8-78 | Power Unit Output Phase Loss Protection | 0, 1 | 1 |

Setting 0: Disabled

Setting 1: Enabled

■ L8-93: LSo Detection Time at Low Speed

Sets the amount of time until baseblock is executed after LSo has been detected at low speed.

A setting of 0.0 s disables this parameter.

| No. | Name | Setting Range | Default |
|-------|---------------------------------|---------------|---------|
| L8-93 | LSo Detection Time at Low Speed | 0.0 to 10.0 s | 1.0 s |

■ L8-94: LSo Detection Level at Low Speed

Determines the detection level of STo at low speed. Set as a percentage of the maximum frequency (E1-04).

| No. | Name | Setting Range | Default |
|-------|----------------------------------|---------------|---------|
| L8-94 | LSo Detection Level at Low Speed | 0 to 10% | 3% |

■ L8-95: Average LSo Frequency at Low Speed

Sets the average number of times LSo can occur at low speed.

| No. | Name | Setting Range | Default |
|-------|------------------------------------|---------------|----------|
| L8-95 | Average LSo Frequency at Low Speed | 1 to 50 times | 10 times |

5.9 n: Special Adjustments

These parameters control a variety of specialized adjustments and functions, including Hunting Prevention, High Slip Braking, and Overexcitation Braking.

◆ n1: Hunting Prevention

Hunting Prevention prevents the drive from hunting as a result of low inertia and operating with light load. Hunting often occurs with a high carrier frequency and an output frequency below 30 Hz.

■ n1-01: Hunting Prevention Selection

Enables or disables the Hunting Prevention function.

Note: This function is available only when using V/f Control. Disable Hunting Prevention when drive response is more important than suppressing motor oscillation. This function may be disabled without problems in applications with high inertia loads or relatively heavy loads.

| No. | Name | Setting Range | Default |
|-------|------------------------------|---------------|---------|
| n1-01 | Hunting Prevention Selection | 0, 1 | 1 |

Setting 0: Disabled

Setting 1: Enabled

■ n1-02: Hunting Prevention Gain Setting

Sets the gain for the Hunting Prevention Function.

| No. | Name | Setting Range | Default |
|-------|---------------------------------|---------------|---------|
| n1-02 | Hunting Prevention Gain Setting | 0.00 to 2.50 | 1.00 |

Although this parameter rarely needs to be changed, it may require adjustment in the following situations:

- If the motor vibrates while lightly loaded and n1-01 = 1, increase the gain by 0.1 until vibration ceases.
- If the motor stalls while n1-01 = 1, decrease the gain by 0.1 until the stalling ceases.

■ n1-03: Hunting Prevention Time Constant

Determines the responsiveness of the Hunting Prevention function (affects the primary delay time for Hunting Prevention).

| No. | Name | Setting Range | Default |
|-------|----------------------------------|---------------|---------------------|
| n1-03 | Hunting Prevention Time Constant | 0 to 500 ms | Determined by o2-04 |

Although this parameter rarely needs to be changed, it may require adjustment in the following situations:

- Increase this value for applications with a large load inertia. A higher setting leads to slower response, which can result in oscillation at lower frequencies.
- Lower this setting if oscillation occurs at low speed.

■ n1-05: Hunting Prevention Gain while in Reverse

This parameter functions the same as n1-02, except it is used when rotating in reverse. See the explanation for n1-02.

Note: n1-02 is enabled for forward and reverse operation when n1-05 = 0.0 ms.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| n1-05 | Hunting Prevention Gain while in Reverse | 0.00 to 2.50 | 0.00 |

◆ n3: High Slip Braking (HSB) and Overexcitation Braking

■ High Slip Braking (V/f)

HSB works in V/f Control only and decreases the stopping time compared to normal deceleration without using dynamic braking options. HSB reduces the output frequency in large steps to stop the motor and produce a high slip, which dissipates the regenerative energy created from decelerating the load in the motor windings. Due to the increased temperature of the motor windings, do not use HSB to frequently stop the motor. The duty cycle should be around 5% or lower.

Notes on Using High Slip Braking

- The set deceleration time is ignored during HSB. Use Overexcitation Deceleration 1 (L3-04 = 4) to stop the motor within a specified time.
- Braking time varies based on the load inertia and motor characteristics.
- Enabling HSB and KEB Ride-Thru simultaneously will trigger an oPE03 error.
- HSB must be triggered by a digital input set to H1-□□ = 68. After the HSB command is given, the drive will not restart until the motor is completely stopped and the Run command is cycled.
- Use parameters n3-01 through n3-04 to adjust HSB.

■ n3-01: High Slip Braking Deceleration Frequency Width

Sets the step width for frequency reduction during HSB. Increase n3-01 if DC bus overvoltage (ov) occurs during HSB.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| n3-01 | High Slip Braking Deceleration Frequency Width | 1 to 20% | 5% |

■ n3-02: High Slip Braking Current Limit

Sets the maximum current to be output during an HSB stop as a percentage of motor rated current (E2-01). Reducing the current limit increases the deceleration time. This value must not exceed the drive overload capacity.

- Lower this setting if overvoltage occurs during HSB.
- Lower this setting if motor current is too high during HSB. High current can damage the motor due to overheat.
- The default setting is 120% when the drive is set for Normal Duty.

| No. | Name | Setting Range | Default |
|-------|---------------------------------|---------------|---------------------|
| n3-02 | High Slip Braking Current Limit | 100 to 200% | Determined by L8-38 |

■ n3-03: High Slip Braking Dwell Time at Stop

When the motor reaches a relatively low speed at the end of HSB, the output frequency is kept at the minimum output frequency set to E1-09 for the time set to n3-03. Increase this time if the inertia is very high and the motor coasts after HSB is complete.

| No. | Name | Setting Range | Default |
|-------|--------------------------------------|---------------|---------|
| n3-03 | High Slip Braking Dwell Time at Stop | 0.0 to 10.0 s | 1.0 s |

■ n3-04: High Slip Braking Overload Time

Sets the time required for an HSB overload fault (oL7) to occur when the drive output frequency does not change during an HSB stop due to excessive load inertia or the load rotating the motor. To protect the motor from overheat, the drive trips with an oL7 fault if these conditions last longer than the time set in n3-04.

| No. | Name | Setting Range | Default |
|-------|---------------------------------|---------------|---------|
| n3-04 | High Slip Braking Overload Time | 30 to 1200 s | 40 s |

■ Overexcitation Deceleration (Induction Motors)

Increases the flux during deceleration and allows shorter deceleration time settings without the use of a braking resistor. Enabled by setting L3-04 to 4 or 5. *Refer to L3-04: Stall Prevention Selection during Deceleration on page 249.*

Notes on Overexcitation Deceleration

- Frequently applying Overexcitation Deceleration raises the motor temperature because regenerative energy is mainly dissipated as heat in the motor. In cases where frequent application is required, make sure the motor temperature does not exceed the maximum allowable value or consider using a braking resistor option in lieu of Overexcitation Deceleration.
- During Overexcitation Deceleration 2, Hunting Prevention in V/f Control is disabled.
- Do not use Overexcitation Deceleration in combination with a braking resistor option.

Parameter Adjustments

- Use parameters n3-13 through n3-23 to adjust Overexcitation Deceleration.
- When repetitive or long Overexcitation Deceleration causes motor overheat, lower the overexcitation gain (n3-13) and reduce the overslip suppression current level (n3-21).
- During Overexcitation Deceleration 1 (L3-04 = 4), the drive decelerates at the active deceleration time (C1-02 and C1-04). Set this time so no overvoltage (ov) fault occurs.

5.9 n: Special Adjustments

- During Overexcitation Deceleration 2 (L3-04 = 5), the drive decelerates using the active deceleration time while adjusting the deceleration rate to keep the DC bus voltage at the level set to L3-17. The actual stopping time will be longer or shorter than the set deceleration time depending on the motor characteristics and the load inertia. Increase the deceleration time if overvoltage occurs (ov).
- Entering a Run command during Overexcitation Deceleration cancels overexcitation operation and the drive reaccelerates to the specified speed.

■ n3-13: Overexcitation Deceleration Gain

Multiplies a gain to the V/f pattern output value during Overexcitation Deceleration to determine the level of overexcitation. The drive returns to the normal V/f value after the motor has stopped or when it is accelerating to the frequency reference.

| No. | Name | Setting Range | Default |
|-------|----------------------------------|---------------|---------|
| n3-13 | Overexcitation Deceleration Gain | 1.00 to 1.40 | 1.10 |

The optimum setting for n3-13 depends on the motor flux saturation characteristics.

- Gradually increase the gain to 1.25 or 1.30 to improve the braking power of Overexcitation Deceleration.
- Lower n3-13 when flux saturation characteristics cause overcurrent. A high setting sometimes causes overcurrent (oC), motor overload (oL1), or drive overload (oL2). Lowering n3-21 can also help remedy these problems.

■ n3-14: High Frequency Injection during Overexcitation Deceleration

Enables High Frequency Injection while Overexcitation Deceleration is executed. Injecting high frequency into the motor increases loss and shortens deceleration time. This function tends to increase audible noise from the motor, and may not be desirable in environments where motor noise is a concern.

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------|
| n3-14 | High Frequency Injection During Overexcitation Deceleration | 0, 1 | 0 |

Setting 0: Disabled

Setting 1: Enabled

■ n3-21: High Slip Suppression Current Level

If the motor current exceeds the value set to n3-21 during Overexcitation Deceleration due to flux saturation, the drive automatically reduces the overexcitation gain. Parameter n3-21 is set as a percentage of the drive rated current.

Set this parameter to a relatively low value to optimize deceleration. If overcurrent, oL1, or oL2 occur during Overexcitation Deceleration, reduce the high slip suppression current level.

| No. | Name | Setting Range | Default |
|-------|-------------------------------------|---------------|---------|
| n3-21 | High Slip Suppression Current Level | 0 to 150% | 100% |

■ n3-23: Overexcitation Operation Selection

Limits the Overexcitation Deceleration operation selected in parameter L3-04 to forward only or reverse only.

| No. | Name | Setting Range | Default |
|-------|------------------------------------|---------------|---------|
| n3-23 | Overexcitation Operation Selection | 0 to 2 | 0 |

Setting 0: Overexcitation Operation as Selected in L3-04 in Forward and Reverse Direction

Setting 1: Overexcitation Operation as Selected in L3-04 in Forward Direction Only

Setting 2: Overexcitation Operation as Selected in L3-04 in Reverse Direction Only

5.10 o: Operator Related Settings

These parameters control the various functions, features, and display of the digital operator.

◆ o1: Digital Operator Display Selection

These parameters determine the data display on the digital operator.

■ o1-01: Drive Mode Unit Monitor Selection

The frequency reference display appears when the drive is powered up. Pressing the up arrow key will display the following data: frequency reference → rotational direction → output frequency → output current → o1-01 selection.

Parameter o1-01 selects the content of the last monitor in this sequence.

| No. | Name | Setting Range | Default |
|-------|-----------------------------------|---------------|-------------|
| o1-01 | Drive Mode Unit Monitor Selection | 104 to 809 | 106 (U1-06) |

■ o1-02: User Monitor Selection after Power Up

Selects which monitor parameter is displayed upon power up. *Refer to U: Monitor Parameters on page 286* for a list of monitors.

| No. | Name | Setting Range | Default |
|-------|---------------------------------------|---------------|---------|
| o1-02 | User Monitor Selection after Power Up | 1 to 5 | 1 |

Setting 1: Frequency Reference (U1-01)

Setting 2: Motor Direction

Setting 3: Output Frequency (U1-02)

Setting 4: Output Current (U1-03)

Setting 5: User-selected Monitor (Set by o1-01)

■ o1-03: Digital Operator Display Selection

Sets the units used to display the frequency reference and output frequency. Set o1-03 to 3 for user-set units before setting parameters o1-10 and o1-11.

| No. | Name | Setting Range | Default |
|-------|------------------------------------|---------------|---------|
| o1-03 | Digital Operator Display Selection | 0 to 3 | 0 |

Setting 0: 0.01 Hz units

Setting 1: 0.01% units (100% = max. output frequency)

Setting 2: r/min units (calculated by the max output frequency and the no. of motor poles)

Setting 3: User-set units (set by o1-09, o1-10, o1-11)

Set the value used for the maximum frequency reference to o1-10. Set the placement of the decimal point in this number to o1-11.

For example, to have the maximum output frequency displayed as “100.00”, set o1-10 to 1000 and o1-11 to 2 (i.e., 1000 with 2 decimal points).

- Note:**
- Parameter o1-03 allows the programmer to change the units used in the following parameters and monitors:
 U1-01: frequency reference
 U1-02: output frequency
 U1-16: output frequency after softstarter (accel/decel ramp generator)
 d1-01 to d1-17: frequency references
 - Setting o1-03 to 2 requires entering the number of motor poles to E2-04.

5.10 o: Operator Related Settings

■ o1-05: LCD Contrast Control

Sets the brightness of the digital operator. The lower the setting, the brighter the LCD contrast. The higher the setting, the darker the LCD contrast.

Note: Available in drive software versions PRG: 8503 and later.

| No. | Name | Setting Range | Default |
|-------|----------------------|---------------|---------|
| o1-05 | LCD Contrast Control | 0 to 5 | 3 |

■ o1-06: User Monitor Selection Mode

Select between standard sequential monitors or selectable monitors to be displayed on the 2nd and 3rd lines of the digital operator display.

Use parameters o1-07 and o1-08 to select and fix the second and third monitors shown in the Home (Frequency Reference) and Monitor screen to ensure that those monitors are always visible when scrolling through the monitor list.

| No. | Name | Setting Range | Default |
|-------|-----------------------------|---------------|---------|
| o1-06 | User Monitor Selection Mode | 0, 1 | 0 |

Setting 0: 3 Mon Sequential (displays the next 2 sequential monitors)

Setting 1: 3 Mon Selectable (set by o1-07 and o1-08)

■ o1-07: Second Line User Monitor Selection

Selects the monitor that is shown in the second line. Effective only when o1-06 is set to 1.

Enter the last three digits of the monitor parameter number to be displayed: U□-□□. For example, set "403" to display monitor parameter U4-03.

| No. | Name | Setting Range | Default |
|-------|------------------------------------|---------------|---------|
| o1-07 | Second Line User Monitor Selection | 101 to 799 | 102 |

■ o1-08: Third Line User Monitor Selection

Selects the monitor that is shown in the third line. Effective only when o1-06 is set to 1.

Enter the last three digits of the monitor parameter number to be displayed: U□-□□. For example, set "403" to display monitor parameter U4-03.

| No. | Name | Setting Range | Default |
|-------|------------------------------------|---------------|---------|
| o1-08 | Second Line User Monitor Selection | 101 to 799 | 103 |

■ o1-09: Frequency Reference Display Units

Selects the monitor that is shown in the third line. Enter the last three digits of the monitor parameter number to be displayed: U□-□□. For example, set "403" to display monitor parameter U4-03.

Note: Parameter is effective only when o1-06 is set to 1.

| No. | Name | Setting Range | Default |
|-------|-----------------------------------|-----------------|---------|
| o1-09 | Frequency Reference Display Units | 0 to 15; 24, 25 | 25 |

Setting 0: Inch of Water (WC)

Setting 1: Pounds per Square Inch (PSI)

Setting 2: Gallons per Minute (GPM)

Setting 3: Degrees Fahrenheit (F)

Setting 4: Cubic Feet per Minute (CFM)

Setting 5: Cubic Meters per Hour (CMH)

Setting 6: Liters per Hour (LPH)

Setting 7: Liters per Second (LPS)

Setting 8: Bar (Bar)

Setting 9: Pascals (Pa)

Setting 10: Degrees Celsius (C)

Setting 11: Meters (Mtr)

Setting 12: Feet (Ft)

Setting 13: Liters per Minute (LPN)

Setting 14: Cubic Meters per Minute (CMM)

Setting 15: Inches of Mercury (Hg)

Setting 24: Custom Units (determined by o1-13 to o1-15)

Setting 25: None

■ **o1-10: User-Set Display Units Maximum Value**

Determines the display value that is equal to the maximum output frequency.

| No. | Name | Setting Range | Default |
|-------|--------------------------------------|---------------|---------------------|
| o1-10 | User-Set Display Units Maximum Value | 1 to 60000 | Determined by o1-03 |

■ **o1-11: User-Set Display Units Decimal Display**

Determines how many decimal points should be used to set and display the frequency reference.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------------------|
| o1-11 | User-Set Display Units Decimal Display | 0 to 3 | Determined by o1-03 |

Setting 0: No Decimal Point

Setting 1: One Decimal Point

Setting 2: Two Decimal Points

Setting 3: Three Decimal Points

■ **o1-13: Frequency Reference and Frequency Related Monitor Custom Units 1**

Sets the first character of the customer-specified unit display when o1-03 is set to 3 and o1-09 is set to 24.

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------|
| o1-13 | Frequency Reference and Frequency Related Monitor Custom Units 1 | 30 to 7A | 41 |

■ **o1-14: Frequency Reference and Frequency Related Monitor Custom Units 2**

Sets the second character of the customer-specified unit display when o1-03 is set to 3 and o1-09 is set to 24.

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------|
| o1-14 | Frequency Reference and Frequency Related Monitor Custom Units 2 | 30 to 7A | 41 |

■ **o1-15: Frequency Reference and Frequency Related Monitor Custom Units 3**

Sets the third character of the customer-specified unit display when o1-03 is set to 3 and o1-09 is set to 24.

5.10 o: Operator Related Settings

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------|
| o1-14 | Frequency Reference and Frequency Related Monitor Custom Units 3 | 30 to 7A | 41 |

◆ o2: Digital Operator Keypad Functions

These parameters determine the functions assigned to the operator keys.

■ o2-01: LO/RE (LOCAL/REMOTE) Key Function Selection

Determines whether the LO/RE key on the digital operator will be enabled for switching between LOCAL and REMOTE.

| No. | Name | Setting Range | Default |
|-------|------------------------------|---------------|---------|
| o2-01 | LO/RE Key Function Selection | 0, 1 | 1 |

Setting 0: Disabled

The LO/RE key is disabled.

Setting 1: Enabled

The LO/RE switches between LOCAL and REMOTE operation. Switching is possible during stop only. When LOCAL is selected, the LED indicator on the LO/RE key will light up.

WARNING! Sudden Movement Hazard. The drive may start unexpectedly if the Run command is already applied when switching from LOCAL mode to REMOTE mode when b1-07 = 1, resulting in death or serious injury. Check all mechanical or electrical connections thoroughly before making any setting changes to o2-01 and b1-07. [Table 5.36](#) lists the setting combinations for o2-01 and b1-07.

Table 5.36 LO/RE Key and b1-07

| o2-01 | b1-07 | Switch from LOCAL to REMOTE | Switch from REMOTE to LOCAL |
|-------|-------|--|-----------------------------|
| 0 | 0 | Not possible | Not possible |
| | 1 | Not possible | Not possible |
| 1 | 0 | Will not run until a new Run command is entered. | Run not possible |
| | 1 | If a Run command is entered, the drive will start running as soon as the LO/RE key is pushed to change from LOCAL to REMOTE. | Run not possible |

■ o2-02: STOP Key Function Selection

Determines if the STOP key on the digital operator will stop drive operation when the drive is controlled from a remote source (i.e., not from digital operator).

| No. | Name | Setting Range | Default |
|-------|-----------------------------|---------------|---------|
| o2-02 | STOP Key Function Selection | 0, 1 | 1 |

Setting 0: Disabled

Setting 1: Enabled

The STOP key will terminate drive operation even if the Run command source is not assigned to the digital operator. Cycle the Run command to restart the drive if the drive has been stopped by pressing the STOP key.

■ o2-03: User Parameter Default Value

After completely setting up drive parameters, save the values as user-set defaults with parameter o2-03. After saving the values, parameter A1-03 (Initialize Parameters) will offer the choice of "1110: User Initialize". Selecting 1110 resets all parameters to the user-set default values. [Refer to A1-03: Initialize Parameters on page 143](#) for details on drive initialization.

| No. | Name | Setting Range | Default |
|-------|------------------------------|---------------|---------|
| o2-03 | User Parameter Default Value | 0 to 2 | 0 |

Setting 0: No Change (Awaiting Command)

Setting 1: Set User Initialize Values

The current parameter settings are saved as user-set default for a later User Initialization. Setting o2-03 to 1 and pressing the ENTER key saves the values and returns the display to 0.

Setting 2: Clear User Initialize Values

All user-set defaults for “User Initialize” are cleared. Setting o2-03 to 2 and pressing the ENTER key erases the values and returns the display to 0.

■ o2-04: Drive Model Selection

Set this parameter when replacing the control board or the terminal board. *Refer to Defaults by Drive Model on page 487* for information on drive model selection.

NOTICE: Drive performance will suffer and protective functions will not operate properly if the correct drive capacity is not set to o2-04.

| No. | Name | Setting Range | Default |
|-------|-----------------------|---------------|------------------------------|
| o2-04 | Drive Model Selection | - | Determined by drive capacity |

Note: Change o2-04 setting only when necessary.

■ o2-05: Frequency Reference Setting Method Selection

Determines if the ENTER key must be pressed after changing the frequency reference using the digital operator while in the Drive Mode.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| o2-05 | Frequency Reference Setting Method Selection | 0, 1 | 0 |

Setting 0: ENTER Key Required

The ENTER key must be pressed every time the frequency reference is changed using the digital operator for the drive to accept the change.

Setting 1: ENTER Key Not Required

The output frequency changes immediately when the reference is changed by the up or down arrow keys on the digital operator. The ENTER key does not need to be pressed. The frequency reference (Fref) is saved to memory after remaining unchanged for 5 seconds.

■ o2-06: Operation Selection when Digital Operator is Disconnected

Determines whether the drive will stop when the remote control extension cable of the digital operator is removed in LOCAL mode or when b1-02 or b1-16 is set to 0. When the operator is reconnected, the display will indicate that it was disconnected.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| o2-06 | Digital Operator Disconnection Operation | 0, 1 | 1 |

Setting 0: Continue Operation

The operation continues.

Setting 1: Trigger a Fault

The operation stops and triggers an oPr fault. The motor coasts to stop.

■ o2-07: Motor Direction at Power Up when Using Operator

Determines the direction the motor will rotate after the drive is powered up and the Run command is given from the digital operator.

Note: This parameter is effective only when the Run command is set to be given from the digital operator (b1-02, b1-16 = 0).

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------|
| o2-07 | Motor Direction at Power Up when Using Operator | 0, 1 | 0 |

Setting 0: Forward**Setting 1: Reverse****■ o2-20: Operator Run Save at Power Loss**

When running during a power loss, the Run command is issued via the digital operator and the Run state is saved to the EEPROM.

When power is restored, the Run command is automatically applied if the LOCAL/REMOTE or FREF conditions have not changed in the drive.

5.10 o: Operator Related Settings

When this parameter is set to 0 (disabled) the drive will ignore the Run state of the drive when power is lost. When this parameter is set to 1 (enabled), and the active Run source is from the digital operator, the drive will save the Run status during power-down.

When power is restored, and the drive is still in operator mode, the previous Run status will be loaded and will apply the Run command.

If the Run command was issued while the drive was running in LOCAL mode (triggered through the operator key) and power was cycled, the drive will not automatically run, as the default starting state is REMOTE operation.

Note: The Run Status is saved on the terminal board and on the control card. If the Run Status does not match (e.g., if the terminal board was replaced), the Run Status is reset and the drive will not run on the next power-up.

WARNING! Sudden Movement Hazard. If o2-20 is set to 1 and o2-06 is set to 0, the drive will continue running when the digital operator is removed and may run automatically when power is cycled, resulting in death or serious injury. Clear all personnel from the drive, motor and machine area before applying power. Secure covers, couplings, shaft keys and machine loads before applying power to the drive.

| No. | Name | Setting Range | Default |
|-------|---------------------------------|---------------|---------|
| o2-20 | Operator Run Save at Power Loss | 0, 1 | 0 |

Setting 0: Disabled

Setting 1: Enabled

◆ o3: Copy Function

These parameters control the Copy function of the digital operator. The Copy function stores parameter settings into the memory of the digital operator to facilitate the transfer of those settings to other drives that are the same model, capacity, and same control mode setting. [Refer to Copy Function Related Displays on page 325](#) for a description of errors and displays.

■ o3-01: Copy Function Selection

Instructs the drive to Read, Write, or Verify parameter settings.

| No. | Name | Setting Range | Default |
|-------|-------------------------|---------------|---------|
| o3-01 | Copy Function Selection | 0 to 3 | 0 |

Setting 0: Copy Select (No Function)

Setting 1: INV --> OP READ

Copies all parameters from the drive to the digital operator.

Note: Set o3-02 to 1 to unlock copy protection.

Setting 2: OP --> INV WRITE

Copies all parameters from the digital operator to the drive.

Setting 3: OP<-->INV VERIFY

Compares the parameters in the drive with the parameter settings saved on the digital operator for matches.

■ o3-02: Copy Allowed Selection

Allows and restricts the use of the Copy function.

| No. | Name | Setting Range | Default |
|-------|------------------------|---------------|---------|
| o3-02 | Copy Allowed Selection | 0, 1 | 0 |

Setting 0: Disabled

Setting 1: Enabled

◆ o4: Maintenance Monitor Settings

■ o4-01: Cumulative Operation Time Setting

Sets the cumulative operation time of the drive. The user can also manually set this parameter to begin keeping track of operation time from some desired value. Total operation time can be viewed in monitor U4-01.

Note: The value in o4-01 is set in 10 h units. For example, a setting of 30 will set the cumulative operation time counter to 300 h. 300 h will also be displayed in monitor U4-01.

| No. | Name | Setting Range | Default |
|-------|-----------------------------------|---------------|---------|
| o4-01 | Cumulative Operation Time Setting | 0 to 9999 | 0 |

■ o4-02: Cumulative Operation Time Selection

Selects the conditions for how the drive keeps track of its total operation time. This time log can be viewed in monitor U4-01.

| No. | Name | Setting Range | Default |
|-------|-------------------------------------|---------------|---------|
| o4-02 | Cumulative Operation Time Selection | 0, 1 | 0 |

Setting 0: Power On Time

The drive logs the time it is connected to a power supply, regardless of whether the motor is running.

Setting 1: Run Time

The drive logs the time that the output is active including when the Run command is active (even if the motor is not rotating) and when there is voltage output.

■ o4-03: Cooling Fan Operation Time Setting

Sets the value for how long the cooling fan has been operating. This value can be viewed in monitor U4-03. Parameter o4-03 also sets the base value used for the cooling fan maintenance, which is displayed in U4-04. Reset this parameter to 0 after replacing the cooling fan.

- Note:**
1. The value in o4-03 increases after every 10 hours of use. A setting of 30 will set the cooling fan operation time counter to 300 h. "300" will be displayed in monitor U4-03.
 2. The cooling fan may require maintenance at an earlier date in harsher environments.

| No. | Name | Setting Range | Default |
|-------|------------------------------------|---------------|---------|
| o4-03 | Cooling Fan Operation Time Setting | 0 to 9999 | 0 |

■ o4-05: Capacitor Maintenance Setting

Sets value of the maintenance monitor for the DC bus capacitors displayed in U4-05 as a percentage of the total expected performance life. Reset this value to 0 after replacing the DC bus capacitors.

Note: The actual maintenance time will depend on the environment where the drive is used.

| No. | Name | Setting Range | Default |
|-------|-------------------------------|---------------|---------|
| o4-05 | Capacitor Maintenance Setting | 0 to 150% | 0% |

■ o4-07: DC Bus Pre-Charge Relay Maintenance Setting

Sets the value of the softcharge bypass relay maintenance time displayed in U4-06 as a percentage of the total expected performance life. Reset this value to 0 after replacing the bypass relay.

Note: The actual maintenance time will depend on the environment where the drive is used.

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------|
| o4-07 | DC Bus Pre-charge Relay Maintenance Setting | 0 to 150% | 0% |

■ o4-09: IGBT Maintenance Setting

Sets the value of the IGBT maintenance time displayed in U4-07 as a percentage of the total expected performance life. Reset this value to 0 after replacing the IGBTs.

Note: The actual maintenance time will depend on the environment where the drive is used.

| No. | Name | Setting Range | Default |
|-------|--------------------------|---------------|---------|
| o4-09 | IGBT Maintenance Setting | 0 to 150% | 0% |

■ o4-11: U2, U3 Initialization

Resets the fault trace and fault history monitors (U2-□□ and U3-□□).

Note: Initializing the drive using A1-03 does not reset these monitors.

| No. | Name | Setting Range | Default |
|-------|-----------------------|---------------|---------|
| o4-11 | U2, U3 Initialization | 0, 1 | 0 |

Setting 0: No Action

The drive keeps the previously saved record concerning fault trace and fault history.

5.10 o: Operator Related Settings

Setting 1: Reset Fault Data

Resets the data for the U2-□□ and U3-□□ monitors. Setting o4-11 to 1 and pressing the ENTER key erases fault data and returns the display to 0.

■ o4-12: kWh Monitor Initialization

Manually resets kWh monitors U4-10 and U4-11. Initializing the drive or cycling the power will not reset these monitors.

| No. | Name | Setting Range | Default |
|-------|----------------------------|---------------|---------|
| o4-12 | kWh Monitor Initialization | 0, 1 | 0 |

Setting 0: No Action

The kWh data are maintained.

Setting 1: Reset kWh Data

Resets the kWh counter. The monitors U4-10 and U4-11 will display “0” after they are initialized. Setting o4-12 to 1 and pressing the ENTER erases kWh data and returns the display to 0.

■ o4-13: Number of Run Commands Counter Initialization

Resets the Run command counter displayed in U4-02. Initializing the drive or cycling the power does not reset this monitor.

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------|
| o4-13 | Number of Run Commands Counter Initialization | 0, 1 | 0 |

Setting 0: No Action

The Run command data are kept.

Setting 1: Number of Run Commands Counter

Resets the Run command counter. The monitor U4-02 will show 0. Setting o4-13 to 1 and pressing the ENTER key erases the counter value and returns the display to 0.

■ o4-17: Real-Time Clock Setting

| No. | Name | Setting Range | Default |
|-------|---------------------------|---------------|---------|
| o4-17 | Set/Reset Real-Time Clock | 0 to 2 | 0 |

Setting 0: — —

No Setting (Default)

Setting 1: Set

When o4-17 is set to 1, the digital operator will show the Clock Adjustment display. In Clock Adjustment Mode the user can adjust the Real-Time Clock.

Setting 2: Reset

When o4-17 is set to 2, the Real-Time Clock data is cleared. A TIM fault will occur until o4-17 is set to 1 and the Real-Time Clock is set.

■ o4-20: Time Display Format

| No. | Name | Setting Range | Default |
|-------|---------------------|---------------|---------|
| o4-20 | Time Display Format | 0, 1 | 0 |

Sets the time display format.

Setting 0: 12-Hour

Setting 1: 24-Hour

5.11 S: Special Application

◆ S1: Dynamic Audible Noise Control Function

The Dynamic Audible Noise Control Function reduces audible noise by suppressing the output voltage.

This function is available when using V/f Control mode and can help to quickly restore output voltage after an impact has caused a sudden increase in the time constant. Dynamic Audible Noise Control is useful in applications where load impact is common.

Energy Saving (b8-01 = 1) and Dynamic Audible Noise Control (S1-01 = 1) cannot be used simultaneously.

Procedure

1. Set S1-01 to 1 to enable Dynamic Audible Noise Control.

Note: 1. When S1-01 is set to 1, the tolerance to impact loading is reduced when compared to V/f Control (without Energy Saving).

2. Disable Dynamic Audible Noise Control for applications without an impact load.

2. Responsiveness is increased because the addition of a load causes the level of the current to rise.

Increase the value of S1-02. The flux will become stronger and the torque will rise, but load movement will be minimized by the Dynamic Audible Noise Control function.

Set S1-03 and S1-04 to a small value. Voltage is recovered quicker during impact load conditions. Under certain conditions voltage stability may become poor.

Lower the value of S1-05. The voltage level will drop and speed up voltage restoration when the load is increased.

3. Increase the value of S1-03 to increase the effectiveness of Dynamic Audible Noise Control if the output voltage remains high.

4. Decrease the value of S1-06 to increase drive response to an impact load.

5. When the output voltage is unstable, increase the difference between S1-03 and S1-04 and increase S1-05 and S1-06 to slow the load response.

■ S1-01: Dynamic Audible Noise Control Selection

Reduces audible noise by decreasing the output voltage in variable torque applications with light loads.

Note: Setting b8-01 to 1 and S1-01 to 1 will trigger an oPE16 error.

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------|
| S1-01 | Dynamic Audible Noise Control Selection | 0 or 1 | 0 |

Setting 0: Disabled

Setting 1: Enabled

■ S1-02: Voltage Reduction Rate

Sets the rate at which the output voltage will be reduced as a percentage of the V/f pattern when operating with no load.

| No. | Name | Setting Range | Default |
|-------|------------------------|----------------|---------|
| S1-02 | Voltage Reduction Rate | 50.0 to 100.0% | 50.0% |

■ S1-03: Voltage Restoration Level

Sets the level when the drive should start restoring the voltage as a percentage of the drive rated torque.

The voltage is reduced when the torque output has decreased to the level set in S1-03.

The method used to reduce the voltage level is selected in accordance with the characteristics of the voltage reduction rate defined by the S1-03 and S1-04 settings.

Note: Setting S1-04 to a value less than that of S1-03 + 10.0 will trigger an oPE02 error.

| No. | Name | Setting Range | Default |
|-------|---------------------------|---------------|---------|
| S1-03 | Voltage Restoration Level | 0.0 to 90.0% | 20.0% |

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■ S1-04: Voltage Restoration Complete Level

Sets the level at which voltage restoration for the V/f pattern is complete as a percentage of the drive rated torque. If the output torque rises above the value of S1-04, then the voltage will be controlled in a manner specified by the V/f pattern setting.

Note: Setting S1-04 to a value less than that of S1-03 + 10.0 will trigger an oPE02 error.

| No. | Name | Setting Range | Default |
|-------|------------------------------------|------------------------|---------|
| S1-04 | Voltage Restoration Complete Level | S1-03 + 10.0 to 100.0% | 50.0% |

■ S1-05: Voltage Restoration Sensitivity Time Constant

Sets the level of sensitivity of the output torque as well as that of the LPF time constant for the voltage reduction rate. The level of sensitivity can be adjusted in accordance with the load response.

The LPF time constant is used to calculate the value of the output torque sensitivity time constant.

The voltage reduction rate is based on the torque output. Select LPF to prevent voltage fluctuation.

The Dynamic Audible Noise Control Function outputs the rate of voltage reduction as a percentage within the allowable range (Max: 100%, Min: S1-02 value).

| No. | Name | Setting Range | Default |
|-------|---|------------------|---------|
| S1-05 | Voltage Restoration Sensitivity Time Constant | 0.000 to 3.000 s | 1.000 s |

■ S1-06: Voltage Restoration Time Constant at Impact

Sets the voltage restoration time constant if an impact load is added.

Sets the time constant that enables the voltage level to rise if the speed suddenly changes upon impact.

| No. | Name | Setting Range | Default |
|-------|---|------------------|---------|
| S1-06 | Voltage Restoration Time Constant at Impact | 0.000 to 1.000 s | 0.050 s |

■ S1-07: Output Phase Loss Level for Dynamic Noise Control

Reduces the output phase loss level when Dynamic Noise Control is active.

| No. | Name | Setting Range | Default |
|-------|---|----------------|---------|
| S1-07 | Output Phase Loss Level for Dynamic Noise Control | 10.0 to 100.0% | 100.0% |

◆ S2: Programmable Run Timers

■ Programmable Run Timers for Real Time Clock (RTC)

Programmable run timers allow the drive to start and stop automatically at specified times. The timers can be configured to run daily, on weekdays, on weekends, or only on specific days of the week.

Sequence Timer 1

When the current time reaches the value set in parameter S2-01 (Sequence Timer 1 Start Time), the drive will execute the action set in parameter S2-04 (Sequence Timer 1 Selection), provided the current day is selected via S2-03 (Sequence Timer 1 Day Selection). The drive will stop executing the S2-04 action when the S2-02 (Sequence Timer 1 Stop Time) is reached.

When S2-04 = 0 or the Disable Sequence Timers multi-function input (H1-□□ = 51) is closed, Sequence Timer 1 has no effect on the drive Run command. The drive runs normally based on the status of the selected run source (b1-02/b1-16). If S2-04 = 1 or 2 and the Disable Sequence Timers input is open, the drive will run during the Sequence Timer 1 active time, provided the drive has a valid Run command. The frequency reference that is used is set by S2-05 (Sequence Timer 1 Reference Source). When S2-04 = 2, PI control is disabled.

If the Cancel Active Sequence Timer multi-function input (H1-□□ = 52) transitions from open to closed while Sequence Timer 1 is active, the timer will be disabled until the next scheduled sequence timer occurrence. Sequence Timer 1 can be re-enabled by cycling the drive Run command. The Sequence Timer 1 multi-function output (H2-□□ = 50) will close while Sequence Timer 1 is active regardless of the S2-04 selection.

When S2-01 = S2-02, Sequence Timer 1 is active continuously for the days selected in S2-03. The timer will start at the S2-01/S2-02 time on the first day and stop at the same time on the last day. If only one day is selected in S2-03, the timer will stop at 24:00 on that day. If "daily" is selected in S2-03, the timer will run from the start/stop time until 24:00 every day.

An S2-01 or S2-02 setting of 24:00 corresponds to midnight on the following day. For example, if S2-01 = 8:00, S2-02 = 24:00, and S2-03 = 9 (Saturday), Sequence Timer 1 will be active from 8:00 AM Saturday until 12:00 AM Sunday.

When S2-04 = 1 or 2, Sequence Timer 1 is active and the drive is running, the digital operator screen will appear as shown in [Figure 5.85](#).

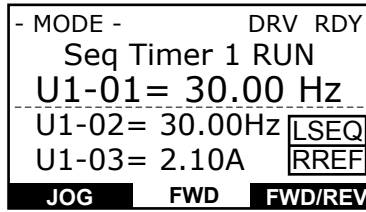


Figure 5.85 Sequence Timer 1 Run

When the drive has a run command, S2-04 = 1 or 2 and Sequence Timer 1 is not active, the digital operator will appear as shown in [277](#).

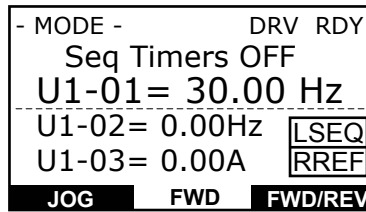


Figure 5.86 Sequence Timers Off

Sequence Timers 2 to 4

These timers operate identically to Sequence Timer 1. Parameters S2-06 to S2-20 configure Sequence Timers 2 to 4.

Priority

If multiple sequence timers overlap, the timer with the lowest number has priority.

Sequence Timer 1 = highest priority

Sequence Timer 4 = lowest priority

Note: Jog Forward/Reverse has higher priority than any of the Sequence Timers.

Examples of Sequence Timers

If multiple sequence timers overlap, the timer with the lowest number has priority.

Sequence Timer 1 = highest priority

Sequence Timer 4 = lowest priority

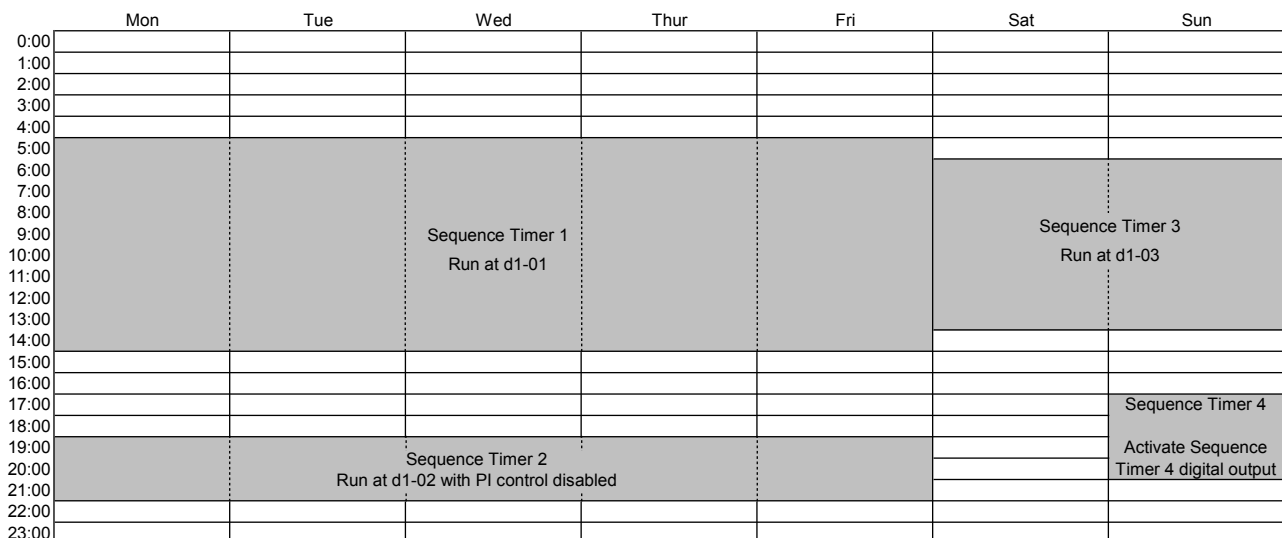


Figure 5.87 Sequence Timer Example 1

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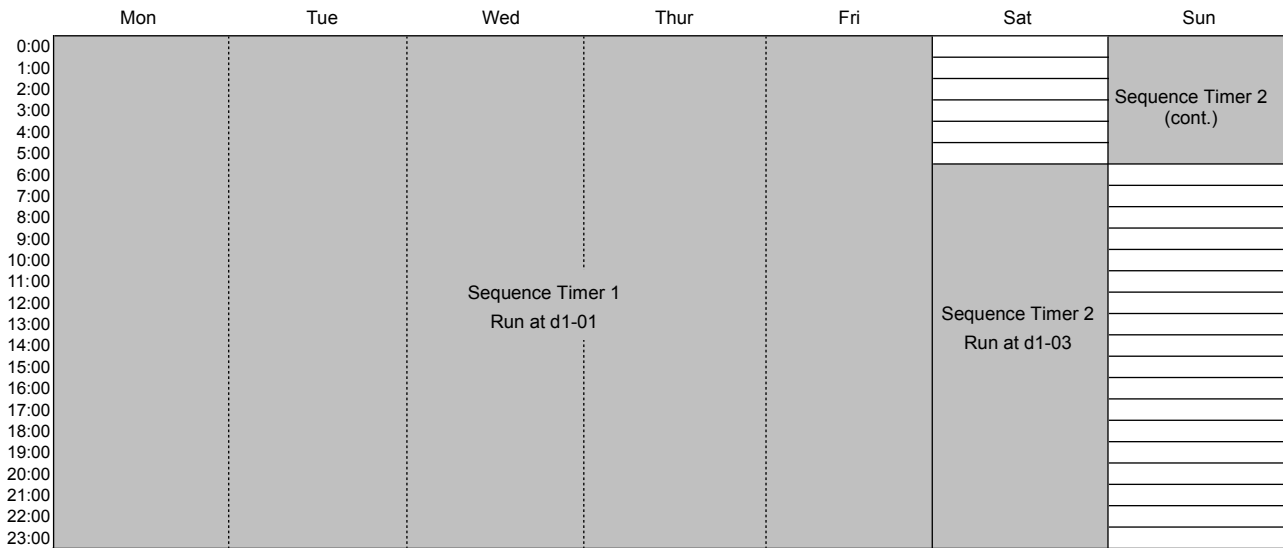


Figure 5.88 Sequence Timer Example 2

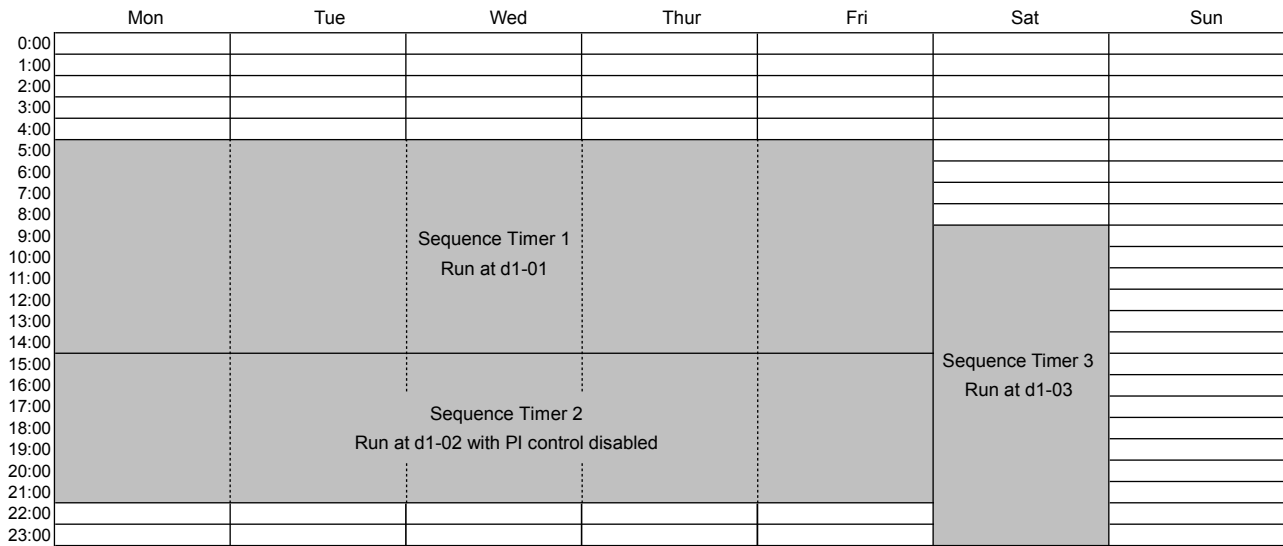


Figure 5.89 Sequence Timer Example 3

Timing Charts

In [Figure 5.90](#) S2-04 = 1, S2-05 = 0, S2-09 = 2, S2-10 = 1. It shows the effect of Run command and sequence timer disable input.

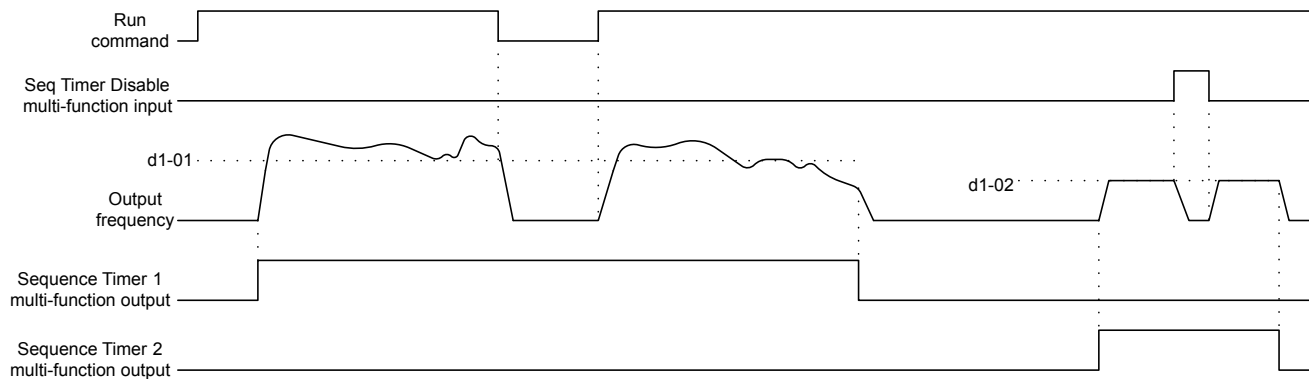


Figure 5.90 Timing Chart 1

In **Figure 5.91** S2-04 = 1, S2-05 = 0, S2-09 = 2, S2-10 = 1. It shows the effect of sequence timer disable input.

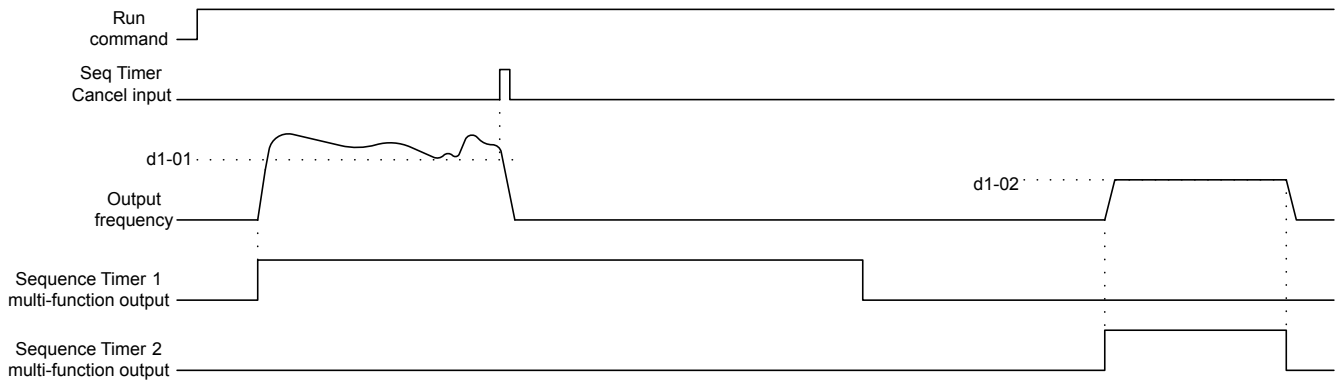


Figure 5.91 Timing Chart 2

In **Figure 5.92** S2-04 = 1, S2-05 = 0, S2-09 = 2, S2-10 = 1. It shows the effect of sequence timer cancel input with run recycle.

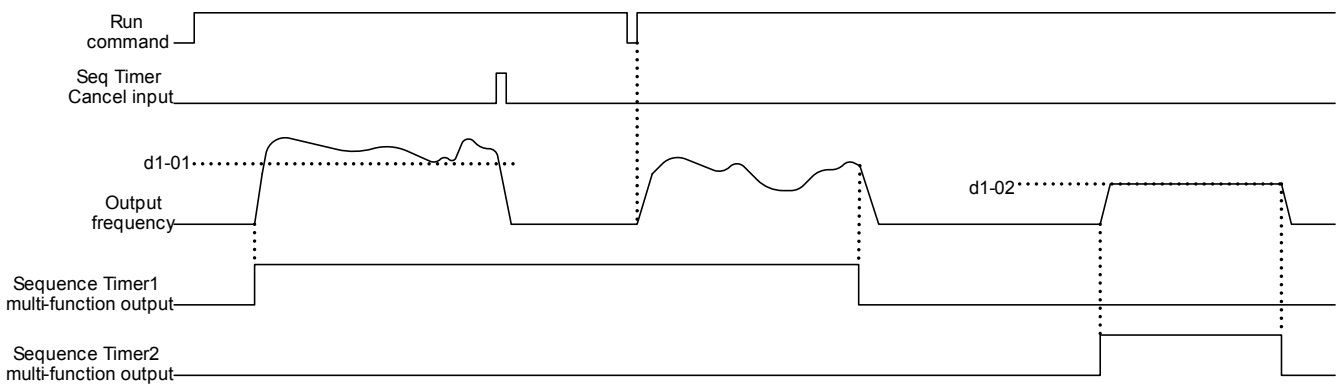


Figure 5.92 Timing Chart 3

In **Figure 5.93** S2-04 = 1, S2-05 = 0, S2-09 = 2, S2-10 = 1. It shows the effect of HAND mode.

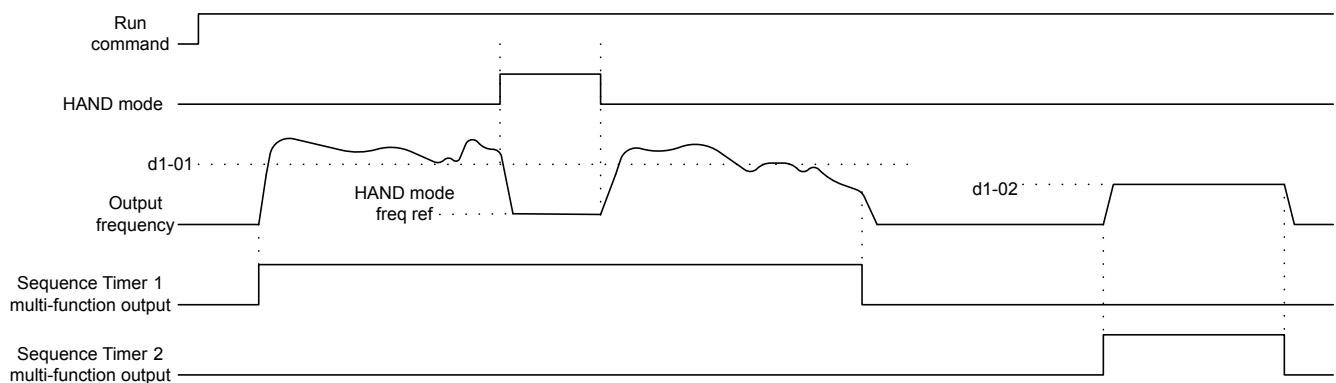


Figure 5.93 Timing Chart 4

■ **S2-01/S2-06/S2-11/S2-16: Sequence Timers 1 to 4 Start Time**

Sets the start times for timers 1 to 4.

If the Stop Time is set to a higher value than the Start Time, the Sequence Timers will be active starting from the set Start Time, run through midnight, and stop the following day at the set Stop Time.

Note: Setting the sequence timer start time to a higher value than the sequence timer stop time disables that sequence timer in drive software versions PRG: 8551 and earlier.

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| No. | Name | Setting Range | Default |
|-------|-----------------------------|------------------------|-------------|
| S2-01 | Sequence Timer 1 Start Time | 12:00AM to 11:59PM </> | 12:00AM </> |
| S2-06 | Sequence Timer 2 Start Time | 12:00AM to 11:59PM </> | 12:00AM </> |
| S2-11 | Sequence Timer 3 Start Time | 12:00AM to 11:59PM </> | 12:00AM </> |
| S2-16 | Sequence Timer 4 Start Time | 12:00AM to 11:59PM </> | 12:00AM </> |

<1> Default is 00:00 and range is 00:00 to 24:00 when o4-20 is set to 1 (24-hour).

■ S2-02/S2-07/S2-12/S2-17: Sequence Timers 1 to 4 Stop Time

Sets the stop times for timers 1 to 4. The values must be set greater than or equal to S2-01/S2-06/S2-11/S2-16.

| No. | Name | Setting Range | Default |
|-------|----------------------------|----------------|---------|
| S2-02 | Sequence Timer 1 Stop Time | 00:00 to 24:00 | 00:00 |
| S2-07 | Sequence Timer 2 Stop Time | 00:00 to 24:00 | 00:00 |
| S2-12 | Sequence Timer 3 Stop Time | 00:00 to 24:00 | 00:00 |
| S2-17 | Sequence Timer 4 Stop Time | 00:00 to 24:00 | 00:00 |

■ S2-03/S2-08/S2-13/S2-18: Sequence Timers 1 to 4 Day Selection

Sets the days for which sequence timers 1 to 4 are active.

| No. | Name | Setting Range | Default |
|-------|--------------------------------|---------------|---------|
| S2-03 | Sequence Timer 1 Day Selection | 0 to 10 | 0 |
| S2-08 | Sequence Timer 2 Day Selection | 0 to 10 | 0 |
| S2-13 | Sequence Timer 3 Day Selection | 0 to 10 | 0 |
| S2-18 | Sequence Timer 4 Day Selection | 0 to 10 | 0 |

Setting 0: Timer Disabled

Setting 1: Daily

Setting 2: Mon - Fri

Setting 3: Sat - Sun

Setting 4: Monday

Setting 5: Tuesday

Setting 6: Wednesday

Setting 7: Thursday

Setting 8: Friday

Setting 9: Saturday

Setting 10: Sunday

■ S2-04/S2-09/S2-14/S2-19: Sequence Timers 1/2/3/4 Selection

Sets the action that occurs when sequence timers 1 to 4 are active.

- Note:**
1. Setting 3 is available in drive software versions PRG: 8552 and later.
 2. Setting 3 is not available in drive models 4A0930 and 4A1200.

| No. | Name | Setting Range | Default |
|-------|----------------------------|---------------|---------|
| S2-04 | Sequence Timer 1 Selection | 0 to 3 | 0 |
| S2-09 | Sequence Timer 2 Selection | 0 to 3 | 0 |
| S2-14 | Sequence Timer 3 Selection | 0 to 3 | 0 |
| S2-19 | Sequence Timer 4 Selection | 0 to 3 | 0 |

Setting 0: Digital Output Only

Setting 1: Run

Setting 2: Run - PI Disable

Setting 3: Allow Alternation

When Sequence Selection is set to Allow Alternation and that timer is enabled (S2-03, S2-08, S2-13, S2-18 > 0), the drive will only allow MEMOBUS alternation to occur during the time specified in the corresponding Sequence Timer. Alternation is disabled when the timer deactivates.

■ **S2-05/S2-10/S2-15/S2-20: Sequence Timers 1/2/3/4 Reference Source**

Selects the frequency reference source used for running the drive when sequence timers 1 to 4 are active (only applicable when S2-04/S2-09/S2-14/S2-19 are set to 1 or 2).

| No. | Name | Setting Range | Default |
|-------|-----------------------------------|---------------|---------|
| S2-05 | Sequence Timer 1 Reference Source | 0 to 7 | 0 |
| S2-10 | Sequence Timer 2 Reference Source | 0 to 7 | 0 |
| S2-15 | Sequence Timer 3 Reference Source | 0 to 7 | 0 |
| S2-20 | Sequence Timer 4 Reference Source | 0 to 7 | 0 |

Setting 0: Operator (d1-01)

Setting 1: Operator (d1-02)

Setting 2: Operator (d1-03)

Setting 3: Operator (d1-04)

Setting 4: Terminals

Setting 5: Serial Communication

Setting 6: Option Card

Setting 7: Pulse Input

◆ **S3: Secondary PI (PI2) Control**

The drive has a built in PI (Proportional + Integral) controller that can be used for closed loop control of system variables such as pressure or temperature. The difference between the target and the feedback value (deviation) is fed into the PI controller and the PI controller outputs the frequency to U5-□□ for monitoring. *Refer to b5: PID Control on page 160* for details.

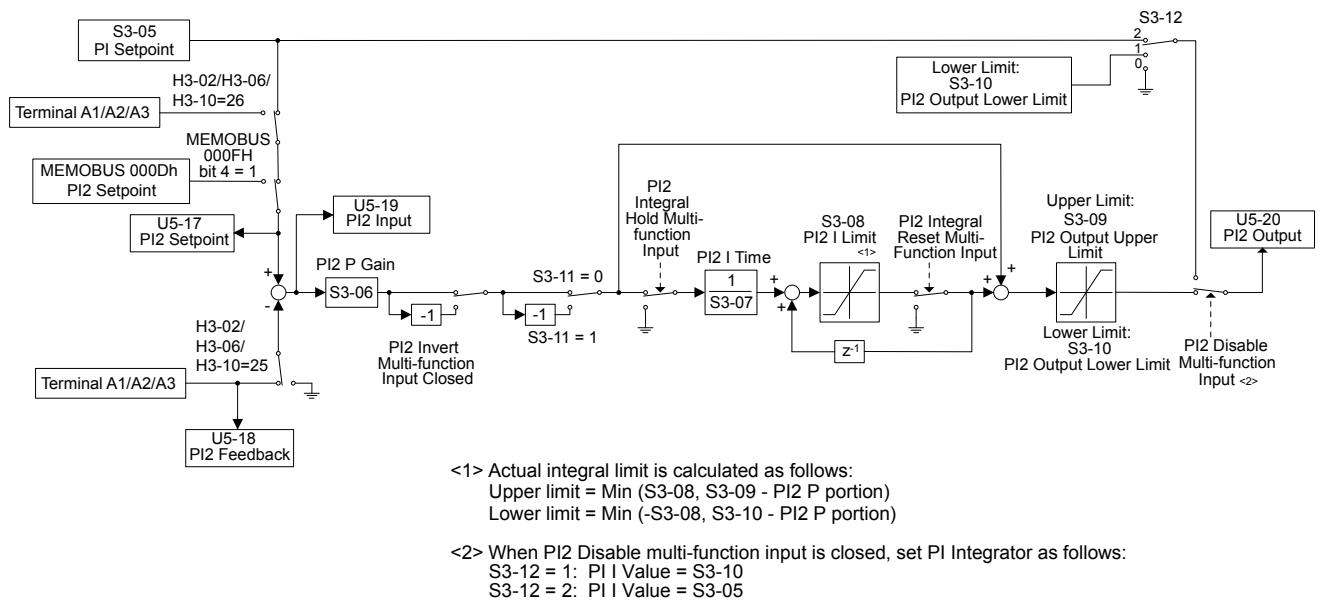


Figure 5.94 PI2 Block Diagram

■ **S3-01: Secondary PI Enable Selection**

Determines when the secondary PI controller is enabled.

5.11 S: Special Application

| No. | Name | Setting Range | Default |
|-------|-------------------------------|---------------|---------|
| S3-01 | Secondary PI Enable Selection | 0 to 3 | 0 |

Setting 0: Secondary PI Disabled

Setting 1: Always

Setting 2: Drive Running

Setting 3: Motor Running

Available when the drive is not at zero speed, not in base block, and not in DC injection.

■ S3-02: Secondary PI User Display

Sets the scale value of 100% PI input. The decimal place shifts based on S3-03.

| No. | Name | Setting Range | Default |
|-------|---------------------------|---------------|-----------|
| S3-02 | Secondary PI User Display | 0 to 60000 | 10000 <1> |

<1> Unit is determined by S3-03.

■ S3-03: Secondary PI Display Digits

Sets the decimal place display for secondary PI units.

| No. | Name | Setting Range | Default |
|-------|-----------------------------|---------------|---------|
| S3-03 | Secondary PI Display Digits | 0 to 3 | 2 |

Setting 0: No Decimal Places

Setting 1: One Decimal Place

Setting 2: Two Decimal Places

Setting 3: Three Decimal Places

■ S3-04: Secondary PI Unit Selection

Sets units for secondary PI control function.

| No. | Name | Setting Range | Default |
|-------|-----------------------------|---------------|---------|
| S3-04 | Secondary PI Unit Selection | 0 to 15 | 15 |

Setting 0: Inch of Water (WC)

Setting 1: Pounds per Square Inch (PSI)

Setting 2: Gallons per Minute (GPM)

Setting 3: Degrees Fahrenheit (F)

Setting 4: Cubic Feet per Minute (CFM)

Setting 5: Cubic Meters per Hour (CMH)

Setting 6: Liters per Hour (LPH)

Setting 7: Liters per Second (LPS)

Setting 8: Bar (Bar)

Setting 9: Pascals (Pa)

Setting 10: Degrees Celsius (C)

Setting 11: Meters (Mtr) (Ft: Feet)

Setting 12: Liters per Minute (LPM)

Setting 13: Cubic Meters per Minute (CMM)

Setting 14: No Unit

Setting 15: Percentage (%)

■ S3-05: Secondary PI Setpoint Value

Sets the secondary PI controller target value

| No. | Name | Setting Range | Default |
|-------|-----------------------------|--------------------|----------|
| S3-05 | Secondary PI Setpoint Value | 0.00 to 600.00 <1> | 0.00 <2> |

<1> Upper limit is S3-02, decimal place holder is determined by S3-03.

<2> Unit is determined by S3-04.

■ S3-06: Secondary PI Proportional Gain Setting

Sets the proportional gain of the secondary PI controller. A setting of 0.00 disables P control.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| S3-06 | Secondary PI Proportional Gain Setting | 0.00 to 25.00 | 1.00 |

■ S3-07: Secondary PI Integral Time Setting

Sets the integral time for the secondary PI controller. A setting of 0.0s disables integral control.

| No. | Name | Setting Range | Default |
|-------|------------------------------------|----------------|---------|
| S3-07 | Secondary PI Integral Time Setting | 0.0 to 360.0 s | 1.0 s |

■ S3-08: Secondary PI Integral Limit Setting

Sets the maximum output possible from the integrator.

| No. | Name | Setting Range | Default |
|-------|-------------------------------------|---------------|---------|
| S3-08 | Secondary PI Integral Limit Setting | 0.0 to 100.0% | 100.0% |

■ S3-09: Secondary PI Output Upper Limit

Sets the maximum output possible from the secondary PI controller.

| No. | Name | Setting Range | Default |
|-------|---------------------------------|---------------|---------|
| S3-09 | Secondary PI Output Upper Limit | 0 to 100.0% | 100.0% |

■ S3-10: Secondary PI Output Lower Limit

Sets the minimum output possible from the secondary PI controller.

| No. | Name | Setting Range | Default |
|-------|---------------------------------|-------------------|---------|
| S3-10 | Secondary PI Output Lower Limit | -100.00 to 100.00 | 0.00% |

■ S3-11: Secondary PI Output Level Selection

Sets the secondary PI controller output direction.

| No. | Name | Setting Range | Default |
|-------|-------------------------------------|---------------|---------|
| S3-11 | Secondary PI Output Level Selection | 0 or 1 | 0 |

Setting 0: Normal Output (Direct Acting)

Setting 1: Reverse Output (Reverse Acting)

■ S3-12: Secondary PI Disable Mode

Selects the secondary PI controller output when disabled.

| No. | Name | Setting Range | Default |
|-------|---------------------------|---------------|---------|
| S3-12 | Secondary PI Disable Mode | 0 to 2 | 0 |

Setting 0: No Output (0%)

Setting 1: Lower Limit (S3-10)

Setting 2: Setpoint

■ S3-13: Secondary PI Low Feedback Detection Level

Sets the secondary PI low feedback detection level.

| No. | Name | Setting Range | Default |
|-------|---|--------------------|----------|
| S3-13 | Secondary PI Low Feedback Detection Level | 0.00 to 600.00 </> | 0.00 </> |

<1> Upper limit is S3-02, decimal place holder is determined by S3-03.

<2> Unit is determined by S3-04.

5.11 S: Special Application

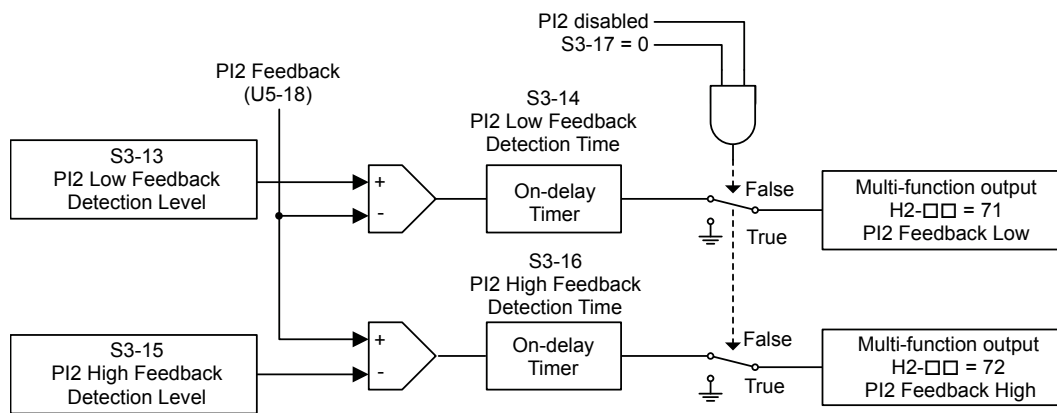


Figure 5.95 PI Low Feedback Detection Level

■ S3-14: Secondary PI Low Feedback Detection Time

Sets the secondary PI low feedback detection delay time in seconds.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| S3-14 | Secondary PI Low Feedback Detection Time | 0.0 to 25.5 s | 1.0 s |

■ S3-15: Secondary PI High Feedback Level

Sets the secondary PI high feedback detection level.

| No. | Name | Setting Range | Default |
|-------|----------------------------------|--------------------|-----------|
| S3-15 | Secondary PI High Feedback Level | 0.00 to 600.00 <1> | 300.0 <2> |

<1> Upper limit is S3-02, decimal place holder is determined by S3-03.

<2> Unit is determined by S3-04.

■ S3-16: Secondary PI High Feedback Detection Time

Sets the secondary PI high feedback detection delay time in seconds.

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------|
| S3-16 | Secondary PI High Feedback Detection Time | 0.0 to 25.5 s | 1.0 s |

■ S3-17: Secondary PI Feedback Detection Selection

Selects when secondary PI controller low and high feedback detection is active.

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------|
| S3-17 | Secondary PI Feedback Detection Selection | 0 or 1 | 0 |

Setting 0: Secondary PI Enabled

Setting 1: Always

◆ S6: P1000 Protection

■ S6-01: Emergency Override Speed

Sets the speed command used in emergency override mode when S6-02 = 0.

| No. | Name | Setting Range | Default |
|-------|--------------------------|-------------------|---------|
| S6-01 | Emergency Override Speed | 0.00 to 240.00 Hz | 0.00 Hz |

■ S6-02: Emergency Override Reference Selection

Selects the emergency override speed source.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| S6-02 | Emergency Override Reference Selection | 0, 1 | 0 |

Setting 0: Use S6-01 Reference

Setting 1: Use Frequency Reference

■ S6-07: Output Phase Loss Detection Level for Dynamic Audible Noise Control

Sets the output phase loss detection level for Dynamic Audible Noise Control. Decrease the setting in steps of 10% when output phase loss is detected erroneously. This setting rarely needs to be changed.

| No. | Name | Setting Range | Default |
|-------|---|----------------|---------|
| S6-07 | Output Phase Loss Detection Level for Dynamic Audible Noise Control | 10.0 to 100.0% | 100.0% |

◆ T: Motor Tuning

Auto-Tuning automatically sets and tunes parameters required for optimal motor performance.

Refer to Auto-Tuning on page 129 for details on Auto-Tuning parameters.

5.12 U: Monitor Parameters

Monitor parameters let the user view various aspects of drive performance using the digital operator display. Some monitors can be output from terminals FM and AM by assigning the specific monitor parameter number (U□-□□) to H4-01 and H4-04. [Refer to H4-01, H4-04: Multi-Function Analog Output Terminal FM, AM Monitor Selection on page 230](#) for details on assigning functions to an analog output.

◆ U1: Operation Status Monitors

Status monitors display drive status data such as output frequency and output current. [Refer to U1: Operation Status Monitors on page 479](#) for a complete list of U1-□□ monitors and descriptions.

◆ U2: Fault Trace

Use these monitor parameters to view the status of various drive aspects when a fault occurs.

This information is helpful for determining the cause of a fault. [Refer to U2: Fault Trace on page 481](#) for a complete list of U2-□□ monitors and descriptions.

U2-□□ monitors are not reset when the drive is initialized. [Refer to o4-11: U2, U3 Initialization on page 273](#) for instructions on how to reset these monitor values.

Note: Fault histories are not kept when CPF00, CPF01, CPF06, CPF24, oFA00, oFb00, oFC00, Uv1, Uv2, or Uv3 occur.

◆ U3: Fault History

These parameters display faults that have occurred during operation as well as the drive operation time when those faults occurred. [Refer to U3: Fault History on page 482](#) for a complete list of U3-□□ monitors and descriptions.

U3-□□ monitors are not reset when the drive is initialized. [Refer to o4-11: U2, U3 Initialization on page 273](#) for instructions on how to reset these monitor values.

Note: Fault histories are not kept when CPF00, CPF01, CPF06, CPF24, oFA00, oFb00, oFC00, Uv1, Uv2, or Uv3 occur.

◆ U4: Maintenance Monitors

Maintenance monitors show:

- Runtime data of the drive and cooling fans and number of Run commands issued
- Maintenance data and replacement information for various drive components
- kWh data
- Highest peak current that has occurred and output frequency at the time the peak current occurred
- Motor overload status information
- Detailed information about the present Run command and frequency reference source selection

[Refer to U4: Maintenance Monitors on page 483](#) for a complete list of U4-□□ monitors and descriptions.

◆ U5: PID Monitors

These monitors display various aspects of PID control. [Refer to PID Block Diagram on page 163](#) for details on how these monitors display PID data.

[Refer to U5: PID Monitors on page 485](#) for a complete list of U5-□□ monitors and descriptions.

◆ U6: Operation Status Monitors

U6 Control monitors show motor secondary current data.

[Refer to U6: Operation Status Monitors on page 485](#) for a complete list of U6-□□ monitors and descriptions.

Troubleshooting

This chapter provides descriptions of the drive faults, alarms, errors, related displays, and guidance for troubleshooting. This chapter can also serve as a reference guide for tuning the drive during a trial run.

| | | |
|-------------|---|------------|
| 6.1 | SECTION SAFETY..... | 288 |
| 6.2 | MOTOR PERFORMANCE FINE-TUNING..... | 290 |
| 6.3 | DRIVE ALARMS, FAULTS, AND ERRORS..... | 291 |
| 6.4 | FAULT DETECTION..... | 295 |
| 6.5 | ALARM DETECTION..... | 311 |
| 6.6 | OPERATOR PROGRAMMING ERRORS..... | 319 |
| 6.7 | AUTO-TUNING FAULT DETECTION..... | 322 |
| 6.8 | COPY FUNCTION RELATED DISPLAYS..... | 325 |
| 6.9 | DIAGNOSING AND RESETTING FAULTS..... | 327 |
| 6.10 | TROUBLESHOOTING WITHOUT FAULT DISPLAY..... | 329 |

6.1 Section Safety

DANGER

Electrical Shock Hazard

Before servicing, disconnect all power to the equipment. The internal capacitor remains charged even after the power supply is turned off. The charge indicator LED will extinguish when the DC bus voltage is below 50 Vdc. To prevent electric shock, wait for at least the time specified on the warning label, once all indicators are OFF, measure for unsafe voltages to confirm the drive is safe prior to servicing.

Failure to comply will result in death or serious injury.

WARNING

Electrical Shock Hazard

Do not operate equipment with covers removed.

Failure to comply could result in death or serious injury.

The diagrams in this section may illustrate drives without covers or safety shields to display details. Be sure to reinstall covers or shields before operating the drives and run the drives according to the instructions described in this manual.

Always ground the motor-side grounding terminal.

Improper equipment grounding could result in death or serious injury by contacting the motor case.

Do not touch terminals before the capacitors have fully discharged.

Failure to comply could result in death or serious injury.

Before servicing, disconnect all power to the equipment. The internal capacitor remains charged even after the power supply is turned off. The charge indicator LED will extinguish when the DC bus voltage is below 50 Vdc. To prevent electric shock, wait for at least the time specified on the warning label; after all indicators are OFF, measure for unsafe voltages to confirm the drive is safe prior to servicing.

After blowing a fuse or tripping a GFCI, do not attempt to restart the drive or operate peripheral devices until five minutes pass and CHARGE lamp is OFF.

Failure to comply could result in death, serious injury, and damage to the drive.

Check wiring and peripheral device ratings to identify the cause of trips.

Contact your supplier if the cause cannot be identified.

Do not allow unqualified personnel to perform work on the drive.

Failure to comply could result in death or serious injury.

Installation, maintenance, inspection and servicing must be performed only by authorized personnel familiar with installation, adjustment and maintenance of AC drives.

Do not perform work on the drive while wearing loose clothing, jewelry, or without eye protection.

Failure to comply could result in death or serious injury.

Remove all metal objects such as watches and rings, secure loose clothing and wear eye protection before beginning work on the drive.

Do not remove covers or touch circuit boards while the power is on.

Failure to comply could result in death or serious injury.

Fire Hazard

Tighten all terminal screws to the specified tightening torque.

Loose electrical connections could result in death or serious injury by fire due to overheating of electrical connections.

Do not use an improper voltage source.

Failure to comply could result in death or serious injury by fire.

Verify that the rated voltage of the drive matches the voltage of the incoming drive input power before applying power.

⚠ WARNING**Do not use improper combustible materials.**

Failure to comply could result in death or serious injury by fire.

Attach the drive to metal or other noncombustible material.

NOTICE**Observe proper electrostatic discharge procedures (ESD) when handling the drive and circuit boards.**

Failure to comply may result in ESD damage to the drive circuitry.

Never connect or disconnect the motor from the drive while the drive is outputting voltage.

Improper equipment sequencing could result in damage to the drive.

Do not use unshielded cable for control wiring.

Failure to comply may cause electrical interference resulting in poor system performance. Use shielded twisted-pair wires and ground the shield to the ground terminal of the drive.

Do not modify the drive circuitry.

Failure to comply could result in damage to the drive and will void warranty.

Yaskawa is not responsible for modification of the product made by the user.

Check all the wiring after installing the drive and connecting other devices to ensure that all connections are correct.

Failure to comply could result in damage to the drive.

6.2 Motor Performance Fine-Tuning

This section offers helpful information for counteracting oscillation, hunting, and other problems that occur while performing a trial run. Refer to the appropriate control method in this section.

Note: This section describes commonly edited parameters that may be set incorrectly. Consult Yaskawa for more information on detailed settings and for fine-tuning the drive.

◆ Fine-Tuning V/f Control

Table 6.1 Parameters for Fine-Tuning Performance in V/f Control

| Problem | Parameter No. | Corrective Action | Default | Suggested Setting |
|--|--|---|---|----------------------|
| Motor hunting and oscillation at speeds between 10 and 40 Hz | Hunting Prevention Gain (n1-02) | <ul style="list-style-type: none"> Reduce the setting if insufficient motor torque relative to the size of the load causes hunting. Increase the setting when motor hunting and oscillation occur with a light load. Reduce the setting if hunting occurs when using a motor with a relatively low inductance, such as a high-frequency motor or a motor with a larger frame size. | 1.00 | 0.10 to 2.00 |
| <ul style="list-style-type: none"> Motor noise Motor hunting and oscillation at speeds up to 40 Hz | Carrier Frequency Selection (C6-02) | <ul style="list-style-type: none"> Increase the carrier frequency If the motor noise is too loud. Lower the carrier frequency when motor hunting and oscillation occur at speeds up to 40 Hz. The default setting for the carrier frequency depends on the drive capacity (o2-04). | 1 (2 kHz) | 1 to max. setting |
| <ul style="list-style-type: none"> Poor torque or speed response Motor hunting and oscillation | Torque Compensation Primary Delay Time (C4-02) | <ul style="list-style-type: none"> Reduce the setting if motor torque and speed response are too slow. Increase the setting if motor hunting and oscillation occur. | 200 ms | 100 to 1000 ms |
| <ul style="list-style-type: none"> Poor motor torque at speeds below 10 Hz Motor hunting and oscillation | Torque Compensation Gain (C4-01) | <ul style="list-style-type: none"> Increase the setting if motor torque is insufficient at speeds below 10 Hz. Reduce the setting if motor hunting and oscillation with a relatively light load. | 1.00 | 0.50 to 1.50 |
| <ul style="list-style-type: none"> Poor motor torque at low speeds Motor instability at motor start | Mid Output Voltage A (E1-08) Minimum Output Voltage (E1-10) | <ul style="list-style-type: none"> Increase the setting if motor torque is insufficient at speeds below 10 Hz. Reduce the setting If motor instability occurs at motor start. | Depends on o2-04, Drive Model Selection | Default setting ±5 V |
| Poor speed precision (V/f control) | Slip Compensation Gain (C3-01) | Set the motor-rated current (E2-01), motor-rated slip (E2-02), and motor no-load current (E2-03), then adjust the slip compensation gain (C3-01). | 0.0 (no slip compensation) | 0.5 to 1.5 |

◆ Parameters to Minimize Motor Hunting and Oscillation

In addition to the parameters discussed in [Table 6.1](#), parameters in [Table 6.2](#) indirectly affect motor hunting and oscillation.

Table 6.2 Parameters that Affect Control Performance in Applications

| Name (Parameter No.) | Application |
|--|---|
| Dwell Function (b6-01 through b6-04) | Prevents motor speed loss by maintaining the output frequency when working with heavy loads or when there is powerful backlash on the machine side. |
| Accel/Decel Time (C1-01 through C1-11) | Adjusting accel and decel times will affect the torque presented to the motor during acceleration or deceleration. |
| S-Curve Characteristics (C2-01 through C2-04) | Prevents shock at the beginning and end of acceleration and deceleration. |
| Jump Frequency (d3-01 through d3-04) | Skips over the resonant frequencies of connected machinery. |
| Analog Filter Time Constant (H3-13) | Prevents fluctuation in the analog input signal due to noise. |
| Stall Prevention (L3-01 through L3-06, L3-11) | <ul style="list-style-type: none"> Prevents motor speed loss and overvoltage when the load is too heavy or during sudden acceleration/ deceleration. Adjustment is not normally necessary because Stall Prevention is enabled as a default. Set L3-04 to 0 to disable Stall Prevention during deceleration when using a braking resistor. |

6.3 Drive Alarms, Faults, and Errors

◆ Types of Alarms, Faults, and Errors

Check the digital operator for information about possible faults if the drive or motor fails to operate. *Refer to Using the Digital Operator on page 109.*

If problems occur that are not covered in this manual, contact the nearest Yaskawa representative with the following information:

- Drive model
- Software version
- Date of purchase
- Description of the problem

Table 6.3 contains descriptions of the various types of alarms, faults, and errors that may occur while operating the drive.

Table 6.3 Types of Alarms, Faults, and Errors

| Type | Drive Response |
|--------------------------------|--|
| Faults | <p>When the drive detects a fault:</p> <ul style="list-style-type: none"> • The digital operator displays text indicating the specific fault and the ALM indicator LED remains lit until the fault is reset. • The fault interrupts drive output and the motor coasts to a stop. • Some faults allow the user to select the stopping method when the fault occurs. • Fault output terminals MA-MC will close, and MB-MC will open. <p>The drive will remain inoperable until the fault is cleared. <i>Refer to Fault Reset Methods on page 328.</i></p> |
| Minor Faults and Alarms | <p>When the drive detects an alarm or a minor fault:</p> <ul style="list-style-type: none"> • The digital operator displays text indicating the specific alarm or minor fault, and the ALM indicator LED flashes. • The drive continues running the motor, although some alarms allow the user to select a stopping method when the alarm occurs. • A multi-function contact output set to be tripped by a minor fault (H2- □□ = 10) closes. If the output is set to be tripped by an alarm, the contact will not close. • The digital operator displays text indicating a specific alarm and the ALM indicator LED flashes. <p>Remove the cause of the problem to reset a minor fault or alarm.</p> |
| Operation Errors | <p>An operation error occurs when parameter settings conflict or do not match hardware settings (such as with an option card). When the drive detects an operation error:</p> <ul style="list-style-type: none"> • The digital operator displays text indicating the specific error. • Multi-function contact outputs do not operate. <p>The drive will not operate the motor until the error has been reset. Correct the settings that caused the operation error to clear the error.</p> |
| Tuning Errors | <p>Tuning errors occur while performing Auto-Tuning. When the drive detects a tuning error:</p> <ul style="list-style-type: none"> • The digital operator displays text indicating the specific error. • Multi-function contact outputs do not operate. • Motor coasts to stop. <p>Remove the cause of the error and repeat the Auto-Tuning process.</p> |
| Copy Function Errors | <p>Copy Function Errors occur when using the digital operator or the USB Copy Unit to copy, read, or verify parameter settings.</p> <ul style="list-style-type: none"> • The digital operator displays text indicating the specific error. • Multi-function contact outputs do not operate. <p>Pressing any key on the digital operator will clear the fault. Investigate the cause of the problem (such as model incompatibility) and try again.</p> |

◆ Alarm and Error Displays

■ Faults

Table 6.4 gives an overview of possible fault codes. Conditions such as overvoltages can trip faults and alarms. It is important to distinguish between faults and alarms to determine the proper corrective actions.

When the drive detects a fault, the ALM indicator LED lights, the fault code appears on the digital operator, and the fault contact MA-MB-MC triggers. An alarm is present if the ALM LED blinks and the fault code on the digital operator flashes. *Refer to Minor Faults and Alarms on page 293* for a list of alarm codes.

Table 6.4 Fault Displays

| Digital Operator Display | Name | Page | Digital Operator Display | Name | Page |
|--|--|------|--------------------------|---|------|
| bAT | Digital Operator Battery Voltage Low | 295 | oFA00 <?> | Option Card Connection Error (CN5-A) | 301 |
| boL | Braking Transistor Overload Fault | 295 | oFA01 | Option Card Fault (CN5-A) | 301 |
| bUS | Option Communication Error | 295 | oFA03 to oFA06 | Option Card Error (CN5-A) | 301 |
| CE | MEMOBUS/Modbus Communication Error | 295 | oFA10, oFA11 | Option Card Error (CN5-A) | 301 |
| CPF11 to CPF14 <?> | Control Circuit Error | 296 | oFA12 to oFA17 | Option Card Connection Error (CN5-A) | 301 |
| CPF16 to CPF19 <?> | Control Circuit Error | 296 | oFA30 to oFA43 | Comm Option Card Connection Error (CN5-A) | 301 |
| CPF02 | A/D Conversion Error | 296 | oFb00 <?> | Option Card Connection Error (CN5-B) | 301 |
| CPF03 | Control Board Connection Error | 296 | oFb01 | Option Card Fault (CN5-B) | 302 |
| CPF06 <?> | EEPROM Memory Data Error | 296 | oFb02 | Option Card Fault (CN5-B) | 302 |
| CPF07, CPF08 | Terminal Board Connection Error | 296 | oFb03, oFb11 | Option Card Error (CN5-B) | 302 |
| CPF20, CPF21 <?> | Control Circuit Error | 296 | oFb12 to oFb17 | Option Card Connection Error (CN5-B) | 302 |
| CPF22 | Hybrid IC Error | 297 | oFC00 <?> | Option Card Connection Error (CN5-C) | 302 |
| CPF23 | Control Board Connection Error | 297 | oFC01 | Option Card Fault (CN5-C) | 302 |
| CPF24 <?> | Drive Unit Signal Fault | 297 | oFC02 | Option Card Fault (CN5-C) | 302 |
| CPF25 | Terminal Board Not Connected | 297 | oFC03, oFC11 | Option Card Error (CN5-C) | 302 |
| CPF26 to CPF35, CPF40 to CPF43 <?> | Control Circuit Error | 297 | oFC12 to oFC17 | Option Card Connection Error (CN5-C) | 302 |
| E5 | SI-T3 Watchdog Timer Error | 297 | oFC50 to oFC55 | Option Card Error (CN5-C) | 303 |
| EF0 | Option Card External Fault | 297 | oH | Heatsink Overheat | 303 |
| EF1 to EF8 | External Fault (input terminal S1 to S8) | 297 | oH1 | Heatsink Overheat | 303 |
| Err | EEPROM Write Error | 298 | oH3 | Motor Overheat Alarm (PTC input) | 315 |
| FAn | Internal Fan Fault | 297 | oH4 | Motor Overheat Fault (PTC input) | 303 |
| FbH | Excessive PID Feedback | 299 | oH5 <?> | Motor Overheat (NTC Input) | 303 |
| FbL | PID Feedback Loss | 299 | oL1 | Motor Overload | 303 |
| GF | Ground Fault | 299 | oL2 | Drive Overload | 304 |
| LF | Output Phase Loss | 299 | oL3 | Overtorque Detection 1 | 304 |
| LF2 | Current Imbalance | 300 | oL4 | Overtorque Detection 2 | 305 |
| LF3 <?> | Power Unit Output Phase Loss 3 | 300 | oL7 | High Slip Braking oL | 305 |
| nSE | Node Setup Error | 300 | oPr | Operator Connection Fault | 305 |
| oC | Overcurrent | 300 | ov | Overvoltage | 305 |
| | | | PF | Input Phase Loss | 306 |
| | | | rF | Braking Resistor Fault | 306 |

| Digital Operator Display | Name | Page |
|--------------------------|------------------------------------|---------------------|
| rH | Dynamic Braking Resistor | 306 |
| rr | Dynamic Braking Transistor | 307 |
| SC | IGBT Short Circuit or Ground Fault | 307 |
| SEr | Too Many Speed Search Restarts | 307 |
| TdE | Time Data Error | 307 |
| THo <4> | Thermistor Disconnect | 307 |
| TIE | Time Interval Error | 307 |
| TIM | Time Not Set | 308 |
| UL3 | Undertorque Detection 1 | 308 |
| UL4 | Undertorque Detection 2 | 308 |
| UL6 | Motor Underload | 308 |

| Digital Operator Display | Name | Page |
|--------------------------|-----------------------------------|---------------------|
| UnbC <4> | Current Unbalance | 308 |
| Uv1 <3> | Undervoltage | 309 |
| Uv2 <3> | Control Power Supply Undervoltage | 309 |
| Uv3 <3> | Soft Charge Circuit Fault | 309 |
| Uv4 <4> | Gate Drive Board Undervoltage | 309 |
| voF | Output Voltage Detection Fault | 310 |
| vToL | VT Overload | 310 |

- <1> Displayed as CPF00 when occurring at drive power up. When one of the faults occurs after successfully starting the drive, the display will show CPF01.
- <2> Displayed as CPF20 when occurring at drive power up. When one of the faults occurs after successfully starting the drive, the display will show CPF21.
- <3> Fault histories are not kept when CPF00, CPF01, CPF06, CPF24, oFA00, oFb00, oFC00, Uv1, Uv2, or Uv3 occur.
- <4> Detected in models 4A0930 and 4A1200.

■ Minor Faults and Alarms

Refer to [Table 6.5](#) for an overview of possible alarm codes. Conditions such as overvoltages can trip faults and alarms. It is important to distinguish between faults and alarms to determine the proper corrective actions.

When the drive detects an alarm, the ALM indicator LED blinks and the alarm code display flashes. Most alarms trigger a digital output programmed for alarm output (H2-□□ = 10). A fault (not an alarm) is present if the ALM LED lights without blinking. [Refer to Faults on page 292](#) for information on fault codes.

Table 6.5 Minor Fault and Alarm Displays

| Digital Operator Display | Name | Minor Fault Output (H2-□□ = 10) | Page | Digital Operator Display | Name | Minor Fault Output (H2-□□ = 10) | Page |
|--------------------------|---|---------------------------------|---------------------|---------------------------------------|---|---------------------------------|---------------------|
| AEr | SI-T Station Number Setting Error (CC-Link, CANopen, MECHATROLINK-II) | YES | 311 | ILIM Cur Lim Foldback <0x59> | Current Limit Foldback | - | 314 |
| bAT | HOA Keypad Battery Voltage Low | YES | 295 | LT-1 | Cooling Fan Maintenance Time | No output <1> | 314 |
| bb | Drive Baseblock | No output | 311 | LT-2 | Capacitor Maintenance Time | No output <1> | 315 |
| boL | Braking Transistor Overload Fault | YES | 311 | LT-3 | Soft Charge Bypass Relay Maintenance Time | No output <1> | 315 |
| bUS | Option Card Communications Error | YES | 311 | LT-4 | IGBT Maintenance Time (50%) | No output <1> | 315 |
| CALL | Serial Communication Transmission Error | YES | 312 | oH | Heatsink Overheat | YES | 315 |
| CE | MEMOBUS/Modbus Communication Error | YES | 312 | oH2 | Drive Overheat | YES | 315 |
| CrST | Cannot Reset | YES | 312 | oH3 | Motor Overheat | YES | 315 |
| dnE | Drive Disabled | YES | 312 | oH5 <2> | Motor Overheat | YES | 315 |
| E5 | SI-T3 Watchdog Timer Error | YES | 297 | ov | Overvoltage | YES | 316 |
| EoF | Emergency Override Forward Run | YES | 313 | PASS | MEMOBUS/Modbus Test Mode Complete | No output | 316 |
| Eor | Emergency Override Reverse Run | YES | 313 | rUn | During Run 2, Motor Switch Command Input | YES | 317 |
| EF | Run Command Input Error | YES | 313 | SE | MEMOBUS/Modbus Test Mode Fault | YES | 317 |
| EF0 | Option Card External Fault | YES | 313 | TdE | Time Data Error | YES | 307 |
| EF1 to EF8 | External Fault (input terminal S1 to S8) | YES | 313 | | | | |
| FbH | Excessive PID Feedback | YES | 314 | | | | |
| FbL | PID Feedback Loss | YES | 314 | | | | |
| HCA | Current Alarm | YES | 314 | | | | |

6.3 Drive Alarms, Faults, and Errors

| Digital Operator Display | Name | Minor Fault Output (H2-□□ = 10) | Page |
|--------------------------|-----------------------------|---------------------------------|------|
| THo <2> | Thermistor Disconnect | YES | 317 |
| TIE | Time Interval Error | YES | 307 |
| TrPC | IGBT Maintenance Time (90%) | YES | 317 |
| UL6 | Motor Underload | YES | 308 |
| Uv | Undervoltage | YES | 317 |

<1> Output when H2-□□ = 2F.

<2> Detected in models 4A0930 and 4A1200.

| Digital Operator Display | Name | Minor Fault Output (H2-□□ = 10) | Page |
|--------------------------------------|---------------------------|---------------------------------|------|
| wRUn | Run Delay Timer is Active | YES | 317 |
| 1PH 1-Phase Foldback <0x5A> | Single Phase Foldback | – | 317 |

■ Operation Errors

Table 6.6 Operation Error Displays

| Digital Operator Display | Name | Page |
|--------------------------|---|------|
| oPE01 | Drive Unit Setting Error | 319 |
| oPE02 | Parameter Setting Range Error | 319 |
| oPE03 | Multi-Function Input Setting Error | 319 |
| oPE04 | Terminal Board Mismatch Error | 320 |
| oPE05 | Run Command Selection Error | 320 |
| oPE07 | Multi-Function Analog Input Selection Error | 320 |

| Digital Operator Display | Name | Page |
|--------------------------|-------------------------------------|------|
| oPE09 | PID Control Selection Error | 321 |
| oPE10 | V/f Data Setting Error | 321 |
| oPE11 | Carrier Frequency Setting Error | 321 |
| oPE13 | Pulse Train Monitor Selection Error | 321 |
| oPE28 | Sequence Timer Error | 321 |

■ Auto-Tuning Errors

Table 6.7 Auto-Tuning Error Displays

| Digital Operator Display | Name | Page |
|--------------------------|--|------|
| End1 | Excessive V/f Setting | 322 |
| End2 | Motor Iron Core Saturation Coefficient Error | 322 |
| End3 | Rated Current Setting Alarm | 322 |
| End4 | Adjusted Slip Value Fell Below Lower Limit | 322 |
| End5 | Resistance Between Lines Error | 322 |
| End6 | Leakage Inductance Alarm | 322 |
| End7 | No-Load Current Alarm | 323 |
| Er-01 | Motor Data Error | 323 |
| Er-02 | Alarm | 323 |

| Digital Operator Display | Name | Page |
|--------------------------|-------------------------------|------|
| Er-03 | STOP Button Input | 323 |
| Er-04 | Line-to-Line Resistance Error | 323 |
| Er-05 | No-Load Current Error | 323 |
| Er-08 | Rated Slip Error | 324 |
| Er-09 | Acceleration Error | 324 |
| Er-11 | Motor Speed Error | 324 |
| Er-12 | Current Detection Error | 324 |
| Er-13 | Leakage Inductance Error | 324 |
| Er-17 | Reverse Prohibited Error | 324 |

■ Errors and Displays When Using the Copy Function

Table 6.8 Copy Errors

| Digital Operator Display | Name | Page |
|--------------------------|---------------------------------------|------|
| CoPy | Writing parameter settings (flashing) | 325 |
| CPyE | Error writing data | 325 |
| CSEr | Copy unit error | 325 |
| dFPS | Drive model mismatch | 325 |
| End | Task complete | 325 |
| iFEr | Communication error | 325 |

| Digital Operator Display | Name | Page |
|--------------------------|---|------|
| ndAT | Model, voltage class, capacity mismatch | 325 |
| rdEr | Error reading data | 326 |
| rEAd | Reading parameter settings (flashing) | 326 |
| vAEr | Voltage class, capacity mismatch | 326 |
| vFyE | Parameter setting mismatch | 326 |
| vrFy | Comparing parameter settings (flashing) | 326 |

6.4 Fault Detection

◆ Fault Displays, Causes, and Possible Solutions

Faults are detected for drive protection, and cause the drive to stop while triggering the fault output terminal MA-MB-MC. Remove the cause of the fault and manually clear the fault before attempting to run the drive again.

Table 6.9 Detailed Fault Displays, Causes, and Possible Solutions

| Digital Operator Display | | Fault Name |
|---|-----|--|
| bAT | bAT | Digital Operator Battery Voltage Low |
| Cause | | Possible Solution |
| The digital operator battery is low | | Replace the digital operator battery. |
| Digital Operator Display | | Fault Name |
| boL | boL | Braking Transistor Overload Fault |
| Cause | | Possible Solution |
| The wrong braking resistor is installed | | Select the correct braking resistor. |
| Digital Operator Display | | Fault Name |
| bUS | bUS | Option Communication Error |
| Cause | | Possible Solution |
| No signal was received from the PLC | | <ul style="list-style-type: none"> • The connection was lost after establishing initial communication. • Only detected when the run command frequency reference is assigned to an option card. |
| Faulty communications wiring or an existing short circuit | | <ul style="list-style-type: none"> • Check for faulty wiring. • Correct the wiring. • Check for disconnected cables and short circuits and repair as needed. |
| Communication data error occurred due to noise | | <ul style="list-style-type: none"> • Check the various options available to minimize the effects of noise. • Counteract noise in the control circuit, main circuit, and ground wiring. • Ensure that other equipment such as switches or relays do not cause noise. Use surge absorbers if necessary. • Use only recommended cables or other shielded line. Ground the shield on the controller side or the drive input power side. • Separate all communication wiring from drive power lines. Install an EMC noise filter to the drive power supply input. |
| The option card is damaged | | Replace the option card if there are no problems with the wiring and the error continues to occur. |
| The option card is not properly connected to the drive | | <ul style="list-style-type: none"> • The connector pins on the option card do not line up properly with the connector pins on the drive. • Reinstall the option card. |
| Digital Operator Display | | Fault Name |
| CE | CE | MEMOBUS/Modbus Communication Error |
| Cause | | Possible Solution |
| Faulty communications wiring or an existing short circuit | | <ul style="list-style-type: none"> • Control data was not received for the CE detection time set to H5-09. • Check for faulty wiring. • Correct the wiring. • Check for disconnected cables and short circuits and repair as needed. |
| Communication data error occurred due to noise | | <ul style="list-style-type: none"> • Check the various options available to minimize the effects of noise. • Counteract noise in the control circuit, main circuit, and ground wiring. • Use only recommended cables or other shielded line. Ground the shield on the controller side or the drive input power side. • Ensure that other equipment such as switches or relays do not cause noise. Use surge suppressors if required. • Separate all communication wiring from drive power lines. Install an EMC noise filter to the drive power supply input. |

6.4 Fault Detection

| Digital Operator Display | | Fault Name |
|---|----------------------------------|--|
| <i>CPF00</i> or <i>CPF01</i> | CPF11 to CPF14 CPF16 to CPF19 | Control Circuit Error |
| Cause | | Possible Solution |
| There is a self-diagnostic error in the control circuit | | <ul style="list-style-type: none"> • Cycle power to the drive. • If the problem continues, replace the control board or the entire drive. Contact Yaskawa or a Yaskawa representative for instructions on replacing the control board. |
| Connector on the operator is damaged | | Replace the operator. |

| Digital Operator Display | | Fault Name |
|----------------------------|-------|--|
| <i>CPF02</i> | CPF02 | A/D Conversion Error |
| | | An A/D conversion error or control circuit error occurred. |
| Cause | | Possible Solution |
| Control circuit is damaged | | <ul style="list-style-type: none"> • Cycle power to the drive. • If the problem continues, replace the control board or the entire drive. Contact Yaskawa or a Yaskawa representative for instructions on replacing the control board. |

| Digital Operator Display | | Fault Name |
|---|-------|--|
| <i>CPF03</i> | CPF03 | Control Board Connection Error |
| | | Connection error between the control board and the drive |
| Cause | | Possible Solution |
| There is a connection error | | <ul style="list-style-type: none"> • Turn off the power and check the connection between the control board and the drive. • If the problem continues, replace the control board or the entire drive. Contact Yaskawa or a Yaskawa representative for instructions on replacing the control board. |
| Drive fails to operate properly due to electrical signal interference | | <ul style="list-style-type: none"> • Check the various options available to minimize the effects of noise. • Counteract noise in the control circuit, main circuit, and ground wiring. • Use only recommended cables or other shielded line. Ground the shield on the controller side or the drive input power side. • Ensure that other equipment such as switches or relays do not cause noise. Use surge suppressors if required. • Separate all communication wiring from drive power lines. Install an EMC noise filter to the drive power supply input. |

| Digital Operator Display | | Fault Name |
|--|-------|---|
| <i>CPF06</i> | CPF06 | EEPROM Memory Data Error |
| | | Error in the data saved to EEPROM |
| Cause | | Possible Solution |
| There is an error in EEPROM control circuit | | <ul style="list-style-type: none"> • Turn off the power and check the connection between the control board and the drive. • If the problem continues, replace the control board or the entire drive. Contact Yaskawa or a Yaskawa representative for instructions on replacing the control board. |
| The power supply was switched off while parameters were being saved to the drive | | Reinitialize the drive (A1-03 = 2220, 3330). |

| Digital Operator Display | | Fault Name |
|---|-------|---|
| <i>CPF07</i> | CPF07 | Terminal Board Connection Error |
| <i>CPF08</i> | CPF08 | |
| Cause | | Possible Solution |
| There is a faulty connection between the terminal board and the control board | | <ul style="list-style-type: none"> • Turn off the power and reconnect the terminal board. • If the problem continues, replace the control board or the entire drive. Contact Yaskawa or a Yaskawa representative for instructions on replacing the control board. |

| Digital Operator Display | | Fault Name |
|------------------------------|----------------|--|
| <i>CPF20</i> or <i>CPF21</i> | CPF20 or CPF21 | Control Circuit Error |
| Cause | | Possible Solution |
| Hardware is damaged | | <ul style="list-style-type: none"> • Cycle power to the drive. • If the problem continues, replace the control board or the entire drive. Contact Yaskawa or a Yaskawa representative for instructions on replacing the control board. |

| Digital Operator Display | | Fault Name |
|---|----------------------------------|--|
| <i>CPF22</i> | CPF22 | Hybrid IC Failure |
| Cause | | Possible Solution |
| Hybrid IC failure on the power board | | <ul style="list-style-type: none"> • Cycle power to the drive. • If the problem continues, replace the power board or the entire drive. Contact Yaskawa or a Yaskawa representative for instructions on replacing the power board. |
| Digital Operator Display | | Fault Name |
| <i>CPF23</i> | CPF23 | Control Board Connection Error |
| Cause | | Possible Solution |
| Hardware is damaged | | <ul style="list-style-type: none"> • Turn off the power and check the connection between the control board and the drive. • If the problem continues, replace the control board or the entire drive. Contact Yaskawa or a Yaskawa representative for instructions on replacing the control board. |
| Digital Operator Display | | Fault Name |
| <i>CPF24</i> | CPF24 | Drive Unit Signal Fault |
| Cause | | Possible Solution |
| Hardware is damaged | | <ul style="list-style-type: none"> • The drive capacity cannot be detected correctly (drive capacity is checked when the drive is powered up). • If the problem continues, replace the control board or the entire drive. Contact Yaskawa or a Yaskawa representative for instructions on replacing the control board. |
| Digital Operator Display | | Fault Name |
| <i>CPF25</i> | CPF25 | Terminal Board Not Connected |
| Cause | | Possible Solution |
| Terminal board is not connected correctly | | Reconnect the terminal board to the connector on the drive, then cycle the power to the drive. |
| Digital Operator Display | | Fault Name |
| <i>CPF26 to CPF35</i> <i>CPF40 to CPF43</i> | CPF26 to CPF35 CPF40 to CPF43 | Control Circuit Error |
| Cause | | Possible Solution |
| Hardware is damaged | | <ul style="list-style-type: none"> • CPU error • If the problem continues, replace the control board or the entire drive. Contact Yaskawa or a Yaskawa representative for instructions on replacing the control board. |
| Digital Operator Display | | Fault Name |
| <i>E5</i> | E5 | MECHATROLINK Watchdog Timer Error |
| Cause | | Possible Solution |
| Data has not been received from the PLC | | <ul style="list-style-type: none"> • The watchdog timed out. • Execute DISCONNECT or ALM_CLR, then issue a CONNECT command or SYNC_SET command and proceed to phase 3. Refer to the SI-T3 Option Technical Manual for more details on troubleshooting. |
| Digital Operator Display | | Fault Name |
| <i>EF0</i> | EF0 | Option Card External Fault |
| Cause | | Possible Solution |
| An external fault was received from the PLC and F6-03 is set to a value other than 3. | | <ul style="list-style-type: none"> • An external fault condition is present. • Remove the cause of the external fault. • Remove the external fault input from the PLC. |
| Problem with the PLC program | | Check the PLC program and correct problems. |
| Digital Operator Display | | Fault Name |
| <i>EF1</i> | EF1 | External Fault (input terminal S1) |
| Cause | | Possible Solution |
| <i>EF2</i> | | External Fault (input terminal S2) |
| | | External fault at multi-function input terminal S1. |
| | | External fault at multi-function input terminal S2. |

6.4 Fault Detection

| Digital Operator Display | | Fault Name |
|---|-----|--|
| <i>EF3</i> | EF3 | External Fault (input terminal S3) |
| | | External fault at multi-function input terminal S3. |
| <i>EF4</i> | EF4 | External Fault (input terminal S4) |
| | | External fault at multi-function input terminal S4. |
| <i>EF5</i> | EF5 | External Fault (input terminal S5) |
| | | External fault at multi-function input terminal S5. |
| <i>EF6</i> | EF6 | External Fault (input terminal S6) |
| | | External fault at multi-function input terminal S6. |
| <i>EF7</i> | EF7 | External Fault (input terminal S7) |
| | | External fault at multi-function input terminal S7. |
| <i>EF8</i> | EF8 | External Fault (input terminal S8) |
| | | External fault at multi-function input terminal S8. |
| Cause | | Possible Solution |
| An external device tripped an alarm function | | Remove the cause of the external fault and reset the fault. |
| Wiring is incorrect | | <ul style="list-style-type: none"> Properly connect the signal lines to the terminals assigned for external fault detection (H1-□□ = 20 to 2B). Reconnect the signal line. |
| Multi-function contact input setting is incorrect | | <ul style="list-style-type: none"> Check for unused terminals set for H1-□□ = 20 to 2B (External Fault). Change the terminal settings. |

| Digital Operator Display | | Fault Name |
|--|-----|--|
| <i>Err</i> | Err | EEPROM Write Error |
| | | Data cannot be written to the EEPROM |
| Cause | | Possible Solution |
| Noise has corrupted data while writing to the EEPROM | | <ul style="list-style-type: none"> Press “ENTER” on the digital operator. Correct the parameter setting. Cycle power to the drive. If the problem continues, replace the control board or the entire drive. Contact Yaskawa or a Yaskawa representative for instructions on replacing the control board. |
| Hardware problem | | If the problem continues, replace the control board or the entire drive. Contact Yaskawa or a Yaskawa representative for instructions on replacing the control board. |

| Digital Operator Display | | Fault Name |
|---|-----|--|
| <i>FAn</i> | FAn | Internal Fan Fault |
| | | Fan or magnetic contactor failure (detected when L8-32 = 0 to 2) |
| Cause | | Possible Solution |
| Internal cooling fan has malfunctioned | | <ul style="list-style-type: none"> Cycle power to the drive. Check for fan operation. Verify the cumulative operation time of the fan with monitor U4-03, and verify the cumulative operation time of the fan maintenance timer with U4-04. If the cooling fan has exceeded its expected performance life or is damaged in any other way, replace the fan. |
| Fault detected in the internal cooling fan or magnetic contactor to the power supply. | | <ul style="list-style-type: none"> Cycle power to the drive. If the fault continues to occur, replace the power board/gate drive board or the entire drive. Contact Yaskawa or a Yaskawa representative for instructions on replacing the power board/gate drive board. |

| Digital Operator Display | | Fault Name |
|---|-----|---|
| FbH | FbH | Excessive PID Feedback PID feedback input is greater than the level set to b5-36 for longer than the time set to b5-37. Set b5-12 to 2 or 5 to enable fault detection. |
| Cause | | Possible Solution |
| Parameters are set inappropriately | | Check b5-36 and b5-37 settings. |
| Incorrect PID feedback wiring | | Correct the wiring. |
| There is a problem with the feedback sensor | | <ul style="list-style-type: none"> Check the sensor on the control side. Replace the sensor if damaged. |

| Digital Operator Display | | Fault Name |
|---|-----|--|
| FbL | FbL | PID Feedback Loss PID feedback loss detection is programmed to trigger a fault (b5-12 = 2 or 5) and the PID feedback level is below the detection level set to b5-13 for longer than the time set to b5-14. |
| Cause | | Possible Solution |
| Parameters are set inappropriately | | Check b5-13 and b5-14 settings. |
| Incorrect PID feedback wiring | | Correct the wiring. |
| There is a problem with the feedback sensor | | <ul style="list-style-type: none"> Check the sensor on the control side. Replace the sensor if damaged. |

| Digital Operator Display | | Fault Name |
|--|----|--|
| GF | GF | Ground Fault <ul style="list-style-type: none"> A current short to ground exceeded 50% of rated current on the output side of the drive. Setting L8-09 to 1 enables ground fault detection. |
| Cause | | Possible Solution |
| Motor insulation is damaged | | <ul style="list-style-type: none"> Check the insulation resistance of the motor. Replace the motor. |
| A damaged motor cable is creating a short circuit | | <ul style="list-style-type: none"> Check the motor cable. Remove the short circuit and reapply power to the drive Check the resistance between the cable and the ground terminal ⊕. Replace the cable. |
| Excessive leakage current at the drive output | | <ul style="list-style-type: none"> Reduce the carrier frequency. Reduce the amount of stray capacitance. |
| The drive started to run during a current offset fault or while coasting to a stop | | <ul style="list-style-type: none"> Set b3-01 to 1 to enable Speed Search at Start. Perform Speed Search 1 or 2 (H1-□□ = 61 or 62) via one of the external terminals. |
| Hardware problem | | If the problem continues, replace the control board or the entire drive. Contact Yaskawa or a Yaskawa representative for instructions on replacing the control board. |

| Digital Operator Display | | Fault Name |
|--|----|---|
| LF | LF | Output Phase Loss <ul style="list-style-type: none"> Phase loss on the output side of the drive. Setting L8-07 to 1 or 2 enables Phase Loss Detection. |
| Cause | | Possible Solution |
| The output cable is disconnected | | <ul style="list-style-type: none"> Check for wiring errors and properly connect the output cable. Correct the wiring. |
| The motor winding is damaged | | <ul style="list-style-type: none"> Check the resistance between motor lines. Replace the motor if the winding is damaged. |
| The output terminal is loose | | <ul style="list-style-type: none"> Apply the tightening torque specified in this manual to fasten the terminals. <i>Refer to Main Circuit Wire Gauges and Tightening Torques on page 85</i> for details. |
| The rated current of the motor being used is less than 5% of the drive rated current | | Check the drive selection and motor capacities. |
| An output transistor is damaged | | If the problem continues, replace the control board or the entire drive. Contact Yaskawa or a Yaskawa representative for instructions on replacing the control board. |
| A single-phase motor is being used | | The drive cannot operate a single phase motor. |

6.4 Fault Detection

| Digital Operator Display | | Fault Name |
|--|-----|---|
| LF2 | LF2 | Output Current Imbalance One or more of the phases in the output current are lost. |
| Cause | | Possible Solution |
| Phase loss has occurred on the output side of the drive | | <ul style="list-style-type: none"> Check for faulty wiring or poor connections on the output side of the drive. Correct the wiring. |
| Terminal wires are loose on the output side of the drive | | Apply the tightening torque specified in this manual to fasten the terminals. <i>Refer to Main Circuit Wire Gauges and Tightening Torques on page 85</i> for details. |
| The output circuit is damaged | | If the problem continues, replace the control board or the entire drive. Contact Yaskawa or a Yaskawa representative for instructions on replacing the control board. |
| Motor impedance or motor phases are uneven | | <ul style="list-style-type: none"> Measure the line-to-line resistance for each motor phase. Ensure all values match. Replace the motor. |

| Digital Operator Display | | Fault Name |
|--|-----|---|
| LF3 <1> | LF3 | Power Unit Output Phase Loss 3 <ul style="list-style-type: none"> Phase loss occurred on the output side Setting L8-78 to 1 enables Power Unit Output Phase Loss Protection |
| Cause | | Possible Solution |
| The gate drive board in the power unit is damaged. | | Cycle the power supply. <i>Refer to Diagnosing and Resetting Faults on page 327</i> for details. If the fault continues to occur, replace the gate drive board or the entire drive. Contact Yaskawa or a Yaskawa representative for instructions on replacing the gate drive board. |
| Cable to the current detection circuit in the power unit is damaged or not connected properly. | | Check for incorrect wiring and correct any wiring mistakes. |
| Cable between the output rectifier and the power unit is loose or not connected. | | Contact Yaskawa or your nearest sales representative for instructions. |

<1> Detected in models 4A0930 and 4A1200.

| Digital Operator Display | | Fault Name |
|--|-----|---|
| nSE | nSE | Node Setup Error A terminal assigned to the node setup function closed during run. |
| Cause | | Possible Solution |
| The node setup terminal closed during run. A Run command was issued while the node setup function was active. | | Stop the drive when using the node setup function. |

| Digital Operator Display | | Fault Name |
|--|----|--|
| oC | oC | Overcurrent Drive sensors detected an output current greater than the specified overcurrent level. |
| Cause | | Possible Solution |
| The motor has been damaged due to overheating or the motor insulation is damaged | | <ul style="list-style-type: none"> Check the insulation resistance. Replace the motor. |
| One of the motor cables has shorted out or there is a grounding problem | | <ul style="list-style-type: none"> Check the motor cables. Remove the short circuit and reapply power to the drive. Check the resistance between the motor cables and the ground terminal ⊕. Replace damaged cables. |
| The load is too heavy | | <ul style="list-style-type: none"> Measure the current flowing into the motor. Replace the drive with a larger capacity drive if the current value exceeds the rated current. Determine if there is sudden fluctuation in the current level. Reduce the load to avoid sudden changes in the current level or switch to a larger drive. |
| The acceleration or deceleration times are too short | | Calculate the torque needed during acceleration relative to the load inertia and the specified acceleration time. If it is not possible to set the proper amount of torque, make the following changes: <ul style="list-style-type: none"> Increase the acceleration time (C1-01, C1-03). Increase the S-curve characteristics (C2-01 through C2-04). Increase the capacity of the drive. |

| | |
|--|--|
| The drive is attempting to operate a specialized motor or a motor larger than the maximum size allowed | <ul style="list-style-type: none"> Check the motor capacity. Ensure that the rated capacity of the drive is greater than or equal to the capacity rating found on the motor nameplate. |
| Magnetic contactor (MC) on the output side of the drive has turned on or off | Set up the operation sequence so the MC does not trip while the drive is outputting current. |
| V/f setting is not operating as expected | <ul style="list-style-type: none"> Check the ratios between the voltage and frequency. Set parameters E1-04 through E1-10 appropriately. Lower the voltage if it is too high relative to the frequency. |
| Excessive torque compensation | <ul style="list-style-type: none"> Check the amount of torque compensation. Reduce the torque compensation gain (C4-01) until there is no speed loss and less current. |
| Drive fails to operate properly due to noise interference | <ul style="list-style-type: none"> Review the possible solutions provided for handling noise interference. Review the section on handling noise interference on page 334 and check the control circuit lines, main circuit lines, and ground wiring. |
| Overexcitation gain is set too high | <ul style="list-style-type: none"> Check if the fault occurs simultaneously with overexcitation function operation. Consider motor flux saturation and reduce the value of n3-13 (Overexcitation Deceleration Gain). |
| Run command was applied while motor was coasting | <ul style="list-style-type: none"> Set b3-01 to 1 to enable Speed Search at Start. Program the Speed Search command input through one of the multi-function contact input terminals (H1-□□ = 61 or 62). |
| The rated output current of the drive is too small | Use a larger drive. |

| Digital Operator Display | | Fault Name |
|--|-------|--|
| <i>oFR00</i> | oFA00 | Option Card Connection Error at Option Port CN5-A |
| | | Option compatibility error |
| Cause | | Possible Solution |
| The option card installed into port CN5-A is incompatible with the drive | | Check if the drive supports the option card to be installed. Contact Yaskawa for assistance. |

| Digital Operator Display | | Fault Name |
|--|-------|---|
| <i>oFR01</i> | oFA01 | Option Card Fault at Option Port CN5-A |
| | | Option not properly connected |
| Cause | | Possible Solution |
| The option card connection to port CN5-A is faulty | | <ul style="list-style-type: none"> Turn off the power and reconnect the option card. Check if the option card is properly plugged into the option port. Make sure the card is fixed properly. If the option is not a communication option card, try to use the card in a different option port. If the option card works properly in a different option port, CN5-A is damaged, and the drive requires replacement. If the error persists (oFb01 or oFC01 occur), replace the option card. |

| Digital Operator Display | | Fault Name |
|------------------------------------|----------------|--|
| <i>oFR03 to oFR06</i> | oFA03 to oFA06 | Option Card Error Occurred at Option Port CN5-A |
| <i>oFR10, oFR11</i> | oFA10, oFA11 | |
| <i>oFR12 to oFR17</i> | oFA12 to oFA17 | Option Card Connection Error (CN5-A) |
| <i>oFR30 to oFR43</i> | oFA30 to oFA43 | Communication Option Card Connection Error (CN5-A) |
| Cause | | Possible Solution |
| Option card or hardware is damaged | | <ul style="list-style-type: none"> Cycle power to the drive. If the problem continues, replace the control board or the entire drive. Contact Yaskawa or a Yaskawa representative for instructions on replacing the control board. |

| Digital Operator Display | | Fault Name |
|--|-------|---|
| <i>oFb00</i> | oFb00 | Option Card Fault at Option Port CN5-B |
| | | Option compatibility error |
| Cause | | Possible Solution |
| The option card installed into port CN5-B is incompatible with the drive | | Make sure the drive supports the option card to be installed. Contact Yaskawa for assistance. |
| A communication option card has been installed in option port CN5-B | | Communication option cards are only supported by option port CN5-A. It is not possible to install more than one communication option. |

6.4 Fault Detection

| Digital Operator Display | | Fault Name |
|--|-------|---|
| <i>oFb01</i> | oFb01 | Option Card Fault at Option Port CN5-B |
| | | Option not properly connected |
| Cause | | Possible Solution |
| The option card connection to port CN5-B is faulty | | <ul style="list-style-type: none"> • Turn off the power and reconnect the option card. • Check if the option card is properly plugged into the option port. Make sure the card is fixed properly. • Try to use the card in a different option port. If the option card works properly in a different option port, CN5-B is damaged, and the drive requires replacement. If the error persists (oFA01 or oFC01 occur), replace the option card. |

| Digital Operator Display | | Fault Name |
|---|-------|--|
| <i>oFb02</i> | oFb02 | Option Card Fault at Option Port CN5-B |
| | | Same type of option card is currently connected |
| Cause | | Possible Solution |
| An option card of the same type is already installed in option port CN5-A | | Only one of each option card type can only be installed simultaneously. Make sure only one type of option card is connected. |
| An input option card is already installed in option port CN5-A | | Install a communication option. More than one of the same type of card cannot be installed simultaneously. |

| Digital Operator Display | | Fault Name |
|------------------------------------|----------------|--|
| <i>oFb03 to oFb11</i> | oFb03 to oFb11 | Option card error occurred at Option Port CN5-B |
| <i>oFb12 to oFb17</i> | oFb12 to oFb17 | |
| Cause | | Possible Solution |
| Option card or hardware is damaged | | <ul style="list-style-type: none"> • Cycle power to the drive. • If the problem continues, replace the control board or the entire drive. Contact Yaskawa or a Yaskawa representative for instructions on replacing the control board. |

| Digital Operator Display | | Fault Name |
|--|-------|---|
| <i>oFC00</i> | oFC00 | Option Card Connection Error at Option Port CN5-C |
| | | Option compatibility error |
| Cause | | Possible Solution |
| The option card installed into port CN5-C is incompatible with the drive | | Confirm that the drive supports the option card to be installed. Contact Yaskawa for assistance. |
| A communication option card has been installed in option port CN5-C | | Communication option cards are only supported by option port CN5-A. It is not possible to install more than one communication option. |

| Digital Operator Display | | Fault Name |
|---|-------|---|
| <i>oFC01</i> | oFC01 | Option Card Fault at Option Port CN5-C |
| | | Option not properly connected |
| Cause | | Possible Solution |
| The option card connection to port CN5-C is faulty. | | <ul style="list-style-type: none"> • Turn the power off and reconnect the option card. • Check if the option card is properly plugged into the option port. Make sure the card is fixed properly. • Try to use the card in a different option port. If the option card works properly in a different option port, CN5-C is damaged, and the drive requires replacement. If the error persists (oFA01 or oFb01 occur), replace the option card. |

| Digital Operator Display | | Fault Name |
|---|-------|---|
| <i>oFC02</i> | oFC02 | Option Card Fault at Option Port CN5-C |
| | | Same type of option card is currently connected |
| Cause | | Possible Solution |
| An option card of the same type is already installed in option port CN5-A or CN5-B. | | Only one of each option card type can only be installed simultaneously. Make sure only one type of option card is connected. |
| An input option card is already installed in option port CN5-A or CN5-B. | | Install a communication option, a digital input option, or an analog input option. More than one of the same type of card cannot be installed simultaneously. |

| Digital Operator Display | | Fault Name |
|--------------------------|----------------|---|
| <i>oFC03 to oFC11</i> | oFC03 to oFC11 | Option Card Error Occurred at Option Port CN5-C |
| <i>oFC12 to oFC17</i> | oFC12 to oFC17 | |

| Digital Operator Display | | Fault Name |
|------------------------------------|--|--|
| Cause | | Possible Solution |
| Option card or hardware is damaged | | <ul style="list-style-type: none"> • Cycle power to the drive. • If the problem continues, replace the control board or the entire drive. Contact Yaskawa or a Yaskawa representative for instructions on replacing the control board. |

| Digital Operator Display | | Fault Name |
|------------------------------------|----------------|---|
| Cause | | Possible Solution |
| oFC50 to oFC55 | oFC50 to oFC55 | Option Card Error Occurred at Option Port CN5-C |
| Option card or hardware is damaged | | Refer to the option manual for details. |

| Digital Operator Display | | Fault Name |
|-------------------------------------|----|--|
| Cause | | Possible Solution |
| oH | oH | Heatsink Overheat The heatsink temperature exceeded the overheat pre-alarm level set to L8-02. The default value for L8-02 is determined by drive model selection (o2-04). |
| Surrounding temperature is too high | | <ul style="list-style-type: none"> • Check the temperature surrounding the drive. Verify temperature is within drive specifications. • Improve the air circulation within the enclosure panel. • Install a fan or air conditioner to cool the surrounding area. • Remove anything near the drive that might be producing excessive heat. |
| Load is too heavy | | <ul style="list-style-type: none"> • Measure the output current. • Decrease the load. • Lower the carrier frequency selection (C6-02). |
| Internal cooling fan is stopped | | <ul style="list-style-type: none"> • Replace the cooling fan. • After replacing the cooling fan, set parameter o4-03 to 0 to reset the cooling fan maintenance. |

| Digital Operator Display | | Fault Name |
|-------------------------------------|-----|---|
| Cause | | Possible Solution |
| oH1 | oH1 | Overheat 1 (Heatsink Overheat) The heatsink temperature exceeded the drive overheat level. Overheat level is determined by drive capacity (o2-04). |
| Surrounding temperature is too high | | <ul style="list-style-type: none"> • Check the temperature surrounding the drive. • Improve the air circulation within the enclosure panel. • Install a fan or air conditioner to cool the surrounding area. • Remove anything near the drive that might be producing excessive heat. |
| Load is too heavy | | <ul style="list-style-type: none"> • Measure the output current. • Lower the carrier frequency selection (C6-02). • Reduce the load. |

| Digital Operator Display | | Fault Name |
|--------------------------|-----|--|
| Cause | | Possible Solution |
| oH5 <I> | oH5 | Motor Overheat (NTC Input) The motor temperature exceeded the level set to L1-16 (or L1-18 for motor 2) |
| Motor has overheated | | <ul style="list-style-type: none"> • Reduce the load. • Check the ambient temperature. |

<I> Detected in models 4A0930 and 4A1200.

| Digital Operator Display | | Fault Name |
|--|-----|---|
| Cause | | Possible Solution |
| oL1 | oL1 | Motor Overload The electronic motor overload protection tripped |
| Load is too heavy | | Reduce the load. |
| Cycle times are too short during acceleration and deceleration | | Increase the acceleration and deceleration times (C1-01 through C1-04). |

6.4 Fault Detection

| | |
|---|---|
| A general-purpose motor is driven below the rated speed with a high load | <ul style="list-style-type: none"> Reduce the load. Increase the speed. If the motor is supposed to operate at low speeds, either increase the motor capacity or use a motor specifically designed to operate in the desired speed range. |
| The output voltage is too high | <ul style="list-style-type: none"> Adjust the user-set V/f pattern (E1-04 through E1-10) by reducing E1-08 and E1-10. Do not set E1-08 and E1-10 too low. This reduces load tolerance at low speeds. |
| The wrong motor rated current is set to E2-01 | <ul style="list-style-type: none"> Check the motor-rated current. Enter the motor rated current to parameter E2-01 as indicated on the motor nameplate. |
| The base frequency is set incorrectly | <ul style="list-style-type: none"> Check the rated frequency indicated on the motor nameplate. Enter the rated frequency to E1-06 (Base Frequency). |
| The electrical thermal protection characteristics and motor overload characteristics do not match | <ul style="list-style-type: none"> Check the motor characteristics. Correct the type of motor protection that has been selected (L1-01). Install an external thermal relay. |
| The electrical thermal relay is operating at the wrong level | <ul style="list-style-type: none"> Check the current rating listed on the motor nameplate. Check the value set for the motor rated current (E2-01). |
| Motor overheated by overexcitation operation | <ul style="list-style-type: none"> Overexcitation increases the motor loss and the motor temperature. Excessive duration of overexcitation may cause motor damage. Prevent excessive overexcitation operation or apply proper cooling to the motor. Reduce the excitation deceleration gain (n3-13). Set L3-04 (Stall Prevention during Deceleration) to a value other than 4. |
| Parameters related to Speed Search are set incorrectly | <ul style="list-style-type: none"> Check values set to Speed Search related parameters. Adjust the Speed Search current and Speed Search deceleration times (b3-02 and b3-03 respectively). After Auto-Tuning, set b3-24 to 1 to enable Speed Estimation Speed Search. |
| Output current fluctuation due to power supply loss | Check the power supply for phase loss. |

| Digital Operator Display | | Fault Name |
|--|-----|--|
| oL2 | oL2 | Drive Overload |
| | | The thermal sensor of the drive triggered overload protection. |
| Cause | | Possible Solution |
| Load is too heavy | | Reduce the load. |
| Acceleration or deceleration time is too short | | Increase the settings for the acceleration and deceleration times (C1-01 through C1-04). |
| The output voltage is too high | | <ul style="list-style-type: none"> Adjust the preset V/f pattern (E1-04 through E1-10) by reducing E1-08 and E1-10. Do not lower E1-08 and E1-10 excessively. This reduces load tolerance at low speeds. |
| Drive capacity is too small | | Replace the drive with a larger model. |
| Overload occurred when operating at low speeds | | <ul style="list-style-type: none"> Reduce the load when operating at low speeds. Replace the drive with a model that is one frame size larger. Lower the carrier frequency (C6-02). |
| Excessive torque compensation | | Reduce the torque compensation gain in parameter C4-01 until there is no speed loss but less current. |
| Parameters related to Speed Search are set incorrectly | | <ul style="list-style-type: none"> Check the settings for all Speed Search related parameters. Adjust the current used during Speed Search (b3-03) and the Speed Search deceleration time (b3-02). After Auto-Tuning, set b3-24 to 1 to enable Speed Estimation Speed Search. |
| Output current fluctuation due to input phase loss | | Check the power supply for phase loss. |

| Digital Operator Display | | Fault Name |
|--|-----|---|
| oL3 | oL3 | Overtorque Detection 1 |
| | | The current has exceeded the value set for Torque Detection Level 1 (L6-02) for longer than the allowable time (L6-03). |
| Cause | | Possible Solution |
| Parameter settings are not appropriate for the load | | Check L6-02 and L6-03 settings. |
| Fault on the machine side (e.g., machine is locked up) | | Check the status of the load. Remove the cause of the fault. |

| Digital Operator Display | | Fault Name |
|---|-----|---|
| oL4 | oL4 | Overtorque Detection 2 |
| | | The current has exceeded the value set for Torque Detection Level 2 (L6-05) for longer than the allowable time (L6-06). |
| Cause | | Possible Solution |
| Parameter settings are not appropriate for the load | | Check the settings of parameters L6-05 and L6-06. |

| Digital Operator Display | | Fault Name |
|---|-----|---|
| oL7 | oL7 | High Slip Braking oL |
| | | The output frequency stayed constant for longer than the time set to n3-04 during High Slip Braking. |
| Cause | | Possible Solution |
| Excessive load inertia | | <ul style="list-style-type: none"> Reduce deceleration times in parameters C1-02 and C1-04 for applications that do not use High Slip Braking. Use a braking resistor to shorten deceleration time. |
| Motor is driven by the load | | |
| Something on the load side is restricting deceleration | | |
| The overload time during High Slip Braking is too short | | <ul style="list-style-type: none"> Increase parameter n3-04 (High-slip Braking Overload Time). Install a thermal relay and increase the setting of n3-04 to maximum value. |

| Digital Operator Display | | Fault Name |
|--|-----|--|
| oPr | oPr | External Digital Operator Connection Fault |
| | | The external operator has been disconnected from the drive. |
| Cause | | Possible Solution |
| External operator is not properly connected to the drive | | <ul style="list-style-type: none"> Check the connection between the operator and the drive. Replace the cable if damaged. Turn off the drive input power and disconnect the operator. Reconnect the operator and reapply drive input power. |

| Digital Operator Display | | Fault Name |
|---|----|--|
| ov | ov | Overvoltage |
| | | Voltage in the DC bus has exceeded the overvoltage detection level. |
| Cause | | Possible Solution |
| Deceleration time is too short and regenerative energy is flowing from the motor into the drive | | <ul style="list-style-type: none"> Increase the deceleration time (C1-02 and C1-04). Install a dynamic braking resistor or a dynamic braking resistor unit. Set L3-04 to 1 to enable stall prevention during deceleration. Stall Prevention is enabled as the default setting. |
| Fast acceleration time causes the motor to overshoot the speed reference | | <ul style="list-style-type: none"> Check if sudden drive acceleration triggers an overvoltage alarm. Increase the acceleration time. Use longer S-curve acceleration and deceleration times. Enable the Overvoltage Suppression function (L3-11 = 1). Lengthen the S-curve at acceleration end. |
| Excessive braking load | | The braking torque was too high, causing regenerative energy to charge the DC bus. Reduce the braking torque, use a dynamic braking option, or lengthen decel time. |
| Surge voltage entering from the drive input power | | Install a DC link choke. |
| Ground fault in the output circuit causes the DC bus capacitor to overcharge | | <ul style="list-style-type: none"> Check the motor wiring for ground faults. Correct grounding shorts and reapply power. |

6.4 Fault Detection

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|---|--|
| Improper parameters related to Speed Search (including Speed Search after a momentary power loss and after a fault restart) | <ul style="list-style-type: none"> • Check the settings for Speed Search-related parameters. • Enable Speed Search restart function (b3-19 greater than or equal to 1 to 10). • Adjust the current level during Speed Search and the deceleration time (b3-02 and b3-03 respectively). • Perform Stationary Auto-Tuning for line-to-line resistance and then set b3-14 to 1 to enable Speed Estimation Speed Search. |
| Drive input power voltage is too high | <ul style="list-style-type: none"> • Check the voltage. • Lower drive input power voltage within the limits listed in the specifications. |
| The braking transistor or braking resistor are wired incorrectly | <ul style="list-style-type: none"> • Check braking transistor and braking resistor wiring for errors. • Properly rewire the braking resistor device. |
| Drive fails to operate properly due to noise interference | <ul style="list-style-type: none"> • Review the list of possible solutions provided for controlling noise. • Review the section on handling noise interference on page 334 and check the control circuit lines, main circuit lines, and ground wiring. |
| Load inertia is set incorrectly | <ul style="list-style-type: none"> • Check the load inertia settings when using KEB, overvoltage suppression, or Stall Prevention during deceleration. • Adjust the load inertia ratio in L3-25 to better match the load. |
| Motor hunting occurs | <ul style="list-style-type: none"> • Adjust the parameters that control hunting. • Set the gain for Hunting Prevention (n1-02). • Adjust the AFR time constant (n2-02 and n2-03). |

| Digital Operator Display | | Fault Name |
|---|----|--|
| \overline{PF} | PF | Input Phase Loss |
| | | Drive input power has an open phase or has a large imbalance of voltage between phases. Detected when L8-05 is set 1 (enabled). |
| Cause | | Possible Solution |
| There is phase loss in the drive input power | | <ul style="list-style-type: none"> • Check for wiring errors in the main circuit drive input power. • Correct the wiring. |
| There is loose wiring in the drive input power terminals | | <ul style="list-style-type: none"> • Ensure the terminals are tightened properly. • Apply the tightening torque as specified in this manual. <i>Refer to Main Circuit Wire Gauges and Tightening Torques on page 85</i> for details. |
| There is excessive fluctuation in the drive input power voltage | | <ul style="list-style-type: none"> • Check the voltage from the drive input power. • Review the possible solutions for stabilizing the drive input power. |
| There is poor balance between voltage phases | | Stabilize drive input power or disable phase loss detection. |
| The main circuit capacitors are worn | | <ul style="list-style-type: none"> • Check the maintenance time for the capacitors (U4-05). • Replace the main capacitor(s) if U4-05 is greater than 90%. For instructions on replacing the capacitor(s), contact Yaskawa or a Yaskawa representative. <p>Check for problems with the drive input power. If drive input power appears normal but the alarm continues to occur, replace either the control board or the entire drive. For instructions on replacing the control board, contact Yaskawa or a Yaskawa representative.</p> |

| Digital Operator Display | | Fault Name |
|---|----|---|
| \overline{rF} | rF | Braking Resistor Fault |
| | | The resistance of the braking resistor is too low. |
| Cause | | Possible Solution |
| The proper braking resistor option has not been installed | | Select a braking resistor option that it fits the drive braking transistor specification. |
| A regenerative converter, regenerative unit, or braking unit is being used and the ⊕1 or ⊕3 terminal is connected to ⊖ terminal | | Set L8-55 to 0 to disable the braking transistor protection selection. |

| Digital Operator Display | | Fault Name |
|---|----|---|
| \overline{rH} | rH | Braking Resistor Overheat |
| | | Braking resistor protection was triggered. Fault detection is enabled when L8-01 = 1 (disabled as a default). |
| Cause | | Possible Solution |
| Deceleration time is too short and excessive regenerative energy is flowing back into the drive | | <ul style="list-style-type: none"> • Check the load, deceleration time, and speed. • Reduce the load inertia. • Increase the deceleration times (C1-01 to C1-04). • Replace the dynamic braking option with a larger device that can handle the power that is discharged. |

| | |
|---|--|
| The duty cycle is too high | Check the duty cycle. Maximum of 3% duty cycle is available when L8-01 = 1. |
| Excessive braking inertia | Recalculate braking load and braking power. Reduce the braking load by adjusting braking resistor settings. |
| The braking operation duty cycle is too high | Check the braking operation duty cycle. Braking resistor protection for ERF-type braking resistors (L8-01 = 1) allows a braking duty cycle of maximum 3%. |
| The proper braking resistor has not been installed | <ul style="list-style-type: none"> • Check the specifications and conditions for the braking resistor device. • Select the optimal braking resistor. |
| Note: The magnitude of the braking load trips the braking resistor overheat alarm, NOT the surface temperature. Using the braking resistor more frequently than its rating permits will trip the alarm even when the braking resistor surface is not very hot. | |

| Digital Operator Display | | Fault Name |
|-----------------------------------|----|--|
| rr | rr | Dynamic Braking Transistor |
| Cause | | Possible Solution |
| The braking transistor is damaged | | <ul style="list-style-type: none"> • Cycle power to the drive and check for reoccurrence of the fault. • Replace either the control board or the entire drive. For instructions on replacing the control board, contact Yaskawa or a Yaskawa representative. |
| The control circuit is damaged | | |

| Digital Operator Display | | Fault Name |
|--|----|---|
| SC | SC | IGBT Short Circuit or Ground Fault |
| Cause | | Possible Solution |
| IGBT fault | | <ul style="list-style-type: none"> • Check motor wiring. • Turn off the power supply, then turn it on. If the problem continues, contact your Yaskawa representative or the nearest Yaskawa sales office. |
| IGBT short circuit detection circuit fault | | |
| The drive is damaged | | <ul style="list-style-type: none"> • Check the drive output side short circuit for a broken output transistor B1 and U/T1, V/T2, W/T3 – and U/T1, V/T2, W/T3 • Contact your Yaskawa representative or nearest Yaskawa sales office. |

| Digital Operator Display | | Fault Name |
|--|-----|--|
| SEr | SEr | Too Many Speed Search Restarts |
| Cause | | Possible Solution |
| Parameters related to Speed Search are set to the wrong values | | <ul style="list-style-type: none"> • Reduce the detection compensation gain during Speed Search (b3-10). • Increase the current level when attempting Speed Search (b3-17). • Increase the detection time during Speed Search (b3-18). • Repeat Auto-Tuning. |
| The motor is coasting in the opposite direction of the Run command | | |
| | | Set b3-14 to 1 to enable Bi-Directional Speed Search. |

| Digital Operator Display | | Fault Name |
|---|-----|---|
| TdE | TdE | Time Data Error |
| Cause | | Possible Solution |
| An error has occurred in the Real-Clock Time function of the digital operator | | Replace the digital operator. For instructions on replacing the digital operator, contact Yaskawa or your nearest sales representative. |

| Digital Operator Display | | Fault Name |
|---|-----|------------------------------|
| THo | THo | Thermistor Disconnect |
| Cause | | Possible Solution |
| The motor thermistor is not connected properly. | | Check the thermistor wiring. |

<1> Detected in models 4A0930 and 4A1200.

| Digital Operator Display | | Fault Name |
|--------------------------|-----|---------------------|
| TIE | TIE | Time Interval Error |
| Cause | | Possible Solution |

6.4 Fault Detection

| An error has occurred in the Real-Clock Time function of the digital operator | | Replace the digital operator. For instructions on replacing the digital operator, contact Yaskawa or your nearest sales representative. |
|---|------|---|
| Digital Operator Display | | Fault Name |
| TIM | TIM | Time Not Set |
| Cause | | Possible Solution |
| The Real-Time Clock for the digital operator is not set in parameter o4-17 | | Set o4-17 to 1 to set the time for the digital operator. The drive will display the "TIM" alarm (Time Not Set) when the Real time Clock is not set . Additionally, at power up, if the "TIM" condition is present, the drive will automatically switch to the time setting screen (o4-17 = 1) for 30 seconds to prompt the user to set the Real-Time Clock. |
| <ul style="list-style-type: none"> The drive is a new drive, first power-up condition o4-17 was set to 2, Reset, by the user, manually clearing the Real-Time Clock data. | | |
| The user did not set the Real Time Clock when prompted following power-up. | | Cycle power to the drive and set the Real Time Clock within 30 seconds of power-up, or set the clock manually via parameter o4-17. |
| The digital operator battery is low or the battery has been replaced | | Replace the digital operator battery and set the Real-Time Clock. |
| An error has occurred in the Real-Time Clock function of the digital operator | | Replace the digital operator. For instructions on replacing the digital operator, contact Yaskawa or your nearest sales representative. |
| Digital Operator Display | | Fault Name |
| <i>UL3</i> | UL3 | Undertorque Detection 1 |
| | | The current has fallen below the minimum value set for Torque Detection Level 1 (L6-02) for longer than the allowable time (L6-03). |
| Cause | | Possible Solution |
| Parameter settings are not appropriate for the load | | Check the settings of parameters L6-02 and L6-03. |
| There is a fault on the machine side | | Check the load for any problems. |
| Digital Operator Display | | Fault Name |
| <i>UL4</i> | UL4 | Undertorque Detection 2 |
| | | The current has fallen below the minimum value set for Torque Detection Level 2 (L6-05) for longer than the allowable time (L6-06). |
| Cause | | Possible Solution |
| Parameter settings are not appropriate for the load | | Check L6-05 and L6-06 settings |
| There is a fault on the machine side | | Check the load for any problems. |
| Digital Operator Display | | Fault Name |
| UL6 | UL6 | Motor Underload |
| | | The weight of the load has fallen below the underload curve defined in L6-14. |
| Cause | | Possible Solution |
| The output current has fallen below the motor underload curve defined in L6-14 for longer than the time set to L6-03 | | Adjust the value set to L6-14 so that output current remains above the motor underload curve during normal operation. |
| Digital Operator Display | | Fault Name |
| <i>UnbC</i> <1> | UnbC | Current Unbalance |
| | | Current flow has become unbalanced. |
| Cause | | Possible Solution |
| The internal current sensor has detected a current unbalance situation. | | <ul style="list-style-type: none"> Check wiring Check for damaged transistors. Check for short circuits or grounding problems on the connected motor. |

<1> Detected in models 4A0930 and 4A1200.

| Digital Operator Display | | Fault Name |
|---|-----|--|
| Uv1 | Uv1 | DC Bus Undervoltage |
| | | <p>One of the following conditions occurred while the drive was running:</p> <ul style="list-style-type: none"> • Voltage in the DC bus fell below the undervoltage detection level (L2-05). • For 200 V class drives: approximately 190 V • For 400 V class drives: approximately 380 V (350 V when E1-01 is less than 400) • For 600 V class drives: approximately 475 V <p>The fault is output only if L2-01 is set to 0 or 1 and the DC bus voltage has fallen below the level set to L2-05 for longer than the time set to L2-02.</p> |
| Cause | | Possible Solution |
| Input power phase loss | | <ul style="list-style-type: none"> • The main circuit drive input power is wired incorrectly. • Correct the wiring. |
| One of the drive input power wiring terminals is loose | | <ul style="list-style-type: none"> • Ensure there are no loose terminals. • Apply the tightening torque specified in this manual to fasten the terminals. <i>Refer to Main Circuit Wire Gauges and Tightening Torques on page 85</i> for details. |
| There is a problem with the voltage from the drive input power | | <ul style="list-style-type: none"> • Check the voltage. • Correct the voltage to be within the range listed in drive input power specifications. • If there is no problem with the power supply to the main circuit, check for problems with the main circuit magnetic contactor. |
| The power has been interrupted | | Correct the drive input power. |
| The main circuit capacitors are worn | | <ul style="list-style-type: none"> • Check the maintenance time for the capacitors (U4-05). • Replace either the control board or the entire drive if U4-05 exceeds 90%. For instructions on replacing the control board, contact Yaskawa or a Yaskawa representative. |
| The relay or contactor on the soft-charge bypass relay is damaged | | <ul style="list-style-type: none"> • Cycle power to the drive and see if the fault reoccurs. • Check monitor U4-06 for the performance life of the soft-charge bypass relay. • Replace either the control board or the entire drive if U4-06 exceeds 90%. For instructions on replacing the control board, contact Yaskawa or a Yaskawa representative. |

| Digital Operator Display | | Fault Name |
|---|-----|---|
| Uv2 | Uv2 | Control Power Supply Voltage Fault |
| | | Voltage is too low for the control drive input power. |
| Cause | | Possible Solution |
| In drive models 2A0004 to 2A0056 or 4A0002 to 4A0031, L2-02 was changed from its default value without installing a Momentary Power Loss Ride-Thru unit | | Correct the setting to L2-02 or install an optional Momentary Power Loss Ride-Thru unit. |
| Control power supply wiring is damaged | | <ul style="list-style-type: none"> • Cycle power to the drive. Check if the fault reoccurs. • If the problem continues, replace the control board, the entire drive, or the control power supply. For instructions on replacing the control board, contact Yaskawa or a Yaskawa representative. |
| Internal circuitry is damaged | | <ul style="list-style-type: none"> • Cycle power to the drive. Check if the fault reoccurs. • If the problem continues, replace either the control board or the entire drive. For instructions on replacing the control board, contact Yaskawa or a Yaskawa representative. |

| Digital Operator Display | | Fault Name |
|---|-----|--|
| Uv3 | Uv3 | Undervoltage 3 (Soft-Charge Bypass Relay Fault) |
| | | The soft-charge bypass relay failed. |
| Cause | | Possible Solution |
| The relay or contactor on the soft-charge bypass relay is damaged | | <ul style="list-style-type: none"> • Cycle power to the drive and see if the fault reoccurs. • Check monitor U4-06 for the performance life of the soft-charge bypass relay. • Replace either the control board or the entire drive if U4-06 exceeds 90%. For instructions on replacing the control board, contact Yaskawa or a Yaskawa representative. |

6.4 Fault Detection

| Digital Operator Display | | Fault Name |
|---|-----|---|
| Uv4 <I> | Uv4 | Gate Drive Board Undervoltage Voltage drop in the gate drive board circuit |
| Cause | | Possible Solution |
| Not enough power is being supplied to the gate drive board. | | <ul style="list-style-type: none"> • Cycle power to the drive and see if the fault reoccurs. <i>Refer to Diagnosing and Resetting Faults on page 327</i> for details. • If the problem continues, replace either the gate drive board or the entire drive. For instructions on replacing the gate drive board, contact Yaskawa or a Yaskawa representative. |

<I> Detected in models 4A0930 and 4A1200.

| Digital Operator Display | | Fault Name |
|---|-----|--|
| voF | voF | Output Voltage Detection Fault Problem detected with the voltage on the output side of the drive. |
| Cause | | Possible Solution |
| Hardware is damaged. Internal drive module MC / FAN overheat protection circuit board is due to abnormal ambient operating power. | | <ul style="list-style-type: none"> • Lower ambient temperature. • Replace the control board or the entire drive. For instructions on replacing the control board, contact Yaskawa or a Yaskawa representative. |

| Digital Operator Display | | Fault Name |
|---|------|---|
| vToL | vToL | VT Overload |
| Cause | | Possible Solution |
| The output current of the drive has been elevated for a set length of time. | | The application may not be suited for the drive <ul style="list-style-type: none"> • The application may not be suited for the drive • The drive is undersized for the load |

6.5 Alarm Detection

◆ Alarm Codes, Causes, and Possible Solutions

Alarms are drive protection functions that do not necessarily cause the drive to stop. After removing the cause of an alarm, the drive will return to the same status it was before the alarm occurred.

When an alarm has been triggered, the ALM light on the digital operator display blinks and the alarm code display flashes. If a multi-function output is set for an alarm (H2-□□ = 10), that output terminal will be triggered.

Note: If a multi-function output is set to close when an alarm occurs (H2-□□ = 10), it will also close when maintenance periods are reached, triggering alarms LT-1 through LT-4 (triggered only if H2-□□ = 2F).

Table 6.10 Alarm Codes, Causes, and Possible Solutions

| Digital Operator Display | | Minor Fault Name |
|--|-----|--|
| <i>AEr</i> | AEr | Station Address Setting Error (CC-Link, CANopen, MECHATROLINK) |
| | | Option card node address is outside of the acceptable setting range. |
| Cause | | Possible Solutions |
| Station number is set outside the possible setting range. | | <ul style="list-style-type: none"> Set parameter F6-10 to the proper value when using a CC-Link option. Set parameter F6-35 to the proper value when using a CANopen option. |
| Digital Operator Display | | Minor Fault Name |
| <i>bb</i> | bb | Baseblock |
| | | Drive output interrupted as indicated by an external baseblock signal. |
| Cause | | Possible Solutions |
| External baseblock signal was entered via one of the multi-function input terminals (S1 to S8). | | Check external sequence and baseblock signal input timing. Note: Baseblock alarm “bb” will not activate a digital output programmed for minor fault H2-0□ = 10. Set H2-0□ = 8 or 1B to activate a digital output for “bb”. |
| Digital Operator Display | | Minor Fault Name |
| <i>boL</i> | boL | Braking Transistor Overload Fault |
| | | The braking transistor in the drive has been overloaded. |
| Cause | | Possible Solutions |
| The proper braking resistor has not been installed. | | Select the proper braking resistor. |
| Use a regen converter, regen unit, braking unit, or other device to connect the +1 or +3 terminal to the - terminal. | | Set L8-55 to 0 to disable Internal Braking Transistor Protection. |
| The use rate of the braking transistor is high (i.e., the regen converter is large or the repetition frequency is high). | | <ul style="list-style-type: none"> Change to a CDBR type braking unit. Change to a regen converter. Increase the deceleration time. |
| The braking transistor inside the drive is faulty. | | Replace the drive. |
| Digital Operator Display | | Minor Fault Name |
| <i>bUS</i> | bUS | Option Communication Error |
| | | <ul style="list-style-type: none"> The connection was lost after initial communication was established. Assign a Run command frequency reference to the option. |
| Cause | | Possible Solutions |
| Connection is broken or master controller stopped communicating. | | <ul style="list-style-type: none"> Check for faulty wiring. Correct the wiring. Check for disconnected cables and short circuits. Repair as needed. |
| Option is damaged. | | If there are no problems with the wiring and the fault continues to occur, replace the option. |
| The option is not properly connected to the drive. | | <ul style="list-style-type: none"> The connector pins on the option are not properly lined up with the connector pins on the drive. Reinstall the option. |

6.5 Alarm Detection

| Digital Operator Display | Minor Fault Name |
|-------------------------------------|--|
| A data error occurred due to noise. | <ul style="list-style-type: none"> • Check options available to minimize the effects of noise. • Take steps to counteract noise in the control circuit wiring, main circuit lines and ground wiring. • Try to reduce noise on the controller side. • Use surge absorbers on magnetic contactors or other equipment causing the disturbance. • Use recommended cables or some other type of shielded line. Ground the shield to the controller side or on the input power side. • Separate the wiring for communication devices from the drive input power lines. Install an EMC noise filter to the drive input power. |

| Digital Operator Display | Minor Fault Name |
|--|---|
| CALL | Serial Communication Transmission Error |
| CALL | Communication has not yet been established. |
| Cause | Possible Solutions |
| Communications wiring is faulty, there is a short circuit, or something is not connected properly. | <ul style="list-style-type: none"> • Check for wiring errors. • Correct the wiring. • Check for disconnected cables and short circuits. Repair as needed. |
| Programming error on the master side. | Check communications at start-up and correct programming errors. |
| Communications circuitry is damaged. | <ul style="list-style-type: none"> • Perform a self-diagnostics check. • If the problem continues, replace either the control board or the entire drive. For instructions on replacing the control board, contact Yaskawa or your nearest sales representative. |
| Termination resistor setting is incorrect. | Install a termination resistor at both ends of a communication line. Set the internal termination resistor switch correctly on slave drives. Place DIP switch S2 to the ON position. |

| Digital Operator Display | Minor Fault Name |
|--|---|
| CE | MEMOBUS/Modbus Communication Error |
| CE | Control data was not received correctly for two seconds. |
| Cause | Possible Solutions |
| A data error occurred due to noise. | <ul style="list-style-type: none"> • Check options available to minimize the effects of noise. • Take steps to counteract noise in the control circuit wiring, main circuit lines, and ground wiring. • Reduce noise on the controller side. • Use surge absorbers for the magnetic contactors or other components that may be causing the disturbance. • Use only recommended shielded line. Ground the shield on the controller side or on the drive input power side. • Separate all wiring for communication devices from drive input power lines. Install an EMC noise filter to the drive input power supply. |
| Communication protocol is incompatible. | <ul style="list-style-type: none"> • Check the H5 parameter settings and the protocol setting in the controller. • Ensure settings are compatible. |
| The CE detection time (H5-09) is set shorter than the time required for a communication cycle to take place. | <ul style="list-style-type: none"> • Check the PLC. • Change the software settings in the PLC. • Set a longer CE detection time using parameter H5-09. |
| Incompatible PLC software settings or there is a hardware problem. | <ul style="list-style-type: none"> • Check the PLC. • Remove the cause of the error on the controller side. |
| Communications cable is disconnected or damaged. | <ul style="list-style-type: none"> • Check the connector to make sure the cable has a signal. • Replace the communications cable. |

| Digital Operator Display | Minor Fault Name |
|--|--|
| CrST | Cannot Reset |
| Cause | Possible Solutions |
| Fault reset was being executed when a Run command was entered. | <ul style="list-style-type: none"> • Ensure that a Run command cannot be entered from the external terminals or option during fault reset. • Turn off the Run command. |

| Digital Operator Display | Minor Fault Name |
|--|-------------------------------|
| dnE | Drive Disabled |
| Cause | Possible Solutions |
| “Drive Enable” is set to a multi-function contact input (H1-□□ = 6A) and that signal was switched off. | Check the operation sequence. |

| Digital Operator Display | | Minor Fault Name |
|--------------------------|----|--|
| EF | EF | Forward/Reverse Run Command Input Error |
| | | Both forward run and reverse run closed simultaneously for longer than 0.5 s. |
| Cause | | Possible Solutions |
| Sequence error | | Check the forward and reverse command sequence and correct the problem. Note: When minor fault EF detected, motor ramps to stop. |

| Digital Operator Display | | Minor Fault Name |
|---|-----|--|
| EF0 | EF0 | Option Card External Fault |
| | | An external fault condition is present. |
| Cause | | Possible Solutions |
| An external fault was received from the PLC with F6-03 set to 3, which allows the drive to continue running after an external fault occurs. | | <ul style="list-style-type: none"> Remove the cause of the external fault. Remove the external fault input from the PLC. |
| There is a problem with the PLC program. | | Check the PLC program and correct problems. |

| Digital Operator Display | | Minor Fault Name |
|--|-----|---|
| EF1 | EF1 | External Fault (Input Terminal S1) |
| | | External fault at multi-function input terminal S1. |
| EF2 | EF2 | External fault (input terminal S2) |
| | | External fault at multi-function input terminal S2. |
| EF3 | EF3 | External fault (input terminal S3) |
| | | External fault at multi-function input terminal S3. |
| EF4 | EF4 | External fault (input terminal S4) |
| | | External fault at multi-function input terminal S4. |
| EF5 | EF5 | External fault (input terminal S5) |
| | | External fault at multi-function input terminal S5. |
| EF6 | EF6 | External fault (input terminal S6) |
| | | External fault at multi-function input terminal S6. |
| EF7 | EF7 | External fault (input terminal S7) |
| | | External fault at multi-function input terminal S7. |
| EF8 | EF8 | External fault (input terminal S8) |
| | | External fault at multi-function input terminal S8. |
| Cause | | Possible Solutions |
| An external device has tripped an alarm function. | | Remove the cause of the external fault and reset the multi-function input value. |
| Wiring is incorrect. | | <ul style="list-style-type: none"> Ensure the signal lines have been connected properly to the terminals assigned for external fault detection (H1-□□ = 2C to 2F). Reconnect the signal line. |
| Multi-function contact inputs are set incorrectly. | | <ul style="list-style-type: none"> Check if the unused terminals have been set for H1-□□ = 2C to 2F (External Fault). Change the terminal settings. |

| Digital Operator Display | | Minor Fault Name |
|---|-----|---|
| EoF | EoF | Emergency Override Forward Run |
| Cause | | Possible Solution |
| The multi-function digital input for EmergOverrideFWD (H1-□□ = AF) has been closed. | | Open H1-□□ = AF if the emergency condition is no longer present |

| Digital Operator Display | | Minor Fault Name |
|---|-----|---|
| Eor | Eor | Emergency Override Reverse Run |
| Cause | | Possible Solution |
| The multi-function digital input for EmergOverrideREV (H1-□□ = B0) has been closed. | | Open H1-□□ = B0 if the emergency condition is no longer present |

6.5 Alarm Detection

| Digital Operator Display | | Minor Fault Name |
|---|-----|--|
| <i>FbH</i> | FbH | Excessive PID Feedback The PID feedback input is higher than the level set to b5-36 for longer than the time set to b5-37, and b5-12 is set to 1 or 4. |
| Cause | | Possible Solutions |
| Parameter settings for b5-36 and b5-37 are incorrect. | | Check parameters b5-36 and b5-37. |
| PID feedback wiring is faulty. | | Correct the wiring. |
| Feedback sensor has malfunctioned. | | Check the sensor and replace it if damaged. |
| Feedback input circuit is damaged. | | Replace either the control board or the entire drive. For instructions on replacing the control board, contact Yaskawa or your nearest sales representative. |

| Digital Operator Display | | Minor Fault Name |
|---|-----|--|
| <i>FbL</i> | FbL | PID Feedback Loss The PID feedback input is lower than the level set to b5-13 for longer than the time set to b5-14. |
| Cause | | Possible Solutions |
| Parameter settings for b5-13 and b5-14 are incorrect. | | Check parameters b5-13 and b5-14. |
| PID feedback wiring is faulty. | | Correct the wiring. |
| Feedback sensor has malfunctioned. | | Check the sensor and replace it if damaged. |
| Feedback input circuit is damaged. | | Replace either the control board or the entire drive. For instructions on replacing the control board, contact Yaskawa or your nearest sales representative. |

| Digital Operator Display | | Minor Fault Name |
|---|-----|---|
| <i>HcA</i> | HCA | Current Alarm Drive current exceeded overcurrent warning level (150% of the rated current). |
| Cause | | Possible Solutions |
| Load is too heavy. | | Reduce the load for applications with repetitive operations (i.e., stops and starts), or replace the drive. |
| Acceleration and deceleration times are too short. | | <ul style="list-style-type: none"> Calculate the torque required during acceleration and for the inertia moment. If the torque level is not right for the load, take the following steps: <ul style="list-style-type: none"> Increase the acceleration and deceleration times (C1-01 through C1-04). Increase the capacity of the drive. |
| A special-purpose motor is being used, or the drive is attempting to run a motor greater than the maximum allowable capacity. | | <ul style="list-style-type: none"> Check the motor capacity. Use a motor appropriate for the drive. Ensure the motor is within the allowable capacity range. |
| The current level increased due to Speed Search after a momentary power loss or while attempting to perform a fault restart. | | The alarm will only appear briefly. There is no need to take action to prevent the alarm from occurring in such instances. |

| Digital Operator Display | | Minor Fault Name |
|------------------------------------|--|--|
| ILIM Cur Lim Foldback <0x59> | | Current Limit Foldback |
| | | Drive output speed is being limited due to the output current limit. |
| Cause | | Possible Solutions |
| Excessive load | | Reduce the load or replace the drive with a higher capacity drive. |

| Digital Operator Display | | Minor Fault Name |
|---|------|--|
| <i>Lf-1</i> | LT-1 | Cooling Fan Maintenance Time The cooling fan has reached its expected maintenance period and may need to be replaced. |
| | | Note: The signal closes when the maintenance period ends if H2-□□ = 2F. The signal will not close if H2-□□ = 10. |
| Cause | | Possible Solutions |
| The cooling fan has reached 90% of its expected performance life. | | Replace the cooling fan and set o4-03 to 0 to reset the Maintenance Monitor. |

| Digital Operator Display | | Minor Fault Name |
|---|------|--|
| LF-2 | LT-2 | Capacitor Maintenance Time |
| | | The main circuit and control circuit capacitors are nearing the end of their expected performance life. Note: The signal closes when the maintenance period ends if H2-□□ = 2F. The signal will not close if H2-□□ = 10. |
| Cause | | Possible Solutions |
| The main circuit and control circuit capacitors have reached 90% of their expected performance lives. | | Replace the drive. |

| Digital Operator Display | | Minor Fault Name |
|--|------|--|
| LF-3 | LT-3 | Soft Charge Bypass Relay Maintenance Time |
| | | The DC bus soft charge relay is nearing the end of its expected performance life. Note: The signal closes when the maintenance period ends if H2-□□ = 2F. The signal will not close if H2-□□ = 10. |
| Cause | | Possible Solutions |
| The DC bus soft charge relay has reached 90% of expected performance life. | | Replace the drive. |

| Digital Operator Display | | Minor Fault Name |
|--|------|---|
| LF-4 | LT-4 | IGBT Maintenance Time (50%) |
| | | IGBTs have reached 50% of their expected performance life. Note: The signal closes when the maintenance period ends if H2-□□ = 2F. The signal will not close if H2-□□ = 10. |
| Cause | | Possible Solutions |
| IGBTs have reached 50% of their expected performance life. | | Check the load, carrier frequency, and output frequency. |

| Digital Operator Display | | Minor Fault Name |
|---|----|--|
| oH | oH | Heatsink Overheat |
| | | The temperature of the heatsink exceeded the overheat pre-alarm level set to L8-02 (90-100 °C). Default value for L8-02 is determined by drive model selection (o2-04). |
| Cause | | Possible Solutions |
| Surrounding temperature is too high | | <ul style="list-style-type: none"> Check the surrounding temperature. Improve the air circulation within the enclosure panel. Install a fan or air conditioner to cool surrounding area. Remove anything near drive that may cause extra heat. |
| Internal cooling fan has stopped. | | <ul style="list-style-type: none"> Replace the cooling fan. After replacing the drive, set parameter o4-03 to 0 to reset the cooling fan operation time. |
| Airflow around the drive is restricted. | | <ul style="list-style-type: none"> Provide proper installation space around the drive as indicated in the manual. <i>Refer to Installation Orientation and Spacing on page 48</i> for details. Allow for the proper space and ensure that there is sufficient circulation around the control panel. Check for dust or other foreign materials clogging the cooling fan. Clear debris caught in the fan that restricts air circulation. |

| Digital Operator Display | | Minor Fault Name |
|--|-----|--|
| oH2 | oH2 | Heatsink Overheat Warning |
| | | “Heatsink Overheat Warning” was input to a multi-function input terminal, S1 through S8 (H1-□□ = B). |
| Cause | | Possible Solutions |
| An external device triggered an overheat warning in the drive. | | Search for the device that tripped the overheat warning. Remove the cause of the problem. |

| Digital Operator Display | | Minor Fault Name |
|--------------------------|-----|---|
| oH3 | oH3 | Motor Overheat |
| | | The motor overheat signal entered to a multi-function analog input terminal exceeded the alarm level (H3-02, H3-06 or H3-10 = E). |
| Cause | | Possible Solutions |

6.5 Alarm Detection

| Digital Operator Display | Minor Fault Name |
|--|--|
| Motor thermostat wiring is faulty (PTC input). | Repair the PTC input wiring. |
| There is a fault on the machine side (e.g., the machine is locked up). | <ul style="list-style-type: none"> Check the status of the machine. Remove the cause of the fault. |
| Motor has overheated. | <ul style="list-style-type: none"> Check the load size, accel/decel times, and cycle times. Decrease the load. Increase accel and decel times (C1-01 to C1-04). Adjust the preset V/f pattern (E1-04 through E1-10). This involves reducing E1-08 and E1-10. Note: Refrain from lowering E1-08 and E1-10 excessively to prevent a reduction in load tolerance at low speeds. Check the motor-rated current. Enter motor-rated current on motor nameplate (E2-01). Ensure the motor cooling system is operating normally. Repair or replace the motor cooling system. |

| Digital Operator Display | Fault Name |
|--------------------------|--|
| oH4 | Motor Overheat Fault (PTC Input) |
| oH4 | <ul style="list-style-type: none"> The motor overheat signal to analog input terminal A1, A2, or A3 exceeded the fault detection level. Detection requires setting multi-function analog inputs H3-02, H3-10, or H3-06 to E. |
| Cause | Possible Solution |
| Motor has overheated | <ul style="list-style-type: none"> Check the size of the load, the accel/decel times, and the cycle times. Decrease the load. Increase the acceleration and deceleration times (C1-01 through C1-04). |
| | <ul style="list-style-type: none"> Adjust the preset V/f pattern (E1-04 through E1-10) by reducing E1-08 and E1-10. Do not set E1-08 and E1-10 too low. This reduces load tolerance at low speeds. |
| | <ul style="list-style-type: none"> Check the motor rated current. Enter the motor rated current to parameter E2-01 as indicated on the motor nameplate. Ensure the motor cooling system is operating normally. Repair or replace the motor cooling system. |

| Digital Operator Display | Minor Fault Name |
|---|---|
| ou | DC Bus Overvoltage |
| ou | <p>The DC bus voltage exceeded the trip point.</p> <ul style="list-style-type: none"> For 200 V class drives: approximately 410 V For 400 V class drives: approximately 820 V (740 V when E1-01 is less than 400) For 600 V class drives: approximately 1040 V |
| Cause | Possible Solutions |
| Surge voltage present in the drive input power. | <ul style="list-style-type: none"> Install a DC link choke or an AC reactor. Voltage surge can result from a thyristor convertor and a phase advancing capacitor operating on the same drive input power system. |
| The motor is short-circuited. | <ul style="list-style-type: none"> Check the motor power cable, relay terminals and motor terminal box for short circuits. Correct grounding shorts and turn the power back on. |
| Ground current has overcharged the main circuit capacitors via the drive input power. | |
| Noise interference causes the drive to operate incorrectly. | <ul style="list-style-type: none"> Review possible solutions for handling noise interference. Review section on handling noise interference and check control circuit lines, main circuit lines and ground wiring. If the magnetic contactor is identified as a source of noise, install a surge protector to the MC coil. |
| | |

| Digital Operator Display | Minor Fault Name |
|--|---|
| PASS | MEMOBUS/Modbus Comm. Test Mode Complete |
| Cause | Possible Solutions |
| MEMOBUS/Modbus test has finished normally. | This verifies that the test was successful. |

| Digital Operator Display | | Minor Fault Name |
|--|-----|--|
| rUn | rUn | Motor Switch during Run |
| Cause | | Possible Solutions |
| A motor switch command was entered during run. | | Change the operation pattern so that the motor switch command is entered while the drive is stopped. |

| Digital Operator Display | | Minor Fault Name |
|--|----|--|
| SE | SE | MEMOBUS/Modbus Communication Test Mode Error |
| Cause | | Possible Solutions |
| A digital input set to 67H (MEMOBUS/Modbus test) was closed while the drive was running. | | Stop the drive and run the test again. |

| Digital Operator Display | | Minor Fault Name |
|--|------|-----------------------------|
| $TrPC$ | TrPC | IGBT Maintenance Time (90%) |
| Cause | | Possible Solutions |
| IGBTs have reached 90% of their expected performance life. | | Replace the drive. |

| Digital Operator Display | | Minor Fault Name |
|---|----|---|
| Uv | Uv | Undervoltage |
| Cause | | Possible Solutions |
| Phase loss in the drive input power. | | Check for wiring errors in the main circuit drive input power. Correct the wiring. |
| Loose wiring in the drive input power terminals. | | <ul style="list-style-type: none"> Ensure the terminals have been properly tightened. Apply the tightening torque to the terminals as specified. <i>Refer to Main Circuit Wire Gauges and Tightening Torques on page 85.</i> |
| There is a problem with the drive input power voltage. | | <ul style="list-style-type: none"> Check the voltage. Lower the voltage of the drive input power so that it is within the limits listed in the specifications. |
| Drive internal circuitry is worn. | | <ul style="list-style-type: none"> Check the maintenance time for the capacitors (U4-05). Replace either the control board or the entire drive if U4-05 exceeds 90%. For instructions on replacing the control board, contact Yaskawa or your nearest sales representative. |
| The drive input power transformer is too small and voltage drops when the power is switched on. | | <ul style="list-style-type: none"> Check for an alarm when the magnetic contactor, line breaker, and leakage breaker are closed. Check the capacity of the drive input power transformer. |
| Air inside the drive is too hot. | | Check the temperature inside the drive. |
| The CHARGE light is broken or disconnected. | | Replace either the control board or the entire drive. For instructions on replacing the control board, contact Yaskawa or your nearest sales representative. |

| Digital Operator Display | | Minor Fault Name |
|---|------|--|
| $WrUn$ | WrUn | Waiting for Run |
| Cause | | Possible Solutions |
| The Run command has been applied and the b1-11 timer is active. | | Adjust b1-11 to the desired delay time. The drive will start normally after the b1-11 timer expires. |

| Digital Operator Display | | Minor Fault Name |
|-----------------------------------|--|---|
| 1PH 1-Phase Foldback <0x5A> | | Output speed is being limited because of excessive DC bus voltage ripple. |
| Cause | | Possible Solutions |

6.5 Alarm Detection

| Digital Operator Display | Minor Fault Name |
|--|-------------------------|
| An input phase has been lost or too much load is being drawn by the motor in a single-phase application. | Reduce the output load. |

6.6 Operator Programming Errors

◆ Operator Programming Error Codes, Causes, and Possible Solutions

An Operator Programming Error (oPE) occurs when a contradictory parameter is set or an individual parameter is set to an inappropriate value.

The drive will not operate until the parameter or parameters causing the problem are set correctly. An oPE, however, does not trigger an alarm or fault output. If an oPE occurs, investigate the cause and refer to [Table 6.11](#) for the appropriate action. When an oPE appears on the operator display, press the ENTER button to view U1-18 and see which parameter is causing the oPE.

Table 6.11 oPE Codes, Causes, and Possible Solutions

| Digital Operator Display | | Error Name |
|--|-------|---|
| oPE01 | oPE01 | Drive Capacity Setting Fault |
| | | Drive capacity and the value set to o2-04 do not match. |
| Cause | | Possible Solutions |
| The drive model selection (o2-04) and the actual capacity of the drive are not the same. | | Correct the value set to o2-04. |

| Digital Operator Display | | Error Name |
|---|-------|---|
| oPE02 | oPE02 | Parameter Range Setting Error |
| | | Use U1-18 to find parameters set outside the range. |
| Cause | | Possible Solutions |
| Parameters were set outside the possible setting range. | | Set parameters to the proper values. |
| Note: When multiple errors occur simultaneously, other errors are given precedence over oPE02. | | |

| Digital Operator Display | | Error Name |
|---|-------|--|
| oPE03 | oPE03 | Multi-Function Input Selection Error |
| | | A contradictory setting is assigned to multi-function contact inputs H1-01 to H1-08. |
| Cause | | Possible Solutions |
| <ul style="list-style-type: none"> The same function is assigned to two multi-function inputs. Excludes “Not used” and “External Fault.” | | <ul style="list-style-type: none"> Ensure all multi-function inputs are assigned to different functions. Re-enter the multi-function settings to ensure this does not occur. |
| The Up command was set but the Down command was not, or vice versa (settings 10 vs. 11). | | Properly set the functions that required for use in combination with other functions. |
| The Up 2 command was set but the Down 2 command was not, or vice versa (settings 75 vs. 76). | | |
| <ul style="list-style-type: none"> Run/Stop command for a 2-wire sequence was set (H1-□□ = 42), but Forward/Reverse command (H1-□□ = 43) was not. “Drive Enable” is set to multi-function input S1 or S2 (H1-01 = 6A or H1-02 = 6A). | | Properly set the functions that required for use in combination with other functions. |
| Two of the following functions are set simultaneously: <ul style="list-style-type: none"> Up/Down Command (10 vs. 11) Up 2/Down 2 Command (75 vs. 76) Hold Accel/Decel Stop (A) Analog Frequency Reference Sample/Hold (1E) Offset Frequency 1, 2, 3 Calculations (44, 45, 46) | | <ul style="list-style-type: none"> Check if contradictory settings have simultaneously been assigned to the multi-function input terminals. Correct setting errors. |
| The Up/Down command (10, 11) and PID control (b5-01) are enabled simultaneously. | | Set b5-01 to 0 to disable control PID or disable the Up/Down command. |

6.6 Operator Programming Errors

| Digital Operator Display | Error Name |
|--|---|
| Settings for N.C. and N.O. input for the following functions were selected simultaneously: <ul style="list-style-type: none"> External Search Command 1 and External Search Command 2 (61 vs. 62) Fast Stop N.O. and Fast Stop N.C. (15 vs. 17) KEB for Momentary Power Loss and High Slip Braking (65, 66, 7A, 7B vs. 68) Motor Switch Command and Accel/Decel Time 2 (16 vs. 1A) KEB Command 1 and KEB Command 2 (65, 66 vs. 7A, 7B) FWD Run Command (or REV) and FWD/REV Run Command (2-wire) (40, 41 vs. 42, 43) External DB Command and Drive Enable (60 vs. 6A) Motor Switch Command and Up 2/Down 2 Command (16 vs. 75, 76) | <ul style="list-style-type: none"> Check if contradictory settings have simultaneously been assigned to the multi-function input terminals. Correct setting errors. |
| One of the following settings was entered while H1-□□ = 2 (External Reference 1/2): <ul style="list-style-type: none"> b1-15 = 4 (Pulse Train Input) but the pulse train input selection is not set for the frequency reference (H6-01 > 0) b1-15 or b1-16 set to 3 but no option card is connected Although b1-15 = 1 (Analog Input) and H3-02 or H3-10 are set to 0 (Frequency Bias) | Correct the settings for the multi-function input terminal parameters. |
| H2-□□ is set to 38 (Drive Enabled) and H1-□□ is not set to 6A (Drive Enable). | |

| Digital Operator Display | Error Name | | | | | | |
|---|------------|-------|--------------|--|---|--|--|
| <table border="1"> <tr> <td>oPE04</td> <td>oPE04</td> </tr> <tr> <td colspan="2" style="text-align: center;">Cause</td> </tr> <tr> <td colspan="2">The drive, control board, or terminal board have been replaced and the parameter settings between the control board and the terminal board no longer match.</td> </tr> </table> | oPE04 | oPE04 | Cause | | The drive, control board, or terminal board have been replaced and the parameter settings between the control board and the terminal board no longer match. | | Initialization Required, Term <-> Ctrl Chg |
| oPE04 | oPE04 | | | | | | |
| Cause | | | | | | | |
| The drive, control board, or terminal board have been replaced and the parameter settings between the control board and the terminal board no longer match. | | | | | | | |
| Possible Solutions | | | | | | | |
| Set A1-03 to 5550 to load the parameter settings stored in the terminal board to the drive. Initialize parameters after drive replacement by setting A1-03 to 1110 or 2220. | | | | | | | |

| Digital Operator Display | Error Name | | | | | | | | | | |
|--|------------|-------|--------------|--|---|--|---|--|---|--|--|
| <table border="1"> <tr> <td>oPE05</td> <td>oPE05</td> </tr> <tr> <td colspan="2" style="text-align: center;">Cause</td> </tr> <tr> <td colspan="2">Frequency reference is assigned to an option card (b1-01 = 3) and an input option card is not connected to the drive.</td> </tr> <tr> <td colspan="2">The Run command is assigned to an option card (b1-02 = 3) and an input option card is not connected to the drive.</td> </tr> <tr> <td colspan="2">Frequency reference is assigned to the pulse train input (b1-01 = 4) and terminal RP is not set for frequency reference input (H6-01 > 0)</td> </tr> </table> | oPE05 | oPE05 | Cause | | Frequency reference is assigned to an option card (b1-01 = 3) and an input option card is not connected to the drive. | | The Run command is assigned to an option card (b1-02 = 3) and an input option card is not connected to the drive. | | Frequency reference is assigned to the pulse train input (b1-01 = 4) and terminal RP is not set for frequency reference input (H6-01 > 0) | | Run Command/Frequency Reference Source Selection Error |
| oPE05 | oPE05 | | | | | | | | | | |
| Cause | | | | | | | | | | | |
| Frequency reference is assigned to an option card (b1-01 = 3) and an input option card is not connected to the drive. | | | | | | | | | | | |
| The Run command is assigned to an option card (b1-02 = 3) and an input option card is not connected to the drive. | | | | | | | | | | | |
| Frequency reference is assigned to the pulse train input (b1-01 = 4) and terminal RP is not set for frequency reference input (H6-01 > 0) | | | | | | | | | | | |
| Possible Solutions | | | | | | | | | | | |
| Reconnect the input option card to the drive. | | | | | | | | | | | |
| Set H6-01 to 0. | | | | | | | | | | | |

| Digital Operator Display | Error Name | | | | | | |
|---|------------|-------|--------------|--|--|--|---|
| <table border="1"> <tr> <td>oPE07</td> <td>oPE07</td> </tr> <tr> <td colspan="2" style="text-align: center;">Cause</td> </tr> <tr> <td colspan="2">At least two analog input terminals are set to the same function (i.e., at least two of these parameters have the same setting: H3-02, H3-10, or H3-06).</td> </tr> </table> | oPE07 | oPE07 | Cause | | At least two analog input terminals are set to the same function (i.e., at least two of these parameters have the same setting: H3-02, H3-10, or H3-06). | | Multi-Function Analog Input Selection Error A contradictory setting is assigned to multi-function analog inputs H3-02, H3-10, or H3-06 and PID functions conflict. |
| oPE07 | oPE07 | | | | | | |
| Cause | | | | | | | |
| At least two analog input terminals are set to the same function (i.e., at least two of these parameters have the same setting: H3-02, H3-10, or H3-06). | | | | | | | |
| Possible Solutions | | | | | | | |
| Change the settings to H3-02, H3-10, and H3-06 so that functions no longer conflict. | | | | | | | |
| Note: Both 0 (Frequency Reference Bias) and F (Not Used) can be set to H3-02, H3-10, or H3-06 simultaneously. | | | | | | | |
| The following simultaneous contradictory settings: <ul style="list-style-type: none"> H3-02, H3-10, or H3-06 = B (PID Feedback) while H6-01 (Pulse Train Input) = 1 (PID Feedback) H3-02, H3-10, or H3-06 = C (PID Target Value) while H6-01 = 2 (pulse train input sets the PID target value) H3-02, H3-10, or H3-06 = C (PID Target Value) while b5-18 = 1 (enables b5-19 as the target PID value) H6-01 = 2 (PID target) while b5-18 = 1 (enables b5-19 as the target PID value) | | | | | | | |
| Disable one of the PID selections. | | | | | | | |

| Digital Operator Display | | Error Name |
|--|-------|--|
| <i>oPE09</i> | oPE09 | PID Control Selection Fault |
| | | PID control function selection is incorrect. Requires that PID control is enabled (b5-01 = 1 to 4). |
| Cause | | Possible Solutions |
| The following simultaneous contradictory settings have occurred: <ul style="list-style-type: none"> • b5-15 is not set to 0.0 (PID Sleep Function Operation Level) • The stopping method is set to either DC Injection Braking or coast to stop with a timer (b1-03 = 2 or 3). | | <ul style="list-style-type: none"> • Set b5-15 to a value other than 0.0. • Set the stopping method to coast to stop or ramp to stop (b1-03 = 0 or 1). |
| b5-01 is set to 1 or 2, enabling PID control, but the lower limit for the frequency reference (d2-02) is not set to 0 while reverse output is enabled (b5-11 = 1). | | Correct the parameter settings. |
| b5-01 is set to 3 or 4, enabling PID control, but the lower limit for the frequency reference (d2-01) is not 0. | | Correct the parameter settings. |
| b5-45 > b5-43 and b5-44 | | Correct the parameter settings. |

| Digital Operator Display | | Error Name |
|----------------------------|-------|--|
| <i>oPE10</i> | oPE10 | V/f Data Setting Error |
| | | One of the following setting errors has occurred: E1-09 ≤ E1-07 < E1-06 ≤ E1-11 ≤ E1-04 |
| Cause | | Possible Solutions |
| V/f pattern setting error. | | Correct the settings for E1-04, E1-06, E1-07, E1-09, and E1-11. |

| Digital Operator Display | | Error Name |
|---|-------|--|
| <i>oPE11</i> | oPE11 | Carrier Frequency Setting Error |
| | | Correct the setting for the carrier frequency. |
| Cause | | Possible Solutions |
| The following simultaneous contradictory settings have occurred: C6-05 > 6 and C6-04 > C6-03 (carrier frequency lower limit is greater than the upper limit). If C6-05 ≤ 6, the drive operates at C6-03. | | Correct the parameter settings. |
| The upper and lower limits between C6-02 and C6-05 are contradictory. | | |

| Digital Operator Display | | Error Name |
|---|-------|---|
| oPE28 | oPE28 | Sequence Timer Error |
| | | One or more of the sequence timers is not set in the correct order. |
| Cause | | Possible Solutions |
| One of the following contradictory settings is true: <ul style="list-style-type: none"> • S2-01 > S2-02 • S2-06 > S2-07 • S2-11 > S2-12 • S2-16 > S2-17 | | Correct the parameter settings. |

6.7 Auto-Tuning Fault Detection

Auto-Tuning faults in this section are displayed on the digital operator and will cause the motor to coast to a stop. Auto-Tuning faults do not trigger a multi-function digital output set for fault or alarm output.

An End□ error on the digital operator display indicates Auto-Tuning has successfully completed with discrepancies in the calculations. Restart Auto-Tuning after fixing the cause of the End□ error.

The drive may be used in the application if no cause can be identified despite the existence of an End□ error.

An Er□ error indicates that Auto-Tuning has not completed successfully. Check for the cause of the error using the tables in this section, and perform Auto-Tuning again after fixing the cause.

◆ Auto-Tuning Codes, Causes, and Possible Solutions

Table 6.12 Auto-Tuning Codes, Causes, and Possible Solutions

| Digital Operator Display | | Error Name |
|--|------|--|
| End1 | End1 | Excessive V/f Setting (detected only during Rotational Auto-Tuning and displayed after Auto-Tuning is complete) |
| Cause | | Possible Solutions |
| The torque reference exceeded 20% during Auto-Tuning. | | <ul style="list-style-type: none"> • Prior to Auto-Tuning, verify the information on the motor nameplate. • Enter proper values from motor nameplate to parameters T1-02 and T1-04 and repeat Auto-Tuning. • If possible, disconnect the motor from the load and perform Auto-Tuning. If the load cannot be uncoupled, use the current Auto-Tuning results. |
| The results from Auto-Tuning the no-load current exceeded 80%. | | |
| Digital Operator Display | | Error Name |
| End2 | End2 | Motor Iron-Core Saturation Coefficient (detected only during Rotational Auto-Tuning and displayed after Auto-Tuning is complete) |
| Cause | | Possible Solutions |
| Motor data entered during Auto-Tuning was incorrect. | | <ul style="list-style-type: none"> • Make sure the data entered to the T1 parameters match the information written on the motor nameplate. • Restart Auto-Tuning and enter the correct information. • Check and correct faulty motor wiring. • Disconnect the motor from machine and perform Rotational Auto-Tuning. |
| Results from Auto-Tuning are outside the parameter setting range, assigning the iron-core saturation coefficients (E2-07 and E2-08) to temporary values. | | |
| Digital Operator Display | | Error Name |
| End3 | End3 | Rated Current Setting Alarm (displayed after Auto-Tuning is complete) |
| Cause | | Possible Solutions |
| The correct current rating printed on the motor nameplate was not entered into T1-04. | | <ul style="list-style-type: none"> • Check the setting of parameter T1-04. • Check the motor data and repeat Auto-Tuning. |
| Digital Operator Display | | Error Name |
| End4 | End4 | Adjusted Slip Calculation Error |
| Cause | | Possible Solutions |
| The calculated slip is outside the allowable range. | | <ul style="list-style-type: none"> • Make sure the data entered for Auto-Tuning is correct. • If possible, perform Rotational Auto-Tuning. If not possible, perform Stationary Auto-Tuning 2. |
| Digital Operator Display | | Error Name |
| End5 | End5 | Resistance Tuning Error |
| Cause | | Possible Solutions |
| The calculated resistance value is outside the allowable range. | | <ul style="list-style-type: none"> • Double-check the data entered for the Auto-Tuning process. • Check the motor and motor cable connection for faults. |
| Digital Operator Display | | Error Name |
| End6 | End6 | Leakage Inductance Alarm |
| Cause | | Possible Solutions |
| The calculated leakage inductance value is outside the allowable range. | | Double-check the data entered for the Auto-Tuning process. |

| Digital Operator Display | | Error Name |
|--|------|--|
| End7 | End7 | No-Load Current Alarm |
| Cause | | Possible Solutions |
| The entered no-load current value was outside the allowable range. | | Check and correct faulty motor wiring. |
| Auto-Tuning results were less than 5% of the motor rated current. | | Double-check the data entered for the Auto-Tuning process. |

| Digital Operator Display | | Error Name |
|---|-------|--|
| Er-01 | Er-01 | Motor Data Error |
| Cause | | Possible Solutions |
| Motor data or data entered during Auto-Tuning was incorrect. | | <ul style="list-style-type: none"> Check that the motor data entered to T1 parameters matches motor nameplate input before Auto-Tuning. Restart Auto-Tuning and enter the correct information. |
| Motor output power and motor-rated current settings (T1-02 and T1-04) do not match. | | <ul style="list-style-type: none"> Check the drive and motor capacities. Correct the settings of parameters T1-02 and T1-04. |
| Motor rated current and detected no-load current are inconsistent. | | <ul style="list-style-type: none"> Check the motor rated current and no-load current. Correct the settings of parameters T1-04 and E2-03. |

| Digital Operator Display | | Error Name |
|--|-------|--|
| Er-02 | Er-02 | Minor Fault |
| Cause | | Possible Solutions |
| An alarm was triggered during Auto-Tuning. | | Exit the Auto-Tuning menu, check the alarm code, remove the alarm cause, and repeat Auto-Tuning. |

| Digital Operator Display | | Error Name |
|---|-------|---|
| Er-03 | Er-03 | STOP Button Input |
| Cause | | Possible Solutions |
| Auto-Tuning canceled by pressing STOP button. | | Auto-Tuning did not complete properly. Restart Auto-Tuning. |

| Digital Operator Display | | Error Name |
|---|-------|---|
| Er-04 | Er-04 | Line-to-Line Resistance Error |
| Cause | | Possible Solutions |
| Motor data entered during Auto-Tuning was incorrect. | | <ul style="list-style-type: none"> Make sure the data entered to the T1 parameters match the information written on the motor nameplate. Restart Auto-Tuning and enter the correct information. |
| Results from Auto-Tuning are outside the parameter setting range or the tuning process took too long. | | Check and correct faulty motor wiring. |
| Faulty motor cable or cable connection. | | |

| Digital Operator Display | | Error Name |
|---|-------|---|
| Er-05 | Er-05 | No-Load Current Error |
| Cause | | Possible Solutions |
| Motor data entered during Auto-Tuning was incorrect. | | <ul style="list-style-type: none"> Make sure the data entered to the T1 parameters match the information written on the motor nameplate. Restart Auto-Tuning and enter the correct information. |
| Results from Auto-Tuning are outside the parameter setting range or the tuning process took too long. | | <ul style="list-style-type: none"> Check and correct faulty motor wiring. Perform Rotational Auto-Tuning. |
| The load was too high during Rotational Auto-tuning. | | <ul style="list-style-type: none"> Disconnect the motor from machine and restart Auto-Tuning. If motor and load cannot be uncoupled make sure the load is lower than 30%. If a mechanical brake is installed, make sure it is fully lifted during tuning. |

6.7 Auto-Tuning Fault Detection

| Digital Operator Display | | Error Name |
|---|-------|---|
| $E_r - 08$ | Er-08 | Rated Slip Error |
| Cause | | Possible Solutions |
| Motor data entered during Auto-Tuning was incorrect. | | <ul style="list-style-type: none"> Make sure the data entered to the T1 parameters match the information written on the motor nameplate. Restart Auto-Tuning and enter the correct information. |
| Results from Auto-Tuning are outside the parameter setting range or the tuning process took too long. | | <ul style="list-style-type: none"> Check and correct faulty motor wiring. Perform Rotational Auto-Tuning. |
| The load was too high during rotational Auto-tuning. | | <ul style="list-style-type: none"> Disconnect the motor from machine and restart Auto-Tuning. If motor and load cannot be uncoupled make sure the load is lower than 30%. If a mechanical brake is installed, make sure it is fully lifted during tuning. |

| Digital Operator Display | | Error Name |
|---|-------|---|
| $E_r - 09$ | Er-09 | Acceleration Error |
| Cause | | Possible Solutions |
| The motor did not accelerate for the specified acceleration time. | | <ul style="list-style-type: none"> Increase the acceleration time (C1-01). Disconnect the machine from the motor if possible. |
| The load was too high during Rotational Auto-Tuning. | | <ul style="list-style-type: none"> Disconnect the motor from machine and restart Auto-Tuning. If motor and load cannot be uncoupled make sure the load is lower than 30%. If a mechanical brake is installed, make sure it is fully lifted during tuning. |

| Digital Operator Display | | Error Name |
|-------------------------------|-------|---|
| $E_r - 11$ | Er-11 | Motor Speed Fault |
| Cause | | Possible Solutions |
| Torque reference is too high. | | <ul style="list-style-type: none"> Increase the acceleration time (C1-01). Disconnect the machine from the motor if possible. |

| Digital Operator Display | | Error Name |
|---|-------|---|
| $E_r - 12$ | Er-12 | Current Detection Error |
| Cause | | Possible Solutions |
| One of the motor phases is missing: (U/T1, V/T2, W/T3). | | Check motor wiring and correct any problems. |
| The current exceeded the current rating of the drive. | | <ul style="list-style-type: none"> Check motor wiring for a short between motor lines. Close any magnetic contactors used between motors. |
| The current is too low. | | <ul style="list-style-type: none"> Replace the control board or the entire drive. For instructions on replacing the control board, contact Yaskawa or your nearest sales representative. |
| Attempted Auto-Tuning without motor connected to the drive. | | Connect the motor and restart Auto-Tuning. |
| Current detection signal error. | | Replace the control board or the entire drive. For instructions on replacing the control board, contact Yaskawa or your nearest sales representative. |

| Digital Operator Display | | Error Name |
|--|-------|--|
| $E_r - 13$ | Er-13 | Leakage Inductance Error |
| Cause | | Possible Solutions |
| Drive was unable to complete tuning for leakage inductance within 300 seconds. | | <ul style="list-style-type: none"> Check all wiring and correct any mistakes. Check the motor rated current value written on the motor nameplate and enter the correct value to T1-04. |

| Digital Operator Display | | Error Name |
|--|-------|---|
| $E_r - 17$ | Er-17 | Reverse Prohibited Error |
| Cause | | Possible Solutions |
| Drive is prohibited from rotating the motor in reverse while attempting to perform Inertia Tuning. | | <ul style="list-style-type: none"> Inertia Auto-Tuning cannot be performed if the drive is restricted from rotating in reverse. Assuming it is acceptable for the application to rotate in reverse, set b1-04 to 0 and then perform Inertia Tuning. |

6.8 Copy Function Related Displays

◆ Tasks, Errors, and Troubleshooting

The table below lists the messages and errors that may appear when using the Copy function.

When executing the tasks offered by the Copy function, the operator will indicate the task being performed. When an error occurs, a code appears on the operator to indicate the error. Note that errors related to the Copy function do not trigger a multi-function output terminal that has been set up to close when a fault or alarm occurs. To clear an error, simply press any key on the operator and the error display will disappear.

Table 6.13 lists the corrective action that can be taken when an error occurs.

- Note:**
1. Whenever using the copy function, the drive should be fully stopped.
 2. The drive will not accept a Run command while the Copy function is being executed.
 3. Parameters can only be saved to a drive when the voltage class, capacity, control mode, and software version match.

Table 6.13 Copy Function Task and Error Displays

| Digital Operator Display | | Task |
|---|------|---|
| <i>CoPy</i> | CoPy | Writing Parameter Settings (flashing) |
| Cause | | Possible Solutions |
| Parameters are being written to the drive. | | This is not an error. |
| Digital Operator Display | | Task |
| <i>CPyE</i> | CPyE | Error Writing Data |
| Cause | | Possible Solutions |
| Failed writing parameters | | Attempt to write parameters again. |
| Digital Operator Display | | Task |
| <i>CSEr</i> | CSEr | Copy Unit Error |
| Cause | | Possible Solutions |
| Hardware fault | | Replace the operator or the USB Copy Unit. |
| Digital Operator Display | | Task |
| <i>dFPS</i> | dFPS | Drive Model Mismatch |
| Cause | | Possible Solutions |
| The drives used in the copy and write process are not the same model. | | <ul style="list-style-type: none"> • Verify the model number of the drive from which the parameters were copied and the model of the drive to which those parameters will be written. • Make sure the two drives are the same model and have the same software version. |
| <ul style="list-style-type: none"> • The drive from which the parameters were copied is a different model. • The drive to be written to is a different model. | | |
| | | |
| Digital Operator Display | | Task |
| <i>End</i> | End | Task Complete |
| Cause | | Possible Solutions |
| Finished reading, writing, or verifying parameters. | | This is not an error. |
| Digital Operator Display | | Task |
| <i>iFEr</i> | iFEr | Communication Error |
| Cause | | Possible Solutions |
| A communication error occurred between the drive and the operator or the USB copy unit. | | Check the cable connection. |
| A non-compatible cable is being used to connect the USB Copy Unit and the drive. | | Use the cable originally packaged with the USB Copy Unit. |
| Digital Operator Display | | Task |
| <i>ndAT</i> | ndAT | Model, Voltage Class, Capacity Mismatch |
| Cause | | Possible Solutions |
| | | |

6.8 Copy Function Related Displays

| | |
|--|--|
| The drive from which the parameters were copied and the drive to which the parameters will be written have different electrical specifications, capacities, are set to different control modes, or are different models. | Make sure model numbers and specifications are the same for both drives. |
| The device being used to write the parameters is blank and does not have any parameters saved on it. | Make sure all connections are correct, and copy the parameter settings onto the USB Copy Unit or the operator. |

| Digital Operator Display | | Task |
|--|-------|---|
| <i>r dEr</i> | r dEr | Error Reading Data |
| Cause | | Possible Solutions |
| Failed while attempting to read parameter settings from the drive. | | Press and hold the READ key on the USB Copy Unit for at least one second to have the unit read parameters from the drive. |

| Digital Operator Display | | Task |
|---|-------|---------------------------------------|
| <i>r rAd</i> | r rAd | Reading Parameter Settings (flashing) |
| Cause | | Possible Solutions |
| Displayed while the parameter settings are being read onto the USB Copy Unit. | | This is not an error. |

| Digital Operator Display | | Task |
|---|-------|--|
| <i>v rEr</i> | v rEr | Voltage Class, Capacity Mismatch |
| Cause | | Possible Solutions |
| The drive from which the parameters were copied and the drive on which the Verify mode is being performed have different electrical specifications or are a different capacity. | | Make sure electrical specifications and capacities are the same for both drives. |

| Digital Operator Display | | Task |
|--|-------|---|
| <i>v FyE</i> | v FyE | Parameter settings in the drive and those saved to the copy function are not the same |
| Cause | | Possible Solutions |
| Indicates that parameter settings that have been Read and loaded onto the Copy Unit or Digital Operator are different. | | To synchronize parameters, either write the parameters saved on the USB Copy Unit or digital operator onto the drive, or Read the parameter settings on the drive onto the USB Copy Unit. |

| Digital Operator Display | | Task |
|---|-------|---|
| <i>v rFy</i> | v rFy | Comparing Parameter Settings (flashing) |
| Cause | | Possible Solutions |
| The Verify mode has confirmed that parameters settings on the drive and parameters read to the copy device are identical. | | This is not an error. |

6.9 Diagnosing and Resetting Faults

When a fault occurs and the drive stops, follow the instructions below to remove whatever conditions triggered the fault, then restart the drive.

Note: An oC/SC fault will be displayed in the event of an IGBT failure. It may not be possible to reset this fault until the IGBT problem is corrected.

◆ Fault Occurs Simultaneously with Power Loss

WARNING! Electrical Shock Hazard. Ensure there are no short circuits between the main circuit terminals (R/L1, S/L2, and T/L3) or between the ground and main circuit terminals before restarting the drive. Failure to comply may result in serious injury or death and will cause damage to equipment.

1. Turn on the drive input power.
2. Use monitor parameters U2-□□ to display data on the operating status of the drive just before the fault occurred.
3. Remove the cause of the fault and reset.







Note:

1. To find out what faults were triggered, check the fault history in U2-02. Information on drive status when the fault occurred such as the frequency, current, and voltage can be found in U2-03 through U2-20. [Refer to Viewing Fault Trace Data After Fault on page 327](#) for information on how to view fault data.
2. When the fault continues to be displayed after cycling power, remove the cause of the fault and reset.

◆ If the Drive Still has Power After a Fault Occurs


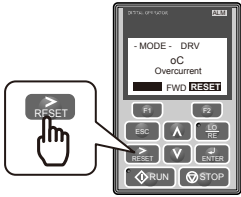
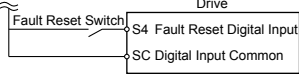
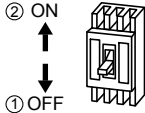
1. Look at the digital operator for information on the fault that occurred.
2. [Refer to Fault Displays, Causes, and Possible Solutions on page 295.](#)
3. Reset the fault. [Refer to Fault Reset Methods on page 328.](#)

◆ Viewing Fault Trace Data After Fault

| Step | | Display/Result |
|--|---|---|
| 1. Turn on the drive input power. The first screen displays. | → | <pre> - MODE - DRV Rdy FREF (OPR) U1-01= 0.00Hz U1-02= 0.00Hz[LSEQ U1-03= 0.00A [LREF JOG FWD FWD/REV </pre> |
| 2. Press  or  until the monitor screen is displayed. | → | <pre> - MODE - DRV Rdy Monitor Menu U1-01= 0.00Hz U1-02= 0.00Hz[LSEQ U1-03= 0.00A [LREF JOG FWD FWD/REV </pre> |
| 3. Press  to display the parameter setting screen. | → | <pre> -MONITR- DRV Rdy Monitor U1-01= 0.00Hz U1-02= 0.00Hz[LSEQ U1-03= 0.00A [LREF JOG FWD FWD/REV </pre> |
| 4. Press  and  to scroll to monitor U2-02. The fault code shown in U2-02 is the fault that occurred most recently. | → | <pre> - MONITR - DRV Rdy Last Fault U2-02= oC U2-03= 0.00Hz[LSEQ U2-04= 0.00Hz[LREF JOG FWD FWD/REV </pre> |
| 5. Press  to view drive status information when fault occurred. Parameters U2-03 through U2-20 help determine the cause of a fault. Parameters to be monitored differ depending on the control mode. | → | <pre> - MONITR - DRV Rdy Frequency Ref U2-03= 0.00Hz U2-04= 0.00Hz[LSEQ U2-05= 0.00A [LREF JOG FWD FWD/REV </pre> <p style="text-align: center;">↑ ↓</p> <pre> - MONITR - DRV Rdy Heatsink Temp U2-20= XX °C U2-01= ---- [LSEQ U2-02= ---- [LREF JOG FWD FWD/REV </pre> |

◆ Fault Reset Methods

When a fault occurs, the cause of the fault must be removed and the drive must be restarted. The table below lists the different ways to restart the drive.

| After the Fault Occurs | Procedure | |
|--|---|---|
| Fix the cause of the fault, restart the drive, and reset the fault | Press  on the digital operator when the error code is displayed. |  |
| Resetting via Fault Reset Digital Input S4 | Close then open the fault signal digital input via terminal S4. S4 is set for "Fault Reset" as default (H1-04 = 14). |  |
| Turn off the main power supply if the above methods do not reset the fault. Reapply power after the digital operator display has turned off. |  | |

Note: If the Run command is present, the drive will disregard any attempts to reset the fault. Remove the Run command before attempting to clear a fault situation.

6.10 Troubleshooting without Fault Display

This section describes troubleshooting problems that do not trip an alarm or fault.

The following symptoms indicate that the drive is not set correctly for proper performance with the motor. *Refer to Motor Performance Fine-Tuning on page 290* for guidance on troubleshooting.

- Motor hunting and oscillation
- Poor motor torque
- Poor speed precision
- Poor motor torque and speed response
- Motor noise



◆ Common Problems

| Common Problems | | Page |
|---|--|------|
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| Motor Does Not Restart after Power Loss | | 336 |

◆ Cannot Change Parameter Settings

| Cause | Possible Solutions |
|---|--|
| The drive is running the motor (i.e., the Run command is present). | <ul style="list-style-type: none"> • Stop the drive and switch over to the Programming Mode. • Most parameters cannot be edited during run. |
| The Access Level is set to restrict access to parameter settings. | <ul style="list-style-type: none"> • Set the Access Level to allow parameters to be edited (A1-01 = 2). |
| The operator is not in the Parameter Setup Mode (the screen will display “PAR”). | <ul style="list-style-type: none"> • See what mode the operator is currently set for. • Parameters cannot be edited when in the Setup Mode (“STUP”). Switch modes so that “PAR” appears on the screen. <i>Refer to The Drive, Programming, and Clock Adjustment Modes on page 114.</i> |
| A multi-function contact input terminal is set to allow or restrict parameter editing (H1-01 through H1-08 = 1B). | <ul style="list-style-type: none"> • When the terminal is open, parameters cannot be edited. • Turn on the multi-function contact input set to 1B. |

6.10 Troubleshooting without Fault Display

| Cause | Possible Solutions |
|---------------------------------|--|
| The wrong password was entered. | <ul style="list-style-type: none"> If the password entered to A1-04 does not match the password saved to A1-05, then drive settings cannot be changed. Reset the password. If you cannot remember the password: <ul style="list-style-type: none"> Scroll to A1-04. Press  and  simultaneously. Parameter A1-05 will appear. Set a new password to parameter A1-05. |
| Undervoltage was detected. | <ul style="list-style-type: none"> Check the drive input power voltage by looking at the DC bus voltage (U1-07). Check all main circuit wiring. |

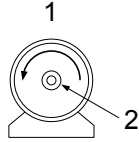
◆ Motor Does Not Rotate Properly after Pressing RUN Button or after Entering External Run Command

■ Motor Does Not Rotate

| Cause | Possible Solutions |
|---|---|
| The drive is not in the Drive Mode. | <ul style="list-style-type: none"> Check if the DRV light on the digital operator is lit. Enter the Drive Mode to begin operating the motor. <i>Refer to The Drive, Programming, and Clock Adjustment Modes on page 114.</i> |
| The LO/RE key was pushed. | Stop the drive and check if the correct frequency reference source is selected. If the operator keypad shall be the source, the LO/RE key LED must be illuminated. If the source is REMOTE, it must be off. Take the following steps to solve the problem: <ul style="list-style-type: none"> Push the LO/RE key. If o2-01 is set to 0, then the LO/RE key will be disabled. |
| Auto-Tuning has just completed. | <ul style="list-style-type: none"> When Auto-Tuning completes, the drive is switched back to the Programming Mode. The Run command will not be accepted unless the drive is in the Drive Mode. Use the digital operator to enter the Drive Mode. <i>Refer to The Drive, Programming, and Clock Adjustment Modes on page 114.</i> |
| A Fast Stop was executed and has not yet been reset. | Reset the Fast Stop command. |
| Settings are incorrect for the source that provides the Run command. | Check parameter b1-02 (Run Command Selection). Set b1-02 so that it corresponds with the correct Run command source. 0: Digital operator 1: Control circuit terminal (default setting) 2: MEMOBUS/Modbus communications 3: Option card |
| There is faulty wiring in the control circuit terminals. | <ul style="list-style-type: none"> Check the wiring for the control terminal. Correct wiring mistakes. Check the input terminal status monitor (U1-10). |
| The drive has been set to accept the frequency reference from the incorrect source. | Check parameter b1-01 (Frequency Reference Selection 1). Set b1-01 to the correct source of the frequency reference. 0: Digital operator 1: Control circuit terminal (default setting) 2: MEMOBUS/Modbus communications 3: Option card 4: Pulse train input (RP) |
| The terminal set to accept the main speed reference is set to the incorrect voltage and/or current. | <i>Refer to Terminals A1, A2, and A3 Input Signal Selection on page 101.</i> |
| Selection for the sink/source mode and the internal/external power supply is incorrect. | Check jumper S3. <i>Refer to Sinking/Sourcing Mode for Digital Inputs on page 101.</i> |
| Frequency reference is too low. | <ul style="list-style-type: none"> Check the frequency reference monitor (U1-01). Increase the frequency by changing the maximum output frequency (E1-09). |
| Multi-function analog input is set up to accept gain for the frequency reference, but no voltage (current) has been provided. | <ul style="list-style-type: none"> Check the multi-function analog input settings. Check if analog input A1, A2, or A3 is set for frequency reference gain (H3-02, H3-10, H3-06 = 1). If so, check if the correct signal is applied to the terminal. The gain and the frequency reference will be 0 if no signal is applied to the gain input. Check if H3-02, H3-10, and H3-06 have been set to the proper values. Check if the analog input value has been set properly. (U1-13 to U1-15) |
| The STOP key was pressed when the drive was started from a REMOTE source. | <ul style="list-style-type: none"> Pressing the STOP key will decelerate the drive to stop. Switch off the Run command and then re-enter a new Run command. Set o2-02 to 0 to disable the STOP key. |

| Cause | Possible Solutions |
|--|---|
| Motor starting torque is too low. | <i>Refer to Motor Performance Fine-Tuning on page 290.</i> |
| Frequency reference value is too low or the drive does not accept the value entered. | Enter a value that is above the minimum output frequency determined by E1-09. |
| The sequence Start/Stop sequence is set up incorrectly. | <ul style="list-style-type: none"> • If the drive is supposed to be set up for a 2-wire sequence, then ensure parameters H1-03 through H1-08 are not set to 0. • If the drive is supposed to be set up for a 3-wire sequence, then one of the parameters H1-03 through H1-08 must be set to 0. Terminal S1 will become the Start, terminal S2 will become the Stop input. |

■ **Motor Rotates in the Opposite Direction from the Run Command**

| Cause | Possible Solutions |
|---|--|
| Phase wiring between the drive and motor is incorrect. | <ul style="list-style-type: none"> • Check the motor wiring. • Switch two motor cables (U, V, and W) to reverse motor direction. • Connect drive output terminals U/T1, V/T2, and W/T3 in the right order to match motor terminals U, V, and W. • Change the setting of parameter b1-14. |
| The forward direction for the motor is set up incorrectly. | <p>Typically, forward is designated as being counterclockwise when looking from the motor shaft (see figure below).</p>  <p>1. Forward Rotating Motor (looking down the motor shaft) 2. Motor Shaft</p> |
| The motor is running at almost 0 Hz and the Speed Search estimated the speed to be in the opposite direction. | <ul style="list-style-type: none"> • Disable bi-directional search (b3-14 = 0) so that Speed Search is performed only in the specified direction. |

Note: Check the motor specifications for the forward and reverse directions. The motor specifications will vary depending on the manufacturer of the motor.

■ **Motor Rotates in One Direction Only**

| Cause | Possible Solutions |
|--|---|
| The drive prohibits reverse rotation. | <ul style="list-style-type: none"> • Check parameter b1-04. • Set parameter b1-04 to 0 to allow the motor to rotate in reverse. |
| A Reverse run signal has not been entered, although 3-Wire sequence is selected. | <ul style="list-style-type: none"> • Make sure that one of the input terminals S3 to S8 used for the 3-Wire sequence has been set for reverse. |

◆ **Motor is Too Hot**

| Cause | Possible Solutions |
|---|---|
| The load is too heavy. | <p>If the load is too heavy for the motor, the motor will overheat as it exceeds its rated torque value for an extended period of time. Keep in mind that the motor also has a short-term overload rating in addition to the possible solutions provided below:</p> <ul style="list-style-type: none"> • Reduce the load. • Increase the acceleration and deceleration times. • Check the values set for the motor protection (L1-01, L1-02) as well as the motor rated current (E2-01). • Increase motor capacity. |
| The air around the motor is too hot. | <ul style="list-style-type: none"> • Check the ambient temperature. • Cool the area until it is within the specified temperature range. |
| The drive is operating in a vector control mode but Auto-Tuning has not yet been performed. | <ul style="list-style-type: none"> • Perform Auto-Tuning. • Calculate the motor value and reset the motor parameters. |

6.10 Troubleshooting without Fault Display

| Cause | Possible Solutions |
|---|---|
| Insufficient voltage insulation between motor phases. | <p>When the motor cable is long, high voltage surges occur between the motor coils and drive switching. Normally, surges can reach up to three times the drive input power supply voltage.</p> <ul style="list-style-type: none"> • Use a motor with a voltage tolerance higher than the max voltage surge. • Use an inverter-duty motor rated for use with AC drives when using the motor on drives rated higher than 200 V class. • Install an AC reactor on the output side of the drive. The carrier frequency should be set to 2 kHz when installing an AC reactor. |
| The motor fan has stopped or is clogged. | Check the motor fan. |
| The carrier frequency is too low. | Increase the carrier frequency to lower the current harmonic distortion and lower the motor temperature. |

◆ oPE02 Error Occurs When Lowering the Motor Rated Current Setting

| Cause | Possible Solutions |
|---|--|
| Motor rated current and the motor no-load current setting in the drive are incorrect. | <ul style="list-style-type: none"> • The user is trying to set the motor rated current in E2-01 to a value lower than the no-load current set in E2-03. • Make sure that value set in E2-01 is higher than E2-03. • If it is necessary to set E2-01 lower than E2-03, first lower the value set to E2-03, then change the setting in E2-01 as needed. |

◆ Motor Stalls during Acceleration or Acceleration Time is Too Long

| Cause | Possible Solutions |
|---|---|
| Torque limit has been reached or current suppression keeps the drive from accelerating. | <p>Take the following steps to resolve the problem:</p> <ul style="list-style-type: none"> • Reduce the load. • Increase motor capacity. <p>Note: Although the drive has a Stall Prevention function and a Torque Compensation Limit function, accelerating too quickly or trying to drive an excessively large load can exceed the capabilities of the motor.</p> |
| Load is too heavy. | |
| Torque limit is not set properly. | Check the torque limit setting. |
| Frequency reference is too low. | <ul style="list-style-type: none"> • Check the maximum output frequency (E1-04). • Increase E1-04 if it is set too low. <p>Check U1-01 for proper frequency reference.</p> <p>Check if a frequency reference signal switch has been set to one of the multi-function input terminals.</p> <p>Check for low gain level set to terminals A1, A2, or A3 (H3-03, H3-11, H3-07).</p> |
| Load is too heavy. | <ul style="list-style-type: none"> • Reduce the load so that the output current remains within the motor rated current. • In extruder and mixer applications, the load will sometimes increase as the temperature drops. • Increase the acceleration time. • Check if the mechanical brake is fully releasing as it should. |
| Acceleration time has been set too long. | Check if the acceleration time parameters have been set too long (C1-01, C1-03). |
| Motor characteristics and drive parameter settings are incompatible with one another. | <ul style="list-style-type: none"> • Set the correct V/f pattern so that it matches the characteristics of the motor being used. • Check the V/f pattern set to E1-03. • Execute Rotational Auto-Tuning. |
| Incorrect frequency reference setting. | <ul style="list-style-type: none"> • Check the multi-function analog input settings. Multi-function analog input terminal A1, A2, or A3 is set for frequency gain (H3-02, H3-10, or H3-06 is set to “1”), but there is no voltage or current input provided. • Make sure H3-02, H3-10, and H3-06 are set to the proper values. • See if the analog input value is set to the right value (U1-13 to U1-15). |
| The Stall Prevention level during acceleration and deceleration set too low. | <ul style="list-style-type: none"> • Check the Stall Prevention level during acceleration (L3-02). • If L3-02 is set too low, acceleration may be taking too long. • Increase L3-02. |
| The Stall Prevention level during run has been set too low. | <ul style="list-style-type: none"> • Check the Stall Prevention level during run (L3-06). • If L3-06 is set too low, speed will drop as the drive outputs torque. • Increase the setting value. |

| Cause | Possible Solutions |
|--|---|
| Drive reached the limitations of the V/f motor control method. | <ul style="list-style-type: none"> The motor cable may be long enough (over 50 m) to require Auto-Tuning for line-to-line resistance. Be aware that V/f Control is comparatively limited when it comes to producing torque at low speeds. |

◆ Drive Frequency Reference Differs from the Controller Frequency Reference Command

| Cause | Possible Solutions |
|--|--|
| The analog input gain and bias for the frequency reference input are set to incorrect values. | <ul style="list-style-type: none"> Check the gain and bias settings for the analog inputs that are used to set the frequency reference. Check parameters H3-03 and H3-04 for input A1, check parameters H3-11, and H3-12 for input A2, and check parameters H3-07 and H3-08 for input A3. Set these parameters to the appropriate values. |
| A frequency bias signal is being entered via analog input terminals A1 to A3. | <ul style="list-style-type: none"> If more than one of multi-function analog inputs A1 to A3 is set for frequency reference bias (H3-02, H3-10, or H3-06 is set to "0"), then the sum of all signals builds the frequency reference. Make sure that H3-02, H3-10, and H3-06 are set appropriately. Check the input level set for terminals A1 to A3 (U1-13 to U1-15). |
| PID control is enabled, and the drive is consequently adjusting the output frequency to match the PID setpoint. The drive will only accelerate to the maximum output frequency set in E1-04 while PID control is active. | If PID control is not necessary for the application, disable it by setting b5-01 to 0. |

◆ Excessive Motor Oscillation and Erratic Rotation

| Cause | Possible Solutions |
|--|---|
| Poor balance between motor phases. | Check drive input power voltage to ensure that it provides stable power. |
| Hunting prevention function is disabled. | <ul style="list-style-type: none"> Enable Hunting Prevention (n1-01 = 1). Increase the AFR gain (n2-01) or the AFR time constant 1 (n2-02). |

◆ Deceleration Takes Longer Than Expected with Dynamic Braking Enabled

| Cause | Possible Solutions |
|--|---|
| L3-04 is set incorrectly. | <ul style="list-style-type: none"> Check the Stall Prevention level during deceleration (L3-04). If a dynamic braking option has been installed, disable Stall Prevention during deceleration (L3-04 = 0). |
| The deceleration time is set too long. | Set deceleration to more appropriate time (C1-02, C1-04). |
| Insufficient motor torque. | <ul style="list-style-type: none"> Assuming parameter settings are normal and that no overvoltage occurs when there is insufficient torque, it is likely that the demand on the motor has exceeded the motor capacity. Use a larger motor. |
| Reaching the torque limit. | <ul style="list-style-type: none"> Check the settings for the torque limit (L7-01 through L7-04). If the torque limit is enabled, deceleration might take longer than expected because the drive cannot output more torque than the limit setting. Ensure the torque limit is set to a high enough value. Increase the torque limit setting. If multi-function analog input terminal A1, A2, or A3 is set to torque limit (H3-02, H3-10, or H3-06 equals 10, 11, 12, or 15), ensure that the analog input levels are set to the correct levels. Ensure H3-02, H3-10, and H3-06 are set to the right levels. Ensure the analog input is set to the correct value (U1-13 to U1-15). |
| Load exceeded the internal torque limit determined by the drive rated current. | Switch to a larger capacity drive. |

◆ Noise From Drive or Motor Cables When the Drive is Powered On

| Cause | Possible Solutions |
|---|--|
| Relay switching in the drive generates excessive noise. | <ul style="list-style-type: none"> • Lower the carrier frequency (C6-02). • Install a noise filter on the input side of drive input power. • Install a noise filter on the output side of the drive. • Place the wiring inside a metal conduit to shield it from switching noise. • Ground the drive and motor properly. • Separate the main circuit wiring and the control lines. • Make sure wires and the motor have been properly grounded. |

◆ Ground Fault Circuit Interrupter (GFCI) Trips During Run

| Cause | Possible Solutions |
|---------------------------------------|--|
| Excessive leakage current trips GFCI. | <ul style="list-style-type: none"> • Check the wiring and rating of peripheral devices. • Increase the GFCI sensitivity or use GFCI with a higher threshold. • Lower the carrier frequency (C6-02). • Reduce the length of the cable used between the drive and the motor. • Disable the internal EMC filter. |

◆ Connected Machinery Vibrates When Motor Rotates

■ Unexpected Noise from Connected Machinery

| Cause | Possible Solutions |
|--|---|
| The carrier frequency is at the resonant frequency of the connected machinery. | Adjust the carrier frequency using parameters C6-02 through C6-05. |
| The drive output frequency is the same as the resonant frequency of the connected machinery. | <ul style="list-style-type: none"> • Adjust the parameters used for the Jump frequency function (d3-01 through d3-04) to skip the problem-causing bandwidth. • Place the motor on a rubber pad to reduce vibration. |

Note: The drive may have trouble assessing the status of the load due to white noise generated from using Swing PWM (C6-02 = 7 to A).

■ Oscillation or Hunting

| Cause | Possible Solutions |
|--|--|
| Insufficient tuning. | Perform Auto-Tuning. <i>Refer to Motor Performance Fine-Tuning on page 290.</i> |
| Gain is too low when using PID control. | <i>Refer to b5: PID Control on page 160 for details.</i> |
| The frequency reference is assigned to an external source and the signal is noisy. | <ul style="list-style-type: none"> • Ensure that noise is not affecting the signal lines. • Separate main circuit wiring and control circuit wiring. • Use twisted-pair cables or shielded wiring for the control circuit. • Increase the analog input time filter constant (H3-13). |
| The cable between the drive and motor is too long. | <ul style="list-style-type: none"> • Perform Auto-Tuning. • Reduce the length of the cable. |

◆ PID Output Fault

| Cause | Possible Solutions |
|---|---|
| No PID feedback input. | <ul style="list-style-type: none"> • Check the multi-function analog input terminal settings. • Set multi-function analog input terminal A1, A2, or A3 for PID feedback (H3-02, H3-10, or H3-06 = B). • A signal input to the terminal selection for PID feedback is needed. • Check the connection of the feedback signal. • Check the various PID-related parameter settings. • No PID feedback input to the terminal causes the value detected to be 0, causing a PID fault and the drive to operate at max frequency. |
| The level of detection and the target value do not correspond with each other. | <ul style="list-style-type: none"> • PID control keeps the difference between target and detection values at 0. Set the input level for the values relative to one another. • Use analog input gains H3-03, H3-07, and H3-11 to adjust PID target and feedback signal scaling. |
| Reverse drive output frequency and speed detection. When output frequency rises, the sensor detects a speed decrease. | Set PID output for reverse characteristics (b5-09 = 1). |
| Adjustment made to PID parameter settings are insufficient. | <i>Refer to b5: PID Control on page 160</i> for details. |

◆ Insufficient Starting Torque

| Cause | Possible Solutions |
|--|---|
| Auto-Tuning has not yet been performed. | Perform Auto-Tuning. <i>Refer to Motor Performance Fine-Tuning on page 290.</i> |
| Only Stationary Auto-Tuning was performed. | Perform Rotational Auto-Tuning. |

◆ Motor Rotates after the Drive Output is Shut Off (Motor Rotates During DC Injection Braking)

| Cause | Possible Solutions |
|---|--|
| DC Injection Braking is set too low and the drive cannot decelerate properly. | <ul style="list-style-type: none"> • Adjust the DC Injection braking settings. • Increase the current level for DC Injection Braking Current (b2-02). • Increase the DC Injection Braking time at stop (b2-04). |
| The stopping method is set so that the drive coasts to stop. | Set b1-03 (Stopping Method Selection) to 0 or 2. |

◆ Output Frequency is Not as High as Frequency Reference

| Cause | Possible Solutions |
|---|---|
| Frequency reference is set within the range of the Jump Frequency. | <ul style="list-style-type: none"> • Adjust the parameters used for the Jump Frequency function (d3-01, d3-02, d3-03). • Enabling the Jump Frequency prevents the drive from outputting the frequencies specified in the Jump range. |
| Upper limit for the frequency reference has been exceeded. | <ul style="list-style-type: none"> • Set the maximum output frequency and the upper limit for the frequency reference to more appropriate values (E1-04, d2-01). • The following calculation yields the upper value for the output frequency: $E1-04 \times d2-01 / 100$ |
| Large load triggered Stall Prevention function during acceleration. | <ul style="list-style-type: none"> • Reduce the load. • Adjust the Stall Prevention level during acceleration (L3-02). |

◆ Sound from Motor

| Cause | Possible Solutions |
|---|---|
| Exceeded 110% of the rated output current of the drive while operating at low speeds. | <ul style="list-style-type: none"> • If the output current rises too high at low speeds, the carrier frequency is automatically reduced and causes a whining or buzzing sound. • If the sound is coming from the motor, disable carrier frequency derating (L8-38 = 0). • Disabling the automatic carrier frequency derating increases the chances of an overload fault (oL2). Switch to a larger capacity motor if oL2 faults occur too frequently. |

◆ Motor Does Not Restart after Power Loss

| Cause | Possible Solutions |
|---|---|
| The Run command was not issued again when power was restored. | <ul style="list-style-type: none">• Check the sequence and wiring that has been set up to enter the Run command.• A relay should be set up to make sure the Run command remains enabled throughout any power loss. |
| The relay that is supposed to maintain the Run command has been switched off. | Check wiring and circuitry for the relay intended to keep the Run command enabled. |

Periodic Inspection & Maintenance

This chapter describes the periodic inspection and maintenance of the drive to ensure that it receives the proper care to maintain overall performance.

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7.1 Section Safety

WARNING

Electrical Shock Hazard

Do not connect or disconnect wiring while the power is on.

Failure to comply could result in death or serious injury.

Before servicing, disconnect all power to the equipment. The internal capacitor remains charged even after the power supply is turned off. The charge indicator LED will extinguish when the DC bus voltage is below 50 Vdc. To prevent electric shock, wait for at least the time specified on the warning label; after all indicators are OFF, measure for unsafe voltages to confirm the drive is safe prior to servicing.

Do not operate equipment with covers removed.

Failure to comply could result in death or serious injury.

The diagrams in this section may show drives without covers or safety shields to show details. Be sure to reinstall covers or shields before operating the drives and run the drives according to the instructions described in this manual.

Always ground the motor-side grounding terminal.

Improper equipment grounding could result in death or serious injury by contacting the motor case.

Do not remove covers or touch circuit boards while the power is on.

Failure to comply could result in death or serious injury.

Do not allow unqualified personnel to perform work on the drive.

Failure to comply could result in death or serious injury.

Installation, maintenance, inspection, and servicing must be performed only by authorized personnel familiar with installation, adjustment, and maintenance of AC drives.

Do not perform work on the drive while wearing loose clothing, jewelry or without eye protection.

Failure to comply could result in death or serious injury.

Remove all metal objects such as watches and rings, secure loose clothing, and wear eye protection before beginning work on the drive.

Do not touch any terminals before the capacitors have fully discharged.

Failure to comply could result in death or serious injury.

Before servicing, disconnect all power to the equipment. The internal capacitor remains charged even after the power supply is turned off. The charge indicator LED will extinguish when the DC bus voltage is below 50 Vdc. To prevent electric shock, wait for at least the time specified on the warning label; after all indicators are OFF, measure the DC bus voltage level to confirm it has reached a safe level.

Fire Hazard

Tighten all terminal screws to the specified tightening torque.

Loose electrical connections could result in death or serious injury by fire due to overheating of electrical connections.

Do not use an improper voltage source.

Failure to comply could result in death or serious injury by fire.

Verify that the rated voltage of the drive matches the voltage of the incoming power supply before applying power.

Do not use improper combustible materials.

Failure to comply could result in death or serious injury by fire.

Attach the drive to metal or other noncombustible material.

NOTICE

Observe proper electrostatic discharge procedures (ESD) when handling the drive and circuit boards.

Failure to comply may result in ESD damage to the drive circuitry.

Follow cooling fan replacement instructions. The cooling fan cannot operate properly when it is installed incorrectly and could seriously damage the drive.

Follow the instructions in this manual to replace the cooling fan, making sure that the label is on top before inserting the cooling fan into the drive. To ensure maximum useful product life, replace both cooling fans when performing maintenance.

Never connect or disconnect the motor from the drive while the drive is outputting voltage.

Improper equipment sequencing could result in damage to the drive.

Do not use unshielded cable for control wiring.

Failure to comply may cause electrical interference resulting in poor system performance. Use shielded, twisted-pair wires and ground the shield to the ground terminal of the drive.

Do not allow unqualified personnel to use the product.

Failure to comply could result in damage to the drive or braking circuit.

Maintenance, inspection, and replacement of parts must be performed only by authorized personnel familiar with installation, adjustment and maintenance of AC drives.

Do not modify the drive circuitry.

Failure to comply could result in damage to the drive and will void warranty.

Yaskawa is not responsible for any modification of the product made by the user. This product must not be modified.

Check all the wiring to ensure that all connections are correct after installing the drive and connecting any other devices.

Failure to comply could result in damage to the drive.

Comply with proper wiring practices.

The motor may run in reverse if the phase order is backward.

Connect motor input terminals U, V and W to drive output terminals U/T1, V/T2, and W/T3. The phase order for the drive and motor should match.

Frequently switching the drive power supply to stop and start the motor can damage the drive.

To get the full performance life out of the electrolytic capacitors and circuit relays, refrain from switching the drive power supply off and on more than once every 30 minutes. Frequent use can damage the drive. Use the drive to stop and start the motor.

Do not operate damaged equipment.

Failure to comply could result in further damage to the equipment.

Do not connect or operate any equipment with visible damage or missing parts.

7.2 Inspection

Power electronics have limited life and may exhibit changes in characteristics or performance deterioration after years of use under normal conditions. To help avoid such problems, it is important to perform preventive maintenance and periodic inspection on the drive.

Drives contain a variety of power electronics such as power transistors, semiconductors, capacitors, resistors, fans, and relays. The electronics in the drive serve a critical role in maintaining proper motor control.

Follow the inspection lists provided in this chapter as a part of a regular maintenance program.

Note: The drive will require more frequent inspection if it is placed in harsh environments, such as:

- High ambient temperatures
- Frequent starting and stopping
- Fluctuations in the AC supply or load
- Excessive vibrations or shock loading
- Dust, metal dust, salt, sulfuric acid, chlorine atmospheres
- Poor storage conditions.

Perform the first equipment inspection one to two years after installation.

◆ Recommended Daily Inspection

Table 7.1 outlines the recommended daily inspection for Yaskawa drives. Check the following items on a daily basis to avoid premature deterioration in performance or product failure. Copy this checklist and mark the “Checked” column after each inspection.

Table 7.1 General Recommended Daily Inspection Checklist

| Inspection Category | Inspection Points | Corrective Action | Checked |
|----------------------|---|--|---------|
| Motor | Inspect for abnormal oscillation or noise coming from the motor. | <ul style="list-style-type: none"> • Check the load coupling. • Measure motor vibration. • Tighten all loose components. | |
| Cooling | Inspect for abnormal heat generated from the drive or motor and visible discoloration. | Check for the following: <ul style="list-style-type: none"> • Excessive load. • Loose connections. • Dirty heatsink or motor. • Ambient temperature. | |
| | Inspect drive cooling fan and circulation fan operation. | Check for the following: <ul style="list-style-type: none"> • Clogged or dirty fan. • Correct Fan operation parameter setting. | |
| Environment | Verify the drive environment complies with the specifications listed in <i>Installation Environment</i> on page 48. | Eliminate the source of contaminants or correct poor environment. | |
| Load | The drive output current should not be higher than the motor or drive rating for an extended period of time. | Check for the following: <ul style="list-style-type: none"> • Excessive load. • Correct motor parameter settings. | |
| Power Supply Voltage | Check main power supply and control voltages. | <ul style="list-style-type: none"> • Correct the voltage or power supply to within nameplate specifications. • Verify all main circuit phases. | |

◆ Recommended Periodic Inspection

Table 7.2 outlines the recommended periodic inspections for Yaskawa drive installations. Although periodic inspections should generally be performed once a year; the drive may require more frequent inspection in harsh environments or with rigorous use. Operating and environmental conditions, along with experience in each application, will determine the actual inspection frequency for each installation. Periodic inspection will help to avoid premature deterioration in performance or product failure. Copy this checklist and mark the “Checked” column after each inspection.

■ Periodic Inspection

WARNING! Electrical Shock Hazard. Do not inspect, connect, or disconnect any wiring while the power is on. Failure to comply can result in serious personal injury. Before servicing, disconnect all power to the equipment. The internal capacitor remains charged even after the power supply is turned off. The charge indicator LED will extinguish when the DC bus voltage is below 50 Vdc. To prevent electric shock, wait for at least the time specified on the warning label; after all indicators are OFF, measure for unsafe voltages to confirm the drive is safe prior to servicing.

Table 7.2 Periodic Inspection Checklist

| Inspection Area | Inspection Points | Corrective Action | Checked |
|---|---|--|---------|
| Main Circuit Periodic Inspection | | | |
| General | <ul style="list-style-type: none"> Inspect equipment for discoloration from overheating or deterioration. Inspect for damaged or deformed parts. | <ul style="list-style-type: none"> Replace damaged components as required. The drive has few serviceable parts and may require complete drive replacement. | |
| | Inspect for dirt, foreign particles, or dust collection on components. | <ul style="list-style-type: none"> Inspect enclosure door seal if used. Remove foreign particles and dust with a vacuum cleaner to avoid touching parts. Replace components if cleaning is not possible. | |
| Conductors and Wiring | <ul style="list-style-type: none"> Inspect wiring and connections for discoloration, damage, or heat stress. Inspect wire insulation and shielding for wear. | Repair or replace damaged wiring. | |
| Terminals | Inspect terminals for stripped, damaged, or loose connections. | Tighten loose screws and replace damaged screws or terminals. | |
| Relays and Contactors | <ul style="list-style-type: none"> Inspect contactors and relays for excessive noise during operation. Inspect coils for signs of overheating such as melted or cracked insulation. | <ul style="list-style-type: none"> Check coil voltage for overvoltage or undervoltage conditions. Replace damaged removable relays, contactors, or circuit board. | |
| Electrolytic Capacitor | <ul style="list-style-type: none"> Inspect for leaking, discoloration, or cracks. Check if the cap has come off, for any swelling, or if the sides have burst open. | The drive has few serviceable parts and may require complete drive replacement. | |
| Diode, IGBT (Power Transistor) | Inspect for dust or other foreign material collected on the surface. | Remove foreign particles and dust with a vacuum cleaner to avoid touching parts. | |
| Motor Periodic Inspection | | | |
| Operation Check | Check for increased vibration or abnormal noise. | Stop the motor and contact qualified maintenance personnel as required. | |
| Control Circuit Periodic Inspection | | | |
| General | <ul style="list-style-type: none"> Inspect terminals for stripped, damaged, or loose connections. Make sure all terminals have been properly tightened. | <ul style="list-style-type: none"> Tighten loose screws and replace damaged screws or terminals. If terminals are integral to a circuit board, then board or drive replacement may be required. | |
| Circuit Boards | Check for any odor, discoloration, and rust. Make sure connections are properly fastened and that no dust or oil mist has accumulated on the surface of the board. | <ul style="list-style-type: none"> Fix any loose connections. If an antistatic cloth or vacuum plunger cannot be used, replace the board. Do not use any solvents to clean the board. Remove foreign particles and dust with a vacuum cleaner to avoid touching parts. The drive has few serviceable parts and may require complete drive replacement. | |
| Cooling System Periodic Inspection | | | |
| Cooling Fan, Circulation Fan, Control Board Cooling Fan | <ul style="list-style-type: none"> Check for abnormal oscillation or unusual noise. Check for damaged or missing fan blades. | <ul style="list-style-type: none"> Replace as required. Refer to Drive Cooling Fans on page 345 for information on cleaning or replacing the fan. | |
| Heatsink | Inspect for dust or other foreign material collected on the surface. | Remove foreign particles and dust with a vacuum cleaner to avoid touching parts. | |

7.2 Inspection

| Inspection Area | Inspection Points | Corrective Action | Checked |
|------------------------------------|---|--|---------|
| Air Duct | Inspect air intake and exhaust openings. They must be free from obstruction and properly installed. | <ul style="list-style-type: none">• Visually inspect the area.• Clear obstructions and clean air duct as required. | |
| Display Periodic Inspection | | | |
| Digital Operator | <ul style="list-style-type: none">• Make sure data appears on the display properly.• Inspect for dust or other foreign material that may have collected on surrounding components. | <ul style="list-style-type: none">• Contact the nearest sales office if there is any trouble with the display or keypad.• Clean the digital operator. | |

7.3 Periodic Maintenance

The drive has Maintenance Monitors that keep track of component wear. This feature provides advance maintenance warning and eliminates the need to shut down the entire system for unexpected problems. The drive allows the user to check predicted maintenance periods for the components listed below.

- Cooling Fan, Circulation Fan, Control Board Cooling Fan
- Electrolytic Capacitors
- Inrush Prevention Circuit
- IGBTs

For replacement parts, contact the distributor where the drive was purchased or contact Yaskawa directly.

◆ Replacement Parts

Table 7.3 contains the estimated performance life of components that require replacement during the life of the drive. Only use Yaskawa replacement parts for the appropriate drive model and revision.

Table 7.3 Estimated Performance Life

| Component | Estimated Performance Life |
|------------------------------|----------------------------|
| Cooling Fan, Circulation Fan | 10 years |
| Electrolytic Capacitors | 10 years <1> |

<1> Electrolytic capacitors cannot be replaced on some lower capacity models. Complete drive replacement may be required for these models.

NOTICE: *Estimated performance life based on specific usage conditions. These conditions are provided for the purpose of replacing parts to maintain performance. Some parts may require more frequent replacement due to poor environments or rigorous use.*

Usage conditions for estimated performance life:

Ambient temperature: Yearly average of 40 °C (IP20/IP00 enclosure)

Yearly average of 30 °C (side-by-side mounting/NEMA 1, UL type 1 enclosure drive or external heatsink installation)

■ Performance Life Monitors Maintenance Monitors

The drive calculates the maintenance period for components that may require replacement during the life of the drive. A percentage of the maintenance period is displayed on the digital operator by viewing the appropriate monitor parameter.

When the maintenance period reaches 100%, there is increased risk that the drive may malfunction. Yaskawa recommends checking the maintenance period regularly to ensure maximum performance life.

Set parameters L8-12 (Ambient Temperature Setting) and L8-35 (Installation Method Selection) for use with the installation environment when using maintenance monitors.

Refer to Recommended Periodic Inspection on page 341 for details.

Table 7.4 Performance Life Monitors Used for Component Replacement

| Parameter | Component | Contents |
|-----------|--------------------------------|--|
| U4-03 | Cooling Fan Circulation Fan | Displays the accumulated operation time of the fan from 0 to 99999 hours. This value is automatically reset to 0 after it reaches 99999. |
| U4-04 | Control Board Cooling Fan | Displays the accumulated fan operation time as a percentage of the specified maintenance period. |
| U4-05 | DC Bus Capacitors | Displays the accumulated time the capacitors are used as a percentage of the specified maintenance period. |
| U4-06 | Pre-charge Circuit | Displays the number of times the drive is powered up as a percentage of the performance life of the inrush circuit. |
| U4-07 | IGBT | Displays the percentage of the maintenance period reached by the IGBTs. |

7.3 Periodic Maintenance

■ Alarm Outputs for Maintenance Monitors

An output can be set up to inform the user when a specific components has neared its expected performance life.

When one of multi-function digital output terminals has been assigned the maintenance monitor function (H2-□□ = 2F), the terminal will close when the cooling fan, DC bus capacitors, or DC bus pre-charge relay reach 90% of the expected performance life, or when the IGBTs have reached 50% of their expected performance life. Additionally the digital operator will display an alarm like shown in [Table 7.5](#) to indicate the specific components that may need maintenance.

Table 7.5 Maintenance Alarms

| Digital Operator Alarm Display | | Function | Corrective Action |
|--------------------------------|------|---|---|
| LT-1 <1> | LT-1 | The cooling fans have reached 90% of their designated life time. | Replace the cooling fan. |
| LT-2 <1> | LT-2 | The DC bus capacitors have reached 90% of their designated life time. | Contact a Yaskawa representative or the nearest Yaskawa sales office on possible drive replacement. |
| LT-3 <1> | LT-3 | The pre-charge circuit has reached 90% of its designated life time. | Contact a Yaskawa representative or the nearest Yaskawa sales office on possible drive replacement. |
| LT-4 <1> | LT-4 | The IGBTs have reached 50% of their designated life time. | Check the load, carrier frequency, and output frequency. |
| TrPC <2> | TrPC | The IGBTs have reached 90% of their designated life time. | Contact a Yaskawa representative or the nearest Yaskawa sales office on possible drive replacement. |

<1> This alarm message will be output only if the Maintenance Monitor function is assigned to one of the digital outputs (H2-□□ = 2F). The alarm will also trigger a digital output that is programmed for alarm indication (H2-□□ = 10).

<2> This alarm message will always be output, even if the Maintenance Monitor function is not assigned to any of the digital outputs (H2-□□ = 2F). The alarm will also trigger a digital output that is programmed for alarm indication (H2-□□ = 10).

■ Related Drive Parameters

Use parameters o4-03, o4-05, o4-07, and o4-09 to reset a Maintenance Monitor to zero after replacing a specific component. [Refer to Parameter List on page 431](#) for details on parameter settings.

NOTICE: *If these parameters are not reset after the corresponding parts have been replaced, the Maintenance Monitor function will continue to count down the performance life from the value that was reached with the old part. If the Maintenance Monitor is not reset, the drive will not have the correct value of the performance life for the new component.*

7.4 Drive Cooling Fans

NOTICE: Follow cooling fan replacement instructions. The cooling fan cannot operate properly when installed incorrectly and could seriously damage the drive. To ensure maximum useful product life, replace all cooling fans when performing maintenance.

Contact a Yaskawa representative or the nearest Yaskawa sales office to order replacement cooling fans as required.

For drives with multiple cooling fans, replace all the fans when performing maintenance to ensure maximum product performance life.

◆ Number of Cooling Fans

| Drive Model | Cooling Fans | Circulation Fans | Control Board Cooling Fans | Page |
|--------------------------------|--------------|------------------|----------------------------|------------|
| Three-Phase 200 V Class | | | | |
| 2A0004 | – | – | – | – |
| 2A0006 | – | – | – | – |
| 2A0008 | – | – | – | – |
| 2A0010 | – | – | – | – |
| 2A0012 | – | – | – | – |
| 2A0018 | 1 | – | – | 349 |
| 2A0021 | 1 | – | – | |
| 2A0030 | 2 | – | – | |
| 2A0040 | 2 | – | – | |
| 2A0056 | 2 | – | – | |
| 2A0069 | 2 | – | – | |
| 2A0081 | 2 | – | – | |
| 2A0110 | 2 | – | – | 351 |
| 2A0138 | 2 | – | – | 355 |
| 2A0169 | 2 | – | – | |
| 2A0211 | 2 | – | – | |
| 2A0250 | 2 | – | – | |
| 2A0312 | 2 | – | – | |
| 2A0360 | 3 | 1 | – | |
| 2A0415 | 3 | 1 | – | |
| Three-Phase 400 V Class | | | | |
| 4A0002 | – | – | – | – |
| 4A0004 | – | – | – | – |
| 4A0005 | – | – | – | – |
| 4A0007 | 1 | – | – | 349 |
| 4A0009 | 1 | – | – | |
| 4A0011 | 1 | – | – | |
| 4A0018 | 2 | – | – | |
| 4A0023 | 2 | – | – | |
| 4A0031 | 2 | – | – | |
| 4A0038 | 2 | – | – | |
| 4A0044 | 2 | – | – | 351 |
| 4A0058 | 2 | – | – | |
| 4A0072 | 2 | – | – | 353 |
| 4A0088 | 2 | – | – | |
| 4A0103 | 2 | – | – | |

7.4 Drive Cooling Fans

| Drive Model | Cooling Fans | Circulation Fans | Control Board Cooling Fans | Page |
|--------------------------------|--------------|------------------|----------------------------|------|
| 4A0139 | 2 | – | – | 355 |
| 4A0165 | 2 | – | – | |
| 4A0208 | 2 | – | – | |
| 4A0250 | 3 | – | – | |
| 4A0296 | 3 | – | – | |
| 4A0362 | 3 | 1 | – | |
| 4A0414 | 3 | 1 | – | 359 |
| 4A0515 | 3 | 2 | 2 | 361 |
| 4A0675 | 3 | 2 | 2 | |
| 4A0930 | 6 | 4 | 4 | 364 |
| 4A1200 | 6 | 4 | 4 | |
| Three-Phase 600 V Class | | | | |
| 5A0003 | – | – | – | – |
| 5A0004 | – | – | – | – |
| 5A0006 | 1 | – | – | 349 |
| 5A0009 | 1 | – | – | |
| 5A0011 | 2 | – | – | |
| 5A0017 | 2 | – | – | |
| 5A0022 | 2 | – | – | |
| 5A0027 | 2 | – | – | |
| 5A0032 | 2 | – | – | |
| 5A0041 | 2 | – | – | 351 |
| 5A0052 | 2 | – | – | |
| 5A0062 | 2 | – | – | 355 |
| 5A0077 | 2 | – | – | |
| 5A0099 | 2 | – | – | |
| 5A0125 | 2 | – | – | |
| 5A0145 | 2 | – | – | |
| 5A0192 | 3 | – | – | |
| 5A0242 | 3 | 1 | – | |

◆ Cooling Fan Component Names

WARNING! Electrical Shock Hazard. Do not connect or disconnect wiring while the power is on. Failure to comply can result in serious personal injury. Before servicing the drive, disconnect all power to the equipment. The internal capacitor remains charged even after the power supply is turned off. After shutting off the power, wait for at least the amount of time specified on the drive before touching any components.

CAUTION! Burn Hazard. Do not touch a hot drive heatsink. Failure to comply could result in minor or moderate injury. Shut off the power to the drive when replacing the cooling fan. To prevent burns, wait at least 15 minutes and ensure the heatsink has cooled down.

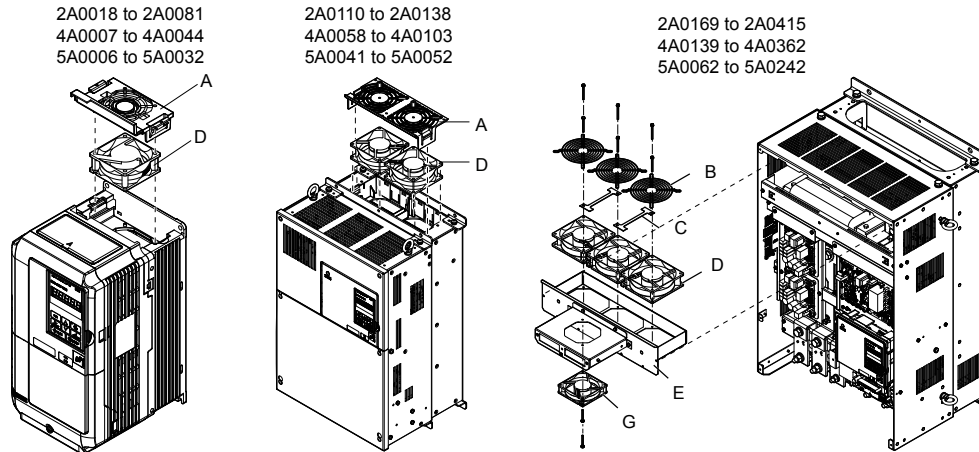


Figure 7.1 Cooling Fan Component Names

Remaining models can be found on the following page.

7.4 Drive Cooling Fans

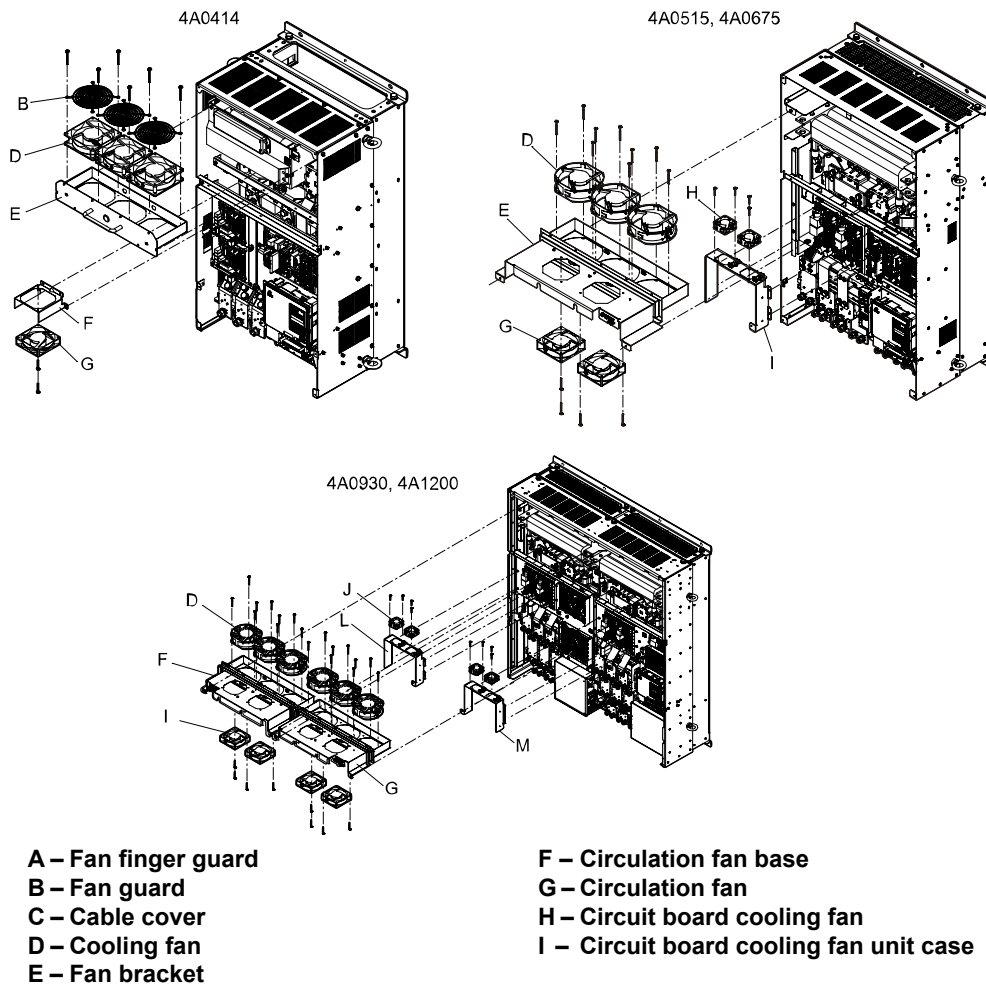


Figure 7.2 Cooling Fan Component Names (Continued)

◆ Cooling Fan Replacement: 2A0018 to 2A0081, 4A0007 to 4A0044, and 5A0006 to 5A0032

WARNING! *Electrical Shock Hazard. Do not connect or disconnect wiring while the power is on. Failure to comply can result in serious personal injury. Before servicing the drive, disconnect all power to the equipment. The internal capacitor remains charged even after the power supply is turned off. After shutting off the power, wait for at least the amount of time specified on the drive before touching any components.*

CAUTION! *Burn Hazard. Do not touch a hot drive heatsink. Failure to comply could result in minor or moderate injury. Shut off the power to the drive when replacing the cooling fan. To prevent burns, wait at least 15 minutes and ensure the heatsink has cooled down.*

NOTICE: *Follow cooling fan replacement instructions. Improper fan replacement could cause damage to equipment. Make sure the fan is facing upwards when installing the replacement fan into the drive. Replace all fans when performing maintenance to help ensure maximum useful product life.*

■ Removing the Cooling Fan Finger Guard and Cooling Fan

1. Depress the right and left sides of the fan cover tabs and pull upward. Remove the fan cover from the top of the drive. The following figure illustrates a drive with a single cooling fan.

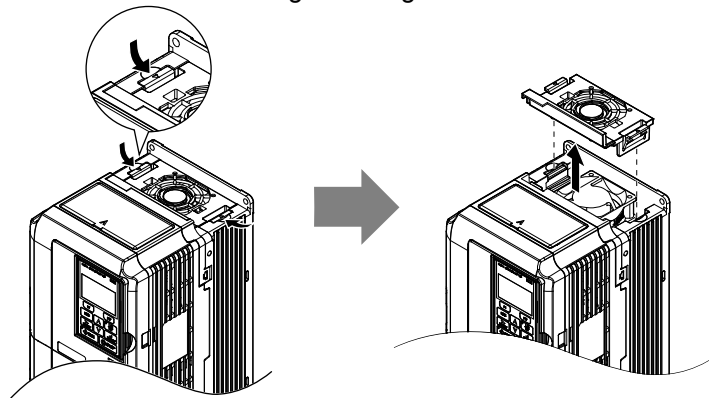


Figure 7.3 Remove the Cooling Fan Finger Guard: 2A0018 to 2A0081, 4A0007 to 4A0044, and 5A0006 to 5A0032

2. Remove the cooling fan cartridge. Disconnect the pluggable connector and remove the fan.

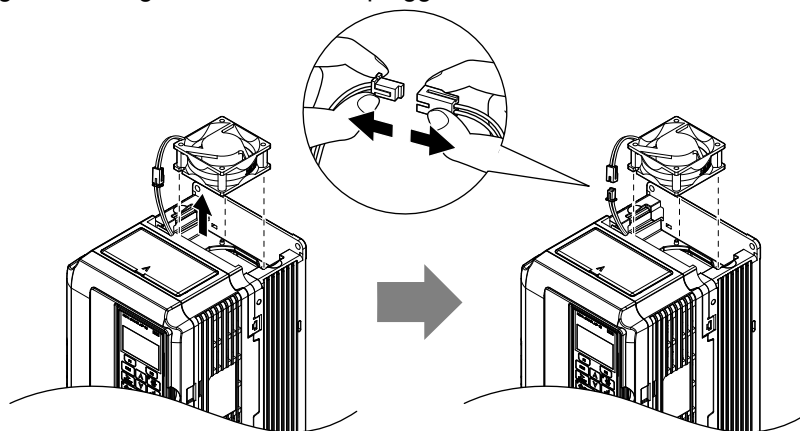


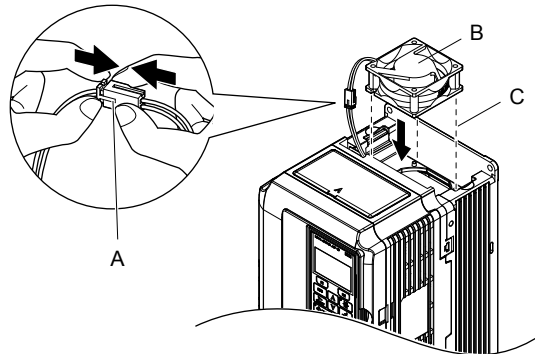
Figure 7.4 Remove the Cooling Fan: 2A0018 to 2A0081, 4A0007 to 4A0044, and 5A0006 to 5A0032

■ Installing the Cooling Fan

NOTICE: Prevent Equipment Damage. Follow cooling fan replacement instructions. Improper cooling fan replacement could result in damage to equipment. When installing the replacement cooling fan into the drive, make sure the fan is facing upwards. To ensure maximum useful product life, replace all cooling fans when performing maintenance.

Reverse the procedure described above to reinstall the cooling fan.

1. Install the replacement cooling fan into the drive, ensuring the alignment pins line up as shown in the figure below.

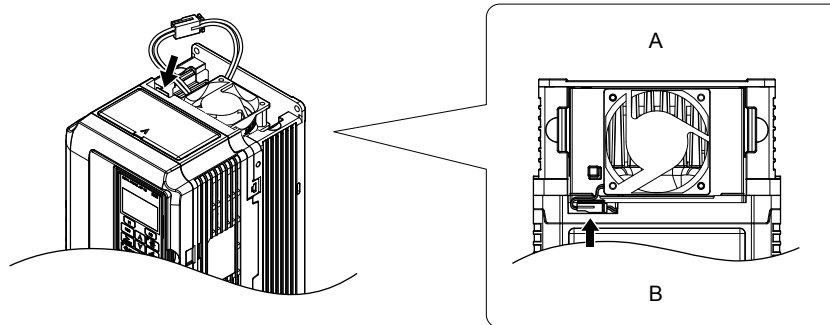


A – Push the connectors together so no space remains between them
B – Label facing up

C – Make sure the alignment pins line up properly

Figure 7.5 Install the Cooling Fan: 2A0018 to 2A0081, 4A0007 to 4A0044, and 5A0006 to 5A0032

2. Properly connect the fan power lines, then place the cable back into the recess of the drive.



A – Back

B – Front

Figure 7.6 Connect the Cooling Fan Power Supply Connectors: 2A0018 to 2A0081, 4A0007 to 4A0044, and 5A0006 to 5A0032

3. While pressing in on the hooks on the left and right sides of the fan finger guard, guide the fan finger guard until it clicks back into place.

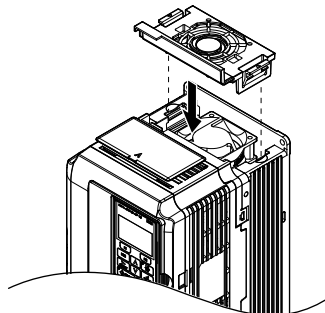


Figure 7.7 Reattach the Fan Finger Guard: 2A0018 to 2A0081, 4A0007 to 4A0044, and 5A0006 to 5A0032

4. Turn on the power supply and set o4-03 to 0 to reset the Maintenance Monitor cooling fan operation time.

◆ Cooling Fan Replacement: 2A0110, 2A0138, 4A0058, 4A0072, 5A0041, and 5A0052

These models allow access to the fans from the back or top of the drive for fan replacement. The drive can also be dismantled to replace the fans.

WARNING! *Electrical Shock Hazard. Do not connect or disconnect wiring while the power is on. Failure to comply can result in serious personal injury. Before servicing the drive, disconnect all power to the equipment. The internal capacitor remains charged even after the power supply is turned off. After shutting off the power, wait for at least the amount of time specified on the drive before touching any components.*

CAUTION! *Burn Hazard. Do not touch a hot drive heatsink. Failure to comply could result in minor or moderate injury. Shut off the power to the drive when replacing the cooling fan. To prevent burns, wait at least 15 minutes and ensure the heatsink has cooled down.*

NOTICE: *Follow cooling fan replacement instructions. Improper fan replacement could cause damage to equipment. Make sure the fan is facing upwards when installing the replacement fan into the drive. Replace all fans when performing maintenance to help ensure maximum useful product life.*

■ Removing the Cooling Fan Finger Guard and Cooling Fan

1. While pressing in on the hooks located on the left and right sides of the fan finger guard, free the fan finger guard leading by lifting the back end first.

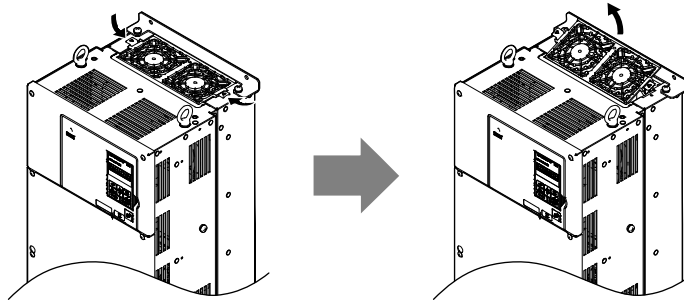


Figure 7.8 Remove the Cooling Fan Finger Guard: 2A0110, 2A0138, 4A0058, 4A0072, 5A0041, and 5A0052

2. Lift out the back end of the fan finger guard first. Unplug the replay connector and free the fan finger guard from the drive.

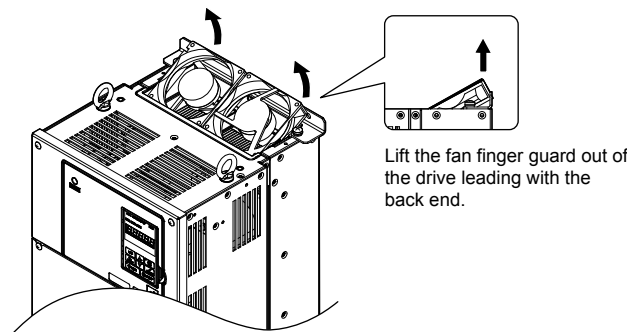


Figure 7.9 Remove the Cooling Fan: 2A0110, 2A0138, 4A0058, 4A0072, 5A0041, and 5A0052

■ Installing the Cooling Fan

Reverse the procedure described above to reinstall the cooling fan.

1. Properly connect the fan power lines.
2. Place the power supply connectors and cable back into the recess of the drive.

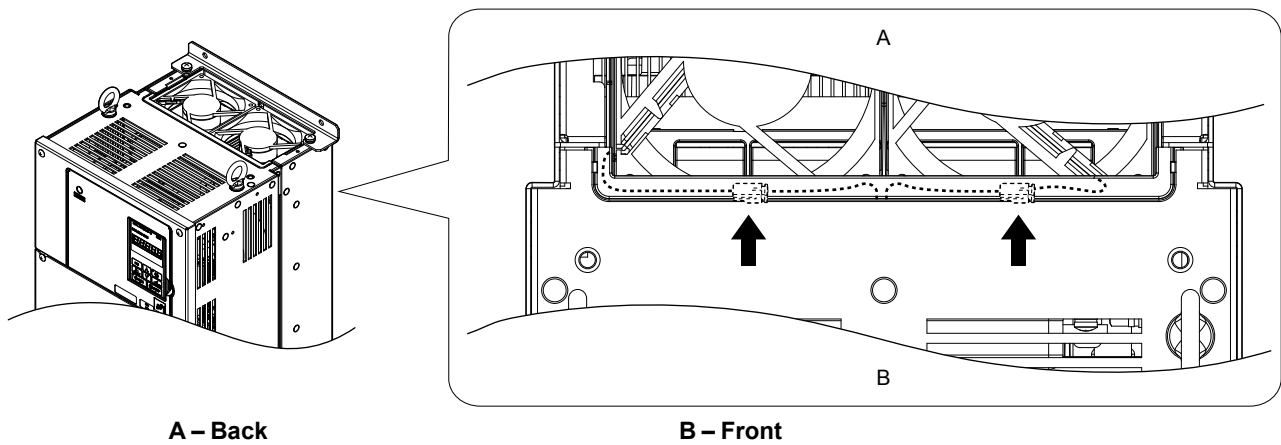


Figure 7.10 Cooling Fan Power Supply Connectors: 2A0110, 2A0138, 4A0058, 4A0072, 5A0041, and 5A0052

3. Install the replacement fan into the drive.

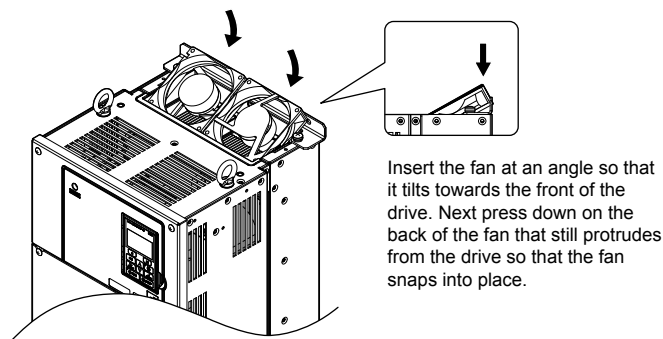


Figure 7.11 Install the Cooling Fan: 2A0110, 2A0138, 4A0058, 4A0072, 5A0041, and 5A0052

4. Tilt up the back end of the fan finger guard and slide the fan finger guard into the opening near the front of the drive, then guide the fan finger guard into place.

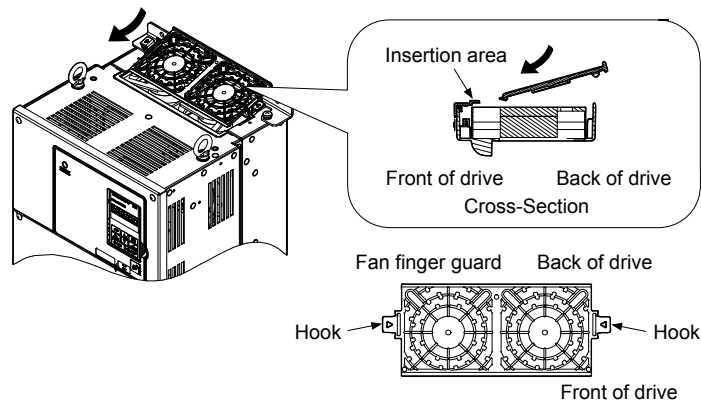


Figure 7.12 Reattach the Fan Cover: 2A0110, 2A0138, 4A0058, 4A0072, 5A0041, and 5A0052

5. Press in on the hooks of the left and right sides of the fan cover and guide the fan finger guard until it clicks into place.

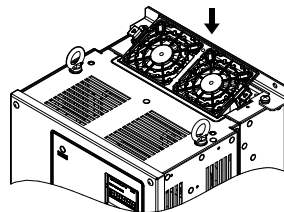


Figure 7.13 Reattach the Fan Finger Guard: 2A0110, 2A0138, 4A0058, 4A0072, 5A0041, and 5A0052

6. Turn on the power supply and set o4-03 to 0 to reset the Maintenance Monitor cooling fan operation time.

◆ Cooling Fan Replacement: 4A0088 and 4A0103

These models allow access to the fans from the back or top of the drive for fan replacement. The drive can also be dismantled to replace the fans.

WARNING! *Electrical Shock Hazard. Do not connect or disconnect wiring while the power is on. Failure to comply can result in serious personal injury. Before servicing the drive, disconnect all power to the equipment. The internal capacitor remains charged even after the power supply is turned off. After shutting off the power, wait for at least the amount of time specified on the drive before touching any components.*

CAUTION! *Burn Hazard. Do not touch a hot drive heatsink. Failure to comply could result in minor or moderate injury. Shut off the power to the drive when replacing the cooling fan. To prevent burns, wait at least 15 minutes and ensure the heatsink has cooled down.*

NOTICE: *Follow cooling fan replacement instructions. Improper fan replacement could cause damage to equipment. Make sure the fan is facing upwards when installing the replacement fan into the drive. Replace all fans when performing maintenance to help ensure maximum useful product life.*

■ Removing the Cooling Fan Finger Guard and Cooling Fan

1. While pressing in on the hooks located on the left and right sides of the fan finger guard, free the fan finger guard by lifting the back end first.

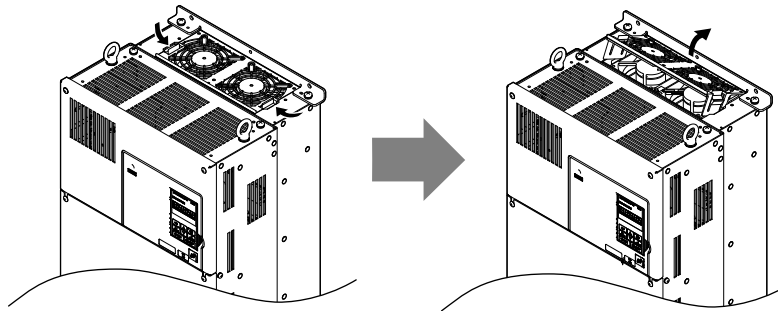


Figure 7.14 Remove the Cooling Fan Finger Guard: 4A0088 and 4A0103

2. Lift up directly on the cooling fan as shown in [Figure 7.15](#). Unplug the relay connector and release the fan from the drive.

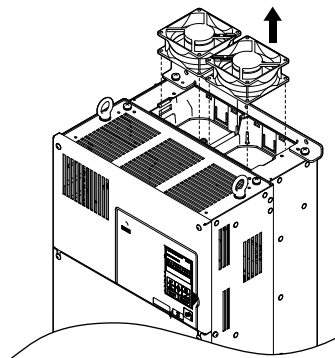


Figure 7.15 Remove the Cooling Fan: 4A0088 and 4A0103

■ Installing the Cooling Fan

Reverse the procedure describe above to reinstall the cooling fan.

1. Install the replacement fan into the drive. Align the pins as shown in [Figure 7.16](#).

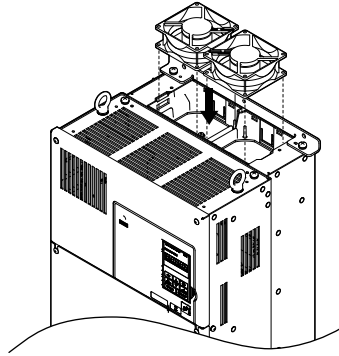
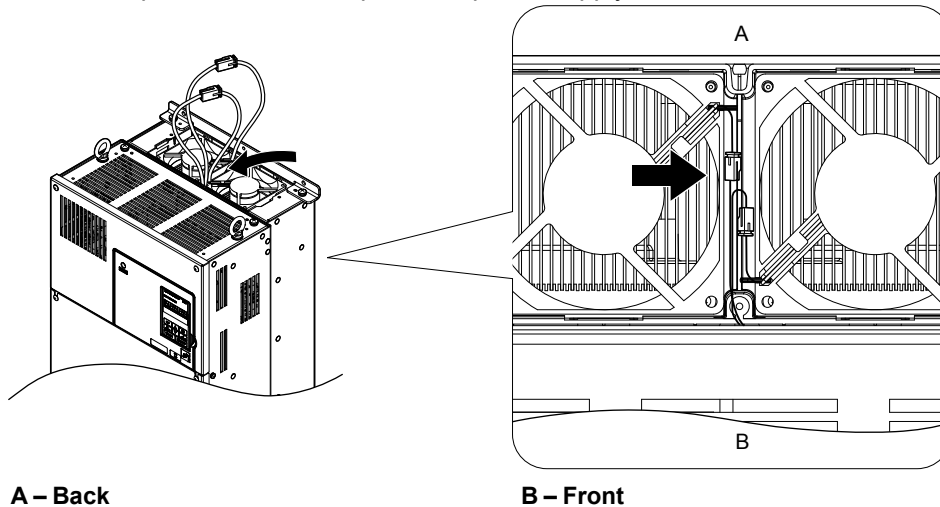


Figure 7.16 Install the Cooling Fan: 4A0088 and 4A0103

2. Properly connect the fan power lines then replace the power supply connectors and cables into the recess of the drive.



A – Back

B – Front

Figure 7.17 Cooling Fan Power Supply Connectors: 4A0088 and 4A0103

3. Angle the fan finger guard as shown in [Figure 7.18](#) and insert the connector tabs into the corresponding holes on the drive.

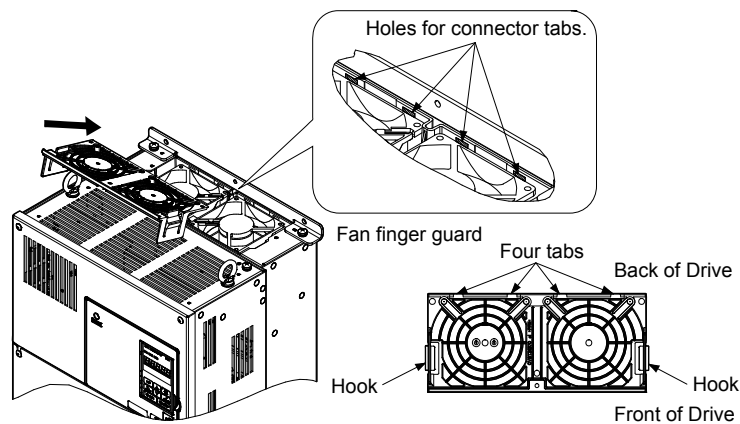


Figure 7.18 Reattach the Fan Finger Guard: 4A0088 and 4A0103

4. While pressing in on the hooks of the left and right sides of the fan finger guard, guide the fan finger guard until it clicks back into place.

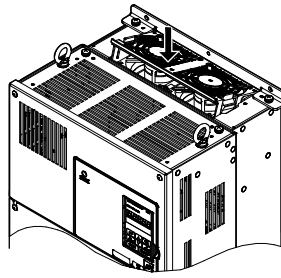


Figure 7.19 Reattach the Fan Finger Guard: 4A0088 and 4A0103

5. Turn on the power supply and set o4-03 to 0 to reset the Maintenance Monitor cooling fan operation time.

◆ Cooling Fan Replacement: 2A0169 to 2A0415, 4A0139 to 4A0362, and 5A0062 to 5A0242

These models allow access to the fans from the front of the drive for fan replacement.

WARNING! *Electrical Shock Hazard. Do not connect or disconnect wiring while the power is on. Failure to comply can result in serious personal injury. Before servicing the drive, disconnect all power to the equipment. The internal capacitor remains charged even after the power supply is turned off. After shutting off the power, wait for at least the amount of time specified on the drive before touching any components.*

CAUTION! *Burn Hazard. Do not touch a hot drive heatsink. Failure to comply could result in minor or moderate injury. Shut off the power to the drive when replacing the cooling fan. To prevent burns, wait at least 15 minutes and ensure the heatsink has cooled down.*

NOTICE: *Follow cooling fan and circulation fan replacement instructions. Improper fan replacement may cause damage to equipment. When installing the replacement fan into the drive, make sure the fan is facing upwards. Replace all fans when performing maintenance to help ensure maximum useful product life.*

■ Removing and Disassembling the Cooling Fan Unit

1. Remove the terminal cover and front cover.
2. Remove the fan connector (CN6).

Remove the fan connectors (CN6, CN7) in models 2A0360, 2A0415, 4A0362, and 5A0242.

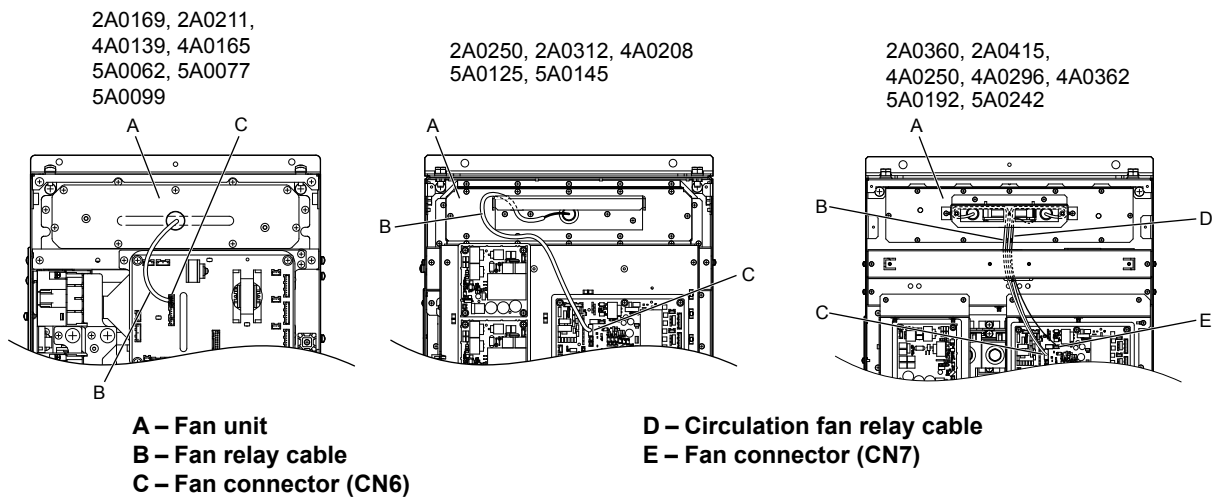


Figure 7.20 Cooling Fan Replacement: Fan Unit and Connectors

3. Remove the screws holding the fan unit in place and slide the fan unit out of the drive.

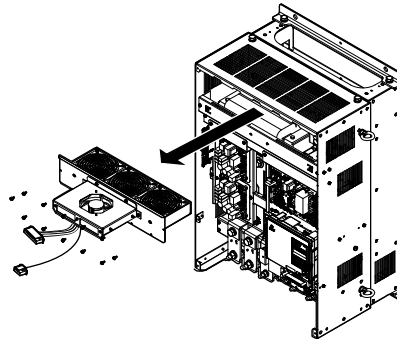


Figure 7.21 Remove the Fan Unit: 2A0169 to 2A0415, 4A0139 to 4A0362, and 5A0062 to 5A0242

4. Remove the fan guard and replace the cooling fans.

Note: Do not pinch the fan cable between parts when reassembling the fan unit.

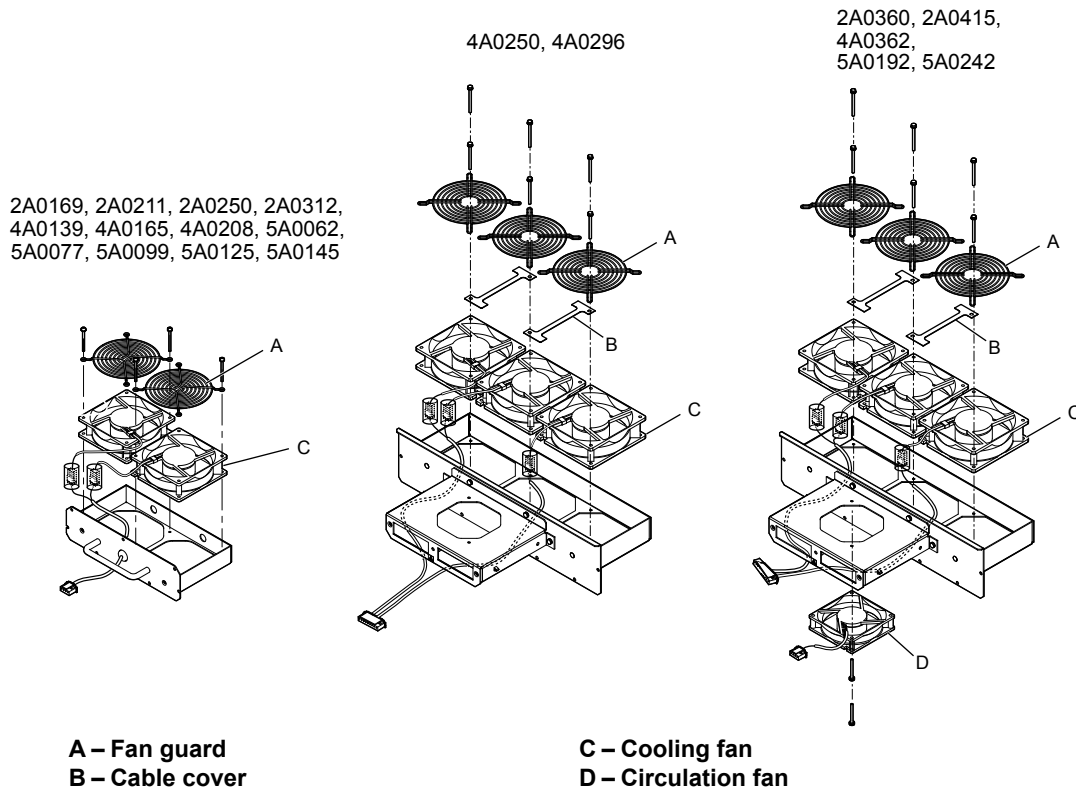
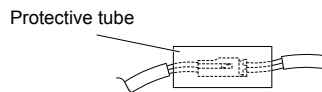


Figure 7.22 Fan Unit Disassembly: 2A0169 to 2A0415, 4A0139 to 4A0362, and 5A0062 to 5A0242

■ Cooling Fan Wiring: 2A0169, 2A0211, 4A0139, 4A0165, and 5A0062 to 5A0099

1. Position the protective tube so the fan connector sits in the center of the protective tube.



2. Place the fan connector covered by the tube as shown in [Figure 7.23](#).

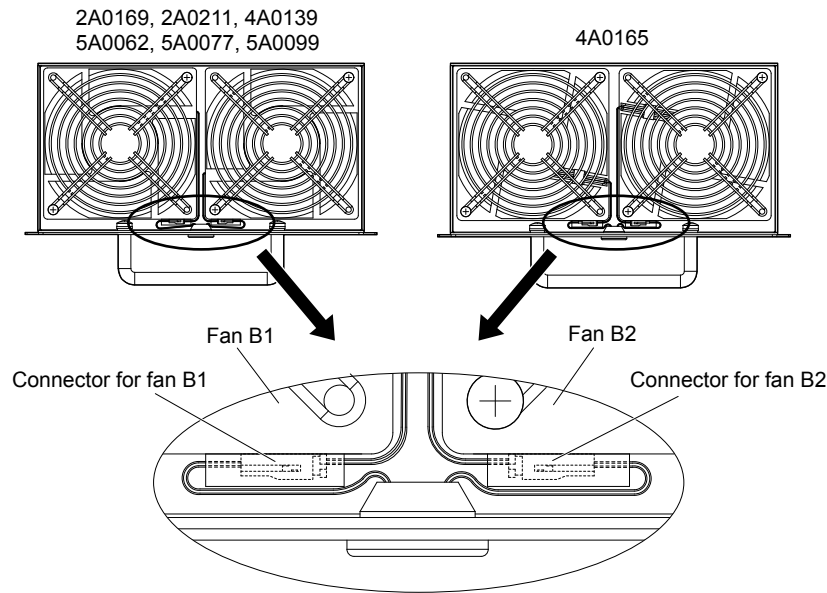
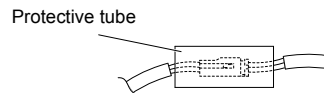


Figure 7.23 Cooling Fan Wiring: 2A0169, 2A0211, 4A0139, 4A0165, and 5A0062 to 5A0099

3. Make sure that the protective tube does not stick out beyond the fan guard.

■ Cooling Fan Wiring: 2A0250, 2A0312, 4A0208, 5A0125, and 5A0145

1. Position the protective tube so the fan connector sits in the center of the protective tube.



2. Insert the connector for fan B2 and guide the lead wire for fan B2 so the cable hook holds it in place. Insert the connector for fan B1.

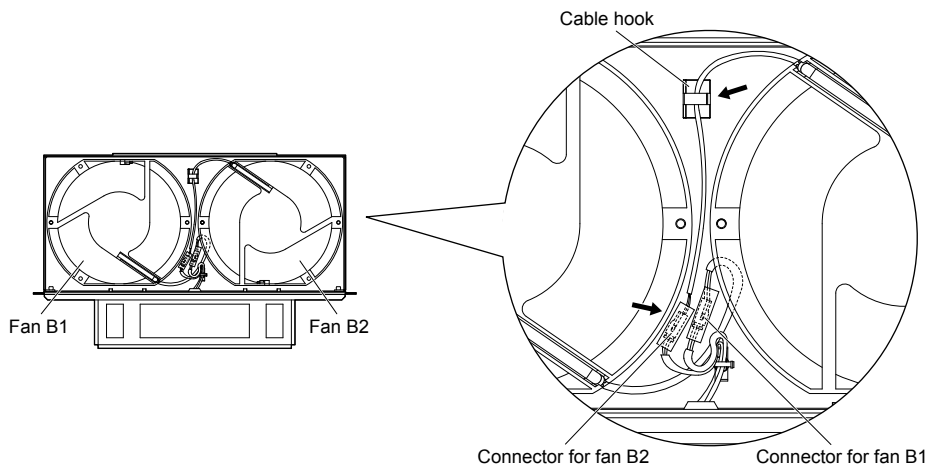
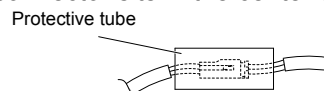


Figure 7.24 Cooling Fan Wiring: 2A0250, 2A0312, 4A0208, 5A0125, and 5A0145

3. Make sure that the protective tube does not stick out beyond the fan guard.

■ Cooling Fan Wiring: 2A0360, 2A0415, 4A0250 to 4A0362, 5A0192, and 5A0242

1. Position the protective tube so the fan connector sits in the center of the protective tube.



2. In the space between fans 1 and 2, place the fan connector for fan B2 in front of the fan connector for fan B1.
3. Place the connector for fan B3 between fans B2 and B3.

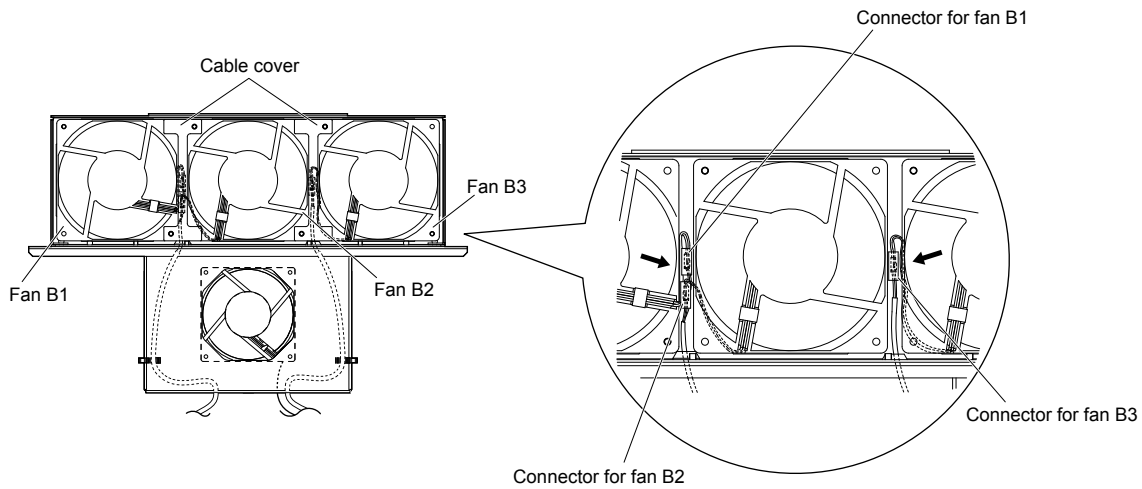


Figure 7.25 Cooling Fan Wiring: 2A0360, 2A0415, 4A0250 to 4A0362, 5A0192, and 5A0242

4. Double-check the relay connector to ensure it is properly connected.
5. Reattach the cable cover to its original position and tighten the screws so the fan guard holds the cable cover in place.

Note: Do not pinch the fan cable between parts when reassembling the fan unit.

■ Installing the Cooling Fan Unit

1. Reverse the procedure described above to reinstall the cooling fan unit.

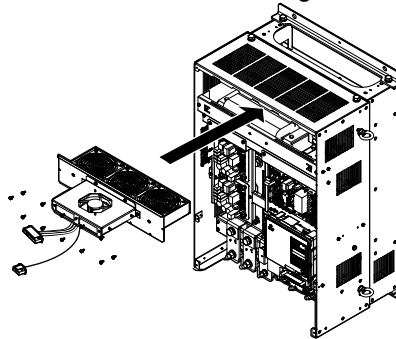


Figure 7.26 Install the Cooling Fan Unit: 2A0169 to 2A0415 and 4A0139 to 4A0362, and 5A0062 to 5A0242

2. Reattach the covers and digital operator.
3. Turn on the power supply and set o4-03 to 0 to reset the Maintenance Monitor cooling fan operation time.

◆ Cooling Fan Replacement: 4A0414

This model allows access to the fans from the front of the drive for fan replacement.

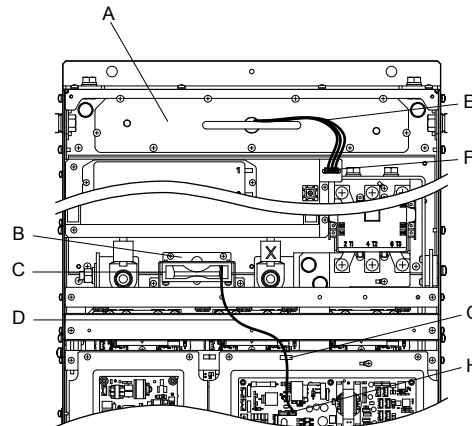
WARNING! *Electrical Shock Hazard. Do not connect or disconnect wiring while the power is on. Failure to comply can result in serious personal injury. Before servicing the drive, disconnect all power to the equipment. The internal capacitor remains charged even after the power supply is turned off. After shutting off the power, wait for at least the amount of time specified on the drive before touching any components.*

CAUTION! *Burn Hazard. Do not touch a hot drive heatsink. Failure to comply could result in minor or moderate injury. Shut off the power to the drive when replacing the cooling fan. To prevent burns, wait at least 15 minutes and ensure the heatsink has cooled down.*

NOTICE: *Follow cooling fan and circulation fan replacement instructions. Improper fan replacement may cause damage to equipment. When installing the replacement fan into the drive, make sure the fan is facing upwards. Replace all fans when performing maintenance to help ensure maximum useful product life.*

■ Removing and Disassembling the Cooling Fan Unit

1. Remove the terminal cover and front covers 1 and 2.
2. Remove the fan connector (CN6).



| | |
|---------------------------------|-------------------------|
| A – Fan unit | E – Fan relay cable |
| B – Circulation fan unit | F – Fan connector (CN6) |
| C – Circulation fan | G – Hook |
| D – Circulation fan relay cable | H – Fan connector (CN7) |

Figure 7.27 Component Names: 4A0414

3. Remove the circulation fan relay cable from the hook. Remove the fan connector (CN7).
4. Remove the screws holding the fan units in place and slide the fan units out of the drive.

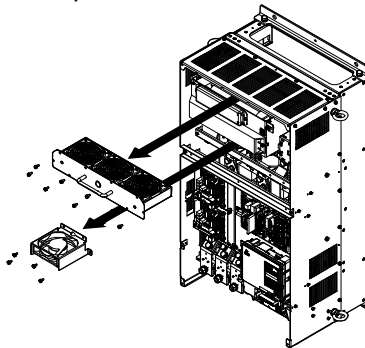


Figure 7.28 Remove the Fan Unit: 4A0414

5. Remove the fan guard and circulation fan casing. Replace the cooling fans.

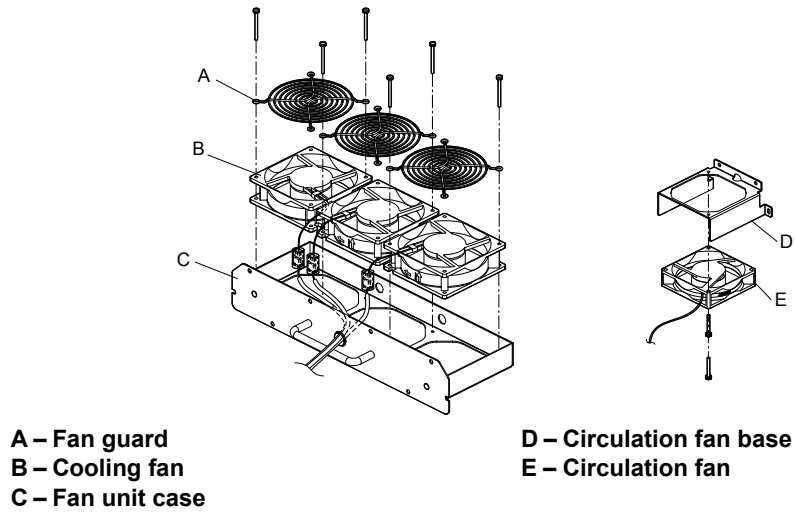
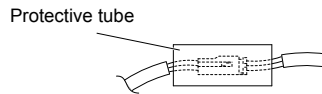


Figure 7.29 Fan Unit Disassembly: 4A0414

■ Cooling Fan Wiring

1. Position the protective tube so the fan connector sits in the center of the protective tube.



2. Place the fan connector covered by the tube as shown in [Figure 7.30](#).

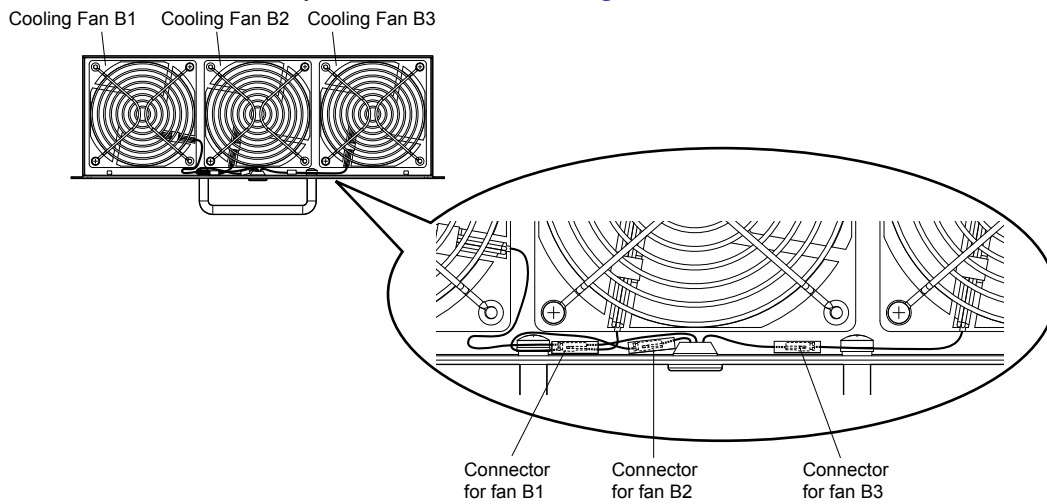


Figure 7.30 Cooling Fan Wiring: 4A0414

3. Double-check the relay connector to ensure that it is properly connected.

■ Installing the Cooling Fan Unit

1. Reverse the procedure described above to reinstall the cooling fan unit.

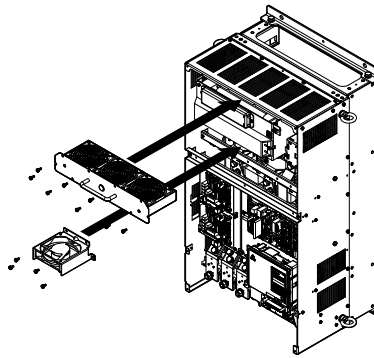


Figure 7.31 Install the Cooling Fan Unit: 4A0414

2. Reattach the covers and digital operator.
3. Turn on the power supply and set o4-03 to 0 to reset the Maintenance Monitor cooling fan operation time.

◆ Cooling Fan Replacement: 4A0515 and 4A0675

These models allow access to the fans from the front of the drive for fan replacement.

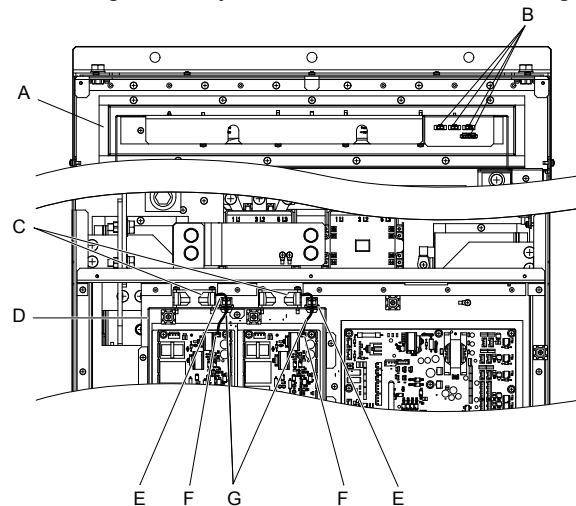
WARNING! *Electrical Shock Hazard. Do not connect or disconnect wiring while the power is on. Failure to comply can result in serious personal injury. Before servicing the drive, disconnect all power to the equipment. The internal capacitor remains charged even after the power supply is turned off. After shutting off the power, wait for at least the amount of time specified on the drive before touching any components.*

CAUTION! *Burn Hazard. Do not touch a hot drive heatsink. Failure to comply could result in minor or moderate injury. Shut off the power to the drive when replacing the cooling fan. To prevent burns, wait at least 15 minutes and ensure the heatsink has cooled down.*

NOTICE: *Follow cooling fan and circulation fan replacement instructions. Improper fan replacement may cause damage to equipment. When installing the replacement fan into the drive, make sure the fan is facing upwards. Replace all fans when performing maintenance to help ensure maximum useful product life.*

■ Removing and Disassembling the Cooling Fan Unit

1. Remove the terminal cover and front covers 1 and 2.
2. Remove the connectors for the cooling fan relay and the circuit board cooling fan.



- | | |
|------------------------------------|---|
| A – Fan unit | E – Hook |
| B – Fan relay connector | F – Circuit board cooling fan connector |
| C – Circuit board cooling fan | G – Circuit board cooling fan cable |
| D – Circuit board cooling fan case | |

Figure 7.32 Component Names: 4A0515 and 4A0675

3. Loosen all nine screws and slide the panel to the right.

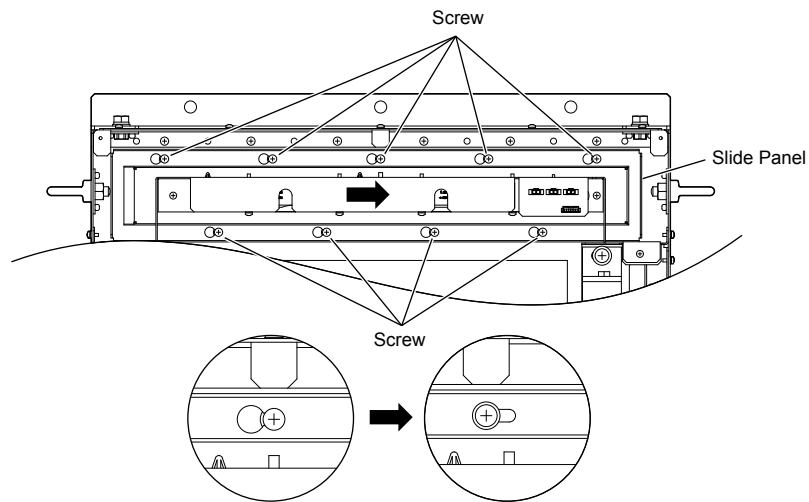


Figure 7.33 Remove the Fan Unit: 4A0515 and 4A0675

4. Remove the slide panel, fan unit, and circuit board cooling fan unit.

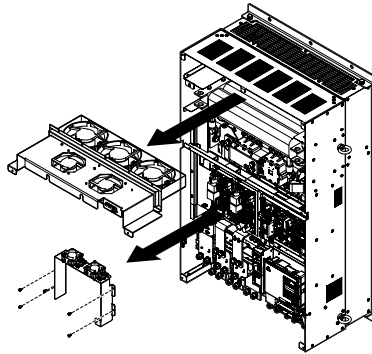
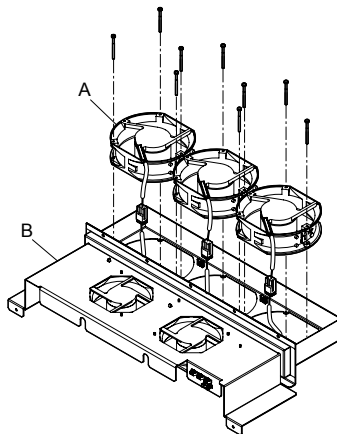


Figure 7.34 Remove the Fan Unit: 4A0515 and 4A0675

5. Replace the cooling fans.

Note: Do not pinch the fan cable between parts when reassembling the fan unit.

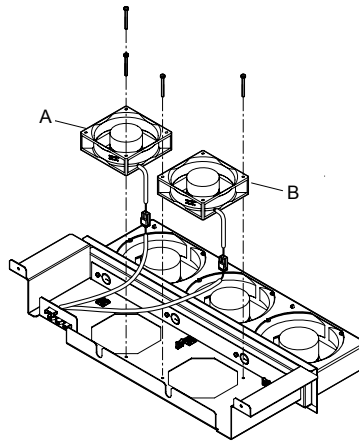


A – Cooling fan

B – Fan unit case

Figure 7.35 Fan Unit Disassembly: 4A0515 and 4A0675

6. Turn the fan unit over and replace the circulation fans.

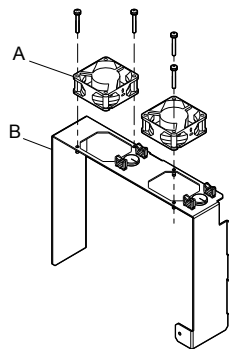


A – Circulation fan 1

B – Circulation fan 2

Figure 7.36 Fan Unit Disassembly: 4A0515 and 4A0675

7. Replace the cooling fans.



A – Circuit board cooling fan

B – Circuit board cooling fan case

Figure 7.37 Fan Unit Disassembly: 4A0515 and 4A0675

■ Cooling Fan Wiring

1. Place the cooling fan connectors and guide the lead wires so they are held in place by the cable hooks.

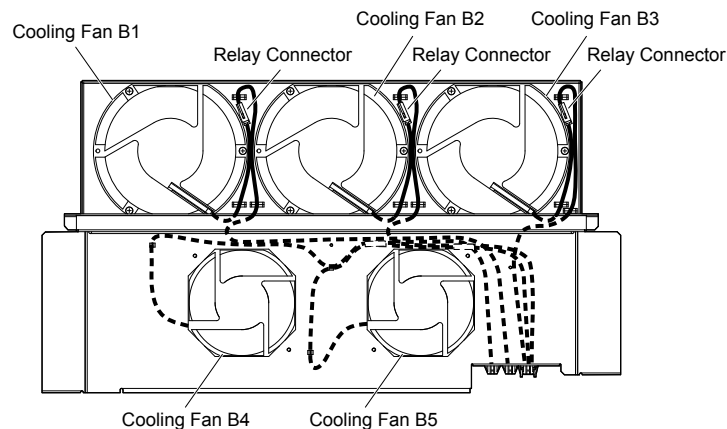


Figure 7.38 Cooling Fan Wiring: 4A0515 and 4A0675

2. Guide the lead wires so that they are held in place by the cable hooks and place the circulation fan connectors between the fan and the fan unit.

7.4 Drive Cooling Fans

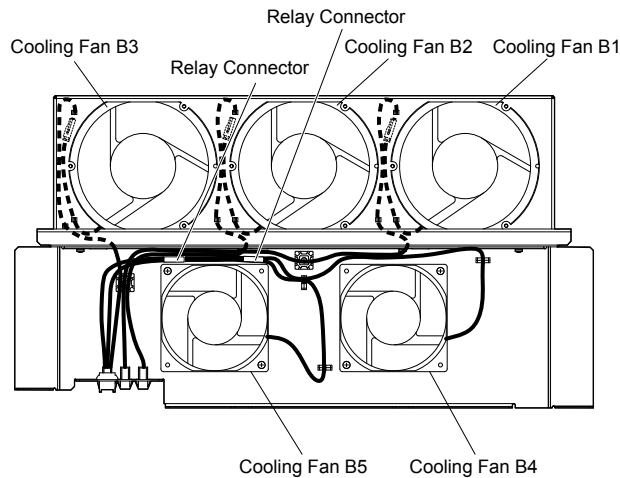
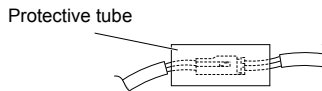


Figure 7.39 Cooling Fan Wiring: 4A0515 and 4A0675

3. Position the protective tube so the fan connector sits in the center of the protective tube. (Circuit board cooling fans only)



4. Guide the lead wires through the provided hooks so the wires are held in place.

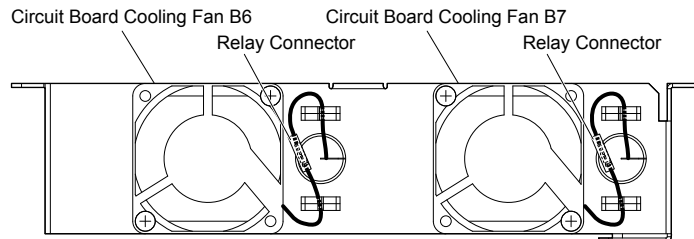


Figure 7.40 Cooling Fan Wiring: 4A0515 and 4A0675

5. Double-check the relay connector to ensure that it is properly connected.

■ Installing the Cooling Fan Unit

1. Reverse the procedure described above to reinstall the cooling fan unit.

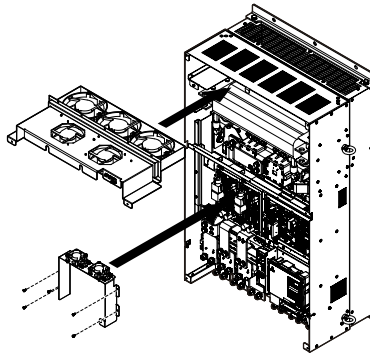


Figure 7.41 Install the Cooling Fan Unit: 4A0515 and 4A0675

2. Reattach the covers and digital operator.
3. Turn on the power supply and set o4-03 to 0 to reset the Maintenance Monitor cooling fan operation time.

◆ Cooling Fan Replacement: 4A0930 and 4A1200

These models allow access to the fans from the front of the drive for fan replacement.

WARNING! Electrical Shock Hazard. Do not connect or disconnect wiring while the power is on. Failure to comply can result in serious personal injury. Before servicing the drive, disconnect all power to the equipment. The internal capacitor remains charged even after the power supply is turned off. After shutting off the power, wait for at least the amount of time specified on the drive before touching any components.

CAUTION! Burn Hazard. Do not touch a hot drive heatsink. Failure to comply could result in minor or moderate injury. Shut off the power to the drive when replacing the cooling fan. To prevent burns, wait at least 15 minutes and ensure the heatsink has cooled down.

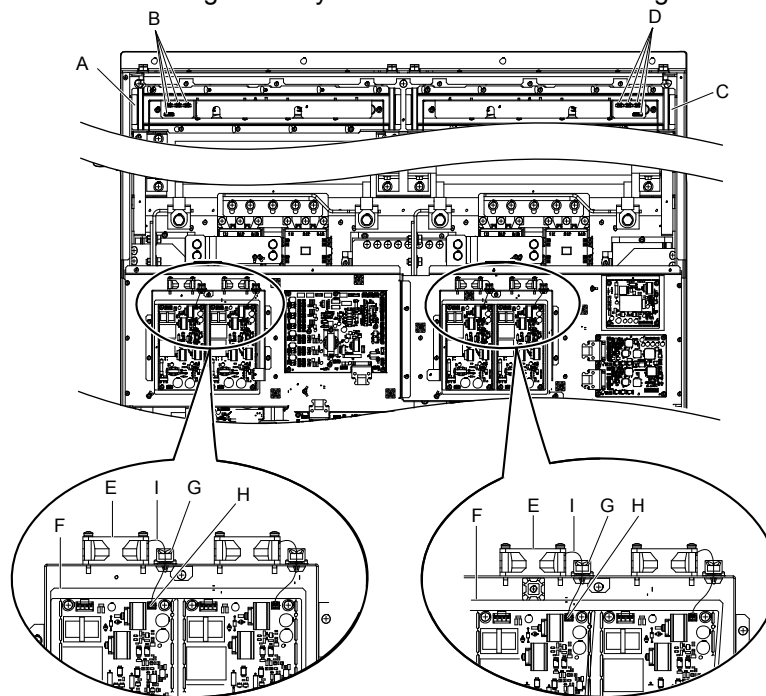
NOTICE: Follow cooling fan and circulation fan replacement instructions. Improper fan replacement may cause damage to equipment. When installing the replacement fan into the drive, make sure the fan is facing upwards. Replace all fans when performing maintenance to help ensure maximum useful product life.

■ Removing and Disassembling the Cooling Fan Unit

1. Remove the terminal cover and front covers 1 and 2.

CAUTION! Crush Hazard. Do not completely remove the cover screws, just loosen them. If the cover screws are removed completely, the terminal cover may fall off and cause an injury. Take special care when removing and reattaching the terminal covers for larger drives.

2. Remove the connectors for the cooling fan relay and the circuit board cooling fan.



Circuit board cooling fan (L)

Circuit board cooling fan (R)

- | | |
|--------------------------------------|--|
| A – Fan unit (L) | F – Circuit board cooling fan case |
| B – Fan relay connector (L) | G – Hook |
| C – Fan unit (R) | H – Circuit board cooling fan connector |
| D – Fan relay connector (R) | I – Circuit board cooling fan cable |
| E – Circuit board cooling fan | |

Figure 7.42 Component Names: 4A0930 and 4A1200

3. Loosen screws A (4 count) and B (18 count) and slide the panel to the right.

Note: The fan unit can be removed by loosening these screws; they do not need to be removed.

7.4 Drive Cooling Fans

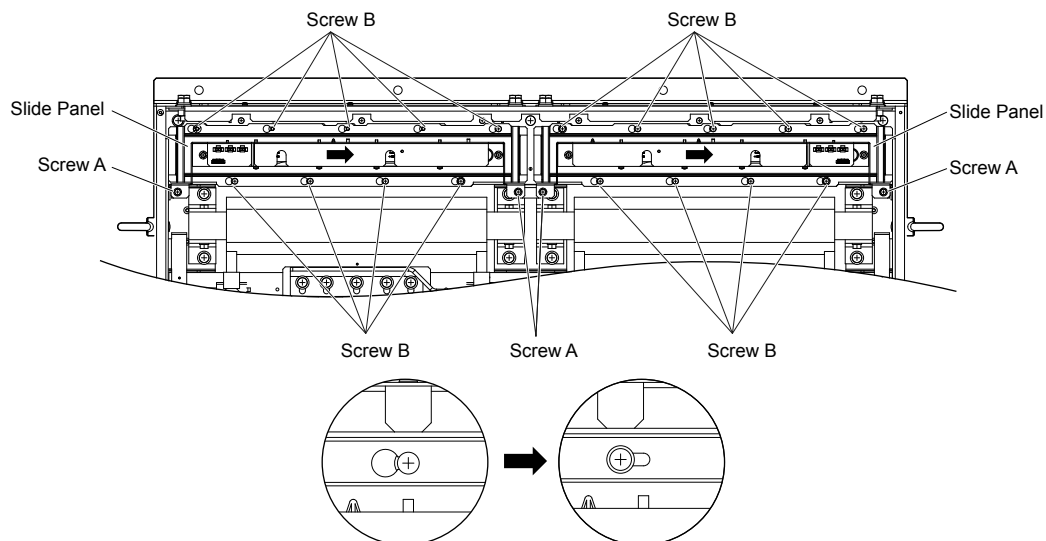


Figure 7.43 Remove the Fan Unit: 4A0930 and 4A1200

4. Remove the slide panel, fan units, and circuit board cooling fan unit.

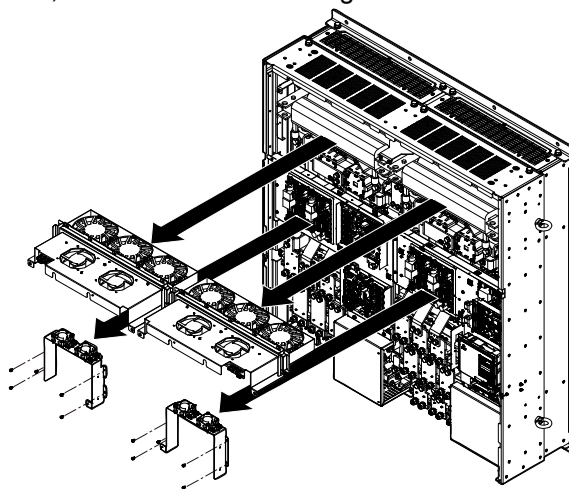
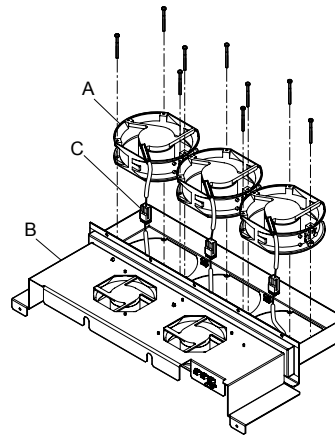


Figure 7.44 Remove the Fan Unit: 4A0930 and 4A1200

5. Replace the cooling fans.

- Note:**
1. [Figure 7.45](#) shows the right side fan unit.
 2. Do not pinch the fan cable between parts when reassembling the fan unit.



A – Cooling fan
B – Fan unit case

C – Cooling fan connector

Figure 7.45 Fan Unit Disassembly: 4A0930 and 4A1200

- Place the cooling fan connectors and guide the lead wires so that they are held in place by the cable hooks.

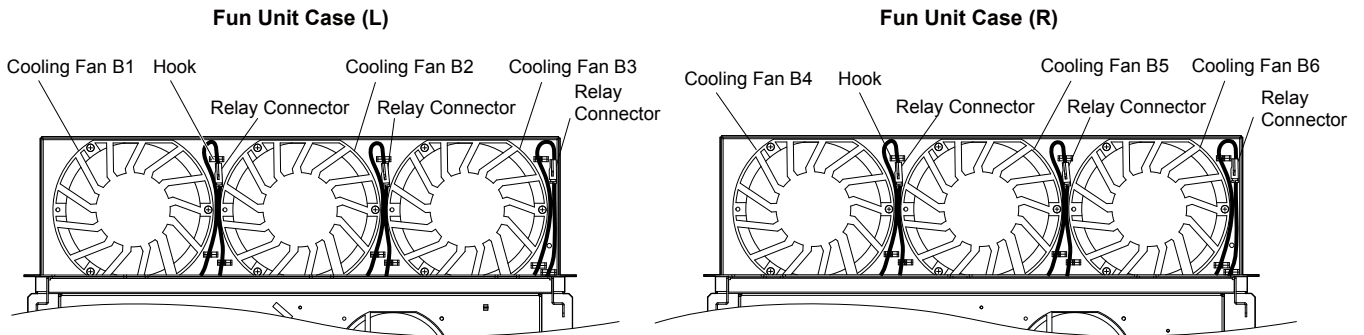
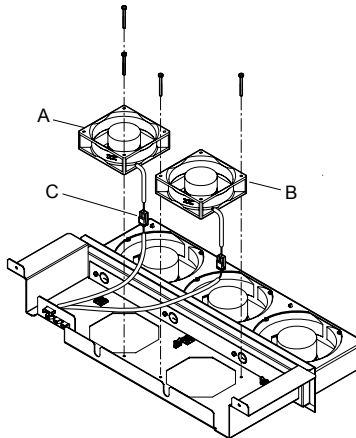


Figure 7.46 Cooling Fan Wiring: 4A0930 and 4A1200

- Turn the fan unit over and replace the circulation fans.



A – Circulation fan 1
B – Circulation fan 2

C – Cooling fan connector

Figure 7.47 Fan Unit Disassembly: 4A0930 and 4A1200

- Place the cooling fan connectors and guide the lead wires so that they are held in place by the cable hooks.

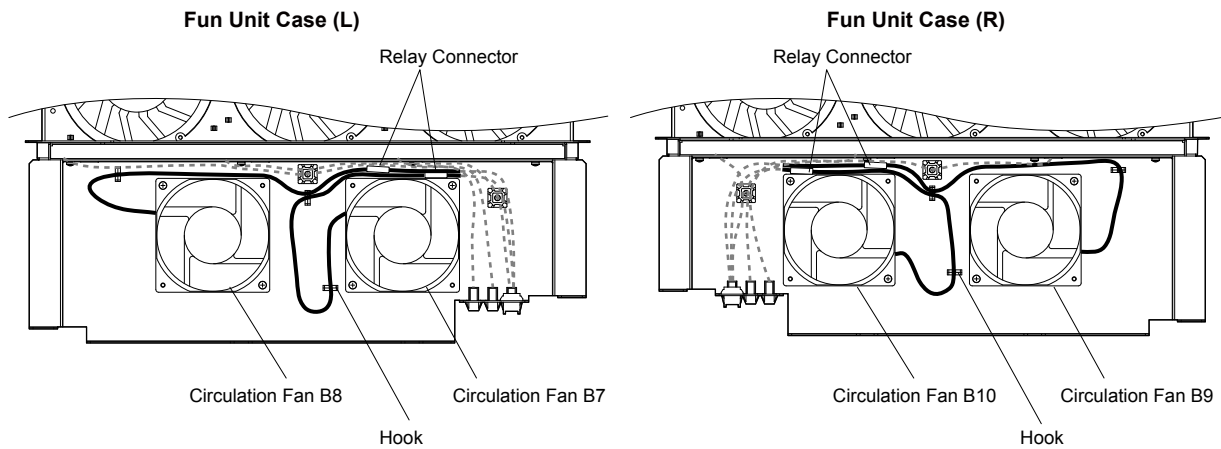
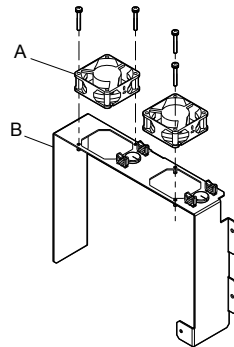


Figure 7.48 Cooling Fan Wiring: 4A0930 and 4A1200

9. Replace the circuit board cooling fans.

Note: [Figure 7.49](#) shows the right side circuit board cooling fan.

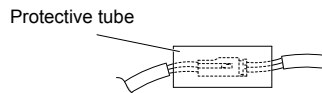


A – Circuit board cooling fan

B – Circuit board cooling fan case

Figure 7.49 Fan Unit Disassembly: 4A0930 and 4A1200

10. Position the protective tube so the fan connector sits in the center of the protective tube. (Circuit board cooling fans only)



11. Guide the lead wires through the provided hooks so the wires are held in place.

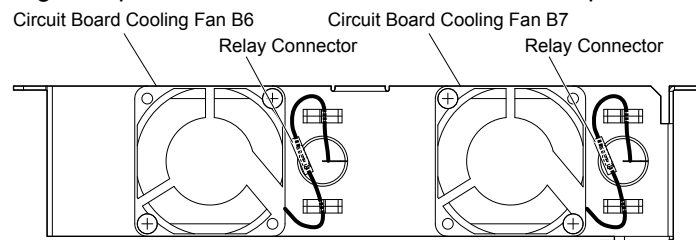


Figure 7.50 Cooling Fan Wiring: 4A0930 and 4A1200

12. Double-check the relay connector to ensure that it is properly connected.

■ Installing the Cooling Fan Unit

1. Reverse the procedure described above to reinstall the cooling fan unit.

Note: Properly connect the relay connectors to the fan unit connectors.

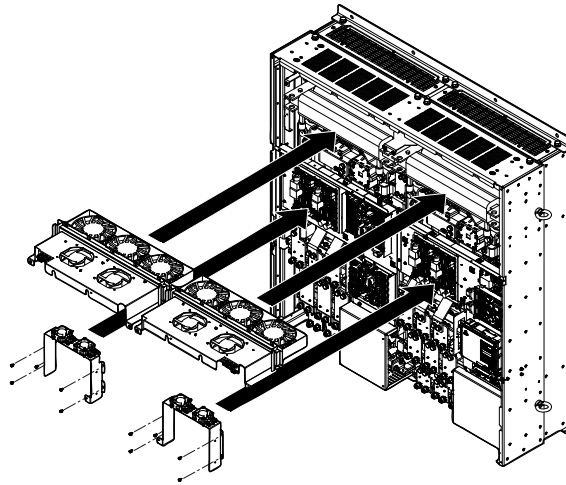


Figure 7.51 Install the Cooling Fan Unit: 4A0930 and 4A1200

2. Reattach the covers and digital operator.
3. Turn on the power supply and set o4-03 to 0 to reset the Maintenance Monitor cooling fan operation time.

7.5 Drive Replacement

◆ Serviceable Parts

The drive contains some serviceable parts. The following parts can be replaced over the life span of the drive:

- Terminal board I/O PCBs
- Cooling fan(s)
- Front cover

Replace the drive if the main power circuitry is damaged. Contact your local Yaskawa representative before replacing parts if the drive is still under warranty. Yaskawa reserves the right to replace or repair the drive according to Yaskawa warranty policy.

◆ Terminal Board

The drive has a modular I/O terminal block that facilitates quick drive replacement. The terminal board contains on-board memory that stores all drive parameter settings and allows the parameters to be saved and transferred to the replacement drive. To transfer the terminal board, disconnect the terminal board from the damaged drive and reconnect it to the replacement drive. There is no need to manually reprogram the replacement drive after transferring the terminal board.

Note: If the damaged drive and the new replacement drive are have different capacities, the data stored in the terminal board cannot be transferred to the new drive and an oPE01 error will appear on the display. The terminal board can still be used, but parameter setting from the old drive cannot be transferred. The replacement drive must be initialized and manually programmed.

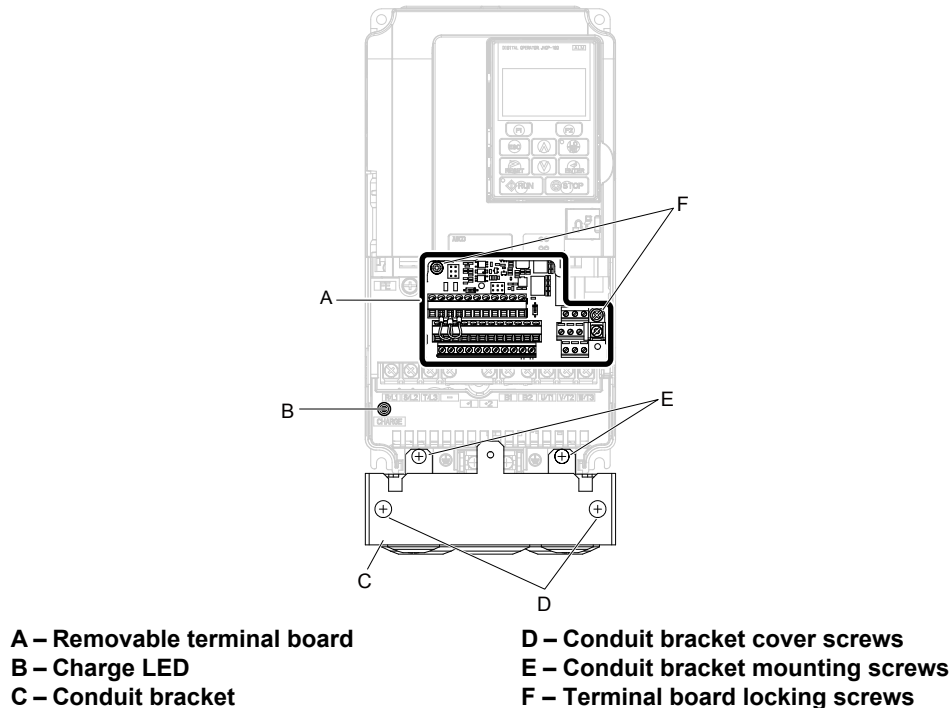


Figure 7.52 Terminal Board

◆ Replacing the Drive

WARNING! *Electrical Shock Hazard. Do not connect or disconnect wiring while the power is on. Failure to comply can result in serious personal injury. Before servicing the drive, disconnect all power to the equipment. The internal capacitor remains charged even after the power supply is turned off. After shutting off the power, wait for at least the amount of time specified on the drive before touching any components.*

WARNING! *Electrical Shock Hazard. Do not allow unqualified personnel to perform work on the drive. Failure to comply could result in serious injury. Installation, maintenance, inspection and servicing must be performed only by authorized personnel familiar with installation, adjustment and maintenance of AC drives.*

NOTICE: *Observe proper electrostatic discharge procedures (ESD) when handling the drive and circuit boards. Failure to comply may result in ESD damage to the drive circuitry.*

The following procedure explains how to replace a drive.

This section provides instructions for drive replacement only.

To install option boards or other types of options, refer to the specific manuals for those options.

NOTICE: *When transferring a braking transistor, braking resistor, or other type of option from a damaged drive to a new replacement drive, make sure it is working properly before reconnecting it to the new drive. Replace broken options to prevent immediate breakdown of the replacement drive.*

1. Remove the terminal cover.

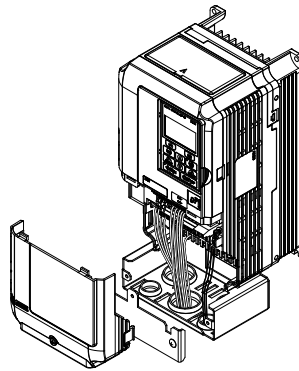


Figure 7.53 Remove the Terminal Cover

2. Loosen the screws holding the terminal board in place. Remove the screw securing the bottom cover and remove the bottom cover from the drive.

Note: IP00/Open Type enclosure drives do not have a bottom cover or conduit.

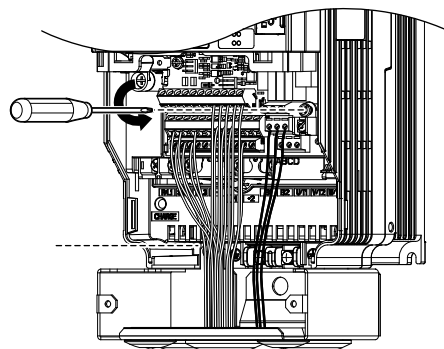


Figure 7.54 Unscrew the Terminal Board and Remove the Bottom Cover

3. Slide the terminal board as illustrated by the arrows to remove it from the drive along with the bottom cover.

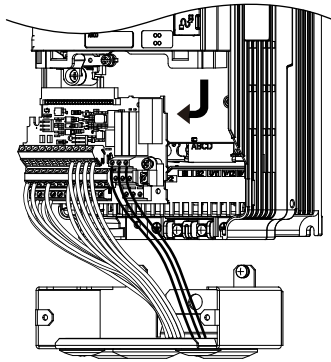


Figure 7.55 Remove the Terminal Board

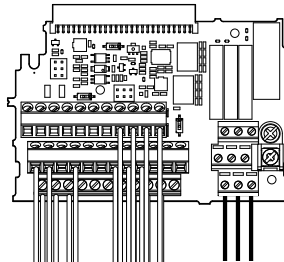


Figure 7.56 Disconnected Removable Terminal Board

4. Disconnect all option cards and options, making sure they are intact before reusing.
5. Replace the drive and wire the main circuit.

■ Installing the Drive

1. After wiring the main circuit, connect the terminal block to the drive as shown in [Figure 7.57](#). Use the installation screw to fasten the terminal block into place.

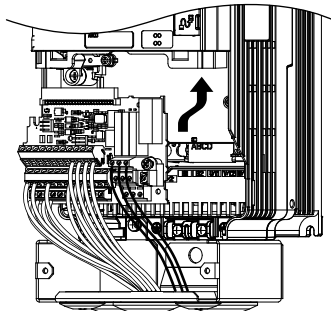


Figure 7.57 Install the Terminal Board

2. Reconnect options for the new drive the same way the options were connected in the old drive. Connect option boards to the same option ports in the new drive that were used in the old drive.
3. Replace the terminal cover.
4. After powering on the drive, all parameter settings are transferred from the terminal board to the drive memory. If an oPE04 error occurs, load the parameter settings saved on the terminal board to the new drive by setting parameter A1-03 to 5550. Reset the Maintenance Monitor function timers by setting parameters o4-01 through o4-12 to 0, and parameter o4-13 to 1.

Peripheral Devices & Options

This chapter explains the installation of peripheral devices and options available for the drive.

| | | |
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8.1 Section Safety

DANGER

Electrical Shock Hazard

Before servicing, disconnect all power to the equipment.

The internal capacitor remains charged even after the power supply is turned off. The charge indicator LED will extinguish when the DC bus voltage is below 50 Vdc. To prevent electric shock, wait for at least the time specified on the warning label, once all indicators are OFF, measure for unsafe voltages to confirm the drive is safe prior to servicing.

Failure to comply will result in death or serious injury.

WARNING

Electrical Shock Hazard

Do not operate equipment with covers removed.

Failure to comply could result in death or serious injury.

The diagrams in this section may show drives without covers or safety shields to show details. Be sure to reinstall covers or shields before operating the drives and run the drives according to the instructions described in this manual.

Do not remove covers or touch circuit boards while the power is on.

Failure to comply could result in death or serious injury.

Do not allow unqualified personnel to perform work on the drive.

Failure to comply could result in death or serious injury.

Installation, maintenance, inspection, and service must be performed only by authorized personnel familiar installation, adjustment, and maintenance of drives.

Do not perform work on the drive while wearing loose clothing, jewelry or without eye protection.

Failure to comply could result in death or serious injury.

Remove all metal objects such as watches and rings, secure loose clothing and wear eye protection before beginning work on the drive.

Always ground the motor-side grounding terminal.

Improper equipment grounding could result in death or serious injury by contacting the motor case.

Do not remove covers or touch circuit boards while the power is on.

Failure to comply could result in death or serious injury.

Do not use damaged wires, place excessive stress on wiring, or damage the wire insulation.

Failure to comply could result in death or serious injury.

Fire Hazard

Tighten all terminal screws to the specified tightening torque.

Loose electrical connections could result in death or serious injury by fire due to overheating of electrical connections.

NOTICE

Observe proper electrostatic discharge procedures (ESD) when handling the drive and circuit boards.

Failure to comply may result in ESD damage to the drive circuitry.

Never connect or disconnect the motor from the drive while the drive is outputting voltage.

Improper equipment sequencing could result in damage to the drive.

If a fuse is blown or a Ground Fault Circuit Interrupter (GFCI) is tripped, check the wiring and the selection of the peripheral devices.

Contact your supplier if the cause cannot be identified after checking the above.

Do not restart the drive or immediately operate the peripheral devices if a fuse is blown or a GFCI is tripped.

Check the wiring and the selection of peripheral devices to identify the cause. Contact your supplier before restarting the drive or the peripheral devices if the cause cannot be identified.

Do not operate damaged equipment.

Failure to comply could result in further damage to the equipment.

Do not connect or operate any equipment with visible damage or missing parts.

Do not use unshielded wire for control wiring.

Failure to comply may cause electrical interference resulting in poor system performance. Use shielded twisted-pair wires and ground the shield to the ground terminal of the drive.

Properly connect all pins and connectors.

Failure to comply may prevent proper operation and possibly damage equipment.

Check all the wiring to ensure that all connections are correct after installing the option and connecting any other devices.

Failure to comply could result in damage to the option.

8.2 Drive Options and Peripheral Devices

Table 8.1 lists the names of the various peripheral devices, accessories, and options available for Yaskawa drives. Contact Yaskawa or your Yaskawa agent to order these peripheral devices.

- **Peripheral Device Selection:** Refer to the Yaskawa catalog for selection and part numbers.
- **Peripheral Device Installation:** Refer to the corresponding option manual for installation instructions.

Table 8.1 Available Peripheral Devices

| Option | Model Number | Description |
|---|---|--|
| Power Options | | |
| DC link choke | – | Improves the power factor by suppressing harmonic distortion from the power supply. |
| AC Reactor | – | Protects the drive when operating from a large power supply and improves the power factor by suppressing harmonic distortion. Highly recommended for power supplies that exceed 600 kVA. |
| Braking Resistor | – | For use with systems that require dynamic braking with up to 3% ED. If higher ED is required, use a Braking Resistor Unit. Note: Not rated for 600 V class drive models. |
| Input/Output Option Cards | | |
| Analog Monitor | AO-A3 | <ul style="list-style-type: none"> • Provides extra multi-function analog output terminals • Output channels: 2 • Output voltage: -10 to 10 V, 11-bit (signed) |
| Communication Option Cards | | |
| EtherNet/IP | SI-EN3 | Connects to an EtherNet/IP network. |
| Modbus TCP/IP | SI-EM3 | Connects to a Modbus TCP/IP network. |
| PROFINET <1> | SI-EP3 | Connects to a PROFINET network. |
| DeviceNet | SI-N3 | Connects to a DeviceNet network |
| PROFIBUS-DP | SI-P3 | Connects to a PROFIBUS-DP network. |
| MECHATROLINK-II | SI-T3 | Connects to a MECHATROLINK-II network. |
| BACnet | SI-B3 | Connects to a BACnet network. |
| CC-Link <2> | SI-C3 | Connects to a CC-Link network |
| CANopen <2> | SI-S3 | Connects to a CANopen network. |
| Interface Options | | |
| Remote Operator Cable | UWR000051, 1 m cable UWR000052, 2 m cable | RJ-45, 8-pin straight through, UTP CAT5e, extension cable (1 m or 2 m) to connect the digital operator for remote operation. |
| USB Copy Unit | JVOP-181 | <ul style="list-style-type: none"> • Allows the user to copy and verify parameter settings between drives. • Functions as an adapter to connect the drive to a USB port on a PC. |
| Mechanical Options | | |
| Attachment for External Heatsink | EZZ020800A/B/C/D | Installation kit for mounting the drive with the heatsink outside of the panel (Side-by-Side mounting possible) |
| IP20/NEMA Type 1 Kit | 100-054-503 100-054-504 | Parts to make the drive conform to IP20/NEMA Type 1 enclosure requirements. |
| IP20/NEMA Type 1, 4, 12 Blank Keypad Kit | UUX0000526 | Provides digital operator (JVOP-180, JVOP-182) functionality on an enclosure designed for IP20/NEMA Type 1, 3R, 4, 4X, 12, or IP□6 environment. This keypad has a blank label on the front. |
| IP20/NEMA Type 1, 4, 12 Yaskawa Logo Keypad Kit | UUX0000527 | Provides digital operator (JVOP-180, JVOP-182) functionality on an enclosure designed for IP20/NEMA Type 1, 3R, 4, 4X, 12, or IP□6 environment. This keypad has a Yaskawa brand label on the front. |
| Others | | |
| 24 V Power Supply | 200 V Class: PS-A10LB 400 V Class: PS-A10HB 600 V Class: PS-A10HB | Supplies the drive controller with 24 Vdc power during main power loss. |
| PC Software Tools | | |
| DriveWizard Industrial | Contact Yaskawa | PC tool for drive setup and parameter management |

<1> Available in drive software versions PRG: 8503 and later.

<2> Limited support. Contact a Yaskawa representative or the nearest Yaskawa sales office for assistance.

8.3 Connecting Peripheral Devices

Figure 8.1 illustrates how to configure the drive and motor to operate with various peripheral devices. Refer to the specific manual for the devices shown below for more detailed installation instructions.

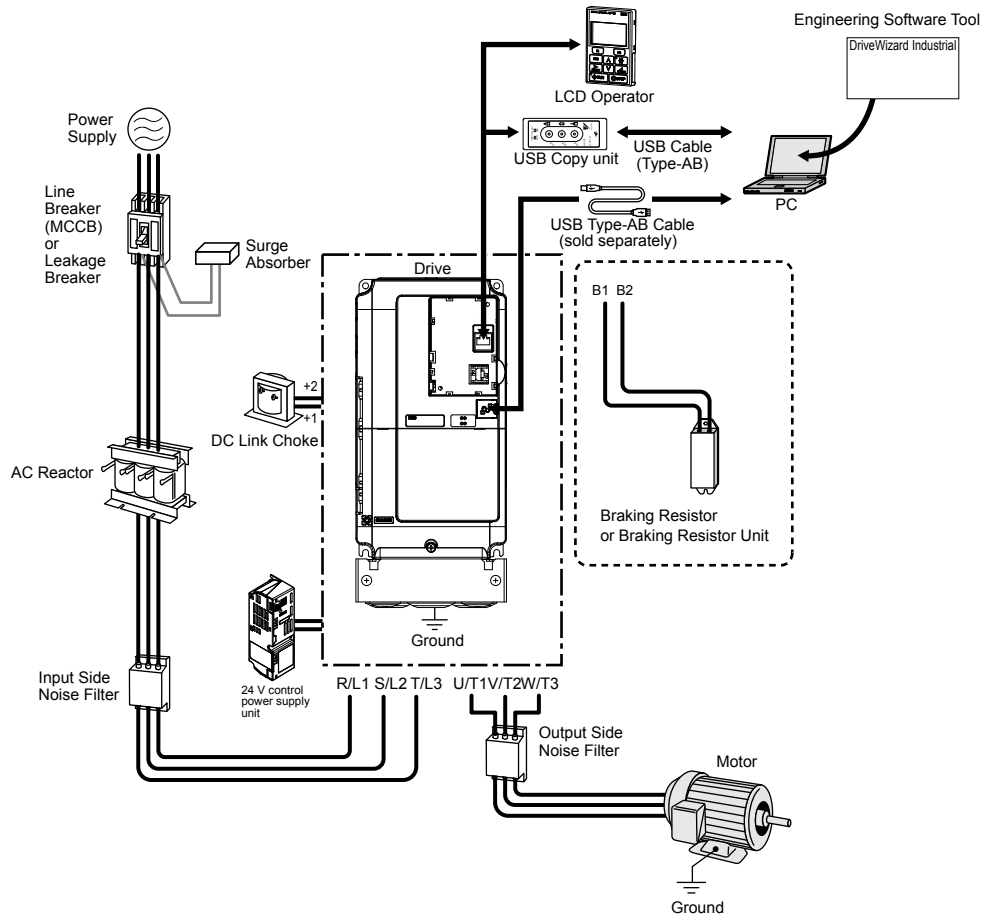


Figure 8.1 Connecting Peripheral Devices

Note: If the drive is set to trigger a fault output when the fault restart function is activated ($L5-02 = 1$), then a sequence to interrupt power when a fault occurs will turn off the power to the drive while the drive attempts to restart. The default setting for L5-02 is 0 (fault output active during restart).

8.4 Option Installation

This section provides instructions on installing the options in [Table 8.2](#).

◆ Prior to Installing the Option

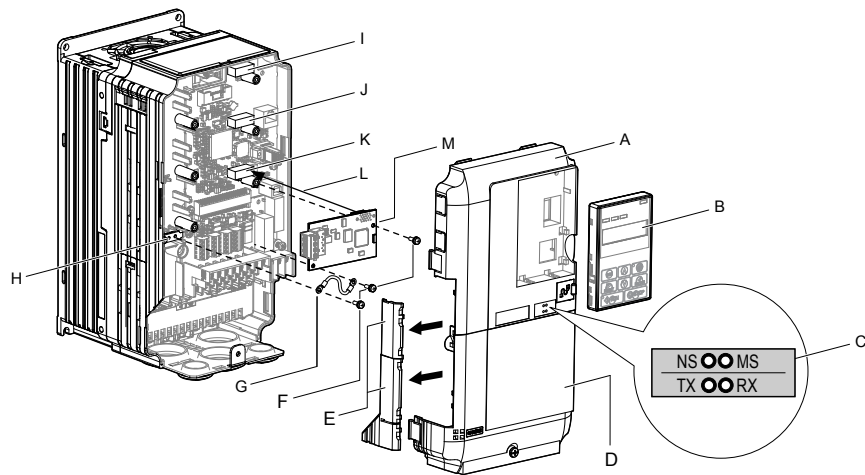
Prior to installing the option, wire the drive, make necessary connections to the drive terminals, and verify that the drive functions normally without the option installed.

[Table 8.2](#) below lists the number of options that can be connected to the drive and the drive ports for connecting those options.

Table 8.2 Option Installation

| Option | Port/Connector | Number of Options Possible |
|--|----------------|----------------------------|
| SI-B3, SI-EN3, SI-EM3, SI-EP3, SI-N3, SI-P3, SI-T3, SI-C3, SI-S3 | CN5-A | 1 |
| AO-A3 | CN5-A, B, C | 1 |

[Figure 8.2](#) shows an exploded view of the drive with the option and related components for reference.



- A – Drive front cover
- B – Digital operator
- C – LED label (for communication options)
- D – Drive terminal cover
- E – Removable tabs for wire routing
- F – Included screws
- G – Ground wire
- H – Drive grounding terminal (FE)
- I – Connector CN5-C
- J – Connector CN5-B
- K – Connector CN5-A
- L – Insertion point for CN5 connector
- M – Option

Figure 8.2 Drive Components with Option

◆ Communication Option Installation Example

Remove the front covers of the drive before installing the option. Communication options can be inserted only into the CN5-A connector located on the drive control board.

Preparing the Drive

1. Shut off power to the drive, wait the appropriate amount of time for voltage to dissipate, then remove the digital operator (B) and front covers (A, D). Front cover removal varies by model.

DANGER! Electrical Shock Hazard. Do not connect or disconnect wiring while the power is on. Failure to comply will result in death or serious injury. Before installing the option, disconnect all power to the drive. The internal capacitor remains charged even after the power supply is turned off. The charge indicator LED will extinguish when the DC bus voltage is below 50 Vdc. To prevent electric shock, wait at least five minutes after all indicators are off and measure the DC bus voltage level to confirm safe level.

NOTICE: Damage to Equipment. Observe proper electrostatic discharge procedures (ESD) when handling the option, drive, and circuit boards. Failure to comply may result in ESD damage to circuitry.

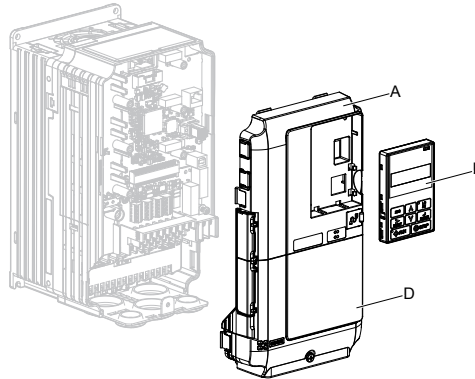


Figure 8.3 Remove the Front Covers and Digital Operator

2. With the front covers and digital operator removed, apply the LED label (C) in the appropriate position on the drive top front cover (A).

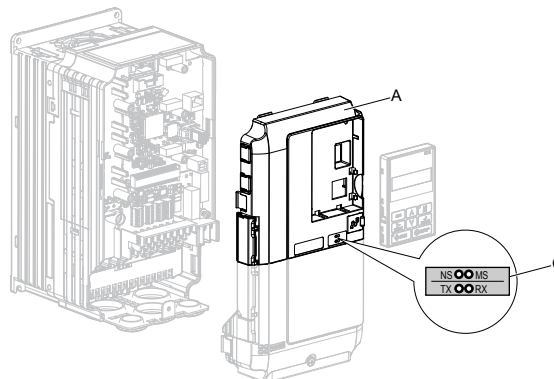


Figure 8.4 Apply the LED Label

Connecting Option and Ground Wire

1. Insert the option (M) into the **CN5-A** connector (K) located on the drive and fasten it using one of the included screws (F).

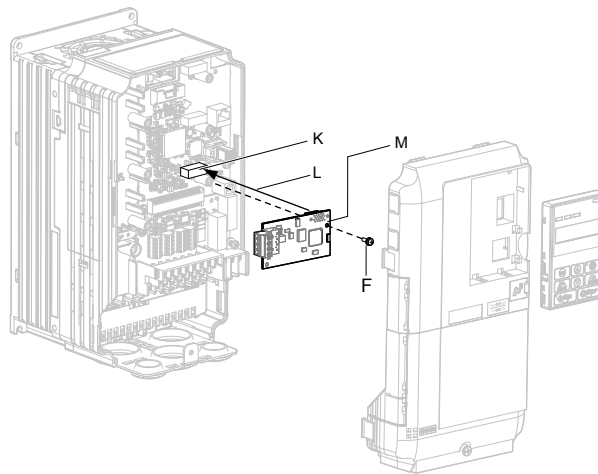


Figure 8.5 Insert the Option

2. Connect the ground wire (G) to the ground terminal (H) using one of the remaining provided screws (F). Connect the other end of the ground wire (G) to the remaining ground terminal and installation hole on the option (M) using the last remaining provided screw (F) and tighten both screws to 0.5 ~ 0.6 N m or (4.4 ~ 5.3 in lbs).

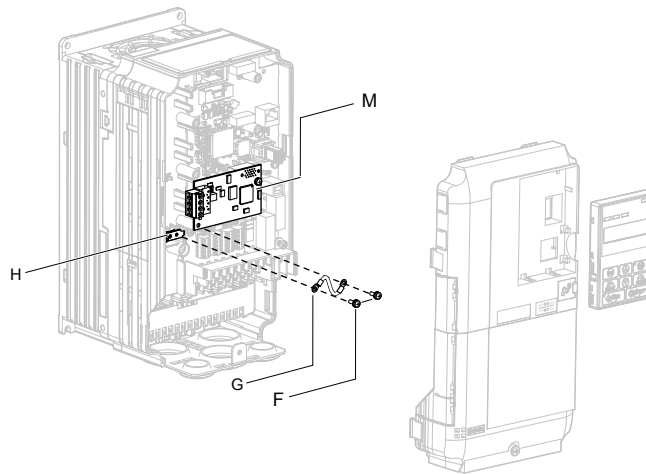


Figure 8.6 Connect the Ground Wire

Note: There are two screw holes on the drive for use as ground terminals. When connecting three options, two ground wires will need to share the same drive ground terminal.

Wiring the Option

1. Route the option wiring.

Depending on the drive model, some drives may require routing the wiring through the side of the front cover to the outside to provide adequate space for the wiring. In these cases, using diagonal cutting pliers, cut out the perforated openings on the left side of the drive front cover. Sharp edges along the cut out should be smoothed down with a file or sand paper to prevent any damage to the wires.

When installing option cards to models 2A0004 to 2A0040, 4A0002 to 4A0023, and 5A0003 to 5A0011, it may be necessary to route the cables connected to the option through the top cover to the outside. Models 2A0056 to 2A0415, 4A0031 to 4A1200, and 5A0017 to 5A0242 have enough space to keep all wiring inside the unit.

2. Connect the communication cables to the option terminal block (TB1).

Note: Separate the communications cables from the main circuit cables and other wiring and power cables. Use properly grounded shielded cables for the communication cables to prevent problems caused by electrical interference.

Replacing the Drive Covers and Digital Operator

1. Replace and secure the front covers of the drive (A, D) and replace the digital operator (B).

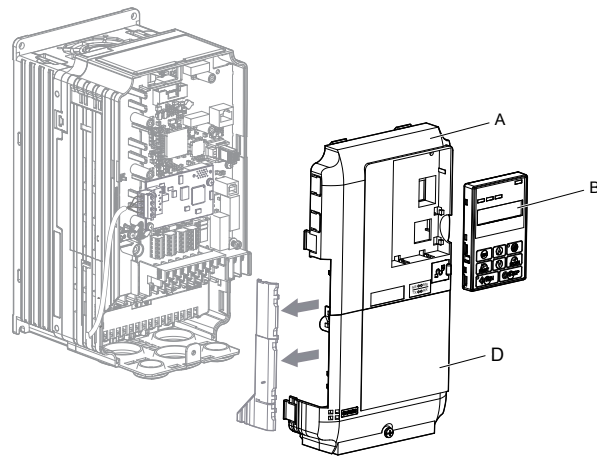


Figure 8.7 Replace the Front Covers and Digital Operator

Note: Take proper precautions when wiring the option so that the front covers will easily fit back onto the drive. Make sure no cables are pinched between the front covers and the drive when replacing the covers.

8.5 Installing Peripheral Devices

This section describes the proper steps and precautions to take when installing or connecting various peripheral devices to the drive.

NOTICE: Use a class 2 power supply when connecting to the control terminals. Improper application of peripheral devices could result in drive performance degradation due to improper power supply. Refer to NEC Article 725 Class 1, Class 2, and Class 3 Remote-Control, Signaling, and Power Limited Circuits for requirements concerning class 2 power supplies.

◆ Dynamic Braking Options

Dynamic braking (DB) helps bring the motor to a smooth and rapid stop when working with high inertia loads. As the drive lowers the frequency of a motor moving a high inertia load, regeneration occurs. This can cause an overvoltage situation when the regenerative energy flows back into the DC bus capacitors. A braking resistor prevents these overvoltage faults.

NOTICE: Do not allow unqualified personnel to use the product. Failure to comply could result in damage to the drive or braking circuit. Carefully review the braking resistor instruction manual when connecting a braking resistor option to the drive.

- Note:**
1. Properly size the braking circuit to dissipate the power required to decelerate the load in the desired time. Ensure that the braking circuit can dissipate the energy for the set deceleration time prior to running the drive.
 2. Set L8-55 to 0 to disable the internal braking transistor of the drive protection when using braking resistor options.
 3. Set L3-04 to 0 to disable Stall Prevention during deceleration when using a regenerative converter, a regenerative unit, a braking resistor, or the Braking Resistor Unit. The default setting for the Stall Prevention function (enabled) will interfere with the braking resistor.

WARNING! Fire Hazard. The braking resistor connection terminals are B1 and B2. Do not connect a braking resistor directly to any other terminals. Improper wiring connections could result in death or serious injury by fire. Failure to comply may result in damage to the braking circuit or drive.

NOTICE: Connect braking resistors to the drive as shown in the I/O wiring examples. Improperly wiring braking circuits could result in damage to the drive or equipment.

■ Installing a Braking Resistor: ERF type

ERF type braking resistors provide dynamic braking capability with up to 3% ED. They can be directly connected to the B1 and B2 terminals of the drive as shown in [Figure 8.8](#).

Enable the drive braking resistor overload protection by setting L8-01 to 1 when using ERF type resistors.

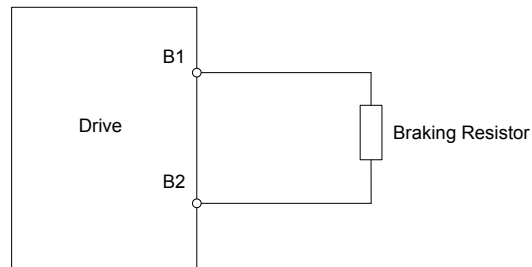


Figure 8.8 Connecting a Braking Resistor: ERF Type

■ Installing a Braking Resistor Unit: LKEB type

LKEB type braking resistors provide dynamic braking capability with up to 10% ED. They can be directly connected to the drives B1 and B2 terminals as shown in [Figure 8.9](#). The LKEB unit has a thermal overload contact that should be utilized in order to switch off the drive in case braking resistor overheat occurs.

The internal braking resistor overload protection of the drive cannot protect LKEB resistors. Set L8-01 to 0 to disable this function.

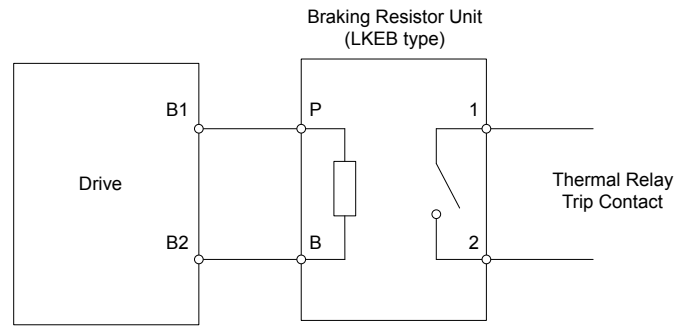


Figure 8.9 Connecting a Braking Resistor Unit: LKEB Type
(Models 2A0004 to 2A0138, 4A0002 to 4A0072, and 5A0003 to 5A0052)

■ Installing Other Types of Braking Resistors

When installing braking resistors other than the ERF or LKEB types, make sure that the drive internal braking transistor will not be overloaded with the required duty cycle and the selected resistance value. Use a resistor that is equipped with a thermal overload relay contact, and utilize this contact to switch off the drive in case of braking resistor overheating.

■ Braking Resistor Overload Protection

WARNING! Fire Hazard. Set up the sequence to shut off the power at the thermal relay trip contact on the braking resistor unit as shown in [Figure 8.10](#) to protect the braking resistor unit from overheating. Failure to comply may cause serious injury or death.

If the drive must be energized to investigate the cause of the problem, disconnect the braking resistor unit before energizing the drive.

If the drive was de-energized, identify the cause of the problem before re-energizing the drive.

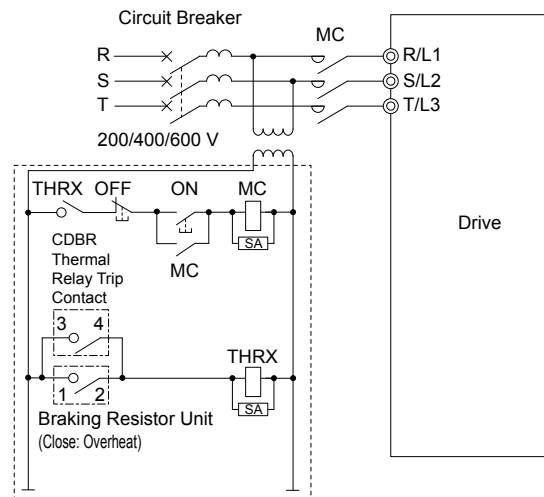


Figure 8.10 Power Supply Interrupt for Overheat Protection (Example)

■ Installing a Braking Unit: CDBR Type

To install a CDBR type braking unit, connect the $\oplus 3$ terminal of the drive to the positive terminal on the braking unit.

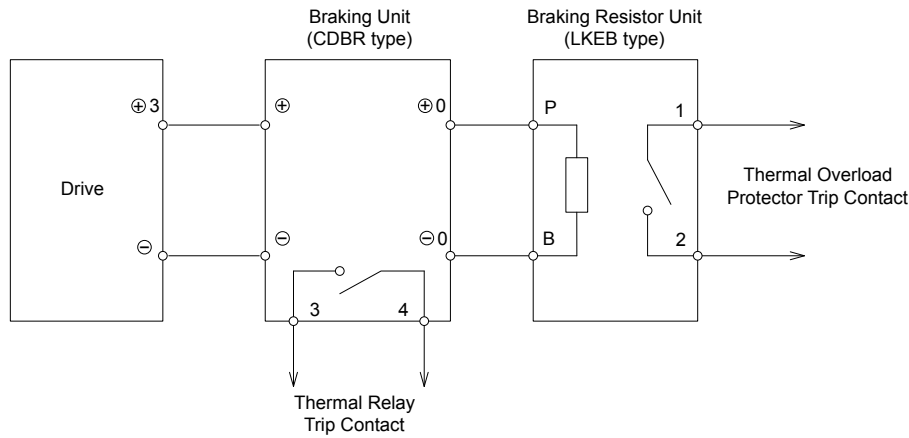
Next, wire together the negative terminals on the drive and braking unit. Terminal $\oplus 2$ is not used.

Connect the braking resistor to CDBR terminals $\oplus 0$ and $\ominus 0$. Refer to [Figure 8.10](#) and [Figure 8.11](#) for proper configuration.

Wire the thermal overload relay normally open contacts of the CDBR and the braking resistor in parallel, and connect this signal to a control circuit as shown in [Figure 8.10](#) to interrupt the main input power supply to the drive in the event of a CDBR or braking resistor overload.

Set L8-55 to 0 to disable dynamic braking transistor protection.

8.5 Installing Peripheral Devices



**Figure 8.11 Connecting a Braking Unit (CDBR type) and Braking Resistor Unit (LKEB type)
Models 2A0169 to 2A0415, 4A0088 to 4A1200 and 5A0125 to 5A0242**

Note: To install a CDBR type braking unit to the drive with a built-in dynamic braking transistor (models 2A0004 to 2A0138, 4A0002 to 4A0072, and 5A0003 to 5A0052), connect the drive B1 terminal to the positive terminal on the braking unit. Next, wire the negative terminals on the drive and braking unit together. Terminal B2 is not used.

■ Using Braking Units in Parallel

When using multiple braking units, install the braking units with a master-slave configuration with a single braking unit acting as the master. *Figure 8.12* illustrates how to wire braking units in parallel.

Wire the normally open thermal overload contact relays of all CDBRs and all braking resistors in parallel, then connect this signal to a control circuit as shown in *Figure 8.10* to interrupt the main input power supply to the drive in the event of a CDBR or braking resistor overload.

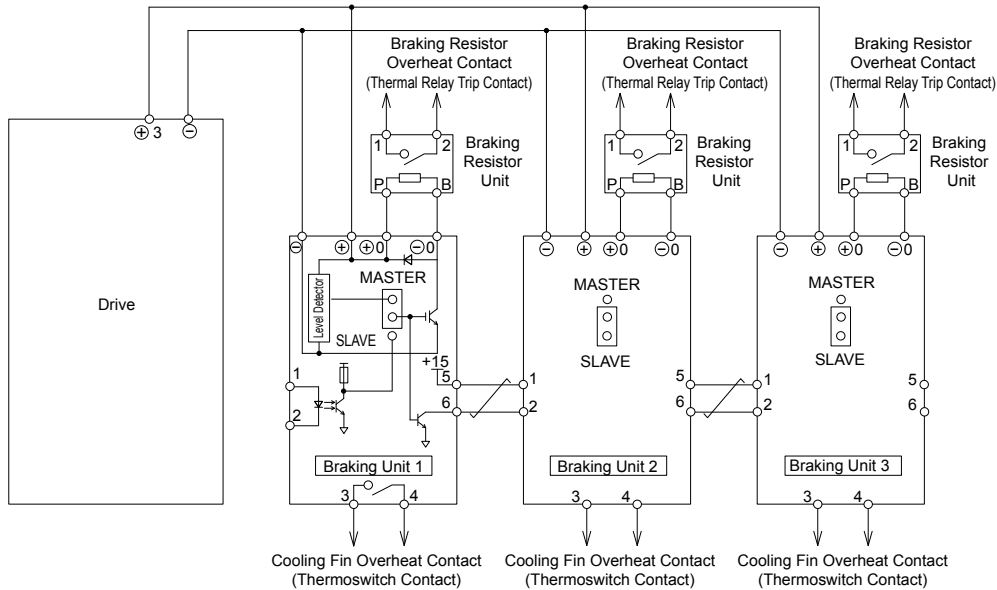


Figure 8.12 Connecting Braking Units in Parallel

◆ Installing a Molded Case Circuit Breaker (MCCB) or Ground Fault Circuit Interrupter (GFCI)

Install an MCCB or GFCI for line protection between the power supply and the main circuit power supply input terminals R/L1, S/L2, and T/L3. This protects the main circuit and devices wired to the main circuit while also providing overload protection.

NOTICE: Prevent Equipment Damage. Install a fuse and a GFCI to models 4A0930 and 4A1200. Failure to comply may result in damage to the power supply in the event of a short circuit.

Consider the following when selecting and installing an MCCB or GFCI:

- The capacity of the MCCB or GFCI should be 1.5 to 2 times the rated output current of the drive. Use an MCCB or GFCI to keep the drive from faulting out instead of using overheat protection (150% for one minute at the rated output current).
- If several drives are connected to one MCCB or GFCI that is shared with other equipment, use a sequence that shuts the power OFF when errors are output by using magnetic contactor (MC) as shown in [Figure 8.13](#).

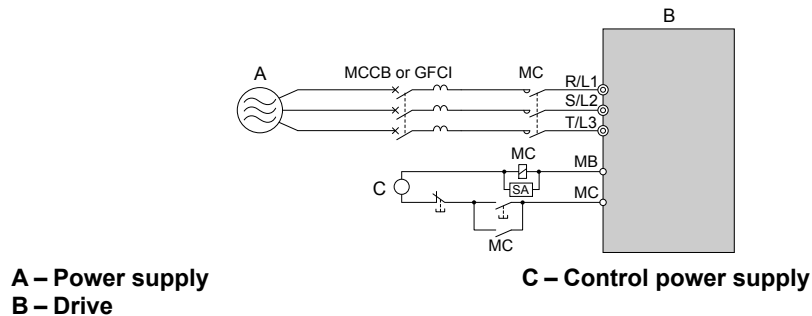


Figure 8.13 Power Supply Interrupt Wiring (Example)

WARNING! Electrical Shock Hazard. Disconnect the MCCB (or GFCI) and MC before wiring terminals. Failure to comply may result in serious injury or death.

■ Application Precautions when Installing a GFCI

Drive outputs generate high-frequency leakage current as a result of high-speed switching. Install a GFCI on the input side of the drive to switch off potentially harmful leakage current.

Factors in determining leakage current:

- Size of the AC drive
- AC drive carrier frequency
- Motor cable type and length
- EMI/RFI filter

If the GFCI trips spuriously, consider changing these items or use a GFCI with a higher trip level.

Note: Choose a GFCI designed specifically for an AC drive. The operation time should be at least 0.1 s with sensitivity amperage of at least 200 mA per drive. The output waveform of the drive and built-in EMC filter may cause an increase in leakage current. This may in turn cause the leakage breaker to malfunction. Increase the sensitivity amperage or lower the carrier frequency to correct the problem.

◆ Installing a Magnetic Contactor at the Power Supply Side

Install a magnetic contactor (MC) to the drive input for the purposes explained below.

■ Disconnecting the Power Supply

Shut off the drive with an MC when a fault occurs in any external equipment such as braking resistors.

NOTICE: Do not connect electromagnetic switches or MCs to the output motor circuits without proper sequencing. Improper sequencing of output motor circuits could result in damage to the drive.

NOTICE: Install an MC on the input side of the drive when the drive should not automatically restart after power loss. To get the full performance life out of the electrolytic capacitors and circuit relays, refrain from switching the drive power supply off and on more than once every 30 minutes. Frequent use can damage the drive. Use the drive to stop and start the motor.

NOTICE: Use a magnetic contactor (MC) to ensure that power to the drive can be completely shut off when necessary. The MC should be wired so that it opens when a fault output terminal is triggered.

- Note:**
1. Install an MC to the drive input side to prevent the drive from restarting automatically when power is restored after momentary power loss.
 2. Set up a delay that prevents the MC from opening prematurely to continue operating the drive through a momentary power loss.

8.5 Installing Peripheral Devices

■ Protecting the Braking Resistor or Braking Resistor Unit

Use an MC on the input side of the drive to protect a braking resistor or braking resistor unit from overheat or fire.

WARNING! Fire Hazard. When using a braking unit, use a thermal relay on the braking resistors and configure a fault contact output for the braking resistor unit to disconnect drive main power via an input contactor. Inadequate braking circuit protection could result in death or serious injury by fire from overheating resistors.

◆ Connecting an AC Reactor or DC Link Choke

AC reactors and DC link chokes suppress surges in current and improve the power factor on the input side of the drive.

Use an AC reactor, a DC link choke, or both in the following situations:

- To suppress harmonic current or improve the power factor of the power supply.
- When using a phase advancing capacitor switch.
- With a large capacity power supply transformer (over 600 kVA).

Note: Use an AC reactor or DC link choke when also connecting a thyristor converter (such as a DC drive) to the same power supply system, regardless of the conditions of the power supply.

■ Connecting an AC Reactor

Note: Set C6-02 to 1 (Carrier Frequency Selection to 2.0 kHz) when connecting an AC reactor to the output side (secondary side) of the drive.

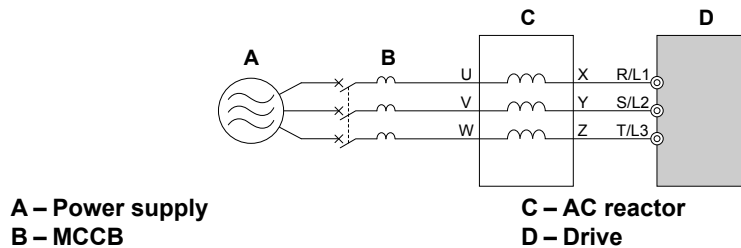


Figure 8.14 Connecting an AC Reactor

■ Connecting a DC Link Choke

A DC link choke can be installed to drive models 2A0004 to 2A0081, 4A0002 to 4A0044, and 5A0003 to 5A0032. When installing a DC link choke, remove the jumper between terminals ⊕1 and ⊕2 (terminals are jumpered for shipment). The jumper must be installed if not using a DC link choke. Refer to [Figure 8.15](#) for an example of DC link choke wiring.

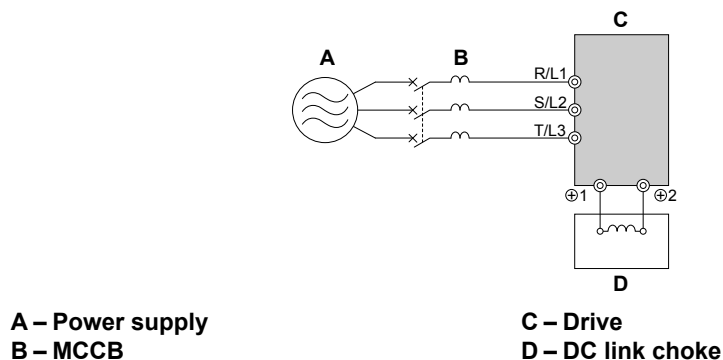


Figure 8.15 Connecting a DC Link Choke

◆ Connecting a Surge Absorber

A surge absorber suppresses surge voltage generated from switching an inductive load near the drive. Inductive loads include magnetic contactors, relays, valves, solenoids, and brakes. Always use a surge absorber or diode when operating with an inductive load.

WARNING! Fire Hazard. Due to surge absorber short circuit on drive output terminals U/T1, V/T2, and W/T3, do not connect surge absorbers to the drive output power terminals. Failure to comply may result in serious injury or death by fire or flying debris.

◆ Connecting a Noise Filter

■ Input-Side Noise Filter

Drive outputs generate noise as a result of high-speed switching. This noise flows from inside the drive back to the power supply, possibly affecting other equipment. Installing a noise filter to the input side of the drive can reduce the amount of noise flowing back into the power supply. This also prevents noise from entering the drive from the power supply.

- Use a noise filter specifically designed for AC drives.
- Install the noise filter as close as possible to the drive.

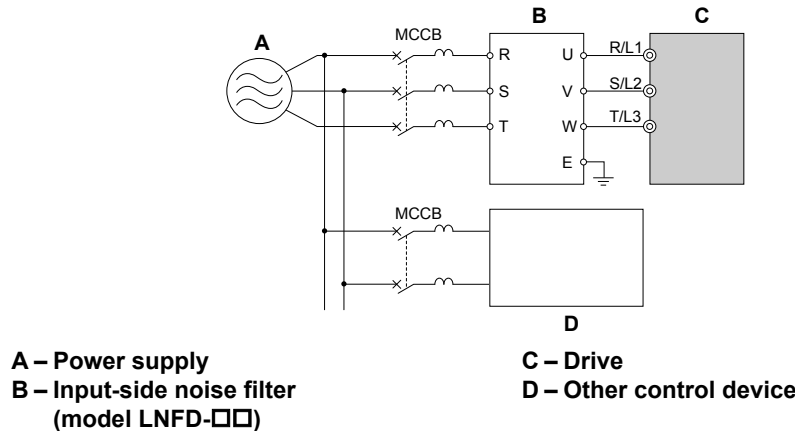


Figure 8.16 Input-Side Noise Filter (Three-Phase 200/400 V)

200 V Class and 400 V Class drive models are tested according to European standards IEC/EN 61800-5-1 and comply with EMC guidelines. [Refer to EMC Guidelines Compliance on page 544](#) for details on EMC filter selection and installation.

■ Output-Side Noise Filter

A noise filter on the output side of the drive reduces inductive noise and radiated noise. [Figure 8.17](#) illustrates an example of output-side noise filter wiring.

NOTICE: Do not connect phase-advancing capacitors or LC/RC noise filters to the output circuits. Improper application of noise filters could result in damage to the drive.

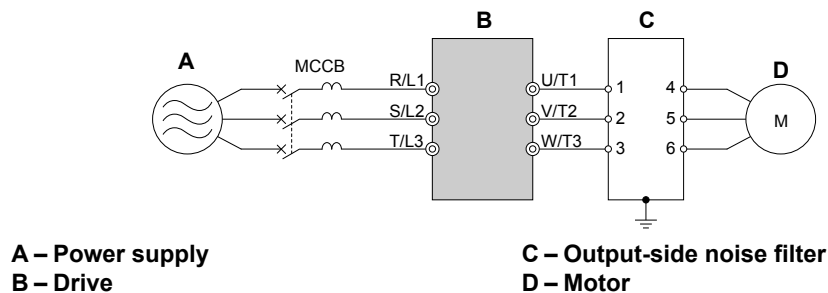


Figure 8.17 Output-Side Noise Filter

- **Radiated Noise:** Electromagnetic waves radiated from the drive and cables create noise throughout the radio bandwidth that can affect surrounding devices.
- **Induced Noise:** Noise generated by electromagnetic induction can affect the signal line and may cause the controller to malfunction.

Preventing Induced Noise

Use a noise filter on the output side or use shielded cables. Lay the cables at least 30 cm away from the signal line to prevent induced noise.

8.5 Installing Peripheral Devices

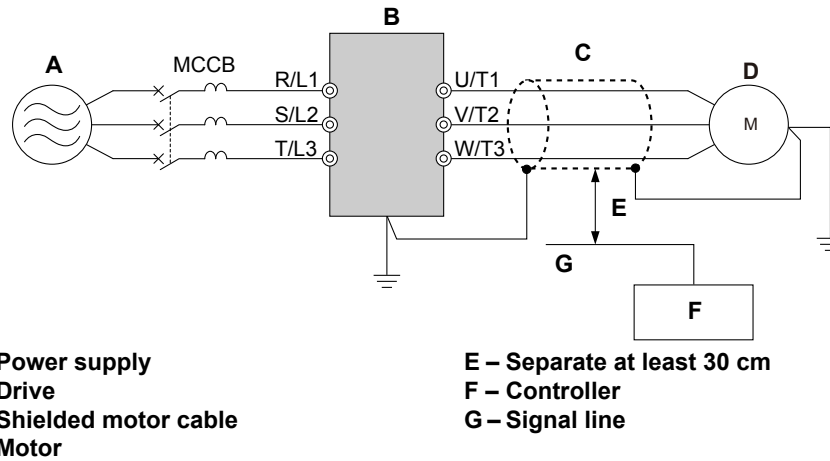


Figure 8.18 Preventing Induced Noise

Reducing Radiated and Radio Frequency Noise

The drive, input lines, and output lines generate radio frequency noise. Use noise filters on input and output sides and install the drive in a metal enclosure panel to reduce radio frequency noise.

Note: The cable running between the drive and motor should be as short as possible.

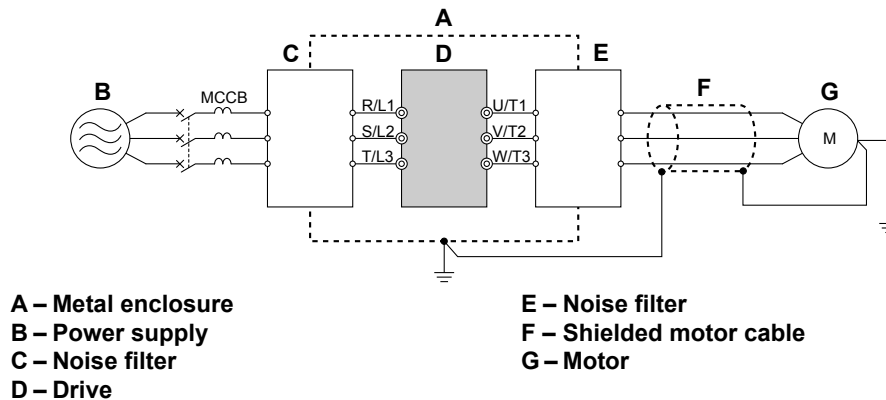


Figure 8.19 Reducing Radio Frequency Noise

◆ Installing Input Fuses

NOTICE: If a fuse is blown or a Ground Fault Circuit Interrupter (GFCI) is tripped, check the wiring and the selection of the peripheral devices. Check the wiring and the selection of peripheral devices to identify the cause. Contact Yaskawa before restarting the drive or the peripheral devices if the cause cannot be identified.

■ Factory Recommended Branch Circuit Protection

Yaskawa recommends installing one of the following types of branch circuit protection to maintain compliance with UL508C. Semiconductor protective type fuses are preferred. Alternate branch circuit protection devices are also listed in [Table 8.3](#).

Table 8.3 Factory Recommended P1000 AC Drive Branch Circuit Protection

| Drive Model | Nominal Output Power HP | AC Drive Input Amps | MCCB Rating Amps ^{<1>} | Time Delay Fuse Rating Amps ^{<2>} | Non-time Delay Fuse Rating Amps ^{<3>} | Bussman Semiconductor Fuse Rating (Fuse Ampere) ^{<4>} |
|--------------------|-------------------------|---------------------|---------------------------------------|--|--|--|
| 200 V Class | | | | | | |
| 2A0004 | 0.75 | 3.9 | 15 | 6.25 | 10 | FWH-70B (70) |
| 2A0006 | 1 - 1.5 | 7.3 | 15 | 12 | 20 | FWH-70B (70) |
| 2A0008 | 2 | 8.8 | 15 | 15 | 25 | FWH-70B (70) |
| 2A0010 | 3 | 10.8 | 20 | 17.5 | 30 | FWH-70B (70) |
| 2A0012 | 3 | 13.9 | 25 | 20 | 40 | FWH-70B (70) |

| Drive Model | Nominal Output Power HP | AC Drive Input Amps | MCCB Rating Amps <1> | Time Delay Fuse Rating Amps <2> | Non-time Delay Fuse Rating Amps <3> | Bussman Semi-conductor Fuse Rating (Fuse Ampere) <4> |
|--------------------|-------------------------|---------------------|----------------------|---------------------------------|-------------------------------------|--|
| 2A0018 | 5 | 18.5 | 35 | 30 | 50 | FWH-90B(90) |
| 2A0021 | 7.5 | 24 | 45 | 40 | 70 | FWH-90B(90) |
| 2A0030 | 10 | 37 | 60 | 60 | 110 | FWH-100B (100) |
| 2A0040 | 15 | 52 | 100 | 90 | 150 | FWH-200B (200) |
| 2A0056 | 20 | 68 | 125 | 110 | 200 | FWH-200B (200) |
| 2A0069 | 25 | 80 | 150 | 125 | 225 | FWH-200B (200) |
| 2A0081 | 30 | 96 | 175 | 150 | 275 | FWH-300A (300) |
| 2A0110 | 40 | 111 | 200 | 175 | 300 | FWH-300A (300) |
| 2A0138 | 50 | 136 | 250 | 225 | 400 | FWH-350A (350) |
| 2A0169 | 60 | 164 | 300 | 250 | 450 | FWH-400A (400) |
| 2A0211 | 75 | 200 | 400 | 350 | 600 | FWH-400A (400) |
| 2A0250 | 100 | 271 | 500 | 450 | 800 | FWH-600A (600) |
| 2A0312 | 125 | 324 | 600 | 500 | 800 | FWH-700A (700) |
| 2A0360 | 150 | 394 | 700 | 600 | 1000 <5> | FWH-800A (800) |
| 2A0415 | 175 | 471 | 900 | 800 | 1400 <5> | FWH-1000A (1000) |
| 400 V Class | | | | | | |
| 4A0002 | 1 | 2.1 | 15 | 3.5 | 6 | FWH-40B (40) |
| 4A0004 | 2 | 4.3 | 15 | 7.5 | 12 | FWH-50B (50) |
| 4A0005 | 3 | 5.9 | 15 | 10 | 17.5 | FWH-70B (70) |
| 4A0007 | 3 | 8.1 | 15 | 12 | 20 | FWH-70B (70) |
| 4A0009 | 5 | 9.4 | 15 | 15 | 25 | FWH-90B (90) |
| 4A0011 | 7.5 | 14 | 25 | 20 | 40 | FWH-90B (90) |
| 4A0018 | 10 | 20 | 40 | 35 | 60 | FWH-80B (80) |
| 4A0023 | 15 | 24 | 45 | 40 | 70 | FWH-100B (100) |
| 4A0031 | 20 | 38 | 75 | 60 | 110 | FWH-125B (125) |
| 4A0038 | 25 | 44 | 75 | 75 | 125 | FWH-200B (200) |
| 4A0044 | 30 | 52 | 100 | 90 | 150 | FWH-250A (250) |
| 4A0058 | 40 | 58 | 100 | 100 | 150 | FWH-250A (250) |
| 4A0072 | 50 | 71 | 125 | 110 | 200 | FWH-250A (250) |
| 4A0088 | 60 | 86 | 150 | 150 | 250 | FWH-250A (250) |
| 4A0103 | 75 | 105 | 200 | 175 | 300 | FWH-250A (250) |
| 4A0139 | 100 | 142 | 250 | 225 | 400 | FWH-350A (350) |
| 4A0165 | 125 | 170 | 300 | 250 | 500 | FWH-400A (400) |
| 4A0208 | 150 | 207 | 400 | 350 | 600 | FWH-500A (500) |
| 4A0250 | 200 | 248 | 450 | 400 | 700 | FWH-600A (600) |
| 4A0296 | 250 | 300 | 600 | 500 | 800 | FWH-700A (700) |
| 4A0362 | 300 | 346 | 600 | 600 | 1000 <5> | FWH-800A (800) |
| 4A0414 | 350 | 410 | 800 | 700 | 1200 <5> | FWH-800A (800) |
| 4A0515 | 400 - 450 | 465 | 900 | 800 | 1350 <5> | FWH-1000A (1000) |
| 4A0675 | 500 - 600 | 657 | 1200 | 1100 <5> | 1800 <5> | FWH-1200A (1200) |
| 4A0930 | 700 - 800 | 922 | Not Applicable | | | FWH-1200A (1200) |
| 4A1200 | 900 - 1000 | 1158 | | | | FWH-1600A (1600) |
| 600 V Class | | | | | | |
| 5A0003 | 2 | 3.6 | 15 | 6.25 | 10 | FWP-50B (50) |
| 5A0004 | 3 | 5.1 | 15 | 8 | 15 | FWP-50B (50) |
| 5A0006 | 5 | 8.3 | 15 | 12 | 20 | FWP-60B (60) |
| 5A0009 | 7.5 | 12 | 20 | 20 | 35 | FWP-60B (60) |

8.5 Installing Peripheral Devices

| Drive Model | Nominal Output Power HP | AC Drive Input Amps | MCCB Rating Amps <1> | Time Delay Fuse Rating Amps <2> | Non-time Delay Fuse Rating Amps <3> | Bussman Semiconductor Fuse Rating (Fuse Ampere) <4> |
|-------------|-------------------------|---------------------|----------------------|---------------------------------|-------------------------------------|---|
| 5A0011 | 10 | 16 | 30 | 25 | 45 | FWP-70B (70) |
| 5A0017 | 15 | 23 | 40 | 40 | 60 | FWP-100B (100) |
| 5A0022 | 20 | 31 | 60 | 50 | 90 | FWP-100B (100) |
| 5A0027 | 25 | 38 | 75 | 60 | 110 | FWP-125A (125) |
| 5A0032 | 30 | 45 | 75 | 75 | 125 | FWP-125A (125) |
| 5A0041 | 40 | 44 | 75 | 75 | 125 | FWP-175A (175) |
| 5A0052 | 50 | 54 | 100 | 90 | 150 | FWP-175A (175) |
| 5A0062 | 60 | 66 | 125 | 110 | 175 | FWP-250A (250) |
| 5A0077 | 75 | 80 | 150 | 125 | 225 | FWP-250A (250) |
| 5A0099 | 100 | 108 | 175 | 175 | 300 | FWP-250A (250) |
| 5A0125 | 125 | 129 | 225 | 225 | 350 | FWP-350A (350) |
| 5A0145 | 150 | 158 | 300 | 275 | 450 | FWP-350A (350) |
| 5A0192 | 200 | 228 | 400 | 350 | 600 | FWP-600A (600) |
| 5A0242 | 250 | 263 | 500 | 450 | 700 | FWP-600A (600) |

- <1> Maximum MCCB Rating is 15 A, or 200 % of drive input current rating, whichever is larger. MCCB voltage rating must be 600 VAC or greater.
- <2> Maximum Time Delay fuse is 175% of drive input current rating. This covers any Class CC, J or T class fuse.
- <3> Maximum Non-time Delay fuse is 300% of drive input current rating. This covers any CC, J or T class fuse.
- <4> When using semiconductor fuses, Bussman FWH and FWP are required for UL compliance. Select FWH for 200 V Class and 400 V Class models and FWP fuses for 600 V models.
- <5> Class L fuse is also approved for this rating.

◆ Attachment for External Heatsink Mounting (IP00 Enclosure)

An external attachment can be used to project the heatsink outside of an enclosure to ensure that there is sufficient air circulation around the heatsink.

Contact a Yaskawa sales representative or Yaskawa directly for more information on this attachment.

◆ Installing a Motor Thermal Overload (oL) Relay on the Drive Output

Motor thermal overload relays protect the motor by disconnecting power lines to the motor due to a motor overload condition.

Install a motor thermal overload relay between the drive and motor:

- When operating multiple motors on a single AC drive.
- When using a power line bypass to operate the motor directly from the power line.

It is not necessary to install a motor thermal overload relay when operating a single motor from a single AC drive. The AC drive has UL recognized electronic motor overload protection built into the drive software.

- Note:**
1. Disable the motor protection function (L1-01 = 0) when using an external motor thermal overload relay.
 2. Create a sequence to produce an external fault (coast to a stop) when triggered.

■ General Precautions when Using Thermal Overload Relays

Consider the following application precautions when using motor thermal overload relays on the output of AC drives to prevent nuisance trips or overheat of the motor at low speeds:

- Low speed motor operation
- Use of multiple motors on a single AC drive
- Motor cable length
- Nuisance tripping resulting from high AC drive carrier frequency

Low Speed Operation and Motor Thermal oL Relays

Generally, thermal relays are applied on general-purpose motors. When general-purpose motors are driven by AC drives, the motor current is approximately 5% to 10% greater than if driven by a commercial power supply. In addition, the cooling capacity of a motor with a shaft-driven fan decreases when operating at low speeds. Motor overheating may occur even when

the load current is within the motor rated value. A thermal relay cannot effectively protect the motor due to the reduction of cooling at low speeds. For this reason, apply the UL recognized electronic thermal overload protection function built into the drive whenever possible.

UL recognized electronic thermal overload function of the drive: Speed-dependent heat characteristics are simulated using data from standard motors and force-ventilated motors. The motor is protected from overload using this function.

Using a Single Drive to Operate Multiple Motors

Set parameter L1-01 to 0 to disable thermal overload protection for the drive.

Note: The UL recognized electronic thermal overload function cannot be applied when operating multiple motors with a single drive.

Long Motor Cables

When a high carrier frequency and long motor cables are used, nuisance tripping of the thermal relay may occur due to increased leakage current. To avoid this, reduce the carrier frequency or increase the tripping level of the thermal overload relay.

Nuisance Tripping Due to a High AC Drive Carrier Frequency

Current waveforms generated by high carrier frequency PWM drives tend to increase the temperature in overload relays. It may be necessary to increase the trip level setting when encountering nuisance triggering of the relay.

WARNING! Fire Hazard. Confirm an actual motor overload condition is not present prior to increasing the thermal oL trip setting. Check local electrical codes before making adjustments to motor thermal overload settings. Failure to comply could result in death or serious injury.

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Appendix: A

Specifications

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| A.4 | DRIVE DERATING DATA..... | 407 |

A.1 Power Ratings

◆ Three-Phase 200 V Class Drive Models 2A0004 to 2A0030

Table A.1 Power Ratings (Three-Phase 200 V Class)

| Item | | Specification | | | | | | | | |
|--|----------------------------------|--|--------|--------|--------|--------|--------|--------|--------|------|
| Drive Model | | 2A0004 | 2A0006 | 2A0008 | 2A0010 | 2A0012 | 2A0018 | 2A0021 | 2A0030 | |
| Maximum Applicable Motor Capacity (HP) <1> | ND Rating | 0.75 | 1 | 2 | 3 | 3 | 5 | 7.5 | 10 | |
| | Input Current (A) <2> | 3.9 | 7.3 | 8.8 | 10.8 | 13.9 | 18.5 | 24 | 37 | |
| Input | Rated Voltage Rated Frequency | Three-phase 200 to 240 Vac 50/60 Hz/270 to 340 Vdc <3> | | | | | | | | |
| | Allowable Voltage Fluctuation | -15 to 10% | | | | | | | | |
| | Allowable Frequency Fluctuation | ±5% | | | | | | | | |
| | Input Power (kVA) | ND Rating | 2.2 | 3.1 | 4.1 | 5.8 | 7.8 | 9.5 | 14 | 18 |
| Output | Rated Output Capacity (kVA) <4> | ND Rating <5> | 1.3 | 2.3 | 3 | 3.7 | 4.6 | 6.7 | 8 | 11.4 |
| | Rated Output Current (A) | ND Rating <5> | 3.5 | 6 | 8 | 9.6 | 12 | 17.5 | 21 | 30 |
| | Overload Tolerance | ND Rating: 120% of rated output current for 60 s (Derating may be required for applications that start and stop frequently) | | | | | | | | |
| | Carrier Frequency | User-adjustable between 1 and 15 kHz <5> | | | | | | | | |
| | Maximum Output Voltage (V) | Three-phase 200 to 240 V (proportional to input voltage) | | | | | | | | |
| Maximum Output Frequency (Hz) | 400 Hz (user-set) | | | | | | | | | |

<1> The motor capacity (HP) refers to a NEC rated 4-pole motor. The rated output current of the drive output amps should be equal to or greater than the motor current. Select the appropriate capacity drive if operating the motor continuously above motor nameplate current.

<2> Assumes operation at the rated output current. Input current rating varies depending on the power supply transformer, input reactor, wiring connections, and power supply impedance.

<3> DC is not available for UL/CE standards.

<4> Rated motor capacity is calculated with a rated output voltage of 220 V.

<5> Carrier frequency default setting is Swing PWM 1 (C6-02 = 7). C6-02 settings 1, 7, 8, 9, and A do not require current derating. All other settings raise the carrier frequency and require current derating.

◆ Three-Phase 200 V Class Drive Models 2A0040 to 2A0211

Table A.2 Power Ratings Continued (Three-Phase 200 V Class)

| Item | | Specification | | | | | | | |
|--|----------------------------------|--|--------|--------|--------|--------|--------|--|--------|
| Drive Model | | 2A0040 | 2A0056 | 2A0069 | 2A0081 | 2A0110 | 2A0138 | 2A0169 | 2A0211 |
| Maximum Applicable Motor Capacity (HP) <1> | ND Rating | 15 | 20 | 25 | 30 | 40 | 50 | 60 | 75 |
| | Input Current (A) <2> | 52 | 68 | 80 | 96 | 111 | 136 | 164 | 200 |
| Input | Rated Voltage Rated Frequency | Three-phase 200 to 240 Vac 50/60 Hz/270 to 340 Vdc <3> | | | | | | | |
| | Allowable Voltage Fluctuation | -15 to 10% | | | | | | | |
| | Allowable Frequency Fluctuation | ±5% | | | | | | | |
| | Input Power (kVA) | 27 | 36 | 44 | 52 | 51 | 62 | 75 | 91 |
| Output | Rated Output Capacity (kVA) <4> | 15.2 | 21 | 26 | 31 | 42 | 53 | 64 | 80 |
| | Rated Output Current (A) | 40 | 56 | 69 | 81 | 110 | 138 | 169 | 211 |
| | Overload Tolerance | ND Rating: 120% of rated output current for 60 s (Derating may be required for applications that start and stop frequently) | | | | | | | |
| | Carrier Frequency | User-adjustable between 1 and 15 kHz <5> | | | | | | User-adjustable between 1 and 10 kHz <5> | |
| | Maximum Output Voltage (V) | Three-phase 200 to 240 V (proportional to input voltage) | | | | | | | |
| | Maximum Output Frequency (Hz) | 400 Hz (user-set) | | | | | | | |

- <1> The motor capacity (HP) refers to a NEC rated 4-pole motor. The rated output current of the drive output amps should be equal to or greater than the motor current. Select the appropriate capacity drive if operating the motor continuously above motor nameplate current.
- <2> Assumes operation at the rated output current. Input current rating varies depending on the power supply transformer, input reactor, wiring connections, and power supply impedance.
- <3> DC is not available for UL/CE standards.
- <4> Rated motor capacity is calculated with a rated output voltage of 220 V.
- <5> Carrier frequency default setting is Swing PWM 1 (C6-02 = 7). C6-02 settings 1, 7, 8, 9, and A do not require current derating. All other settings raise the carrier frequency and require current derating.

◆ Three-Phase 200 V Class Drive Models 2A0250 to 2A0415

Table A.3 Power Ratings Continued (Three-Phase 200 V Class)

| Item | | Specification | | | |
|---|--|--|--------|--------|--------|
| Drive Models | | 2A0250 | 2A0312 | 2A0360 | 2A0415 |
| Maximum Applicable Motor Capacity (HP) <1> | | 100 | 125 | 150 | 175 |
| Input Current (A) <2> | | 271 | 324 | 394 | 471 |
| Input | Rated Voltage Rated Frequency | Three-phase 200 to 240 Vac 50/60 Hz/270 to 340 Vdc <3> | | | |
| | Allowable Voltage Fluctuation | -15 to 10% | | | |
| | Allowable Frequency Fluctuation | ±5% | | | |
| | Input Power (kVA) | 124 | 148 | 180 | 215 |
| Rated Output Capacity (kVA) <4> | | 95 | 119 | 137 | 158 |
| Rated Output Current (A) | | 250 | 312 | 360 | 415 |
| Output | Overload Tolerance | ND Rating: 120% of rated output current for 60 s (Derating may be required for applications that start and stop frequently) | | | |
| | Carrier Frequency | User-adjustable between 1 and 10 kHz <5> | | | |
| | Maximum Output Voltage (V) | Three-phase 200 to 240 V (proportional to input voltage) | | | |
| | Maximum Output Frequency (Hz) | 400 Hz (user-set) | | | |

- <1> The motor capacity (HP) refers to a NEC rated 4-pole motor. The rated output current of the drive output amps should be equal to or greater than the motor current. Select the appropriate capacity drive if operating the motor continuously above motor nameplate current.
- <2> Assumes operation at the rated output current. Input current rating varies depending on the power supply transformer, input reactor, wiring connections, and power supply impedance.
- <3> DC is not available for UL/CE standards.
- <4> Rated motor capacity is calculated with a rated output voltage of 220 V.
- <5> Carrier frequency default setting is Swing PWM 1 (C6-02 = 7). C6-02 settings 1, 7, 8, 9, and A do not require current derating. All other settings raise the carrier frequency and require current derating.

◆ Three-Phase 400 V Class Drive Models 4A0002 to 4A0031

Table A.4 Power Ratings (Three-Phase 400 V Class)

| Item | | Specification | | | | | | | | |
|--|---|--|--------|--------|--------|--------|--------|--------|--------|--------|
| Drive Models | | 4A0002 | 4A0004 | 4A0005 | 4A0007 | 4A0009 | 4A0011 | 4A0018 | 4A0023 | 4A0031 |
| Maximum Applicable Motor Capacity (HP) <1> | ND Rating | 0.75 | 2 | 3 | 3 | 5 | 7.5 | 10 | 15 | 20 |
| | Input Current (A) <2> | 2.1 | 4.3 | 5.9 | 8.1 | 9.4 | 14 | 20 | 24 | 38 |
| Input | Rated Voltage Rated Frequency | Three-phase: 380 to 480 Vac 50/60 Hz/510 to 680 Vdc <3> | | | | | | | | |
| | Allowable Voltage Fluctuation | -15 to 10% | | | | | | | | |
| | Allowable Frequency Fluctuation | ±5% | | | | | | | | |
| | Input Power (kVA) ND Rating | 2.3 | 4.3 | 6.1 | 8.1 | 10.0 | 14.5 | 19.4 | 28.4 | 37.5 |
| Output | Rated Output Capacity (kVA) <4> ND Rating <5> | 1.6 | 3.1 | 4.1 | 5.3 | 6.7 | 8.5 | 13.3 | 17.5 | 24 |
| | Rated Output Current (A) ND Rating <5> | 2.1 | 4.1 | 5.4 | 6.9 | 8.8 | 11.1 | 17.5 | 23 | 31 |
| | Overload Tolerance | ND Rating: 120% of rated output current for 60 s (Derating may be required for applications that start and stop frequently) | | | | | | | | |
| | Carrier Frequency | User-adjustable between 1 and 15 kHz <5> | | | | | | | | |
| | Maximum Output Voltage (V) | Three-phase: 380 to 480 V (proportional to input voltage) | | | | | | | | |
| Maximum Output Frequency (Hz) | 400 Hz (user-adjustable) | | | | | | | | | |

- <1> The motor capacity (HP) refers to a NEC rated 4-pole motor. The rated output current of the drive output amps should be equal to or greater than the motor current. Select the appropriate capacity drive if operating the motor continuously above motor nameplate current.
- <2> Assumes operation at the rated output current. Input current rating varies depending on the power supply transformer, input reactor, wiring conditions, and power supply impedance.
- <3> DC is not available for UL/CE standards.
- <4> Rated motor capacity is calculated with a rated output voltage of 440 V.
- <5> Carrier frequency default setting is Swing PWM 1 (C6-02 = 7). C6-02 settings 1, 7, 8, 9, and A do not require current derating. All other settings raise the carrier frequency and require current derating.

◆ Three-Phase 400 V Class Drive Models 4A0038 to 4A0165

Table A.5 Power Ratings Continued (Three-Phase 400 V Class)

| Item | | Specification | | | | | | | | |
|--|----------------------------------|--|--------|--------|--------|--------|--------|--|--------|-----|
| Drive Models | | 4A0038 | 4A0044 | 4A0058 | 4A0072 | 4A0088 | 4A0103 | 4A0139 | 4A0165 | |
| Maximum Applicable Motor Capacity (HP) <1> | ND Rating | 25 | 30 | 40 | 50 | 60 | 75 | 100 | 125 | |
| | Input Current (A) <2> | 44 | 52 | 58 | 71 | 86 | 105 | 142 | 170 | |
| Input | Rated Voltage Rated Frequency | Three-phase: 380 to 480 Vac 50/60 Hz/510 to 680 Vdc <3> | | | | | | | | |
| | Allowable Voltage Fluctuation | -15 to 10% | | | | | | | | |
| | Allowable Frequency Fluctuation | ±5% | | | | | | | | |
| | Input Power (kVA) | ND Rating | 46.6 | 54.9 | 53.0 | 64.9 | 78.6 | 96.0 | 130 | 156 |
| Output | Rated Output Capacity (kVA) <4> | ND Rating <5> | 29 | 34 | 44 | 55 | 67 | 78 | 106 | 126 |
| | Rated Output Current (A) | ND Rating <5> | 38 | 44 | 58 | 72 | 88 | 103 | 139 | 165 |
| | Overload Tolerance | ND Rating: 120% of rated output current for 60 s (Derating may be required for applications that start and stop frequently) | | | | | | | | |
| | Carrier Frequency | User-adjustable between 1 and 15 kHz <5> | | | | | | User-adjustable between 1 and 10 kHz <5> | | |
| | Maximum Output Voltage (V) | Three-phase: 380 to 480 V (proportional to input voltage) | | | | | | | | |
| Maximum Output Frequency (Hz) | 400 Hz (user-adjustable) | | | | | | | | | |

- <1> The motor capacity (HP) refers to a NEC rated 4-pole motor. The rated output current of the drive output amps should be equal to or greater than the motor current. Select the appropriate capacity drive if operating the motor continuously above motor nameplate current.
- <2> Assumes operation at the rated output current. Input current rating varies depending on the power supply transformer, input reactor, wiring conditions, and power supply impedance.
- <3> DC is not available for UL/CE standards.
- <4> Rated motor capacity is calculated with a rated output voltage of 440 V.
- <5> Carrier frequency default setting is Swing PWM 1 (C6-02 = 7). C6-02 settings 1, 7, 8, 9, and A do not require current derating. All other settings raise the carrier frequency and require current derating.

◆ Three-Phase 400 V Class Drive Models 4A0208 to 4A1200

Table A.6 Power Ratings Continued (Three-Phase 400 V Class)

| Item | | Specification | | | | | | | | |
|--|----------------------------------|--|--------|--------|--------|--------|-------------------------------------|-------------|---------------------------|---------|
| Drive Models | | 4A0208 | 4A0250 | 4A0296 | 4A0362 | 4A0414 | 4A0515 | 4A0675 | 4A0930 | 4A1200 |
| Maximum Applicable Motor Capacity (HP) <1> | ND Rating | 150 | 200 | 250 | 300 | 350 | 400-450 | 500-550 | 750 | 1000 |
| | HD Rating | 125-150 | 150 | 200 | 250 | 300 | 350 | 400-450-500 | 650 | 900 |
| Input Current (A) <2> | ND Rating | 207 | 248 | 300 | 346 | 410 | 465 | 657 | 922 | 1158 |
| | HD Rating | 170 | 207 | 248 | 300 | 346 | 410 | 584 | 830 | 1031 |
| Input | Rated Voltage Rated Frequency | Three-phase: 380 to 480 Vac 50/60 Hz/510 to 680 Vdc <3> | | | | | | | | |
| | Allowable Voltage Fluctuation | -15 to 10% | | | | | | | | |
| | Allowable Frequency Fluctuation | ±5% | | | | | | | | |
| | Input Power (kVA) | ND Rating | 189 | 227 | 274 | 316 | 375 | 425 | 601 | 843 |
| HD Rating | | 155 | 189 | 227 | 274 | 316 | 375 | 534 | 759 | 943 |
| Rated Output Capacity (kVA) <4> | ND Rating <5> | 189 | 227 | 274 | 316 | 375 | 425 | 601 | 843 | 1059 |
| | HD Rating | <6>137 | <6>165 | <6>198 | <6>232 | <6>282 | <5>343 | <5>461 | <5>617 | <5>831 |
| Rated Output Current (A) | ND Rating <5> | 208 | 250 | 296 | 362 | 414 | 515 | 675 | 930 | 1200 |
| | HD Rating | <6>180 | <6>216 | <6>260 | <6>304 | <7>370 | <5>450 | <5>605 | <5>810 | <5>1090 |
| Output | Overload Tolerance | ND Rating: 120% of rated output current for 60 s HD Rating: 150% of rated output current for 60 s (Derating may be required for applications that start and stop frequently) | | | | | | | | |
| | Carrier Frequency | User-adjustable between 1 and 10 kHz | | | | | User-adjustable between 1 and 5 kHz | | | |
| | Maximum Output Voltage (V) | Three-phase: 380 to 480 Vac (proportional to input voltage) | | | | | | | 0.95 × [input voltage] | |
| | Maximum Output Frequency (Hz) | 400 Hz (user-adjustable) | | | | | | | | |
| | | | | | | | | | | |

<1> The motor capacity (HP) refers to a NEC rated 4-pole motor. The rated output current of the drive output amps should be equal to or greater than the motor current. Select the appropriate capacity drive if operating the motor continuously above motor nameplate current.

<2> Assumes operation at the rated output current. Input current rating varies depending on the power supply transformer, input reactor, wiring conditions, and power supply impedance.

<3> DC input is not available for UL standards.

<4> Rated motor capacity is calculated with a rated output voltage of 440 V.

<5> Carrier frequency is set to 2 kHz. Current derating is required in order to raise the carrier frequency.

<6> Carrier frequency can be increased to 5 kHz while keeping this current derating. Higher carrier frequency settings require derating.

<7> Carrier frequency can be increased to 5 kHz while keeping this current derating. Higher carrier frequency settings require derating.

◆ Three-Phase 600 V Class Drive Models 5A0003 to 5A0032

Table A.7 Power Ratings (Three-Phase 600 V Class)

| Item | | Specification | | | | | | | | | | |
|-------------------------------|--|-------------------|--|--------|--------|--------|--------|--|--------|--------|----|--|
| Drive Models | | 5A0003 | 5A0004 | 5A0006 | 5A0009 | 5A0011 | 5A0017 | 5A0022 | 5A0027 | 5A0032 | | |
| Input | Maximum Applicable Motor Capacity (HP) <1> | ND Rating | 2 | 3 | 5 | 7.5 | 10 | 15 | 20 | 25 | 30 | |
| | Input Current (A) <2> | ND Rating | 3.6 | 5.1 | 8.3 | 12 | 16 | 23 | 31 | 38 | 45 | |
| | Rated Voltage Rated Frequency | | Three-phase 500 to 600 Vac 50/60 Hz | | | | | | | | | |
| | Allowable Voltage Fluctuation | | -10 (-15) to +10% | | | | | | | | | |
| | Allowable Frequency Fluctuation | | ±5% | | | | | | | | | |
| Output | Input Power (kVA) | ND Rating | 4.1 | 5.8 | 9.5 | 14 | 18 | 26 | 35 | 43 | 51 | |
| | Rated Output Capacity (kVA) <3> | ND Rating <4> | 2.7 | 3.9 | 6.1 | 9 | 11 | 17 | 22 | 27 | 32 | |
| | Rated Output Current (A) | ND Rating <4> | 2.7 | 3.9 | 6.1 | 9 | 11 | 17 | 22 | 27 | 32 | |
| | Overload Tolerance | | ND Rating: 120% of rated output current for 60 s (Derating may be required for applications that start and stop frequently) | | | | | | | | | |
| | Carrier Frequency | | User-adjustable between 1 and 15 kHz <4> | | | | | User-adjustable between 1 and 10 kHz <4> | | | | |
| | Maximum Output Voltage (V) | | Three-phase 500 to 600 V (proportional to input voltage) | | | | | | | | | |
| Maximum Output Frequency (Hz) | | 400 Hz (user-set) | | | | | | | | | | |

<1> The motor capacity (HP) refers to a NEC rated 4-pole motor. The rated output current of the drive output amps should be equal to or greater than the motor current. Select the appropriate capacity drive if operating the motor continuously above motor nameplate current.

<2> Assumes operation at the rated output current. Input current rating varies depending on the power supply transformer, input reactor, wiring connections, and power supply impedance.

<3> Rated motor capacity is calculated with a rated output voltage of 575 V.

<4> Carrier frequency default setting is Swing PWM 1 (C6-02 = 7). C6-02 settings 1, 7, 8, 9, and A do not require current derating. All other settings raise the carrier frequency and require current derating.

◆ Three-Phase 600 V Class Drive Models 5A0041 to 5A0099

Table A.8 Power Ratings Continued (Three-Phase 600 V Class)

| Item | | Specification | | | | |
|--|----------------------------------|--|--------|--------|--------|---|
| Drive Models | | 5A0041 | 5A0052 | 5A0062 | 5A0077 | 5A0099 |
| Maximum Applicable Motor Capacity (HP) <1> | | 40 | 50 | 60 | 75 | 100 |
| Input Current (A) <2> | | 44 | 54 | 66 | 80 | 108 |
| Input | Rated Voltage Rated Frequency | Three-phase 500 to 600 Vac 50/60 Hz | | | | |
| | Allowable Voltage Fluctuation | -10 (-15) to +10% | | | | |
| | Allowable Frequency Fluctuation | ±5% | | | | |
| | Input Power (kVA) | 50 | 62 | 75 | 91 | 123 |
| Rated Output Capacity (kVA) <3> | | 41 | 52 | 62 | 77 | 99 |
| Rated Output Current (A) | | 41 | 52 | 62 | 77 | 99 |
| Output | Overload Tolerance | ND Rating: 120% of rated output current for 60 s (Derating may be required for applications that start and stop frequently) | | | | |
| | Carrier Frequency | User-adjustable between 1 and 10 kHz <4> | | | | User-adjustable between 1 and 8 kHz <4> |
| | Maximum Output Voltage (V) | Three-phase 500 to 600 V (proportional to input voltage) | | | | |
| | Maximum Output Frequency (Hz) | 400 Hz (user-set) | | | | |

- <1> The motor capacity (HP) refers to a NEC rated 4-pole motor. The rated output current of the drive output amps should be equal to or greater than the motor current. Select the appropriate capacity drive if operating the motor continuously above motor nameplate current.
- <2> Assumes operation at the rated output current. Input current rating varies depending on the power supply transformer, input reactor, wiring connections, and power supply impedance.
- <3> Rated motor capacity is calculated with a rated output voltage of 575 V.
- <4> Carrier frequency default setting is Swing PWM 1 (C6-02 = 7). C6-02 settings 1, 7, 8, 9, and A do not require current derating. All other settings raise the carrier frequency and require current derating.

◆ Three-Phase 600 V Class Drive Models 5A0125 to 5A0242

Table A.9 Power Ratings Continued (Three-Phase 600 V Class)

| Item | | Specification | | | |
|--|----------------------------------|--|--------|--------|--------|
| Drive Models | | 5A0125 | 5A0145 | 5A0192 | 5A0242 |
| Maximum Applicable Motor Capacity (HP) <1> | | 125 | 150 | 200 | 250 |
| Input Current (A) <2> | | 129 | 158 | 228 | 263 |
| Input | Rated Voltage Rated Frequency | Three-phase 500 to 600 Vac 50/60 Hz | | | |
| | Allowable Voltage Fluctuation | -10 (-15) to +10% | | | |
| | Allowable Frequency Fluctuation | ±5% | | | |
| | Input Power (kVA) | 147 | 181 | 261 | 301 |
| Rated Output Capacity (kVA) <3> | | 124 | 144 | 191 | 241 |
| Rated Output Current (A) | | 125 | 145 | 192 | 242 |
| Output | Overload Tolerance | ND Rating: 120% of rated output current for 60 s (Derating may be required for applications that start and stop frequently) | | | |
| | Carrier Frequency | User-adjustable between 1 and 3 kHz <4> | | | |
| | Maximum Output Voltage (V) | Three-phase 500 to 600 V (proportional to input voltage) | | | |
| | Maximum Output Frequency (Hz) | 400 Hz (user-set) | | | |

- <1> The motor capacity (HP) refers to a NEC rated 4-pole motor. The rated output current of the drive output amps should be equal to or greater than the motor current. Select the appropriate capacity drive if operating the motor continuously above motor nameplate current.
- <2> Assumes operation at the rated output current. Input current rating varies depending on the power supply transformer, input reactor, wiring connections, and power supply impedance.
- <3> Rated motor capacity is calculated with a rated output voltage of 575 V.
- <4> Carrier frequency default setting is Swing PWM 1 (C6-02 = 7). C6-02 settings 1, 7, 8, 9, and A do not require current derating. All other settings raise the carrier frequency and require current derating.

A.2 Drive Specifications

- Note:**
1. Perform rotational Auto-Tuning to obtain the performance specifications given below.
 2. For optimum performance life of the drive, install the drive in an environment that meets the required specifications.

| | Item | Specification |
|--------------------------------|---|--|
| Control Characteristics | Control Method | V/f Control (V/f) |
| | Frequency Control Range | 0.01 to 400 Hz |
| | Frequency Accuracy (Temperature Fluctuation) | Digital input: within $\pm 0.01\%$ of the max output frequency (-10 to +40 °C) Analog input: within $\pm 0.1\%$ of the max output frequency (25 °C ± 10 °C) |
| | Frequency Setting Resolution | Digital inputs: 0.01 Hz Analog inputs: 1/2048 of the maximum output frequency setting (11 bit plus sign) Resolution of analog inputs A1 and A3 is 10 bit + sign in current mode |
| | Output Frequency Resolution | 0.001 Hz |
| | Frequency Setting Signal | Main speed frequency reference: DC -10 to +10 V (20 k Ω), DC 0 to +10 V (20 k Ω), 4 to 20 mA (250 Ω), 0 to 20 mA (250 Ω) Main speed reference: Pulse train input (max. 32 kHz) |
| | Starting Torque </> | V/f: 150% at 3 Hz |
| | Speed Control Range </> | V/f: 1:40 |
| | Accel/Decel Time | 0.0 to 6000.0 s (2 selectable combinations of independent acceleration and deceleration settings) |
| | Braking Torque | Approx. 20% (approx. 125% when using braking resistor) </> <ul style="list-style-type: none"> • Short-time decel torque </> : over 100% for 0.4/ 0.75 kW motors, over 50% for 1.5 kW motors, and over 20% for 2.2 kW and above motors </> (overexcitation braking/High Slip Braking: approx. 40%) • Continuous regenerative torque: approx. 20% </> (approx. 125% with dynamic braking resistor option </> : 10% ED, 10s) |
| Braking Transistor | Models 2A0004 to 2A0138, 4A0002 to 4A0072, and 5A0003 to 5A0052 have a built-in braking transistor. | |
| V/f Characteristics | User-selected programs and V/f preset patterns possible | |
| Main Control Functions | Droop Control, Feed Forward Control, Momentary Power Loss Ride-Thru, Speed Search, Overtorque/Undertorque Detection, Torque Limit, 17 Step Speed (max), Accel/decel Switch, S-curve Accel/decel, 3-wire Sequence, Auto-tuning (rotational, stationary tuning), Dwell, Cooling Fan on/off Switch, Slip Compensation, Torque Compensation, Frequency Jump, Upper/lower Limits for Frequency Reference, DC Injection Braking at Start and Stop, Overexcitation Braking, High Slip Braking, PI Control (with sleep function), Energy Saving Control, MEMOBUS/Modbus Comm. (RS-422/RS-485 max, 115.2 kbps), Fault Restart, Application Presets, Removable Terminal Block with Parameter Backup Function, Online Tuning, KEB, Overexcitation Deceleration, Overvoltage Suppression, High Frequency Injection, Dynamic Noise Control | |
| Protection Functions | Motor Protection | Electronic thermal overload relay |
| | Momentary Overcurrent Protection | Drive stops when output current exceeds 170% of rated output current |
| | Overload Protection | Drive stops when rated output current is 120% for 60 s </> |
| | Overvoltage Protection | 200 V class: Stops when DC bus voltage exceeds approx. 410 V 400 V class: Stops when DC bus voltage exceeds approx. 820 V 600 V class: Stops when DC bus voltage exceeds approx. 1040 V |
| | Undervoltage Protection | 200 V class: Stops when DC bus voltage falls below approx. 190 V 400 V class: Stops when DC bus voltage falls below approx. 380 V 600 V class: Stops when DC bus voltage falls below approx. 475 V |

A.2 Drive Specifications

| Item | | Specification |
|----------------------|--------------------------------------|---|
| Protection Functions | Momentary Power Loss Ride-Thru | Immediately stop after 15 ms or longer power loss ^{<6>} . Continuous operation during power loss than 2 s (standard) ^{<7>} |
| | Heatsink Overheat Protection | Thermistor |
| | Braking Resistor Overheat Protection | Overheat input signal for braking resistor (Optional ERF-type, 3% ED) |
| | Stall Prevention | Stall Prevention is available during acceleration, deceleration, and during run. |
| | Ground Protection | Electronic circuit protection ^{<8>} |
| | DC Bus Charge LED | Remains lit until DC bus voltage falls below 50 V |
| Environment | Area of Use | Indoors |
| | Ambient Temperature | -10 to +40 °C (IP20/NEMA Type 1 enclosure), -10 to +50 °C (IP00/Open Type enclosure) |
| | Humidity | 95 RH% or less (no condensation) |
| | Storage Temperature | -20 to +60 °C (short-term temperature during transportation) |
| | Altitude | Up to 1000 meters without derating, up to 3000 m with output current and voltage derating. <i>Refer to Altitude Derating on page 429</i> for details. |
| | Vibration/Shock | 10 to 20 Hz: 9.8 m/s ² ^{<9>} 20 to 55 Hz: 5.9 m/s ² (2A0004 to 2A0211, 4A0002 to 4A0165, and 5A0003 to 5A0099) 2.0 m/s ² (2A0250 to 2A0415, 4A0208 to 4A1200, and 5A0125 to 5A0242) |
| Safety Standard | | UL 508C (Power Conversion), UL/cUL listed, CSA 22.2 No. 14-05 (Industrial Control Equipment), CE marked, RoHS compliant, EN 61800-5-1 (LVD), EN 61800-3 (EMC), IEC60529 |
| Protection Design | | IP00/Open Type enclosure, IP20/NEMA Type 1 enclosure ^{<10>} |

- <1> The accuracy of these values depends on motor characteristics, ambient conditions, and drive settings. Specifications may vary with different motors and with changing motor temperature. Contact Yaskawa for consultation.
- <2> Disable Stall Prevention during deceleration (L3-04 = 0) when using a regenerative converter, a regenerative unit, a braking resistor or the Braking Resistor Unit. The default setting for the Stall Prevention function will interfere with the braking resistor.
- <3> Instantaneous average deceleration torque refers to the torque required to decelerate the motor (uncoupled from the load) from the rated motor speed down to zero in the shortest time.
- <4> Actual specifications may vary depending on motor characteristics.
- <5> Overload protection may be triggered when operating with 150% of the rated output current if the output frequency is less than 6 Hz.
- <6> May be shorter due to load conditions and motor speed.
- <7> A separate Momentary Power Loss Ride-Thru Unit is required for models 2A0004 to 2A0056 and 4A0002 to 4A0031 if the application needs to continue running for up to 2 seconds during a momentary power loss.
- <8> Ground protection cannot be provided when the impedance of the ground fault path is too low, or when the drive is powered up while a ground fault is present at the output.
- <9> Models 4A0930 and 4A1200 are rated at 5.9 m/s².
- <10> Removing the top protective cover or bottom conduit bracket from an IP20/NEMA Type 1 enclosure drive voids NEMA Type 1 protection while maintaining IP20 conformity. This is applicable to models 2A0004 to 2A0211, 4A0002 to 4A0165, and 5A0003 to 5A0242.

A.3 Drive Watt Loss Data

Table A.10 Watt Loss 200 V Class Three-Phase Models

| Drive Model | Normal Duty | | | |
|-------------|-------------------------------------|-------------------|------------------------|----------------|
| | Rated Amps (A) ^{<1>} | Heatsink Loss (W) | Interior Unit Loss (W) | Total Loss (W) |
| 2A0004 | 3.5 | 18.4 | 47 | 66 |
| 2A0006 | 6.0 | 31 | 51 | 82 |
| 2A0008 | 8.0 | 43 | 52 | 95 |
| 2A0010 | 9.6 | 57 | 58 | 115 |
| 2A0012 | 12.0 | 77 | 64 | 141 |
| 2A0018 | 17.5 | 101 | 67 | 168 |
| 2A0021 | 21 | 138 | 83 | 222 |
| 2A0030 | 30 | 262 | 117 | 379 |
| 2A0040 | 40 | 293 | 145 | 437 |
| 2A0056 | 56 | 371 | 175 | 546 |
| 2A0069 | 69 | 491 | 205 | 696 |
| 2A0081 | 81 | 527 | 257 | 785 |
| 2A0110 | 110 | 719 | 286 | 1005 |
| 2A0138 | 138 | 842 | 312 | 1154 |
| 2A0169 | 169 | 1014 | 380 | 1394 |
| 2A0211 | 211 | 1218 | 473 | 1691 |
| 2A0250 | 250 | 1764 | 594 | 2358 |
| 2A0312 | 312 | 2020 | 665 | 2686 |
| 2A0360 | 360 | 2698 | 894 | 3591 |
| 2A0415 | 415 | 2672 | 954 | 3626 |

<1> Value assumes the carrier frequency is 2 kHz (C6-02 = 1, 7, 8, 9, or A).

Table A.11 Watt Loss 400 V Class Three-Phase Models

| Drive Model | Normal Duty | | | |
|-------------|-------------------------------------|-------------------|------------------------|----------------|
| | Rated Amps (A) ^{<1>} | Heatsink Loss (W) | Interior Unit Loss (W) | Total Loss (W) |
| 4A0002 | 2.1 | 20 | 48 | 68 |
| 4A0004 | 4.1 | 32 | 49 | 81 |
| 4A0005 | 5.4 | 45 | 53 | 97 |
| 4A0007 | 6.9 | 62 | 59 | 121 |
| 4A0009 | 8.8 | 66 | 60 | 126 |
| 4A0011 | 11.1 | 89 | 73 | 162 |
| 4A0018 | 17.5 | 177 | 108 | 285 |
| 4A0023 | 23 | 216 | 138 | 354 |
| 4A0031 | 31 | 295 | 161 | 455 |
| 4A0038 | 38 | 340 | 182 | 521 |
| 4A0044 | 44 | 390 | 209 | 599 |
| 4A0058 | 58 | 471 | 215 | 686 |
| 4A0072 | 72 | 605 | 265 | 870 |
| 4A0088 | 88 | 684 | 308 | 993 |
| 4A0103 | 103 | 848 | 357 | 1205 |
| 4A0139 | 139 | 1215 | 534 | 1749 |
| 4A0165 | 165 | 1557 | 668 | 2224 |
| 4A0208 | 208 | 1800 | 607 | 2408 |
| 4A0250 | 250 | 2379 | 803 | 3182 |
| 4A0296 | 296 | 2448 | 905 | 3353 |
| 4A0362 | 362 | 3168 | 1130 | 4298 |

A.3 Drive Watt Loss Data

| Drive Model | Normal Duty | | | |
|-------------|--------------------|-------------------|------------------------|----------------|
| | Rated Amps (A) <1> | Heatsink Loss (W) | Interior Unit Loss (W) | Total Loss (W) |
| 4A0414 | 414 | 3443 | 1295 | 4738 |
| 4A0515 | 515 | 4850 | 1668 | 6518 |
| 4A0675 | 675 | 4861 | 2037 | 6898 |
| 4A0930 | 930 | 8476 | 2952 | 11428 |
| 4A1200 | 1200 | 8572 | 3612 | 12184 |

<1> Value assumes the carrier frequency is 2 kHz (C6-02 = 1, 7, 8, 9, or A).

Table A.12 Watt Loss Three-Phase 600 V Class Three-Phase Models

| Drive Model | Normal Duty | | | |
|-------------|--------------------|-------------------|------------------------|----------------|
| | Rated Amps (A) <1> | Heatsink Loss (W) | Interior Unit Loss (W) | Total Loss (W) |
| 5A0003 | 2.7 | 21.5 | 23.3 | 44.8 |
| 5A0004 | 3.9 | 27.5 | 33.6 | 61.1 |
| 5A0006 | 6.1 | 28.1 | 43.7 | 71.8 |
| 5A0009 | 9.0 | 43.4 | 68.9 | 112.3 |
| 5A0011 | 11 | 56.1 | 88.0 | 144.0 |
| 5A0017 | 17 | 96.6 | 146.7 | 243.2 |
| 5A0022 | 22 | 99.4 | 178.3 | 277.7 |
| 5A0027 | 27 | 132.1 | 227.2 | 359.3 |
| 5A0032 | 32 | 141.6 | 279.9 | 421.5 |
| 5A0041 | 41 | 330.8 | 136.2 | 467.0 |
| 5A0052 | 52 | 427.8 | 166.2 | 594.0 |
| 5A0062 | 62 | 791.2 | 279.0 | 1070.2 |
| 5A0077 | 77 | 959.1 | 329.4 | 1288.6 |
| 5A0099 | 99 | 1253.2 | 411.7 | 1664.9 |
| 5A0125 | 125 | 1641 | 537 | 2178 |
| 5A0145 | 145 | 1860 | 603 | 2463 |
| 5A0192 | 192 | 2420 | 769 | 3189 |
| 5A0242 | 242 | 3100 | 1131 | 4231 |

<1> Value assumes the carrier frequency is 2 kHz (C6-02 = 1, 7, 8, 9, or A).

A.4 Drive Derating Data

The drive can be operated at above the rated temperature, altitude, and default carrier frequency by derating the drive capacity.

◆ Single-Phase Derating

P1000 drives are compatible for use with both three-phase and single-phase input power supplies. The drive output to the motor is always three-phase, regardless of number of input phases.

Output capacity to the motor is derated when using single-phase input power and the drive firmware includes protection for single-phase input applications. This protection is enabled by default. Disabling this protection for single-phase input applications can void warranty and result in premature failure.

Selection of larger models always results in greater output capacity to the motor when supplying the drive with three-phase input power. However, the selection of larger models does not always yield greater output capacity when using the drive with single-phase input power.

Several factors affect the amount of derated drive output capacity when single-phase input power is supplied to the drive, such as:

- single-phase input voltage level
- motor voltage rating
- amount of input impedance.

The tables in this section assist in model selection by considering factors that affect the amount of derating in single-phase input power applications.

■ Single-Phase Input Sizing (Continuous Full Power)

The Output Capacity Motor FLA listed in the tables allows for a 120% overload for 60 seconds. Contact Yaskawa if assistance is needed in selecting drive models for heavy duty/single-phase applications with higher overload requirements.

Note: Adding more impedance than is specified will degrade performance.

Service Factor

When using a service factor greater than 1.15, multiply the nominal power (HP) by the service factor (SF), then select a drive with a higher power rating than the product of that equation.

Example: 1.5 HP x 1.3 SF = 1.95 SF HP

The user should select a 2 HP or larger drive.

Table A.13 240 V Single-Phase Input (-5% to +10%), 230 V Three-Phase Motor

| Drive Model | Without Additional Impedance | | With Additional Impedance (use either DC type or AC type) | | | |
|-------------|------------------------------|----------------------------|--|-----------|---------------------|----------------------------|
| | | | Yaskawa Reactor Part Number | | Motor Power (HP) | Drive Input Current (A) |
| | Motor Power (HP) | Drive Input Current (A) | DC Type | AC Type | | |
| 2A0004 | 1/3 | 4.3 | URX000043 | URX000303 | 1/2 | 4.1 |
| 2A0006 | 3/4 | 7.7 | URX000043 | URX000303 | 3/4 | 5.7 |
| 2A0008 | 1 | 9.5 | 05P00620-0113 | URX000307 | 1 | 7.2 |
| 2A0010 | 1 | 9.5 | 05P00620-0113 | URX000311 | 1 | 7.8 |
| 2A0012 | 1.5 | 13.7 | URX000048 | URX000316 | 2 | 13 |
| 2A0018 | 2 | 19 | 05P00620-0120 | URX000319 | 3 | 19 |
| 2A0021 | 2 | 19 | 05P00620-0120 | URX000323 | 3 | 19 |
| 2A0030 | 3 | 27 | 05P00620-0120 | URX000323 | 3 | 19 |
| 2A0040 | 3 | 27 | 05P00620-0124 | URX000323 | 5 | 30 |
| 2A0056 | 5 | 43 | URX000059 | URX000326 | 7.5 | 42 |
| 2A0069 | 7.5 | 62 | URX000063 | URX000332 | 10 | 56 |
| 2A0081 | 10 | 79 | URX000072 | URX000338 | 15 | 84 |

A.4 Drive Derating Data

| Drive Model | Without Additional Impedance | | With Additional Impedance (use either DC type or AC type) | | | |
|-------------|------------------------------|----------------------------|--|-----------------------|---------------------|----------------------------|
| | | | Yaskawa Reactor Part Number | | Motor Power (HP) | Drive Input Current (A) |
| | Motor Power (HP) | Drive Input Current (A) | DC Type | AC Type | | |
| 2A0110 | 10 | 60 | DC Link Choke Built-in | Do Not Use AC Reactor | 10 | 60 |
| 2A0138 | 15 | 87 | | | 15 | 87 |
| 2A0169 | 20 | 114 | | | 20 | 114 |
| 2A0211 | 25 | 141 | | | 25 | 141 |
| 2A0250 | 30 | 167 | | | 30 | 167 |
| 2A0312 | 40 | 219 | | | 40 | 219 |
| 2A0360 | 50 | 273 | | | 50 | 273 |
| 2A0415 | 60 | 322 | | | 60 | 322 |

Table A.14 480 V Single-Phase Input (-5% to +10%), 460 V Three-Phase Motor

| Drive Model | Without Additional Impedance | | With Additional Impedance (use either DC type or AC type) | | | |
|-------------|------------------------------|----------------------------|--|-----------------------|---------------------|----------------------------|
| | | | Yaskawa Reactor Part Number | | Motor Power (HP) | Drive Input Current (A) |
| | Motor Power (HP) | Drive Input Current (A) | DC Type | AC Type | | |
| 4A0002 | 1/3 | 2.4 | URX000041 | URX000295 | 1/2 | 2.1 |
| 4A0004 | 3/4 | 4.2 | URX000041 | URX000299 | 1 | 3.8 |
| 4A0005 | 1 | 5.1 | 05P00620-0110 | URX000303 | 1.5 | 5.5 |
| 4A0007 | 1.5 | 7.5 | 05P00652-0213 | URX000308 | 2 | 6.7 |
| 4A0009 | 2 | 10 | URX000048 | URX000312 | 3 | 9.5 |
| 4A0011 | 2 | 10 | URX000053 | URX000316 | 3 | 10 |
| 4A0018 | 3 | 13.2 | URX000052 | URX000316 | 3 | 10 |
| 4A0023 | 3 | 14 | URX000052 | URX000316 | 5 | 15 |
| 4A0031 | 7.5 | 30.2 | URX000055 | URX000324 | 7.5 | 22 |
| 4A0038 | 7.5 | 31 | 05P00620-0123 | URX000327 | 10 | 31 |
| 4A0044 | 10 | 38.3 | URX000061 | URX000327 | 10 | 28 |
| 4A0058 | 15 | 42.2 | DC Link Choke Built-in | URX000332 | 15 | 41 |
| 4A0072 | 20 | 55 | | Do Not Use AC Reactor | 20 | 56 |
| 4A0088 | 20 | 56 | | 20 | 56 | |
| 4A0103 | 20 | 57 | | URX000335 | 20 | 54 |
| 4A0139 | 40 | 108 | | URX000341 | 40 | 104 |
| 4A0165 | 40 | 110 | | URX000341 | 40 | 104 |
| 4A0208 | 50 | 136 | | URX000347 | 50 | 130 |
| 4A0250 | 60 | 162 | | URX000347 | 60 | 154 |
| 4A0296 | 60 | 165 | | URX000350 | 75 | 192 |
| 4A0362 | 75 | 205 | | URX000353 | 100 | 251 |
| 4A0414 | 125 | 328 | | URX000356 | 125 | 314 |
| 4A0515 | 125 | 337 | | URX000353 | 125 | 314 |
| 4A0675 | 150 | 405 | | Do Not Use | 150 | 405 |

Table A.15 600 V Single-Phase Input (-5% to +10%), 575 V Three-Phase Motor

| Drive Model | Without Additional Impedance | | With Additional Impedance (use either DC type or AC type) | | | |
|-------------|------------------------------|---------|--|-----------|---------------------|----------------------------|
| | | | Yaskawa Reactor Part Number | | Motor Power (HP) | Drive Input Current (A) |
| | DC Type | AC Type | | | | |
| 5A0003 | 1 | 3.5 | 05P00620-0110 | URX000303 | 1 | 3.5 |
| 5A0004 | 1.5 | 4.8 | URX000044 | URX000306 | 2 | 5 |
| 5A0006 | 2 | 7 | 05P00652-0213 | URX000308 | 3 | 7.6 |
| 5A0009 | 3 | 9.5 | URX000049 | URX000313 | 5 | 11 |
| 5A0011 | 2 | 7.1 | 05P00652-0213 | URX000308 | 3 | 7.7 |
| 5A0017 | 5 | 16 | URX000048 | URX000316 | 5 | 12 |
| 5A0022 | 5 | 16 | URX000053 | URX000320 | 7.5 | 18 |
| 5A0027 | 7.5 | 24 | URX000055 | URX000324 | 10 | 23 |
| 5A0032 | 7.5 | 24 | URX000055 | URX000324 | 10 | 23 |
| 5A0041 | 15 | 34 | DC Link Choke Built-in | URX000326 | 15 | 32 |
| 5A0052 | 15 | 34 | | URX000326 | 15 | 32 |
| 5A0062 | 25 | 57 | | URX000335 | 25 | 54 |
| 5A0077 | 30 | 66 | | URX000338 | 30 | 64 |
| 5A0099 | 30 | 66 | | URX000338 | 30 | 64 |
| 5A0125 | 50 | 106 | | URX000344 | 50 | 102 |
| 5A0145 | 50 | 106 | | URX000344 | 50 | 102 |
| 5A0192 | 75 | 159 | | URX000347 | 75 | 152 |
| 5A0242 | 75 | 159 | | URX000347 | 75 | 152 |

■ Single-Phase Main Circuit Wiring and Tightening Torques

Table A.16 240 V Single-Phase Main Circuit Wiring and Tightening Torques

| Drive Model | Terminal | Recomm. Gauge Without Additional Impedance <1> AWG, kcmil | Recomm. Gauge With Additional Impedance <2> AWG, kcmil | Wire Range AWG, kcmil <3> | Screw Size | Tightening Torque N·m (lb.in.) |
|--|------------------|---|--|------------------------------|---------------|-----------------------------------|
| 2□0004 2□0006 2□0008 2□0010 2□0012 | R/L1, S/L2 | 14 | 14 | 14 to 10 | M4 | 1.2 to 1.5 (10.6 to 13.3) |
| | U/T1, V/T2, W/T3 | 14 | 14 | 14 to 10 | | |
| | ϕ, ϕ1, ϕ2 | - | 14 | 14 to 10 | | |
| | B1, B2 | - | - | 14 to 10 | | |
| | GND | 14 | 14 | 14 to 10 | | |
| 2□0018 2□0021 | R/L1, S/L2 | 10 | 10 | 14 to 10 | M4 | 1.2 to 1.5 (10.6 to 13.3) |
| | U/T1, V/T2, W/T3 | 14 | 14 | 14 to 10 | | |
| | ϕ, ϕ1, ϕ2 | - | 10 | 14 to 10 | | |
| | B1, B2 | - | - | 14 to 10 | | |
| | GND | 10 | 10 | 14 to 10 | | |
| 2□0030 | R/L1, S/L2 | 10 | 10 | 12 to 6 | M4 | 2.1 to 2.3 (18.6 to 20.4) |
| | U/T1, V/T2, W/T3 | 12 | 12 | 12 to 6 | | |
| | ϕ, ϕ1, ϕ2 | - | 10 | 12 to 6 | | |
| | B1, B2 | - | - | 12 to 10 | | |
| | GND | 10 | 10 | 12 to 10 | M5 | 2.0 to 2.5 (17.7 to 22.1) |
| 2□0040 | R/L1, S/L2 | 10 | 8 | 12 to 6 | M4 | 2.1 to 2.3 (18.6 to 20.4) |
| | U/T1, V/T2, W/T3 | 12 | 12 | 12 to 6 | | |
| | ϕ, ϕ1, ϕ2 | - | 8 | 12 to 6 | | |
| | B1, B2 | - | - | 12 to 10 | | |
| | GND | 10 | 8 | 12 to 10 | M5 | 2 to 2.5 (17.7 to 22.1) |

A.4 Drive Derating Data

| Drive Model | Terminal | Recomm. Gauge Without Additional Impedance <1> AWG, kcmil | Recomm. Gauge With Additional Impedance <2> AWG, kcmil | Wire Range AWG, kcmil <3> | Screw Size | Tightening Torque N·m (lb.in.) |
|-------------|------------------|---|--|---------------------------|-----------------------|--------------------------------|
| 2□0056 | R/L1, S/L2 | 4 | 6 | 6 to 4 | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| | U/T1, V/T2, W/T3 | 6 | 6 | 6 to 4 | | |
| | ϕ, ϕ1, ϕ2 | - | 6 | 6 to 4 | | |
| | B1, B2 | - | - | 10 to 8 | M5 | 2 to 2.5 (17.7 to 22.1) |
| | GND | 6 | 6 | 8 to 6 | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| 2□0069 | R/L1, S/L2 | 4 | 4 | 10 to 2 | M8 | 9.9 to 11.0 (87.6 to 97.4) |
| | U/T1, V/T2, W/T3 | 10 | 10 | 10 to 2 | | |
| | ϕ, ϕ1, ϕ2 | - | 4 | 10 to 2 | | |
| | B1, B2 | - | - | 10 to 6 | M5 | 2 to 2.5 (17.7 to 22.1) |
| | GND | 6 | 6 | 6 to 4 | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| 2□0081 | R/L1, S/L2 | 3 | 3 | 10 to 2 | M8 | 9.9 to 11.0 (87.6 to 97.4) |
| | U/T1, V/T2, W/T3 | 10 | 8 | 10 to 2 | | |
| | ϕ, ϕ1, ϕ2 | - | 3 | 10 to 2 | | |
| | B1, B2 | - | - | 10 to 6 | M5 | 2 to 2.5 (17.7 to 22.1) |
| | GND | 6 | 6 | 6 to 4 | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| 2□0110 | R/L1, S/L2 | 4 | 4 | 10 to 1/0 | M8 | 9.9 to 11.0 (79.7 to 97.4) |
| | U/T1, V/T2, W/T3 | 10 | 10 | 10 to 1/0 | | |
| | ϕ, ϕ1 | - | - | 10 to 1/0 | | |
| | B1, B2 | - | - | 10 to 1/0 | | |
| | GND | 6 | 6 | 10 to 1/0 | | |
| 2□0138 | R/L1, S/L2 | 2 | 2 | 10 to 3/0 | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 8 | 8 | 10 to 3/0 | | |
| | ϕ, ϕ1 | - | - | 10 to 3/0 | | |
| | B1, B2 | - | - | 10 to 3/0 | | |
| | GND | 6 | 6 | 10 to 1/0 | M8 | 9 to 11 (79.7 to 97.4) |
| 2□0169 | R/L1, S/L2 | 1/0 | 6 | 10 to 4/0 | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 1/0 | 6 | 10 to 4/0 | | |
| | ϕ, ϕ1 | - | - | 10 to 4/0 | | |
| | ϕ3 | - | - | 10 to 4/0 | | |
| | GND | 3 | 3 | 10 to 4/0 | | |
| 2□0211 | R/L1, S/L2 | 2/0 | 2/0 | 10 to 4/0 | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 1/0 | 1/0 | 10 to 4/0 | | |
| | ϕ, ϕ1 | - | - | 10 to 4/0 | | |
| | ϕ3 | - | - | 10 to 4/0 | | |
| | GND | 2 | 2 | 10 to 4/0 | | |
| 2□0250 | R/L1, S/L2 | 3/0 | 4/0 | up to 250 kcmil | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 3 | 3 | up to 250 kcmil | | |
| | ϕ, ϕ1 | - | - | up to 250 kcmil | | |
| | ϕ3 | - | - | up to 250 kcmil | M10 | 18 to 23 (159 to 204) |
| | GND | 1 | 1/0 | up to 250 kcmil | M12 | 32 to 40 (283 to 354) |
| 2□0312 | R/L1, S/L2 | 1/0 X 2P | 1/0 X 2P | up to 250 kcmil | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 1 | 1 | up to 250 kcmil | | |
| | ϕ, ϕ1 | - | - | up to 250 kcmil | M10 | 18 to 23 (159 to 204) |
| | ϕ3 | - | - | up to 250 kcmil | | |
| GND | 3/0 | 3/0 | up to 250 kcmil | M12 | 32 to 40 (283 to 354) | |

| Drive Model | Terminal | Recomm. Gauge Without Additional Impedance <1> AWG, kcmil | Recomm. Gauge With Additional Impedance <2> AWG, kcmil | Wire Range AWG, kcmil <3> | Screw Size | Tightening Torque N·m (lb.in.) |
|-------------|------------------|--|---|---------------------------|------------|--------------------------------|
| 2□0360 | R/L1, S/L2 | 2/0 X 2P | 2/0 X 2P | up to 250 kcmil | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 2/0 | 2/0 | up to 250 kcmil | | |
| | ⊖, ⊕1 | - | - | up to 250 kcmil | | |
| | ⊕3 | - | - | up to 250 kcmil | M10 | 18 to 23 (159 to 204) |
| | GND | 1 X 2P | 1 X 2P | up to 250 kcmil | M12 | 32 to 40 (283 to 354) |
| 2□0415 | R/L1, S/L2 | 3/0 X 2P | 3/0 X 2P | up to 250 kcmil | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 3/0 | 3/0 | up to 250 kcmil | | |
| | ⊖, ⊕1 | - | - | up to 250 kcmil | | |
| | ⊕3 | - | - | up to 250 kcmil | M10 | 18 to 23 (159 to 204) |
| | GND | 1/0 X 2P | 1/0 X 2P | up to 250 kcmil | M12 | 32 to 40 (283 to 354) |

- <1> Refer to local codes while selecting wire size for terminals ⊖, ⊕1, ⊕2 if these terminals need to be used for other optional power devices.
- <2> The wire size recommended for terminal ⊖, ⊕1, ⊕2 is for DC type additional impedance only. See the additional impedance type recommended in [Table A.13](#) before choosing wire size for terminals ⊖, ⊕1, ⊕2.
- <3> Terminal wire range is the range of wire sizes the terminals can accept. This information is intended to keep within the wire range of the terminals while selecting a wire size for the terminals per local codes for the intended application of these terminals.

Table A.17 480 V Single-Phase Main Circuit Wiring and Tightening Torques

| Drive Model | Terminal | Recomm. Gauge Without Additional Impedance <1> AWG, kcmil | Recomm. Gauge With Additional Impedance <2> AWG, kcmil | Wire Range AWG, kcmil <3> | Screw Size | Tightening Torque N·m (lb.in.) |
|--|------------------|--|---|---------------------------|------------|--------------------------------|
| 4□0002 4□0004 4□0005 4□0007 4□0009 4□0011 | R/L1, S/L2 | 14 | 14 | 14 to 10 | M4 | 1.2 to 1.5 (10.6 to 13.3) |
| | U/T1, V/T2, W/T3 | 14 | 14 | 14 to 10 | | |
| | ⊖, ⊕1, ⊕2 | - | 14 | 14 to 10 | | |
| | B1, B2 | - | - | 14 to 10 | | |
| | GND | 14 | 14 | 14 to 10 | | |
| | 4□0018 | R/L1, S/L2 | 12 | 12 | 12 to 6 | M4 |
| U/T1, V/T2, W/T3 | | 12 | 12 | 12 to 6 | | |
| ⊖, ⊕1, ⊕2 | | - | 12 | 12 to 6 | | |
| B1, B2 | | - | - | 12 to 10 | | |
| GND | | 12 | 12 | 12 to 10 | M5 | 2.0 to 2.5 (17.7 to 221.1) |
| 4□0023 | R/L1, S/L2 | 12 | 12 | 12 to 6 | M4 | 2.1 to 2.3 (18.6 to 20.4) |
| | U/T1, V/T2, W/T3 | 12 | 12 | 12 to 6 | | |
| | ⊖, ⊕1, ⊕2 | - | 12 | 12 to 6 | | |
| | B1, B2 | - | - | 12 to 10 | | |
| | GND | 12 | 12 | 12 to 10 | M5 | 2.0 to 2.5 (17.7 to 221.1) |
| 4□0031 | R/L1, S/L2 | 8 | 10 | 10 to 6 | M5 | 3.6 to 4.0 (31.8 to 35.4) |
| | U/T1, V/T2, W/T3 | 10 | 10 | 10 to 6 | | |
| | ⊖, ⊕1, ⊕2 | - | 10 | 10 to 6 | | |
| | B1, B2 | - | - | 10 to 6 | | |
| | GND | 8 | 10 | 10 to 8 | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| 4□0038 | R/L1, S/L2 | 8 | 8 | 10 to 6 | M5 | 3.6 to 4.0 (31.8 to 35.4) |
| | U/T1, V/T2, W/T3 | 10 | 10 | 10 to 6 | | |
| | ⊖, ⊕1, ⊕2 | - | 10 | 10 to 6 | | |
| | B1, B2 | - | - | 10 to 6 | | |
| | GND | 8 | 8 | 10 to 6 | M6 | 5.4 to 6.0 (47.8 to 53.1) |

A.4 Drive Derating Data

| Drive Model | Terminal | Recomm. Gauge Without Additional Impedance <1> AWG, kcmil | Recomm. Gauge With Additional Impedance <2> AWG, kcmil | Wire Range AWG, kcmil <3> | Screw Size | Tightening Torque N·m (lb.in.) |
|-------------|------------------|---|--|---------------------------|------------|--------------------------------|
| 4□0044 | R/L1, S/L2 | 6 | 6 | 6 to 4 | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| | U/T1, V/T2, W/T3 | 6 | 6 | 6 to 4 | | |
| | ⊖, ⊕1, ⊕2 | - | 6 | 6 to 4 | | |
| | B1, B2 | - | - | 10 to 8 | M5 | 2.7 to 3.0 (23.9 to 26.6) |
| | GND | 6 | 6 | 8 to 6 | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| 4□0058 | R/L1, S/L2 | 8 | 8 | 10 to 1/0 | M8 | 9 to 11 (79.7 to 97.4) |
| | U/T1, V/T2, W/T3 | 10 | 10 | 10 to 1/0 | | |
| | ⊖, ⊕1, ⊕2 | - | - | 10 to 1/0 | | |
| | B1, B2 | - | - | 10 to 1/0 | | |
| | GND | 8 | 8 | 10 to 1/0 | | |
| 4□0072 | R/L1, S/L2 | 4 | 4 | 10 to 1/0 | M8 | 9 to 11 (79.7 to 97.4) |
| | U/T1, V/T2, W/T3 | 10 | 10 | 10 to 1/0 | | |
| | ⊖, ⊕1, ⊕2 | - | - | 10 to 1/0 | | |
| | B1, B2 | - | - | 10 to 1/0 | | |
| | GND | 6 | 6 | 10 to 1/0 | | |
| 4□0088 | R/L1, S/L2 | 4 | 4 | 6 to 250 kcmil | M8 | 9 to 11 (79.7 to 97.4) |
| | U/T1, V/T2, W/T3 | 6 | 6 | 6 to 250 kcmil | | |
| | ⊖, ⊕1 | - | - | 6 to 250 kcmil | | |
| | ⊕3 | - | - | 6 to 250 kcmil | | |
| | GND | 6 | 6 | 6 to 250 kcmil | | |
| 4□0103 | R/L1, S/L2 | 4 | 6 | 6 to 250 kcmil | M8 | 9 to 11 (79.7 to 97.4) |
| | U/T1, V/T2, W/T3 | 6 | 6 | 6 to 250 kcmil | | |
| | ⊖, ⊕1 | - | - | 6 to 250 kcmil | | |
| | ⊕3 | - | - | 6 to 250 kcmil | | |
| | GND | 6 | 6 | 6 to 250 kcmil | | |
| 4□0139 | R/L1, S/L2 | 1 | 1 | 10 to 4/0 | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 6 | 6 | 10 to 4/0 | | |
| | ⊖, ⊕1 | - | - | 10 to 4/0 | | |
| | ⊕3 | - | - | 10 to 4/0 | | |
| | GND | 4 | 4 | 10 to 4/0 | | |
| 4□0165 | R/L1, S/L2 | 1/0 | 1 | 10 to 4/0 | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 6 | 6 | 10 to 4/0 | | |
| | ⊖, ⊕1 | - | - | 10 to 4/0 | | |
| | ⊕3 | - | - | 10 to 4/0 | | |
| | GND | 3 | 4 | 10 to 4/0 | | |
| 4□0208 | R/L1, S/L2 | 2/0 | 2/0 | up to 250 kcmil | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 4 | 4 | up to 250 kcmil | | |
| | ⊖, ⊕1 | - | - | up to 250 kcmil | | |
| | ⊕3 | - | - | up to 250 kcmil | | |
| | GND | 2 | 2 | up to 250 kcmil | | |
| 4□0250 | R/L1, S/L2 | 3/0 | 3/0 | up to 250 kcmil | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 3 | 3 | up to 250 kcmil | | |
| | ⊖, ⊕1 | - | - | up to 250 kcmil | | |
| | ⊕3 | - | - | up to 250 kcmil | | |
| | GND | 1 | 1 | up to 250 kcmil | | |

| Drive Model | Terminal | Recomm. Gauge Without Additional Impedance <1> AWG, kcmil | Recomm. Gauge With Additional Impedance <2> AWG, kcmil | Wire Range AWG, kcmil <3> | Screw Size | Tightening Torque N·m (lb.in.) |
|-------------|------------------|---|--|---------------------------|------------|--------------------------------|
| 4□0296 | R/L1, S/L2 | 3/0 | 1 X 2P | up to 250 kcmil | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 3 | 2 | up to 250 kcmil | | |
| | ⊖, ⊕1 | - | - | up to 250 kcmil | | |
| | ⊕3 | - | - | up to 250 kcmil | M10 | |
| | GND | 1 | 2/0 | up to 250 kcmil | M12 | |
| 4□0362 | R/L1, S/L2 | 1 X 2P | 2/0 X 2P | up to 250 kcmil | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 1 | 1/0 | up to 250 kcmil | | |
| | ⊖, ⊕1 | - | - | up to 250 kcmil | | |
| | ⊕3 | - | - | up to 250 kcmil | M10 | |
| | GND | 2/0 | 3/0 | up to 250 kcmil | M12 | |
| 4□0414 | R/L1, S/L2 | 3/0 X 2P | 3/0 X 2P | up to 250 kcmil | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 3/0 | 3/0 | up to 250 kcmil | | |
| | ⊖, ⊕1 | - | - | up to 250 kcmil | | |
| | ⊕3 | - | - | up to 250 kcmil | | |
| | GND | 1/0 X 2P | 1/0 X 2P | up to 250 kcmil | | |
| 4□0515 | R/L1, S/L2 | 4/0 X 2P | 3/0 X 2P | up to 250 kcmil | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 3/0 | 3/0 | up to 250 kcmil | | |
| | ⊖, ⊕1 | - | - | up to 250 kcmil | | |
| | ⊕3 | - | - | up to 250 kcmil | | |
| | GND | 1/0 X 2P | 1/0 X 2P | up to 250 kcmil | | |
| 4□0675 | R/L1, S/L2 | 1 X 4P | 1 X 4P | up to 250 kcmil | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 4/0 | 4/0 | up to 250 kcmil | | |
| | ⊖, ⊕1 | - | - | up to 250 kcmil | | |
| | ⊕3 | - | - | up to 250 kcmil | | |
| | GND | 3/0 X 2P | 3/0 X 2P | up to 250 kcmil | | |

- <1> Refer to local codes while selecting wire size for terminals ⊖, ⊕1, ⊕2 if these terminals need to be used for other optional power devices.
- <2> The wire size recommended for terminal ⊖, ⊕1, ⊕2 is for DC type additional impedance only. See the additional impedance type recommended in [Table A.14](#) before choosing wire size for terminals ⊖, ⊕1, ⊕2.
- <3> Terminal wire range is the range of wire sizes the terminals can accept. This information is intended to keep within the wire range of the terminals while selecting a wire size for the terminals per local codes for the intended application of these terminals.

Table A.18 600 V Single-Phase Main Circuit Wiring and Tightening Torques

| Drive Model | Terminal | Recomm. Gauge Without Additional Impedance <1> AWG, kcmil | Recomm. Gauge With Additional Impedance <2> AWG, kcmil | Wire Range AWG, kcmil <3> | Screw Size | Tightening Torque N·m (lb.in.) |
|--------------------------------------|------------------|---|--|---------------------------|------------|--------------------------------|
| 5□0003 5□0004 5□0006 5□0009 | R/L1, S/L2 | 14 | 14 | 14 to 10 | M4 | 1.2 to 1.5 (10.6 to 13.3) |
| | U/T1, V/T2, W/T3 | 14 | 14 | 14 to 10 | | |
| | ⊖, ⊕1, ⊕2 | - | 14 | 14 to 10 | | |
| | B1, B2 | - | - | 14 to 10 | | |
| | GND | 14 | 14 | 14 to 10 | | |
| 5□0011 | R/L1, S/L2 | 12 | 12 | 12 to 6 | M4 | 2.1 to 2.3 (18.6 to 20.4) |
| | U/T1, V/T2, W/T3 | 12 | 12 | 12 to 6 | | |
| | ⊖, ⊕1, ⊕2 | - | 12 | 12 to 6 | | |
| | B1, B2 | - | - | 12 to 10 | | |
| | GND | 12 | 12 | 12 to 10 | M5 | 2.0 to 2.5 (17.7 to 22.1) |

A.4 Drive Derating Data

| Drive Model | Terminal | Recomm. Gauge Without Additional Impedance <1> AWG, kcmil | Recomm. Gauge With Additional Impedance <2> AWG, kcmil | Wire Range AWG, kcmil <3> | Screw Size | Tightening Torque N·m (lb.in.) | |
|------------------|------------------|---|--|---------------------------|------------|--------------------------------|---------------------------|
| 5□0017 | R/L1, S/L2 | 10 | 10 | 10 to 6 | M5 | 3.6 to 4.0 (31.8 to 35.4) | |
| | U/T1, V/T2, W/T3 | 10 | 10 | 10 to 6 | | | |
| | ⊖, ⊕1, ⊕2 | - | 10 | 10 to 6 | | | |
| | B1, B2 | - | - | 10 to 6 | | | |
| | GND | 10 | 10 | 10 to 8 | M6 | | 5.4 to 6.0 (47.8 to 53.1) |
| 5□0022 | R/L1, S/L2 | 10 | 10 | 10 to 6 | M5 | 3.6 to 4.0 (31.8 to 35.4) | |
| | U/T1, V/T2, W/T3 | 10 | 10 | 10 to 6 | | | |
| | ⊖, ⊕1, ⊕2 | - | 10 | 10 to 6 | | | |
| | B1, B2 | - | - | 10 to 6 | | | |
| | GND | 10 | 10 | 10 to 8 | M6 | | 5.4 to 6.0 (47.8 to 53.1) |
| 5□0027 5□0032 | R/L1, S/L2 | 6 | 6 | 6 to 4 | M6 | 5.4 to 6.0 (47.8 to 53.1) | |
| | U/T1, V/T2, W/T3 | 6 | 6 | 6 to 4 | | | |
| | ⊖, ⊕1, ⊕2 | - | 6 | 6 to 4 | M5 | | 2.7 to 3.0 (23.9 to 26.6) |
| | B1, B2 | - | - | 10 to 8 | | | |
| | GND | 6 | 6 | 8 to 6 | M6 | | 5.4 to 6.0 (47.8 to 53.1) |
| 5□0041 5□0052 | R/L1, S/L2 | 8 | 8 | 10 to 1/0 | M8 | 9 to 11 (79.7 to 97.4) | |
| | U/T1, V/T2, W/T3 | 10 | 10 | 10 to 1/0 | | | |
| | ⊖, ⊕1, ⊕2 | - | - | 10 to 1/0 | | | |
| | B1, B2 | - | - | 10 to 1/0 | | | |
| | GND | 8 | 8 | 10 to 1/0 | | | |
| 5□0062 | R/L1, S/L2 | 6 | 6 | 10 to 4/0 | M10 | 18 to 23 (159 to 204) | |
| | U/T1, V/T2, W/T3 | 10 | 10 | 10 to 4/0 | | | |
| | ⊖, ⊕1 | - | - | 10 to 4/0 | | | |
| | ⊕3 | - | - | 10 to 4/0 | | | |
| | GND | 6 | 6 | 10 to 4/0 | | | |
| 5□0077 5□0099 | R/L1, S/L2 | 4 | 4 | 10 to 4/0 | M10 | 18 to 23 (159 to 204) | |
| | U/T1, V/T2, W/T3 | 8 | 8 | 10 to 4/0 | | | |
| | ⊖, ⊕1 | - | - | 10 to 4/0 | | | |
| | ⊕3 | - | - | 10 to 4/0 | | | |
| | GND | 4 | 4 | 10 to 4/0 | | | |
| 5□0125 | R/L1, S/L2 | 1 | 1 | up to 250 kcmil | M10 | 18 to 23 (159 to 204) | |
| | U/T1, V/T2, W/T3 | 6 | 6 | up to 250 kcmil | | | |
| | ⊖, ⊕1 | - | - | up to 250 kcmil | | | |
| | ⊕3 | - | - | up to 250 kcmil | | | |
| | GND | 1 | 1 | up to 250 kcmil | | | |
| 5□0145 | R/L1, S/L2 | 1 | 1 | up to 250 kcmil | M10 | 18 to 23 (159 to 204) | |
| | U/T1, V/T2, W/T3 | 6 | 6 | up to 250 kcmil | | | |
| | ⊖, ⊕1 | - | - | up to 250 kcmil | | | |
| | ⊕3 | - | - | up to 250 kcmil | | | |
| | GND | 1 | 1 | up to 250 kcmil | | | |
| 5□0192 | R/L1, S/L2 | 3/0 | 3/0 | up to 250 kcmil | M12 | 32 to 40 (283 to 354) | |
| | U/T1, V/T2, W/T3 | 3 | 3 | up to 250 kcmil | | | |
| | ⊖, ⊕1 | - | - | up to 250 kcmil | M10 | | |
| | ⊕3 | - | - | up to 250 kcmil | | | |
| | GND | 1 | 1 | up to 250 kcmil | | | |

| Drive Model | Terminal | Recomm. Gauge Without Additional Impedance <1> AWG, kcmil | Recomm. Gauge With Additional Impedance <2> AWG, kcmil | Wire Range AWG, kcmil <3> | Screw Size | Tightening Torque N·m (lb.in.) |
|-------------|------------------|---|--|---------------------------|------------|--------------------------------|
| 5□0242 | R/L1, S/L2 | 3/0 | 3/0 | up to 250 kcmil | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 3 | 3 | up to 250 kcmil | | |
| | ⊖, ⊕1 | - | - | up to 250 kcmil | | |
| | ⊕3 | - | - | up to 250 kcmil | M10 | 18 to 23 (159 to 204) |
| | GND | 1 | 1 | up to 250 kcmil | M12 | 32 to 40 (283 to 354) |

- <1> Refer to local codes while selecting wire size for terminals ⊖, ⊕1, ⊕2 if these terminals need to be used for other optional power devices.
- <2> The wire size recommended for terminal ⊖, ⊕1, ⊕2 is for DC type additional impedance only. See the additional impedance type recommended in [Table A.15](#) before choosing wire size for terminals ⊖, ⊕1, ⊕2.
- <3> Terminal wire range is the range of wire sizes the terminals can accept. This information is intended to keep within the wire range of the terminals while selecting a wire size for the terminals per local codes for the intended application of these terminals.

■ Single-Phase Closed-Loop Crimp Terminal Sizes

Table A.19 Panduit Closed-Loop Crimp Terminal Size Single-Phase w/o Additional Impedance

| Drive Model | Terminal | Recomm. Gauge Without Additional Impedance AWG, kcmil | Screw Size | Panduit Ring Terminal (non-insulated) | Panduit Recomm. Installation Tool | Panduit Crimphead / Die Part No. | Insulation Cap Model No. |
|--|------------------|---|------------|---------------------------------------|-----------------------------------|----------------------------------|--------------------------|
| 2□0004 2□0006 2□0008 2□0010 2□0012 | R/L1, S/L2 | 14 | M4 | P14-8R | CT-1570 | - | TP-003 |
| | U/T1, V/T2, W/T3 | 14 | | | | | |
| 2□0018 2□0021 | R/L1, S/L2 | 10 | M4 | P10-8R | CT-1570 | - | TP-005 |
| | U/T1, V/T2, W/T3 | 14 | | P14-8R | | | TP-003 |
| 2□0030 | R/L1, S/L2 | 10 | M4 | P10-8R | CT-1570 | - | TP-005 |
| | U/T1, V/T2, W/T3 | 12 | | | | | |
| 2□0040 | R/L1, S/L2 | 10 | M4 | P10-8R | CT-1570 | - | TP-005 |
| | U/T1, V/T2, W/T3 | 12 | | | | | |
| 2□0056 | R/L1, S/L2 | 4 | M6 | P4-14R | CT-1701 | - | TP-022 |
| | U/T1, V/T2, W/T3 | 6 | | P6-14R | | | TP-014 |
| 2□0069 | R/L1, S/L2 | 4 | M8 | P4-56R | CT-1701 | - | TP-022 |
| | U/T1, V/T2, W/T3 | 10 | | P10-56R | | | TP-005 |
| 2□0081 | R/L1, S/L2 | 3 | M8 | P2-56R | CT-1701 | - | TP-038 |
| | U/T1, V/T2, W/T3 | 10 | | P10-56R | | | TP-005 |
| 2□0110 | R/L1, S/L2 | 4 | M8 | P4-56R | CT-1701 | - | TP-022 |
| | U/T1, V/T2, W/T3 | 10 | | P10-56R | | | TP-005 |
| 2□0138 | R/L1, S/L2 | 2 | M10 | P2-38R | CT-1701 | - | TP-038 |
| | U/T1, V/T2, W/T3 | 8 | | P8-38R | | | TP-008 |
| 2□0169 | R/L1, S/L2 | 1/0 | M10 | S1/0-38R-X | CT-720 | CD-720-2 | TP-060 |
| | U/T1, V/T2, W/T3 | 6 | | S6-38R-E | | CD-720-1 | TP-014 |
| 2□0211 | R/L1, S/L2 | 2/0 | M10 | S2/0-38R | CT-720 | CD-720-2 | TP-060 |
| | U/T1, V/T2, W/T3 | 1/0 | | S1/0-38R | | | TP-038 |
| 2□0250 | R/L1, S/L2 | 3/0 | M12 | S3/0-12R-5 | CT-720 | CD-720-2 | TP-080 |
| | U/T1, V/T2, W/T3 | 3 | | S2-12R-X | | | TP-038 |
| 2□0312 | R/L1, S/L2 | 1/0 X 2P | M12 | S1/0-12R-X (Qty. 2) | CT-720 | CD-720-2 | TP-038 (Qty. 2) |
| | U/T1, V/T2, W/T3 | 1 | | S2-12R-X | | | TP-060 |
| 2□0360 | R/L1, S/L2 | 2/0 X 2P | M12 | S2/0-12R-X (Qty. 2) | CT-720 | CD-720-2 | TP-080 (Qty. 2) |
| | U/T1, V/T2, W/T3 | 2/0 | | S2/0-12R-X | | | TP-080 |

A.4 Drive Derating Data

| Drive Model | Terminal | Recomm. Gauge Without Additional Impedance AWG, kcmil | Screw Size | Panduit Ring Terminal (non-insulated) | Panduit Recomm. Installation Tool | Panduit Crimphead / Die Part No. | Insulation Cap Model No. |
|-------------|------------------|---|------------|---------------------------------------|-----------------------------------|----------------------------------|--------------------------|
| 2□0415 | R/L1, S/L2 | 3/0 X 2P | M12 | S3/0-12R-5 (Qty. 2) | CT-720 | CD-720-2 | TP-080 (Qty. 2) |
| | U/T1, V/T2, W/T3 | 3/0 | | S3/0-12R-5 | | | TP-080 |

Table A.20 JST Closed-Loop Crimp Terminal Size Single-Phase w/o Additional Impedance

| Drive Model | Terminal | Recomm. Gauge Without Additional Impedance AWG, kcmil | Screw Size | JST Ring Terminal (non-insulated) | JST Recomm. Installation Tool | JST Crimphead / Die Part No. | Insulation Cap Model No. |
|--|------------------|---|------------|-----------------------------------|-------------------------------|------------------------------|--------------------------|
| 2□0004 2□0006 2□0008 2□0010 2□0012 | R/L1, S/L2 | 14 | M4 | R2-4 | YA-4 | AD-900 | TP-003 |
| | U/T1, V/T2, W/T3 | 14 | | | | | |
| 2□0018 2□0021 | R/L1, S/L2 | 10 | M4 | R5.5-4 | YA-4 | AD-900 | TP-005 |
| | U/T1, V/T2, W/T3 | 14 | | R2-4 | | | TP-003 |
| 2□0030 | R/L1, S/L2 | 10 | M4 | R5.5-4 | YA-4 | AD-900 | TP-005 |
| | U/T1, V/T2, W/T3 | 12 | | | | | |
| 2□0040 | R/L1, S/L2 | 10 | M4 | R5.5-4 | YA-4 | AD-900 | TP-005 |
| | U/T1, V/T2, W/T3 | 12 | | | | | |
| 2□0056 | R/L1, S/L2 | 4 | M6 | R22-6 | YA-5 | AD-953 | TP-022 |
| | U/T1, V/T2, W/T3 | 6 | | R14-6 | | AD-952 | TP-014 |
| 2□0069 | R/L1, S/L2 | 4 | M8 | R22-8 | YA-5 | AD-953 | TP-022 |
| | U/T1, V/T2, W/T3 | 10 | | R5.5-8 | | YA-4 | AD-900 |
| 2□0081 | R/L1, S/L2 | 3 | M8 | R38-8 | YA-5 | AD-954 | TP-038 |
| | U/T1, V/T2, W/T3 | 10 | | R5.5-8 | | YA-4 | AD-900 |
| 2□0110 | R/L1, S/L2 | 4 | M8 | R22-8 | YA-5 | AD-953 | TP-022 |
| | U/T1, V/T2, W/T3 | 10 | | R5.5-8 | | YA-4 | AD-900 |
| 2□0138 | R/L1, S/L2 | 2 | M10 | R38-10 | YA-5 | AD-954 | TP-038 |
| | U/T1, V/T2, W/T3 | 8 | | R8-10 | | AD-951 | TP-008 |
| 2□0169 | R/L1, S/L2 | 1/0 | M10 | R60-10 | YA-5 | AD-955 | TP-060 |
| | U/T1, V/T2, W/T3 | 6 | | R14-10 | | AD-952 | TP-014 |
| 2□0211 | R/L1, S/L2 | 2/0 | M10 | 70-10 | YF-1 YET-300-1 | TD-323, TD-312 | TP-080 |
| | U/T1, V/T2, W/T3 | 1/0 | | R60-10 | YA-5 | AD-955 | TP-060 |
| 2□0250 | R/L1, S/L2 | 3/0 | M12 | 80-L12 | YF-1 YET-300-1 | TD-323, TD-312 | TP-080 |
| | U/T1, V/T2, W/T3 | 3 | | R38-12 | YA-5 | AD-954 | TP-038 |
| 2□0312 | R/L1, S/L2 | 1/0 X 2P | M12 | R60-14 (Qty. 2) | YA-5 | AD-955 | TP-060 (Qty. 2) |
| | U/T1, V/T2, W/T3 | 1 | | R38-14 | | AD-954 | TP-038 |
| 2□0360 | R/L1, S/L2 | 2/0 X 2P | M12 | 70-14 (Qty. 2) | YF-1 YET-300-1 | TD-323, TD-312 | TP-080 (Qty. 2) |
| | U/T1, V/T2, W/T3 | 2/0 | | 70-14 | | TP-080 | |
| 2□0415 | R/L1, S/L2 | 3/0 X 2P | M12 | 80-L12 (Qty. 2) | YF-1 YET-300-1 | TD-323 TD-312 | TP-080 (Qty. 2) |
| | U/T1, V/T2, W/T3 | 3/0 | | 80-L12 | | TP-080 | |

Table A.21 Panduit Closed-Loop Crimp Terminal Size Single-Phase w/o Additional Impedance

| Drive Model | Terminal | Recomm. Gauge Without Additional Impedance AWG, kcmil | Screw Size | Panduit Ring Terminal (non-insulated) | Panduit Recomm. Installation Tool | Panduit Crimphead / Die Part No. | Insulation Cap Model No. |
|--|------------------|---|------------|---------------------------------------|-----------------------------------|----------------------------------|--------------------------|
| 4□0002 4□0004 4□0005 4□0007 4□0009 4□0011 | R/L1, S/L2 | 14 | M4 | P14-8R | CT-1570 | - | TP-003 |
| | U/T1, V/T2, W/T3 | 14 | | | | | |
| 4□0018 | R/L1, S/L2 | 12 | M4 | P10-8R | CT-1570 | - | TP-005 |
| | U/T1, V/T2, W/T3 | 12 | | | | | |
| 4□0023 | R/L1, S/L2 | 12 | M4 | P10-8R | CT-1570 | - | TP-005 |
| | U/T1, V/T2, W/T3 | 12 | | | | | |
| 4□0031 | R/L1, S/L2 | 8 | M5 | P8-10R | CT-1701 | - | TP-008 |
| | U/T1, V/T2, W/T3 | 10 | | P10-10R | | | TP-005 |
| 4□0038 | R/L1, S/L2 | 8 | M5 | P8-10R | CT-1701 | - | TP-008 |
| | U/T1, V/T2, W/T3 | 10 | | P10-10R | | | TP-005 |
| 4□0044 | R/L1, S/L2 | 6 | M6 | P6-14R | CT-1701 | - | TP-014 |
| | U/T1, V/T2, W/T3 | 6 | | | | | |
| 4□0058 | R/L1, S/L2 | 8 | M8 | P8-56R | CT-1701 | - | TP-008 |
| | U/T1, V/T2, W/T3 | 10 | | P10-56R | | | TP-005 |
| 4□0072 | R/L1, S/L2 | 4 | M8 | P4-56R | CT-1701 | - | TP-022 |
| | U/T1, V/T2, W/T3 | 10 | | P10-56R | | | TP-005 |
| 4□0088 | R/L1, S/L2 | 4 | M8 | P4-56R | CT-1701 | - | TP-022 |
| | U/T1, V/T2, W/T3 | 6 | | P6-56R | | | TP-014 |
| 4□0103 | R/L1, S/L2 | 4 | M8 | P4-56R | CT-1701 | - | TP-022 |
| | U/T1, V/T2, W/T3 | 6 | | P6-56R | | | TP-014 |
| 4□0139 | R/L1, S/L2 | 1 | M10 | S2-38R | CT-720 | CD-720-2 | TP-060 |
| | U/T1, V/T2, W/T3 | 6 | | S6-38R | | CD-720-1 | TP-014 |
| 4□0165 | R/L1, S/L2 | 1/0 | M10 | S1/0-38R | CT-720 | CD-720-2 | TP-060 |
| | U/T1, V/T2, W/T3 | 6 | | S6-38R | | CD-720-1 | TP-014 |
| 4□0208 | R/L1, S/L2 | 2/0 | M10 | S2/0-38R | CT-720 | CD-720-2 | TP-080 |
| | U/T1, V/T2, W/T3 | 4 | | S4-38R | | CD-720-1 | TP-022 |
| 4□0250 | R/L1, S/L2 | 3/0 | M10 | S3/0-38R | CT-720 | CD-720-2 | TP-080 |
| | U/T1, V/T2, W/T3 | 3 | | S2-38R-X | | | TP-038 |
| 4□0296 | R/L1, S/L2 | 3/0 | M12 | S3/0-12R-5 | CT-720 | CD-720-2 | TP-080 |
| | U/T1, V/T2, W/T3 | 3 | | S2-12R-X | | | TP-038 |
| 4□0362 | R/L1, S/L2 | 1 X 2P | M12 | S2-12R-X (Qty. 2) | CT-720 | CD-720-2 | TP-038 (Qty. 2) |
| | U/T1, V/T2, W/T3 | 1 | | S2-12R-X | | | TP-038 |
| 4□0414 | R/L1, S/L2 | 3/0 X 2P | M12 | S3/0-12R-5 (QTY. 2) | CT-720 | CD-720-2 | TP-080 (Qty. 2) |
| | U/T1, V/T2, W/T3 | 3/0 | | S3/0-12R-5 | | | TP-080 |
| 4□0515 | R/L1, S/L2 | 4/0 X 2P | M12 | S4/0-12R-5 (QTY. 2) | CT-720 | CD-720-3 | TP-100 (Qty. 2) |
| | U/T1, V/T2, W/T3 | 3/0 | | S3/0-12R-5 | | CD-720-2 | TP-080 |
| 4□0675 | R/L1, S/L2 | 1 X 4P | M12 | S2-12R-X (QTY. 4) | CT-720 | CD-720-2 | TP-038 (Qty. 4) |
| | U/T1, V/T2, W/T3 | 4/0 | | S4/0-12R-5 | | CD-720-3 | TP-100 |

A.4 Drive Derating Data

Table A.22 JST Closed-Loop Crimp Terminal Size Single-Phase w/o Additional Impedance

| Drive Model | Terminal | Recomm. Gauge Without Additional Impedance AWG, kcmil | Screw Size | JST Ring Terminal (non-insulated) | JST Recomm. Installation Tool | JST Crimphead / Die Part No. | Insulation Cap Model No. |
|--|--------------------------------|---|------------|-----------------------------------|-------------------------------|--|---------------------------|
| 4□0002 4□0004 4□0005 4□0007 4□0009 4□0011 | R/L1, S/L2 U/T1, V/T2, W/T3 | 14 14 | M4 | R2-4 | YA-4 | AD-900 | TP-003 |
| 4□0018 | R/L1, S/L2 U/T1, V/T2, W/T3 | 12 12 | M4 | R5.5-4 | YA-4 | AD-900 | TP-005 |
| 4□0023 | R/L1, S/L2 U/T1, V/T2, W/T3 | 12 12 | M4 | R5.5-4 | YA-4 | AD-900 | TP-005 |
| 4□0031 | R/L1, S/L2 U/T1, V/T2, W/T3 | 8 10 | M5 | R8-5 R5.5-5 | YA-4 | AD-901 AD-900 | TP-008 TP-005 |
| 4□0038 | R/L1, S/L2 U/T1, V/T2, W/T3 | 8 10 | M5 | R8-5 R5.5-5 | YA-4 | AD-901 AD-900 | TP-008 TP-005 |
| 4□0044 | R/L1, S/L2 U/T1, V/T2, W/T3 | 6 6 | M6 | R14-6 | YA-5 | AD-952 | TP-014 |
| 4□0058 | R/L1, S/L2 U/T1, V/T2, W/T3 | 8 10 | M8 | R8-8 R5.5-8 | YA-4 | AD-901 AD-900 | TP-008 TP-005 |
| 4□0072 | R/L1, S/L2 U/T1, V/T2, W/T3 | 4 10 | M8 | R22-8 R5.5-8 | YA-5 YA-4 | AD-953 AD-900 | TP-022 TP-005 |
| 4□0088 | R/L1, S/L2 U/T1, V/T2, W/T3 | 4 6 | M8 | R22-8 R14-8 | YA-5 YA-5 | AD-953 AD-952 | TP-022 TP-014 |
| 4□0103 | R/L1, S/L2 U/T1, V/T2, W/T3 | 4 6 | M8 | R22-8 R14-8 | YA-5 YA-5 | AD-953 AD-952 | TP-022 TP-014 |
| 4□0139 | R/L1, S/L2 U/T1, V/T2, W/T3 | 1 6 | M10 | R38-10 R14-10 | YA-5 | AD-954 AD-952 | TP-060 TP-014 |
| 4□0165 | R/L1, S/L2 U/T1, V/T2, W/T3 | 1/0 6 | M10 | R60-10 R14-10 | YA-5 | AD-955 AD-952 | TP-060 TP-014 |
| 4□0208 | R/L1, S/L2 U/T1, V/T2, W/T3 | 2/0 4 | M10 | 70-10 R22-10 | YF-1 YA-5 YET-300-1 | TD-323, TD-312 AD-953 | TP-080 TP-022 |
| 4□0250 | R/L1, S/L2 U/T1, V/T2, W/T3 | 3/0 3 | M10 | 80-10 R38-10 | YF-1 YET-300-1 | TD-323, TD-312 TD-321, TD-311 | TP-080 TP-060 |
| 4□0296 | R/L1, S/L2 U/T1, V/T2, W/T3 | 3/0 3 | M12 | 80-L12 R38-12 | YF-1 YA-5 YET-300-1 | TD-323, TD-312 AD-954 | TP-080 TP-038 |
| 4□0362 | R/L1, S/L2 U/T1, V/T2, W/T3 | 1 X 2P 1 | M12 | R38-12 (QTY. 2) R38-12 | YA-5 | AD-954 | TP-038 (Qty. 2) TP-038 |
| 4□0414 | R/L1, S/L2 U/T1, V/T2, W/T3 | 3/0 X 2P 3/0 | M12 | 80-L12 (Qty. 2) 80-L12 | YF-1 YET-300-1 | TD-323 TD-312 | TP-080 (Qty. 2) TP-080 |
| 4□0515 | R/L1, S/L2 U/T1, V/T2, W/T3 | 4/0 X 2P 3/0 | M12 | 100-L12 (Qty. 2) 80-L12 | YF-1 YET-300-1 | TD-324 TD-312 TD-323, TD-312 | TP-100 TP-080 |
| 4□0675 | R/L1, S/L2 U/T1, V/T2, W/T3 | 1 X 4P 4/0 | M12 | R38-12 (QTY. 4) 100-L12 | YA-5 YF-1 YET-300-1 | AD-954 TD-324, TD-312 | TP-038 (Qty. 4) TP-100 |

Table A.23 Panduit Closed-Loop Crimp Terminal Size Single-Phase w/o Additional Impedance

| Drive Model | Terminal | Recomm. Gauge Without Additional Impedance AWG, kcmil | Screw Size | Panduit Ring Terminal (non-insulated) | Panduit Recomm. Installation Tool | Panduit Crimphead / Die Part No. | Insulation Cap Model No. |
|--------------------------------------|------------------|---|------------|---------------------------------------|-----------------------------------|----------------------------------|--------------------------|
| 5□0003 5□0004 5□0006 5□0009 | R/L1, S/L2 | 14 | M4 | P14-8R | CT-1570 | - | TP-003 |
| | U/T1, V/T2, W/T3 | 14 | | | | | |
| 5□0011 | R/L1, S/L2 | 12 | M4 | P10-8R | CT-1570 | - | TP-005 |
| | U/T1, V/T2, W/T3 | 12 | | | | | |
| 5□0017 | R/L1, S/L2 | 10 | M5 | P10-10R | CT-1701 | - | TP-005 |
| | U/T1, V/T2, W/T3 | 10 | | | | | |
| 5□0022 | R/L1, S/L2 | 10 | M5 | P10-10R | CT-1701 | - | TP-005 |
| | U/T1, V/T2, W/T3 | 10 | | | | | |
| 5□0027 5□0032 | R/L1, S/L2 | 6 | M6 | P6-14R | CT-1701 | - | TP-014 |
| | U/T1, V/T2, W/T3 | 6 | | | | | |
| 5□0041 5□0052 | R/L1, S/L2 | 8 | M8 | P8-56R | CT-1701 | - | TP-008 |
| | U/T1, V/T2, W/T3 | 10 | | P10-56R | | | TP-005 |
| 5□0062 | R/L1, S/L2 | 6 | M10 | P6-38R | CT-1701 | - | TP-014 |
| | U/T1, V/T2, W/T3 | 10 | | P10-38R | | | TP-005 |
| 5□0077 5□0099 | R/L1, S/L2 | 4 | M10 | S4-38R | CT-720 | CD-720-1 | TP-022 |
| | U/T1, V/T2, W/T3 | 8 | | S8-38R | | | TP-008 |
| 5□0125 | R/L1, S/L2 | 1 | M10 | S2-38R | CT-720 | CD-720-2 | TP-060 |
| | U/T1, V/T2, W/T3 | 6 | | S6-38R | | CD-720-1 | TP-014 |
| 5□0145 | R/L1, S/L2 | 1 | M10 | S2-38R | CT-720 | CD-720-2 | TP-060 |
| | U/T1, V/T2, W/T3 | 6 | | S6-38R | | CD-720-1 | TP-014 |
| 5□0192 | R/L1, S/L2 | 3/0 | M12 | S3/0-12R-5 | CT-720 | CD-720-2 | TP-080 |
| | U/T1, V/T2, W/T3 | 3 | | S2-12R-X | | | TP-038 |
| 5□0242 | R/L1, S/L2 | 3/0 | M12 | S3/0-12R-5 | CT-720 | CD-720-2 | TP-080 |
| | U/T1, V/T2, W/T3 | 3 | | S2-12R-X | | | TP-038 |

Table A.24 JST Closed-Loop Crimp Terminal Size Single-Phase w/o Additional Impedance

| Drive Model | Terminal | Recomm. Gauge Without Additional Impedance AWG, kcmil | Screw Size | JST Ring Terminal (non-insulated) | JST Recomm. Installation Tool | JST Crimphead / Die Part No. | Insulation Cap Model No. |
|--------------------------------------|------------------|---|------------|-----------------------------------|-------------------------------|------------------------------|--------------------------|
| 5□0003 5□0004 5□0006 5□0009 | R/L1, S/L2 | 14 | M4 | R2-4 | YA-4 | AD-900 | TP-003 |
| | U/T1, V/T2, W/T3 | 14 | | | | | |
| 5□0011 | R/L1, S/L2 | 12 | M4 | R5.5-4 | YA-4 | AD-900 | TP-005 |
| | U/T1, V/T2, W/T3 | 12 | | | | | |
| 5□0017 | R/L1, S/L2 | 10 | M5 | R5.5-5 | YA-4 | AD-900 | TP-005 |
| | U/T1, V/T2, W/T3 | 10 | | | | | |
| 5□0022 | R/L1, S/L2 | 10 | M5 | R5.5-5 | YA-4 | AD-900 | TP-005 |
| | U/T1, V/T2, W/T3 | 10 | | | | | |
| 5□0027 5□0032 | R/L1, S/L2 | 6 | M6 | R14-6 | YA-5 | AD-952 | TP-014 |
| | U/T1, V/T2, W/T3 | 6 | | | | | |
| 5□0041 5□0052 | R/L1, S/L2 | 8 | M8 | R8-8 | YA-4 | AD-901 | TP-008 |
| | U/T1, V/T2, W/T3 | 10 | | R5.5-8 | | AD-900 | TP-005 |
| 5□0062 | R/L1, S/L2 | 6 | M10 | R14-10 | YA-5 | AD-952 | TP-014 |
| | U/T1, V/T2, W/T3 | 10 | | R5.5-10 | | | |

A.4 Drive Derating Data

| Drive Model | Terminal | Recomm. Gauge Without Additional Impedance AWG, kcmil | Screw Size | JST Ring Terminal (non-insulated) | JST Recomm. Installation Tool | JST Crimphead / Die Part No. | Insulation Cap Model No. |
|------------------|------------------|---|------------|-----------------------------------|-------------------------------|------------------------------|--------------------------|
| 5□0077 5□0099 | R/L1, S/L2 | 4 | M10 | R22-10 | YA-5 | AD-953 | TP-022 |
| | U/T1, V/T2, W/T3 | 8 | | R8-10 | | AD-951 | TP-008 |
| 5□0125 | R/L1, S/L2 | 1 | M10 | R38-10 | YA-5 | AD-954 | TP-038 |
| | U/T1, V/T2, W/T3 | 6 | | R14-10 | | AD-952 | TP-014 |
| 5□0145 | R/L1, S/L2 | 1 | M10 | R38-10 | YA-5 | AD-954 | TP-038 |
| | U/T1, V/T2, W/T3 | 6 | | R14-10 | | AD-952 | TP-014 |
| 5□0192 | R/L1, S/L2 | 3/0 | M12 | 80-L12 | YF-1 YET-300-1 | TD-323, TD-312 | TP-080 |
| | U/T1, V/T2, W/T3 | 3 | | R38-12 | YA-5 | AD-954 | TP-038 |
| 5□0242 | R/L1, S/L2 | 3/0 | M12 | 80-L12 | YF-1 YET-300-1 | TD-323, TD-312 | TP-080 |
| | U/T1, V/T2, W/T3 | 3 | | R38-12 | YA-5 | AD-954 | TP-038 |

Table A.25 Panduit Closed-Loop Crimp Terminal Size Single-Phase With Additional Impedance

| Drive Model | Terminal | Recomm. Gauge With Additional Impedance AWG, kcmil | Screw Size | Panduit Ring Terminal (non-insulated) | Panduit Recomm. Installation Tool | Panduit Crimphead / Die Part No. | Insulation Cap Model No. |
|--|------------------|--|------------|---------------------------------------|-----------------------------------|----------------------------------|--------------------------|
| 2□0004 2□0006 2□0008 2□0010 2□0012 | R/L1, S/L2 | 14 | M4 | P14-8R | CT-1570 | - | TP-003 |
| | U/T1, V/T2, W/T3 | 14 | | | | | |
| 2□0018 2□0021 | R/L1, S/L2 | 10 | M4 | P10-8R | CT-1570 | - | TP-005 |
| | U/T1, V/T2, W/T3 | 14 | | P14-8R | | | TP-003 |
| 2□0030 | R/L1, S/L2 | 10 | M4 | P10-8R | CT-1570 | - | TP-005 |
| | U/T1, V/T2, W/T3 | 12 | | | | | |
| 2□0040 | R/L1, S/L2 | 8 | M4 | P8-8R | CT-1701 | - | TP-008 |
| | U/T1, V/T2, W/T3 | 12 | | P10-8R | | | TP-005 |
| 2□0056 | R/L1, S/L2 | 6 | M6 | P6-14R | CT-1701 | - | TP-014 |
| | U/T1, V/T2, W/T3 | 6 | | | | | |
| 2□0069 | R/L1, S/L2 | 4 | M8 | P4-56R | CT-1701 | - | TP-022 |
| | U/T1, V/T2, W/T3 | 10 | | P10-56R | | | TP-005 |
| 2□0081 | R/L1, S/L2 | 3 | M8 | P2-56R | CT-1701 | - | TP-038 |
| | U/T1, V/T2, W/T3 | 8 | | P8-56R | | | TP-008 |
| 2□0110 | R/L1, S/L2 | 4 | M8 | P4-56R | CT-1701 | - | TP-022 |
| | U/T1, V/T2, W/T3 | 10 | | P10-56R | | | TP-005 |
| 2□0138 | R/L1, S/L2 | 2 | M10 | P2-38R | CT-1701 | - | TP-038 |
| | U/T1, V/T2, W/T3 | 8 | | P8-38R | | | TP-008 |
| 2□0169 | R/L1, S/L2 | 1/0 | M10 | S1/0-38R-X | CT-720 | CD-720-2 | TP-060 |
| | U/T1, V/T2, W/T3 | 6 | | S6-38R-E | | CD-720-1 | TP-014 |
| 2□0211 | R/L1, S/L2 | 2/0 | M10 | S2/0-38R | CT-720 | CD-720-2 | TP-060 |
| | U/T1, V/T2, W/T3 | 1/0 | | S1/0-38R | | | TP-038 |
| 2□0250 | R/L1, S/L2 | 4/0 | M12 | S4/0-12R-5 | CT-720 | CD-720-2 | TP-100 |
| | U/T1, V/T2, W/T3 | 3 | | S2-12R-X | | | CD720-3 |
| 2□0312 | R/L1, S/L2 | 1/0 X 2P | M12 | S1/0-12R-X (Qty. 2) | CT-720 | CD-720-2 | TP-038 (Qty. 2) |
| | U/T1, V/T2, W/T3 | 1 | | S2-12R-X | | | TP-060 |
| 2□0360 | R/L1, S/L2 | 2/0 X 2P | M12 | S2/0-12R-X (Qty. 2) | CT-720 | CD-720-2 | TP-080 (Qty. 2) |
| | U/T1, V/T2, W/T3 | 2/0 | | S2/0-12R-X | | | TP-080 |

| Drive Model | Terminal | Recomm. Gauge With Additional Impedance AWG, kcmil | Screw Size | Panduit Ring Terminal (non-insulated) | Panduit Recomm. Installation Tool | Panduit Crimphead / Die Part No. | Insulation Cap Model No. |
|-------------|------------------|--|------------|---------------------------------------|-----------------------------------|----------------------------------|--------------------------|
| 2□0415 | R/L1, S/L2 | 3/0 X 2P | M12 | S3/0-12R-5 (Qty. 2) | CT-720 | CD-720-2 | TP-080 (Qty. 2) |
| | U/T1, V/T2, W/T3 | 3/0 | | S3/0-12R-5 | | | TP-080 |

Table A.26 JST Closed-Loop Crimp Terminal Size Single-Phase With Additional Impedance

| Drive Model | Terminal | Recomm. Gauge With Additional Impedance AWG, kcmil | Screw Size | JST Ring Terminal (non-insulated) | JST Recomm. Installation Tool | JST Crimphead / Die Part No. | Insulation Cap Model No. |
|--|------------------|--|------------|-----------------------------------|-------------------------------|------------------------------|--------------------------|
| 2□0004 2□0006 2□0008 2□0010 2□0012 | R/L1, S/L2 | 14 | M4 | R2-4 | YA-4 | AD-900 | TP-003 |
| | U/T1, V/T2, W/T3 | 14 | | | | | |
| 2□0018 2□0021 | R/L1, S/L2 | 10 | M4 | R5.5-4 | YA-4 | AD-900 | TP-005 |
| | U/T1, V/T2, W/T3 | 14 | | R2-4 | | | TP-003 |
| 2□0030 | R/L1, S/L2 | 10 | M4 | R5.5-4 | YA-4 | AD-900 | TP-005 |
| | U/T1, V/T2, W/T3 | 12 | | | | | |
| 2□0040 | R/L1, S/L2 | 8 | M4 | 8-4 | YA-4 | AD-901 | TP-008 |
| | U/T1, V/T2, W/T3 | 12 | | R5.5-4 | | AD-900 | TP-005 |
| 2□0056 | R/L1, S/L2 | 6 | M6 | R14-6 | YA-5 | AD-952 | TP-014 |
| | U/T1, V/T2, W/T3 | 6 | | | | | |
| 2□0069 | R/L1, S/L2 | 4 | M8 | R22-8 | YA-5 | AD-953 | TP-022 |
| | U/T1, V/T2, W/T3 | 10 | | R5.5-8 | | | |
| 2□0081 | R/L1, S/L2 | 3 | M8 | R38-8 | YA-5 | AD-954 | TP-038 |
| | U/T1, V/T2, W/T3 | 8 | | R8-8 | | | |
| 2□0110 | R/L1, S/L2 | 4 | M8 | R22-8 | YA-5 | AD-953 | TP-022 |
| | U/T1, V/T2, W/T3 | 10 | | R5.5-8 | | | |
| 2□0138 | R/L1, S/L2 | 2 | M10 | R38-10 | YA-5 | AD-954 | TP-038 |
| | U/T1, V/T2, W/T3 | 8 | | R8-10 | | | |
| 2□0169 | R/L1, S/L2 | 1/0 | M10 | R60-10 | YA-5 | AD-955 | TP-060 |
| | U/T1, V/T2, W/T3 | 6 | | R14-10 | | | |
| 2□0211 | R/L1, S/L2 | 2/0 | M10 | 70-10 | YF-1 YET-300-1 | TD-323, TD-312 | TP-080 |
| | U/T1, V/T2, W/T3 | 1/0 | | R60-10 | YA-5 | AD-955 | TP-060 |
| 2□0250 | R/L1, S/L2 | 4/0 | M12 | 100-L12 | YF-1 YET-300-1 | TD-324, TD-312 | TP-100 |
| | U/T1, V/T2, W/T3 | 3 | | R38-14 | YA-5 | AD-954 | TP-038 |
| 2□0312 | R/L1, S/L2 | 1/0 X 2P | M12 | R60-14 (Qty. 2) | YA-5 | AD-955 | TP-060 (Qty. 2) |
| | U/T1, V/T2, W/T3 | 1 | | R38-14 | | | AD-954 |
| 2□0360 | R/L1, S/L2 | 2/0 X 2P | M12 | 70-14 (Qty. 2) | YF-1 YET-300-1 | TD-323, TD-312 | TP-080 (Qty. 2) |
| | U/T1, V/T2, W/T3 | 2/0 | | 70-14 | | | TP-080 |
| 2□0415 | R/L1, S/L2 | 3/0 X 2P | M12 | 80-L12 (Qty. 2) | YF-1 YET-300-1 | TD-323 TD-312 | TP-080 (Qty. 2) |
| | U/T1, V/T2, W/T3 | 3/0 | | 80-L12 | | | TP-080 |

A.4 Drive Derating Data

Table A.27 Panduit Closed-Loop Crimp Terminal Size Single-Phase With Additional Impedance

| Drive Model | Terminal | Recomm. Gauge With Additional Impedance AWG, kcmil | Screw Size | Panduit Ring Terminal (non-insulated) | Panduit Recomm.Installation Tool | Panduit Crimphead / Die Part No. | Insulation Cap Model No. |
|--|--------------------------------|--|------------|---------------------------------------|----------------------------------|----------------------------------|---------------------------|
| 4□0002 4□0004 4□0005 4□0007 4□0009 4□0011 | R/L1, S/L2 U/T1, V/T2, W/T3 | 14 14 | M4 | P14-8R | CT-1570 | - | TP-003 |
| 4□0018 | R/L1, S/L2 U/T1, V/T2, W/T3 | 12 12 | M4 | P10-8R | CT-1570 | - | TP-005 |
| 4□0023 | R/L1, S/L2 U/T1, V/T2, W/T3 | 12 12 | M4 | P10-8R | CT-1570 | - | TP-005 |
| 4□0031 | R/L1, S/L2 U/T1, V/T2, W/T3 | 10 10 | M5 | P10-10R | CT-1701 | - | TP-005 |
| 4□0038 | R/L1, S/L2 U/T1, V/T2, W/T3 | 8 10 | M5 | P8-10R P10-10R | CT-1701 | - | TP-008 TP-005 |
| 4□0044 | R/L1, S/L2 U/T1, V/T2, W/T3 | 6 6 | M6 | P6-14R | CT-1701 | - | TP-014 |
| 4□0058 | R/L1, S/L2 U/T1, V/T2, W/T3 | 8 10 | M8 | P8-56R P10-56R | CT-1701 | - | TP-008 TP-005 |
| 4□0072 | R/L1, S/L2 U/T1, V/T2, W/T3 | 4 10 | M8 | P4-56R P10-56R | CT-1701 | - | TP-022 TP-005 |
| 4□0088 | R/L1, S/L2 U/T1, V/T2, W/T3 | 4 6 | M8 | P4-56R P6-56R | CT-1701 | - | TP-022 TP-014 |
| 4□0103 | R/L1, S/L2 U/T1, V/T2, W/T3 | 6 6 | M8 | P6-56R | CT-1701 | - | TP-014 |
| 4□0139 | R/L1, S/L2 U/T1, V/T2, W/T3 | 1 6 | M10 | S2-38R S6-38R | CT-720 | CD-720-2 CD-720-1 | TP-060 TP-014 |
| 4□0165 | R/L1, S/L2 U/T1, V/T2, W/T3 | 1 6 | M10 | S2-38R S6-38R | CT-720 | CD-720-2 CD-720-1 | TP-060 TP-014 |
| 4□0208 | R/L1, S/L2 U/T1, V/T2, W/T3 | 2/0 4 | M10 | S2/0-38R S4-38R | CT-720 | CD-720-2 CD-720-1 | TP-080 TP-022 |
| 4□0250 | R/L1, S/L2 U/T1, V/T2, W/T3 | 3/0 3 | M10 | S3/0-38R S2-38R-X | CT-720 | CD-720-2 | TP-080 TP-038 |
| 4□0296 | R/L1, S/L2 U/T1, V/T2, W/T3 | 1 X 2P 2 | M12 | S2-12R-X (Qty. 2) S2-12R-X | CT-720 | CD-720-2 | TP-038 (Qty. 2) TP-038 |
| 4□0362 | R/L1, S/L2 U/T1, V/T2, W/T3 | 2/0 X 2P 1/0 | M12 | S2/0-12R-X (Qty. 2) S1/0-12R-X | CT-720 | CD-720-2 | TP-080 (Qty. 2) TP-038 |
| 4□0414 | R/L1, S/L2 U/T1, V/T2, W/T3 | 3/0 X 2P 3/0 | M12 | S3/0-12R-5 (QTY. 2) S3/0-12R-5 | CT-720 | CD-720-2 | TP-080 (Qty. 2) TP-080 |
| 4□0515 | R/L1, S/L2 U/T1, V/T2, W/T3 | 3/0 X 2P 3/0 | M12 | S3/0-12R-5 (QTY. 2) S3/0-12R-5 | CT-720 | CD-720-2 | TP-080 (Qty. 2) TP-080 |
| 4□0675 | R/L1, S/L2 U/T1, V/T2, W/T3 | 1 X 4P 4/0 | M12 | S2-12R-X (QTY. 4) S4/0-12R-5 | CT-720 | CD-720-2 CD-720-3 | TP-038 (Qty. 4) TP-100 |

Table A.28 JST Closed-Loop Crimp Terminal Size Single-Phase With Additional Impedance

| Drive Model | Terminal | Recomm. Gauge With Additional Impedance AWG, kcmil | Screw Size | JST Ring Terminal (non-insulated) | JST Recomm. Installation Tool | JST Crimphead / Die Part No. | Insulation Cap Model No. |
|--|------------------|--|------------|-----------------------------------|-------------------------------|------------------------------|--------------------------|
| 4□0002 4□0004 4□0005 4□0007 4□0009 4□0011 | R/L1, S/L2 | 14 | M4 | R2-4 | YA-4 | AD-900 | TP-003 |
| | U/T1, V/T2, W/T3 | 14 | | | | | |
| 4□0018 | R/L1, S/L2 | 12 | M4 | R5.5-4 | YA-4 | AD-900 | TP-005 |
| | U/T1, V/T2, W/T3 | 12 | | | | | |
| 4□0023 | R/L1, S/L2 | 12 | M4 | R5.5-4 | YA-4 | AD-900 | TP-005 |
| | U/T1, V/T2, W/T3 | 12 | | | | | |
| 4□0031 | R/L1, S/L2 | 10 | M5 | R5.5-5 | YA-4 | AD-900 | TP-005 |
| | U/T1, V/T2, W/T3 | 10 | | | | | |
| 4□0038 | R/L1, S/L2 | 8 | M5 | R8-5 | YA-4 | AD-901 | TP-008 |
| | U/T1, V/T2, W/T3 | 10 | | R5.5-5 | | AD-900 | TP-005 |
| 4□0044 | R/L1, S/L2 | 6 | M6 | R14-6 | YA-5 | AD-952 | TP-014 |
| | U/T1, V/T2, W/T3 | 6 | | | | | |
| 4□0058 | R/L1, S/L2 | 8 | M8 | R8-8 | YA-4 | AD-901 | TP-008 |
| | U/T1, V/T2, W/T3 | 10 | | R5.5-8 | | AD-900 | TP-005 |
| 4□0072 | R/L1, S/L2 | 4 | M8 | R22-8 | YA-5 | AD-953 | TP-022 |
| | U/T1, V/T2, W/T3 | 10 | | R5.5-8 | YA-4 | AD-900 | TP-005 |
| 4□0088 | R/L1, S/L2 | 4 | M8 | R22-8 | YA-5 | AD-953 | TP-022 |
| | U/T1, V/T2, W/T3 | 6 | | R14-8 | YA-5 | AD-952 | TP-014 |
| 4□0103 | R/L1, S/L2 | 6 | M8 | R14-8 | YA-5 | AD-952 | TP-014 |
| | U/T1, V/T2, W/T3 | 6 | | | | | |
| 4□0139 | R/L1, S/L2 | 1 | M10 | R38-10 | YA-5 | AD-954 | TP-060 |
| | U/T1, V/T2, W/T3 | 6 | | R14-10 | | AD-952 | TP-014 |
| 4□0165 | R/L1, S/L2 | 1 | M10 | R38-10 | YA-5 | AD-954 | TP-060 |
| | U/T1, V/T2, W/T3 | 6 | | R14-10 | | AD-952 | TP-014 |
| 4□0208 | R/L1, S/L2 | 2/0 | M10 | 70-10 | YF-1 YET-300-1 | TD-323, TD-312 | TP-080 |
| | U/T1, V/T2, W/T3 | 4 | | R22-10 | YA-5 | AD-953 | TP-022 |
| 4□0250 | R/L1, S/L2 | 3/0 | M10 | 80-10 | YF-1 YET-300-1 | TD-323, TD-312 | TP-080 |
| | U/T1, V/T2, W/T3 | 3 | | R38-10 | | TD-321, TD-311 | TP-060 |
| 4□0296 | R/L1, S/L2 | 1 X 2P | M12 | R38-12 (QTY. 2) | YA-5 | AD-954 | TP-038 (Qty. 2) |
| | U/T1, V/T2, W/T3 | 2 | | R38-12 | | | TP-038 |
| 4□0362 | R/L1, S/L2 | 2/0 X 2P | M12 | 70-12(Qty. 2) | YF-1 YET-300-1 | TD-322 TD-311 | TP-080 (Qty. 2) |
| | U/T1, V/T2, W/T3 | 1/0 | | R60-12 | | TD-321 TD-311 | TP-060 |
| 4□0414 | R/L1, S/L2 | 3/0 X 2P | M12 | 80-L12 (Qty. 2) | YF-1 YET-300-1 | TD-323 TD-312 | TP-080 (Qty. 2) |
| | U/T1, V/T2, W/T3 | 3/0 | | 80-L12 | | TP-080 | |
| 4□0515 | R/L1, S/L2 | 3/0 X 2P | M12 | 80-L12 (Qty. 2) | YF-1 YET-300-1 | TD-323 TD-312 | TP-080 (QTY. 2) |
| | U/T1, V/T2, W/T3 | 3/0 | | 80-L12 | | TP-080 | |
| 4□0675 | R/L1, S/L2 | 1 X 4P | M12 | R38-12 (QTY. 4) | YA-5 | AD-954 | TP-038 (Qty. 4) |
| | U/T1, V/T2, W/T3 | 4/0 | | 100-L12 | | | YF-1 YET-300-1 |

A.4 Drive Derating Data

Table A.29 Panduit Closed-Loop Crimp Terminal Size Single-Phase With Additional Impedance

| Drive Model | Terminal | Recomm. Gauge With Additional Impedance AWG, kcmil | Screw Size | Panduit Ring Terminal (non-insulated) | Panduit Recomm. Installation Tool | Panduit Crimphead / Die Part No. | Insulation Cap Model No. |
|--------------------------------------|------------------|--|------------|---------------------------------------|-----------------------------------|----------------------------------|--------------------------|
| 5□0003 5□0004 5□0006 5□0009 | R/L1, S/L2 | 14 | M4 | P14-8R | CT-1570 | - | TP-003 |
| | U/T1, V/T2, W/T3 | 14 | | | | | |
| 5□0011 | R/L1, S/L2 | 12 | M4 | P10-8R | CT-1570 | - | TP-005 |
| | U/T1, V/T2, W/T3 | 12 | | | | | |
| 5□0017 | R/L1, S/L2 | 10 | M5 | P10-10R | CT-1701 | - | TP-005 |
| | U/T1, V/T2, W/T3 | 10 | | | | | |
| 5□0022 | R/L1, S/L2 | 10 | M5 | P10-10R | CT-1701 | - | TP-005 |
| | U/T1, V/T2, W/T3 | 10 | | | | | |
| 5□0027 5□0032 | R/L1, S/L2 | 6 | M6 | P6-14R | CT-1701 | - | TP-014 |
| | U/T1, V/T2, W/T3 | 6 | | | | | |
| 5□0041 5□0052 | R/L1, S/L2 | 8 | M8 | P8-56R | CT-1701 | - | TP-008 |
| | U/T1, V/T2, W/T3 | 10 | | P10-56R | | | TP-005 |
| 5□0062 | R/L1, S/L2 | 6 | M10 | P6-38R | CT-1701 | - | TP-014 |
| | U/T1, V/T2, W/T3 | 10 | | P10-38R | | | TP-005 |
| 5□0077 5□0099 | R/L1, S/L2 | 4 | M10 | S4-38R | CT-720 | CD-720-1 | TP-022 |
| | U/T1, V/T2, W/T3 | 8 | | S8-38R | | | TP-008 |
| 5□0125 | R/L1, S/L2 | 1 | M10 | S2-38R | CT-720 | CD-720-2 | TP-060 |
| | U/T1, V/T2, W/T3 | 6 | | S6-38R | | | CD-720-1 |
| 5□0145 | R/L1, S/L2 | 1 | M10 | S2-38R | CT-720 | CD-720-2 | TP-060 |
| | U/T1, V/T2, W/T3 | 6 | | S6-38R | | | CD-720-1 |
| 5□0192 | R/L1, S/L2 | 3/0 | M12 | S3/0-12R-5 | CT-720 | CD-720-2 | TP-080 |
| | U/T1, V/T2, W/T3 | 3 | | S2-12R-X | | | TP-038 |
| 5□0242 | R/L1, S/L2 | 3/0 | M12 | S3/0-12R-5 | CT-720 | CD-720-2 | TP-080 |
| | U/T1, V/T2, W/T3 | 3 | | S2-12R-X | | | TP-038 |

Table A.30 JST Closed-Loop Crimp Terminal Size Single-Phase With Additional Impedance

| Drive Model | Terminal | Recomm. Gauge With Additional Impedance AWG, kcmil | Screw Size | JST Ring Terminal (non-insulated) | JST Recomm. Installation Tool | JST Crimphead / Die Part No. | Insulation Cap Model No. |
|--------------------------------------|------------------|--|------------|-----------------------------------|-------------------------------|------------------------------|--------------------------|
| 5□0003 5□0004 5□0006 5□0009 | R/L1, S/L2 | 14 | M4 | R2-4 | YA-4 | AD-900 | TP-003 |
| | U/T1, V/T2, W/T3 | 14 | | | | | |
| 5□0011 | R/L1, S/L2 | 12 | M4 | R5.5-4 | YA-4 | AD-900 | TP-005 |
| | U/T1, V/T2, W/T3 | 12 | | | | | |
| 5□0017 | R/L1, S/L2 | 10 | M5 | R5.5-5 | YA-4 | AD-900 | TP-005 |
| | U/T1, V/T2, W/T3 | 10 | | | | | |
| 5□0022 | R/L1, S/L2 | 10 | M5 | R5.5-5 | YA-4 | AD-900 | TP-005 |
| | U/T1, V/T2, W/T3 | 10 | | | | | |
| 5□0027 5□0032 | R/L1, S/L2 | 6 | M6 | R14-6 | YA-5 | AD-952 | TP-014 |
| | U/T1, V/T2, W/T3 | 6 | | | | | |
| 5□0041 5□0052 | R/L1, S/L2 | 8 | M8 | R8-8 | YA-4 | AD-901 | TP-008 |
| | U/T1, V/T2, W/T3 | 10 | | R5.5-8 | | AD-900 | TP-005 |
| 5□0062 | R/L1, S/L2 | 6 | M10 | R14-10 | YA-5 | AD-952 | TP-014 |
| | U/T1, V/T2, W/T3 | 10 | | R5.5-10 | | | |

| Drive Model | Terminal | Recomm. Gauge With Additional Impedance AWG, kcmil | Screw Size | JST Ring Terminal (non-insulated) | JST Recomm. Installation Tool | JST Crimphead / Die Part No. | Insulation Cap Model No. |
|------------------|------------------|--|------------|-----------------------------------|-------------------------------|------------------------------|--------------------------|
| 5□0077 5□0099 | R/L1, S/L2 | 4 | M10 | R22-10 | YA-5 | AD-953 | TP-022 |
| | U/T1, V/T2, W/T3 | 8 | | R8-10 | | AD-951 | TP-008 |
| 5□0125 | R/L1, S/L2 | 1 | M10 | R38-10 | YA-5 | AD-954 | TP-038 |
| | U/T1, V/T2, W/T3 | 6 | | R14-10 | | AD-952 | TP-014 |
| 5□0145 | R/L1, S/L2 | 1 | M10 | R38-10 | YA-5 | AD-954 | TP-038 |
| | U/T1, V/T2, W/T3 | 6 | | R14-10 | | AD-952 | TP-014 |
| 5□0192 | R/L1, S/L2 | 3/0 | M12 | 80-L12 | YF-1 YET-300-1 | TD-323, TD-312 | TP-080 |
| | U/T1, V/T2, W/T3 | 3 | | R38-12 | YA-5 | AD-954 | TP-038 |
| 5□0242 | R/L1, S/L2 | 3/0 | M12 | 80-L12 | YF-1 YET-300-1 | TD-323, TD-312 | TP-080 |
| | U/T1, V/T2, W/T3 | 3 | | R38-12 | YA-5 | AD-954 | TP-038 |

◆ Rated Current Depending on Carrier Frequency

The table below shows the drive output current depending on the carrier frequency settings.

■ Normal Duty Rating (ND)

The 2 kHz values shown for ND in [Table A.33](#) are equal to the drive rated current shown on the drive nameplate. Increasing the carrier frequency above 2 kHz will reduce the ND rated output current of the drive as shown in [Table A.33](#).

Table A.31 Three-Phase 200 V Class Carrier Frequency and Current Derating

| Three-Phase 200 V Class | | | |
|-------------------------|-------------------------|-------|--------|
| Drive Model | Rated Current [A] | | |
| | Normal Duty Rating (ND) | | |
| | 2 kHz | 8 kHz | 15 kHz |
| 2A0004 | 3.5 | 3.2 | 2.56 |
| 2A0006 | 6 | 5 | 4 |
| 2A0008 | 8 | 6.9 | 5.5 |
| 2A0010 | 9.6 | 8 | 6.4 |
| 2A0012 | 12 | 11 | 8.8 |
| 2A0018 | 17.5 | 14 | 11.2 |
| 2A0021 | 21 | 17.5 | 14 |
| 2A0030 | 30 | 25 | 20 |
| 2A0040 | 40 | 33 | 26.4 |
| 2A0056 | 56 | 47 | 37.6 |
| 2A0069 | 69 | 60 | 48 |
| 2A0081 | 81 | 75 | 53 |
| 2A0110 | 110 | 85 | 60 |
| 2A0138 | 138 | 115 | 81 |

| Three-Phase 200 V Class | | | |
|-------------------------|-------------------------|-------|--------|
| Drive Model | Rated Current [A] | | |
| | Normal Duty Rating (ND) | | |
| | 2 kHz | 5 kHz | 10 kHz |
| 2A0169 | 169 | 145 | 116 |
| 2A0211 | 211 | 180 | 144 |
| 2A0250 | 250 | 215 | 172 |
| 2A0312 | 312 | 283 | 226 |
| 2A0360 | 360 | 346 | 277 |
| 2A0415 | 415 | 415 | 332 |

Table A.32 Three-Phase 400 V Class Carrier Frequency and Current Derating

| Three-Phase 400 V Class | | | |
|-------------------------|-------------------------|-------|--------|
| Drive Model | Rated Current [A] | | |
| | Normal Duty Rating (ND) | | |
| | 2 kHz | 8 kHz | 15 kHz |
| 4A0002 | 2.1 | 1.8 | 1.1 |
| 4A0004 | 4.1 | 3.4 | 2 |
| 4A0005 | 5.4 | 4.8 | 2.9 |
| 4A0007 | 6.9 | 5.5 | 3.3 |
| 4A0009 | 8.8 | 7.2 | 4.3 |
| 4A0011 | 11.1 | 9.2 | 5.5 |
| 4A0018 | 17.5 | 14.8 | 8.9 |
| 4A0023 | 23 | 18 | 10.8 |
| 4A0031 | 31 | 24 | 14.4 |

| Three-Phase 400 V Class | | | |
|-------------------------|-------------------------|-------|--------|
| Drive Model | Rated Current [A] | | |
| | Normal Duty Rating (ND) | | |
| | 2 kHz | 8 kHz | 15 kHz |
| 4A0038 | 38 | 31 | 18.6 |
| 4A0044 | 44 | 39 | 23.4 |
| 4A0058 | 58 | 45 | 27 |
| 4A0072 | 72 | 60 | 36 |
| 4A0088 | 88 | 75 | 45 |
| 4A0103 | 103 | 91 | 55 |

| Three-Phase 400 V Class | | | |
|-------------------------|-------------------------|-------|--------|
| Drive Model | Rated Current [A] | | |
| | Normal Duty Rating (ND) | | |
| | 2 kHz | 5 kHz | 10 kHz |
| 4A0139 | 139 | 112 | 78 |
| 4A0165 | 165 | 150 | 105 |
| 4A0208 | 208 | 180 | 126 |
| 4A0250 | 250 | 216 | 151 |
| 4A0296 | 296 | 260 | 182 |
| 4A0362 | 362 | 304 | 213 |
| 4A0414 | 414 | 370 | – |
| 4A0515 | 515 | 397 | – |
| 4A0675 | 675 | 528 | – |
| 4A0930 | 930 | 716 | – |
| 4A1200 | 1200 | 938 | – |

Table A.33 Carrier Frequency and Current Derating

| Three-Phase 600 V Class | | | | |
|-------------------------|-------------------------|-------|--------|--------|
| Drive Model | Rated Current [A] | | | |
| | Normal Duty Rating (ND) | | | |
| | 2 kHz | 8 kHz | 10 kHz | 15 kHz |
| 5A0003 | 2.7 | 2.2 | 2.0 | 1.3 |
| 5A0004 | 3.9 | 3.4 | 3.1 | 2.1 |
| 5A0006 | 6.1 | 4.9 | 4.3 | 2.9 |
| 5A0009 | 9 | 7.5 | 6.6 | 4.5 |
| 5A0011 | 11 | 9.3 | 8.2 | 5.6 |
| 5A0017 | 17 | 13.3 | 11.8 | – |
| 5A0022 | 22 | 17.0 | 15.1 | – |
| 5A0027 | 27 | 22.0 | 19.5 | – |
| 5A0032 | 32 | 27.3 | 24.4 | – |

| Three-Phase 600 V Class | | | | |
|-------------------------|-------------------------|-------|-------|--------|
| Drive Model | Rated Current [A] | | | |
| | Normal Duty Rating (ND) | | | |
| | 2 kHz | 5 kHz | 8 kHz | 10 kHz |
| 5A0041 | 41.0 | 39.7 | 33.5 | 29.4 |
| 5A0052 | 52.0 | 50.3 | 42.5 | 37.3 |
| 5A0062 | 62.0 | 61.3 | 49.7 | 41.9 |
| 5A0077 | 77.0 | 76.2 | 61.7 | 52.0 |
| 5A0099 | 99.0 | 80.0 | 55.1 | – |

A.4 Drive Derating Data

| Three-Phase 600 V Class | | |
|-------------------------|-------------------------|-------|
| Drive Model | Rated Current [A] | |
| | Normal Duty Rating (ND) | |
| | 2 kHz | 3 kHz |
| 5A0125 | 125.0 | 93.0 |
| 5A0145 | 145.0 | 108.0 |
| 5A0192 | 192.0 | 148.0 |
| 5A0242 | 242.0 | 187.0 |

◆ Temperature Derating

To ensure the maximum performance life, the drive output current must be derated as shown in *Figure A.1* when the drive is installed in areas with high ambient temperature or if drives are mounted side-by-side in a cabinet. In order to ensure reliable drive overload protection, set parameters L8-12 and L8-35 according to the installation conditions.

■ Parameter Settings

| No. | Name | Description | Range | Def. |
|-------|-------------------------------|---|------------|--------|
| L8-12 | Ambient Temperature Setting | Adjust the drive overload (oL2) protection level when the drive is installed in an environment that exceeds its ambient temperature rating. | -10 to +50 | +40 °C |
| L8-35 | Installation Method Selection | 0: IP00/Open-Chassis Enclosure 1: Side-by-Side Mounting 2: IP20/NEMA Type 1 Enclosure 3: External Heatsink Installation | 0 to 3 | <1> |

<1> Default setting is determined by drive model.

Setting 0: (Models 2A0250 to 2A0415 and 4A0208 to 4A0675)

Setting 2: (Models 2A0004 to 2A0211, 4A0002 to 4A0165, and 5A0003 to 5A0242).

Setting 0: IP00/Open-Chassis Enclosure

Drive operation between -10 °C and +50 °C allows 100% continuous current without derating.

Setting 1: Side-by-Side Mounting

Drive operation between -10 °C and +30 °C allows 100% continuous current without derating. Operation between +30 °C and +50 °C requires output current derating.

Setting 2: IP20/NEMA 1, UL Type 1 Enclosure

Drive operation between -10 °C and +40 °C allows 100% continuous current without derating. Operation between +40 °C and +50 °C requires output current derating.

Setting 3: External Heatsink Installation

Drive operation between -10 °C and +40 °C allows 100% continuous current without derating. Operation between +40 °C and +50 °C requires output current derating.

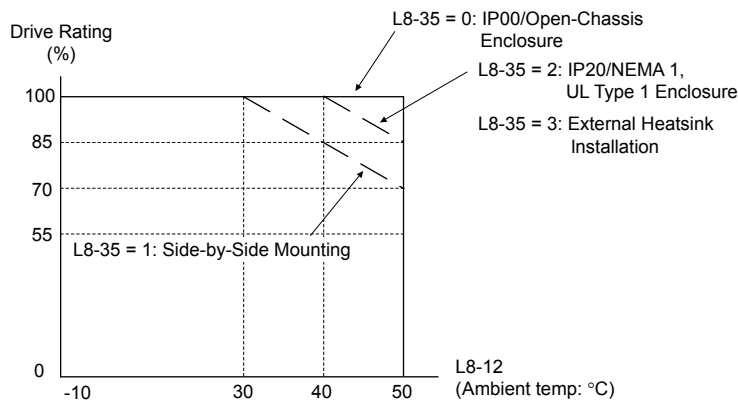


Figure A.1 Ambient Temperature and Installation Method Derating

◆ Altitude Derating

The drive standard ratings are valid for installation altitudes up to 1000 m. For installations from 1000 m to 3000 m, the drive rated voltage and the rated output current must be derated for 0.2% per 100 m.

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Appendix: B

Parameter List

This appendix contains a full listing of all parameters and settings available in the drive.


| | | |
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| B.4 | C: TUNING..... | 441 |
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| B.16 | DEFAULTS BY DRIVE MODEL..... | 487 |

B.1 Understanding Parameter Descriptions

◆ Parameter Icons

The table below lists icons used in this section.

Table B.1 Icons Used in Parameter Descriptions

| Symbol | Description |
|---|--------------------------------------|
|  | Parameter can be changed during run. |

◆ Parameter Groups



Table B.2 P1000 Parameter Groups

| Parameter Group | Name | Page | Parameter Group | Name | Page |
|-----------------|--|---------------------|-----------------|--|---------------------|
| A1 | Initialization Parameters | 433 | H6 | Pulse Train Input/Output | 461 |
| A2 | User Parameters | 433 | L1 | Motor Protection | 463 |
| b1 | Operation Mode Selection | 434 | L2 | Momentary Power Loss Ride-Thru | 463 |
| b2 | DC Injection Braking and Short Circuit Braking | 434 | L3 | Stall Prevention | 464 |
| b3 | Speed Search | 435 | L4 | Speed Detection | 465 |
| b4 | Timer Function | 436 | L5 | Fault Restart | 466 |
| b5 | PID Control | 436 | L6 | Torque Detection | 466 |
| b6 | Dwell Function | 439 | L8 | Drive Protection | 467 |
| b8 | Energy Saving | 440 | n1 | Hunting Prevention | 469 |
| C1 | Acceleration and Deceleration Times | 441 | n3 | High Slip Braking (HSB) and Overexcitation Braking | 469 |
| C2 | S-Curve Characteristics | 441 | o1 | Digital Operator Display Selection | 470 |
| C3 | Slip Compensation | 442 | o2 | Digital Operator Keypad Functions | 471 |
| C4 | Torque Compensation | 442 | o3 | Copy Function | 471 |
| C6 | Carrier Frequency | 442 | o4 | Maintenance Monitor Settings | 472 |
| d1 | Frequency Reference | 443 | S1 | Dynamic Noise Control Function | 473 |
| d3 | Jump Frequency | 444 | S2 | Programmable Run Timers | 473 |
| d6 | Field Weakening and Field Forcing | 445 | S3 | Secondary PI (PI2) Control | 475 |
| E1 | V/f Pattern | 446 | S6 | P1000 Protection | 477 |
| E2 | Motor 1 Parameters | 447 | S7 | Output Current Limit | 477 |
| F4 | Analog Monitor Card (AO-A3) | 448 | T1 | Induction Motor Auto-Tuning | 478 |
| F6, F7 | Communication Option Card | 448 | U2 | Fault Trace | 481 |
| H1 | Multi-Function Digital Inputs | 454 | U3 | Fault History | 482 |
| H2 | Multi-Function Digital Outputs | 457 | U4 | Maintenance Monitors | 483 |
| H3 | Multi-Function Analog Inputs | 458 | U5 | PID Monitors | 485 |
| H4 | Multi-Function Analog Outputs | 460 | U6 | Operation Status Monitors | 485 |
| H5 | MEMOBUS/Modbus Serial Communication | 461 | | | |

B.2 A: Initialization Parameters

The A parameter group creates the operating environment for the drive. This includes the parameter Access Level, Motor Control Method, Password, User Parameters and more.

◆ A1: Initialization

| No. (Addr. Hex) | Name | Description | Values | Page |
|---|------------------------|--|---|------|
| A1-00 (100)  <> | Language Selection | 0: English 1: Japanese 2: German 3: French 4: Italian 5: Spanish 6: Portuguese 7: Chinese | Default: 0 Range: 0 to 7 | 142 |
| A1-01 (101)  <> | Access Level Selection | 0: View and set A1-01 and A1-04. U□-□□ parameters can also be viewed. 1: User Parameters (access to a set of parameters selected by the user, A2-01 to A2-32) 2: Advanced Access (access to view and set all parameters) | Default: 2 Range: 0 to 2 | 142 |
| A1-03 (103) | Initialize Parameters | 0: No initialization 1110: User Initialize (parameter values must be stored using parameter o2-03) 2220: 2-Wire initialization 3330: 3-Wire initialization 5550: oPE04 error reset 8008: Pump 8009: Pump w/ PI 8010: Fan 8011: Fan w/ PI | Default: 0 Range: 0 to 5550; 8008 to 8011 | 143 |
| A1-04 (104) | Password | When the value set into A1-04 does not match the value set into A1-05, parameters A1-01 through A1-03 and A2-01 through A2-33 cannot be changed. | Default: 0000 Min.: 0000 Max.: 9999 | 143 |
| A1-05 (105) | Password Setting | When the value set into A1-04 does not match the value set into A1-05, parameters A1-01 through A1-03 and A2-01 through A2-33 cannot be changed. | Default: 0000 Min.: 0000 Max.: 9999 | 143 |
| A1-06 (127) | Application Preset | 0: General-purpose 8: Pump 9: Pump w/PI 10: Fan 11: Fan w/PI Note: This parameter is not settable. It is used as a monitor only. | Default: 0 Range: 0; 8 to 11 | 146 |

<1> Parameter setting value is not reset to the default value when the drive is initialized.

<2> Default setting value is dependent on the Initialization parameter A1-03.

◆ A2: User Parameters

| No. (Addr. Hex) | Name | Description | Values | Page |
|--------------------------------------|------------------------------------|---|--------------------------------------|------|
| A2-01 to A2-32 (106 to 125) | User Parameters 1 to 32 | Recently edited parameters are listed here. The user can also select parameters to appear here for quicker access. | Default: <> Range: b1-01 to S6-07 | 146 |
| A2-33 (126) | User Parameter Automatic Selection | 0: Parameters A2-01 to A2-32 are reserved for the user to create a list of User Parameters. 1: Save history of recently viewed parameters. Recently edited parameters will be saved to A2-17 through A2-32 for quicker access. | Default: 0 Range: 0, 1 | 146 |

<1> Default setting value is dependent on the Initialization parameter A1-03.

B.3 b: Application

Application parameters configure the source of the Run command, DC Injection Braking, Speed Search, timer functions, PID control, the Dwell function, Energy Savings, and a variety of other application-related settings.

◆ b1: Operation Mode Selection

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|---|---|--------------------------------------|------|
| b1-01 (180) | Frequency Reference Selection 1 | 0: Digital operator 1: Analog input terminals 2: MEMOBUS/Modbus communications 3: Option PCB 4: Pulse input (terminal RP) | Default: 1 Range: 0 to 4 | 147 |
| b1-02 (181) | Run Command Selection 1 | 0: Digital operator 1: Digital input terminals 2: MEMOBUS/Modbus communications 3: Option PCB | Default: 1 Range: 0 to 3 | 148 |
| b1-03 (182) | Stopping Method Selection | 0: Ramp to stop 1: Coast to stop 2: DC Injection Braking to stop 3: Coast with timer | Default: 0 Range: 0 to 3 | 149 |
| b1-04 (183) | Reverse Operation Selection | 0: Reverse enabled. 1: Reverse disabled. | Default: 0 Range: 0, 1 | 151 |
| b1-07 (186) | LOCAL/REMOTE Run Selection | 0: An external Run command must be cycled at the new source in order to be activated. 1: An external Run command at the new source is accepted immediately. | Default: 0 Range: 0, 1 | 151 |
| b1-08 (187) | Run Command Selection in Programming Mode | 0: Run command is not accepted while in Programming Mode. 1: Run command is accepted while in Programming Mode. 2: Prohibit entering Programming Mode during run. | Default: 0 Range: 0 to 2 | 151 |
| b1-11 (1DF) | Run Delay Time Setting | After a Run command is entered, the drive output waits until this delay time has passed before starting. | Default: 0 s Min.: 0 Max.: 600 | 152 |
| b1-14 (1C3) | Phase Order Selection | 0: Standard 1: Switch phase order (reverses the direction of the motor) | Default: 0 Range: 0, 1 | 152 |
| b1-15 (1C4) | Frequency Reference Selection 2 | Enabled when an input terminal set for "External reference" (H1-□□ = 2) closes. 0: Digital operator 1: Terminals (analog input terminals) 2: MEMOBUS/Modbus communications 3: Option card 4: Pulse train input | Default: 0 Range: 0 to 4 | 152 |
| b1-16 (1C5) | Run Command Selection 2 | Enabled when a terminal set for "External reference" (H1-□□ = 2) closes. 0: Digital operator 1: Digital input terminals 2: MEMOBUS/Modbus communications 3: Option card | Default: 0 Range: 0 to 3 | 152 |
| b1-17 (1C6) | Run Command at Power Up | 0: Disregarded. A new Run command must be issued after power up. 1: Allowed. Motor will start immediately after power up if a Run command is already enabled. | Default: 0 Range: 0, 1 | 152 |

◆ b2: DC Injection Braking and Short Circuit Braking

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|--------------------------------------|--|--|------|
| b2-01 (189) | DC Injection Braking Start Frequency | Sets the frequency at which DC Injection Braking starts when "Ramp to stop" (b1-03 = 0) is selected. | Default: 0.5 Hz Min.: 0.0 Max.: 10.0 | 153 |
| b2-02 (18A) | DC Injection Braking Current | Sets the DC Injection Braking current as a percentage of the drive rated current. | Default: 50% Min.: 0 Max.: 100 | 153 |
| b2-03 (18B) | DC Injection Braking Time at Start | Sets DC Injection Braking time at start. Disabled when set to 0.00 seconds. | Default: 0.00 s Min.: 0.00 Max.: 10.00 | 153 |

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|-----------------------------------|---|--|------|
| b2-04 (18C) | DC Injection Braking Time at Stop | Sets DC Injection Braking time at stop. | Default: 0.50 s Min.: 0.00 Max.: 10.00 | 153 |

◆ b3: Speed Search

| No. (Addr. Hex.) | Name | Description | Values | Page |
|------------------|--|---|--|------|
| b3-01 (191) | Speed Search Selection at Start | 0: Disabled 1: Enabled | Default: 0 Range: 0, 1 | 157 |
| b3-02 (192) | Speed Search Deactivation Current | Sets the current level at which the speed is assumed to be detected and Speed Search is ended. Set as a percentage of the drive rated current. | Default: 120% Min.: 0 Max.: 200 | 157 |
| b3-03 (193) | Speed Search Deceleration Time | Sets output frequency reduction time during Speed Search. | Default: 2.0 s Min.: 0.1 Max.: 10.0 | 157 |
| b3-04 (194) | V/f Gain during Speed Search | Determines how much to lower the V/f ratio during Speed Search. Output voltage during Speed Search equals the V/f setting multiplied by b3-04. | Default: </> Min.: 10% Max.: 100% | 157 |
| b3-05 (195) | Speed Search Delay Time | When using an external contactor on the output side, b3-05 delays executing Speed Search after a momentary power loss to allow time for the contactor to close. | Default: 0.2 s Min.: 0.0 Max.: 100.0 | 157 |
| b3-06 (196) | Output Current 1 during Speed Search | Sets the current injected to the motor at the beginning of Speed Estimation Speed Search. Set as a coefficient for the motor rated current. | Default: </> Min.: 0.0 Max.: 2.0 | 157 |
| b3-07 (197) | Output Current 2 during Speed Search (Speed Estimation Type) | Sets the amount of output current during Speed Estimation Speed Search as a coefficient for the no-load current. | Default: </> Min.: 0.0 Max.: 5.0 | 158 |
| b3-08 (198) | Current Control Gain during Speed Search (Speed Estimation Type) | Sets the proportional gain for the current controller during Speed Search. | Default: 0.8 Min.: 0.00 Max.: 6.00 | 158 |
| b3-09 (0199) </> | ACR Integral Time during Speed Search (Speed Estimation Type) | Sets the integral time for the current controller during to adjust responsiveness during Speed Estimation Speed Search. There is normally no need to change this parameter from the default value. | Default: 2.0 ms Min.: 0.0 Max.: 1000.0 | 158 |
| b3-10 (19A) | Speed Search Detection Compensation Gain | Sets the gain which is applied to the speed detected by Speed Estimation Speed Search before the motor is reaccelerated. Increase this setting if ov occurs when performing Speed Search after a relatively long period of baseblock. | Default: 1.05 Min.: 1.00 Max.: 1.20 | 158 |
| b3-12 (19C) | Minimum Current Detection Level during Speed Search | Sets the minimum current detection level during Speed Search. | Default: 6.0 Min.: 2.0 Max.: 10.0 | 158 |
| b3-14 (19E) | Bi-Directional Speed Search Selection | 0: Disabled (uses the direction of the frequency reference) 1: Enabled (drive detects which way the motor is rotating) | Default: 1 Range: 0, 1 | 158 |
| b3-17 (1F0) | Speed Search Restart Current Level | Sets the Speed Search restart current level as a percentage of the drive rated current. | Default: 150% Min.: 0 Max.: 200 | 159 |
| b3-18 (1F1) | Speed Search Restart Detection Time | Sets the time to detect Speed Search restart. | Default: 0.10 s Min.: 0.00 Max.: 1.00 | 159 |
| b3-19 (1F2) | Number of Speed Search Restarts | Sets the number of times the drive can attempt to restart when performing Speed Search. | Default: 3 Min.: 0 Max.: 10 | 159 |
| b3-24 (1C0) | Speed Search Method Selection | 0: Current Detection 1: Speed Estimation | Default: 0 Range: 0, 1 | 159 |
| b3-25 (1C8) | Speed Search Wait Time | Sets the time the drive must wait between each Speed Search restart attempt. | Default: 0.5 s Min.: 0.0 Max.: 30.0 | 159 |
| b3-26 (1C7) | Direction Determining Level | Sets the level that determines the direction of motor rotation. | Default: </> Min.: 40 Max.: 60000 | 159 |

B.3 b: Application

| No. (Addr Hex.) | Name | Description | Values | Page |
|-----------------|---------------------------|---|---------------------------|------|
| b3-27 (1C9) | Start Speed Search Select | Selects a condition to activate Speed Search Selection at Start (b3-01) or External Speed Search Command 1 or 2 from the multi-function input. 0: Triggered when a Run command is issued (normal). 1: Triggered when an external baseblock is released. | Default: 0 Range: 0, 1 | 159 |









<1> Default setting is dependent on parameter o2-04, Drive Model Selection.




<2> Available in drive software versions PRG: 8504 and later.

◆ b4: Timer Function






| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|-------------------------------|---|---|------|
| b4-01 (1A3) | Timer Function On-Delay Time | Sets the on-delay and off-delay times for a digital timer output (H2-□□=12). The output is triggered by a digital input programmed to H1-□□=18). | Default: 0.0 s Min.: 0.0 Max.: 3000.0 | 160 |
| b4-02 (1A4) | Timer Function Off-Delay Time | | Default: 0.0 s Min.: 0.0 Max.: 3000.0 | 160 |






◆ b5: PID Control

| No. (Addr. Hex) | Name | Description | Values | Page |
|--|---------------------------------|--|--|------|
| b5-01 (1A5) | PID Function Setting | 0: Disabled 1: Enabled (PID output becomes output frequency reference, deviation D controlled) | Default: 0 Range: 0, 1 | 164 |
| b5-02 (1A6)  | Proportional Gain Setting (P) | Sets the proportional gain of the PID controller. | Default: 1.00 Min.: 0.00 Max.: 25.00 | 164 |
| b5-03 (1A7)  | Integral Time Setting (I) | Sets the integral time for the PID controller. | Default: 1.0 s Min.: 0.0 Max.: 360.0 | 164 |
| b5-04 (1A8)  | Integral Limit Setting | Sets the maximum output possible from the integrator as a percentage of the maximum output frequency. | Default: 100.0% Min.: 0.0 Max.: 100.0 | 164 |
| b5-05 (1A9)  | Derivative Time (D) | Sets D control derivative time. | Default: 0.00 s Min.: 0.00 Max.: 10.00 | 164 |
| b5-06 (1AA)  | PID Output Limit | Sets the maximum output possible from the entire PID controller as a percentage of the maximum output frequency. | Default: 100.0% Min.: 0.0 Max.: 100.0 | 164 |
| b5-07 (1AB)  | PID Offset Adjustment | Applies an offset to the PID controller output. Set as a percentage of the maximum output frequency. | Default: 0.0% Min.: -100.0 Max.: 100.0 | 164 |
| b5-08 (1AC)  | PID Primary Delay Time Constant | Sets a low pass filter time constant on the output of the PID controller. | Default: 0.00 s Min.: 0.00 Max.: 10.00 | 164 |
| b5-09 (1AD) | PID Output Level Selection | 0: Normal output (direct acting) 1: Reverse output (reverse acting) | Default: 0 Range: 0, 1 | 165 |
| b5-10 (1AE)  | PID Output Gain Setting | Sets the gain applied to the PID output. | Default: 1.00 Min.: 0.00 Max.: 25.00 | 165 |
| b5-11 (1AF) | PID Output Reverse Selection | 0: Negative PID output triggers zero limit. 1: Rotation direction reverses with negative PID output. Note: When using setting 1, make sure reverse operation is permitted by b1-04. | Default: 0 Range: 0, 1 | 165 |

| No. (Addr. Hex) | Name | Description | Values | Page |
|--|--|---|---|------|
| b5-12 (1B0) | PID Feedback Loss Detection Selection | 0: No fault. Digital output only. 1: Fault detection. Alarm output, drive continues operation. 2: Fault detection. Fault output, drive output is shut off. 3: No fault. Digital output only. No fault detection when PID control is disabled. 4: Fault detection. Alarm is triggered and drive continues to run. Fault detection even when PID is disabled. 5: Fault detection. Drive output shuts off. No fault detection when PID control is disabled. | Default: 0 Range: 0 to 5 | 166 |
| b5-13 (1B1) | PID Feedback Loss Detection Level | Sets the PID feedback loss detection level as a percentage of the maximum output frequency. | Default: 0% Min.: 0 Max.: 100 | 166 |
| b5-14 (1B2) | PID Feedback Loss Detection Time | Sets a delay time for PID feedback loss. | Default: 1.0 s Min.: 0.0 Max.: 25.5 | 166 |
| b5-15 (1B3) | PID Sleep Function Start Level | Sets the frequency level that triggers the sleep function. | Default: 0.0 Hz Min.: 0.0 Max.: 400.0 | 167 |
| b5-16 (1B4) | PID Sleep Delay Time | Sets a delay time before the sleep function is triggered. | Default: 0.0 s Min.: 0.0 Max.: 25.5 | 167 |
| b5-17 (1B5) | PID Accel/Decel Time | Sets the acceleration and deceleration time to PID setpoint. | Default: 0.0 s Min.: 0.0 Max.: 6000.0 | 167 |
| b5-18 (1DC) | PID Setpoint Selection | 0: Disabled 1: Enabled | Default: 0 Range: 0, 1 | 168 |
| b5-19 (1DD)  | PID Setpoint Value | Sets the PID target value as a percentage of the maximum output frequency when b5-18 is set to 1. Note: Values set above b5-38 will be internally limited to b5-38 | Default: 0.00% Min.: 0.00 Max.: 600.00 | 168 |
| b5-20 (1E2) | PID Setpoint Scaling | 0: 0.01 Hz units 1: 0.01% units (100% = max output frequency) 2: RPM (number of motor poles must entered) 3: User-set (set scaling to b5-38 and b5-39, units based on b5-46 setting) | Default: 1 Range: 0 to 3 | 169 |
| b5-34 (19F)  | PID Output Lower Limit | Sets the minimum output possible from the PID controller as a percentage of the maximum output frequency. | Default: 0.00% Min.: -100.00 Max.: 100.00 | 172 |
| b5-35 (1A0)  | PID Input Limit | Limits the PID control input (deviation signal) as a percentage of the maximum output frequency. Acts as a bipolar limit. | Default: 1000.0% Min.: 0.0 Max.: 1000.0 | 172 |
| b5-36 (1A1) | PID Feedback High Detection Level | Sets the PID feedback high detection level as a percentage of the maximum output frequency. | Default: 100% Min.: 0 Max.: 100 | 167 |
| b5-37 (1A2) | PID Feedback High Detection Time | Sets the PID feedback high level detection delay time. | Default: 1.0 s Min.: 0.0 Max.: 25.5 | 167 |
| b5-38 (1FE) | PID Setpoint User Display | Scales the PID units to the maximum output frequency. | Default: 10000 Min.: 1 Max.: 60000 | 170 |
| b5-39 (1FF) | PID Setpoint Display Digits | 0: No decimal places 1: One decimal place 2: Two decimal places 3: Three decimal places | Default: 2 Range: 0 to 3 | 170 |
| b5-40 (17F) | Frequency Reference Monitor Content during PID | 0: Display the frequency reference (U1-01) after PID compensation has been added. 1: Display the frequency reference (U1-01) before PID compensation has been added. | Default: 0 Range: 0, 1 | 172 |

B.3 b: Application

| No. (Addr. Hex) | Name | Description | Values | Page |
|---|---|--|--------------------------------------|---------------------|
| b5-41 (160) | PI Output 2 Unit Selection | 0: WC (Inch of water) 1: PSI (Pounds per square inch) 2: GPM (Gallons per minute) 3: F (Degrees Fahrenheit) 4: CFM (Cubic feet per minute) 5: CMH (Cubic meters per hour) 6: LPH (Liters per hour) 7: LPS (Liters per second) 8: Bar (Bar) 9: Pa (Pascal) 10: C (Degrees Celsius) 11: Mtr (Meters) 12: Ft (Feet) 13: LPM (Liters per minute) 14: CMM (Cubic meters per minute) 15: "Hg (Inches of Mercury) 25: None | Default: 0 Range: 0 to 15; 25 | 172 |
| b5-42 (161)  | PI Output 2 Calculation Mode | 0: Linear - the monitor displays PID output 1: Square root - the monitor displays square root PID output 2: Quadratic - the monitor displays 1/(PID output) 3: Cubic - the monitor displays 1/(PID output) Note: Used for U5-14 and U5-15 only. | Default: 0 Range: 0 to 3 | 173 |
| b5-43 (162)  | PI Output 2 Monitor Max Upper 4 Digits | Sets the upper 4 digits of the maximum monitor value. Used with b5-44 to set maximum monitor value of U5-14 and U5-15 at maximum frequency. Note: Used for U5-14 and U5-15 only. | Default: 0 Min.: 0 Max.: 9999 | 173 |
| b5-44 (163)  | PI Output 2 Monitor Max Lower 4 Digits | Sets the lower 4 digits of the maximum monitor value. Used with b5-43 to set maximum monitor value of U5-14 and U5-15 at maximum frequency. Note: Used for U5-14 and U5-15 only. | Default: 0 Min.: 0 Max.: 99.99 | 173 |
| b5-45 (164)  | PI Output 2 Monitor Minimum | Sets the minimum display value at zero speed. This function is effective when b5-42 is set to 0 (Linear output mode). Note: Used for U5-14 and U5-15 only. | Default: 0 Min.: 0 Max.: 999.9 | 173 |
| b5-46 (165) | PID Units Selection | Sets the display units for parameter b5-19, and monitors U5-01, U5-04 and U5-99 0: WC (Inch of water) 1: PSI (Pounds per square inch) 2: GPM (Gallons per minute) 3: F (Degrees Fahrenheit) 4: CFM (Cubic feet per minute) 5: CMH (Cubic meters per hour) 6: LPH (Liters per hour) 7: LPS (Liters per second) 8: Bar (Bar) 9: Pa (Pascal) 10: C (Degrees Celsius) 11: Mtr (Meters) 12: Ft (Feet) 13: LPM (Liters per minute) 14: CMM (Cubic meters per minute) 15: "Hg (Inches of Mercury) 25: None | Default: 0 Range: 0 to 15; 25 | 170 |
| b5-47 (17D) | Reverse Operation Selection 2 by PID Output | 0: Zero limit when PID output is a negative value. 1: Reverse operation when PID output is a negative value (Zero limit if the reverse operation is prohibited by b1-04). | Default: 1 Range: 0, 1 | 172 |
| b5-89 (B89)  | Sleep Method Selection | Determines how the drive sleeps and wakes-up when using PID. 0: Standard 1: EZ Sleep/Wake-up | Default: 0 Range: 0, 1 | 170 |
| b5-90 (B90) </> | EZ Sleep Unit | Sets the unit, range, and resolution of parameters b5-91 and b5-92. 0: Hz 1: RPM (number of motor poles must be entered) | Default: 0 Range: 0, 1 | 171 |

| No. (Addr. Hex) | Name | Description | Values | Page |
|--|------------------|---|---|------|
| b5-91 (B91)  | EZ Minimum Speed | Sets the PID minimum speed and integral lower limit. The internal value is lower limited to the higher setting between b5-34 and d2-02. | Default: 0.0 Hz Range: 0.0 to 400.0 Hz or 0 to 24000 RPM <2> | 171 |
| b5-92 (B92)  | EZ Sleep Level | The drive will go to sleep when the drive output frequency (or speed) is at or below this level for the time set in b5-93. This parameter is internally lower limited to b5-91 (EZ Min Speed) + 1Hz. | Default: 0.0 Hz Range: 0.0 to 400.0 Hz or 0 to 24000 RPM <2> | 171 |
| b5-93 (B93)  | EZ Sleep Time | The drive will go to sleep when the drive output frequency is at or below the level set to b5-92 for the time set in this parameter. | Default: 5.0 s Min.: 0.0 Max.: 1000.0 | 171 |
| b5-94 (B94)  | EZ Wake-up Level | When b5-95 is set to 0 (Absolute), the drive wakes-up when the PID Feedback (H3-□□ = 20) drops below this level for the time set in b5-96. For reverse-acting, the PID Feedback must be above this level for the time set in b5-96. When b5-95 is set to 1 (Setpoint Delta), the drive wakes-up when the PID Feedback (H3-□□ = 20) drops below the PID Setpoint minus this level (for normal acting PID) for the time set in b5-96. For reverse-acting, Wake-up level is PID Setpoint plus this level. The PID Feedback must be above the wake-up level for the time set in b5-96. | Default: 0.00% Min.: 0.00 Max.: 600.00 | 171 |
| b5-95 (B95) <1> | EZ Wake-up Mode | Sets how the wake-up level is determined. 0: Absolute 1: Setpoint Delta | Default: 0 Range: 0, 1 | 171 |
| b5-96 (B96)  | EZ Wake-up Time | The drive will wake up when the PID Feedback drops below the b5-94, EZ Wake-up Level for the time set in this parameter. | Default: 1.0 s Min.: 0.0 Max.: 1000.0 | 172 |

<1> Unit and resolution are determined by b5-20, b5-39 and b5-46. Internally limited to b5-38. Changing b5-20, b5-38 and b5-39 will not automatically update the value of this parameter.

<2> Parameter is only effective when EZ Sleep is enabled by setting b5-89 to 1.

<3> Unit, range and resolution is determined by b5-90. Changing b5-90 will not automatically update the value of this parameter.

◆ b6: Dwell Function

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|--------------------------|--|---|------|
| b6-01 (1B6) | Dwell Reference at Start | Parameters b6-01 and b6-02 set the frequency to hold and the time to maintain that frequency at start. | Default: 0.0 Hz Min.: 0.0 Max.: 400.0 | 175 |
| b6-02 (1B7) | Dwell Time at Start | | Default: 0.0 s Min.: 0.0 Max.: 10.0 | 175 |
| b6-03 (1B8) | Dwell Reference at Stop | Parameters b6-03 and b6-04 set the frequency to hold and the time to maintain that frequency at stop. | Default: 0.0 Hz Min.: 0.0 Max.: 400.0 | 175 |
| b6-04 (1B9) | Dwell Time at Stop | | Default: 0.0 s Min.: 0.0 Max.: 10.0 | 175 |

◆ b8: Energy Saving

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------------|---------------------------------|--|--|---------------------|
| b8-01 (1CC) | Energy Saving Control Selection | 0: Disabled 1: Enabled | Default: 0 Range: 0, 1 | 175 |
| b8-04 (1CF) | Energy Saving Coefficient Value | Determines the level of maximum motor efficiency. Setting range is 0.0 to 2000.0 for drives 3.7 kW and smaller. The display resolution depends on the rated output power of the drive. | Default: <1> <2> Min.: 0.00 Max.: 655.00 | 175 |
| b8-05 (1D0) | Power Detection Filter Time | Sets a time constant filter for output power detection. | Default: 20 ms Min.: 0 Max.: 2000 | 176 |
| b8-06 (1D1) | Search Operation Voltage Limit | Sets the limit for the voltage search operation as a percentage of the motor rated voltage. | Default: 0% Min.: 0 Max.: 100 | 176 |

<1> Default setting is dependent on parameter o2-04, Drive Model Selection.

<2> Parameter value changes automatically if E2-11 is manually changed or changed by Auto-Tuning.

B.4 C: Tuning

C parameters are used to adjust the acceleration and deceleration times, S-curves, torque compensation, and carrier frequency selections.

◆ C1: Acceleration and Deceleration Times

| No. (Addr. Hex) | Name | Description | Values | Page |
|--------------------|--------------------------------------|--|--|------|
| C1-01 (200) | Acceleration Time 1 | Sets the time to accelerate from 0 to maximum frequency. | Default: 10.0 s Min.: 0.0 Max.: 6000.0 <1> | 177 |
| C1-02 (201) | Deceleration Time 1 | Sets the time to decelerate from maximum frequency to 0. | Default: 10.0 s Min.: 0.0 Max.: 6000.0 <1> | 177 |
| C1-03 (202) | Acceleration Time 2 | Sets the time to accelerate from 0 to maximum frequency. | Default: 10.0 s Min.: 0.0 Max.: 6000.0 <1> | 177 |
| C1-04 (203) | Deceleration Time 2 | Sets the time to decelerate from maximum frequency to 0. | Default: 10.0 s Min.: 0.0 Max.: 6000.0 <1> | 177 |
| C1-09 (208) | Fast Stop Time | Sets the time for the Fast Stop function. | Default: 10.0 s Min.: 0.0 Max.: 6000.0 <1> | 178 |
| C1-10 (209) | Accel/Decel Time Setting Units | 0: 0.01 s (0.00 to 600.00 s) 1: 0.1 s (0.0 to 6000.0 s) | Default: 1 Range: 0, 1 | 178 |
| C1-11 (20A) | Accel/Decel Time Switching Frequency | Sets the frequency to switch between accel/decel time settings | Default: 0.0 Hz Min.: 0.0 Max.: 400.0 | 177 |

<1> Setting range value is dependent on parameter C1-10, Accel/Decel Time Setting Units. When C1-10 = 0 (units of 0.01 seconds), the setting range becomes 0.00 to 600.00 seconds.

◆ C2: S-Curve Characteristics

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|---------------------------------------|--|--|------|
| C2-01 (20B) | S-Curve Characteristic at Accel Start | <p>The S-curve can be controlled at the four points shown below.</p> | Default: 0.20 s Min.: 0.00 Max.: 10.00 | 178 |
| C2-02 (20C) | S-Curve Characteristic at Accel End | | Default: 0.20 s Min.: 0.00 Max.: 10.00 | 178 |
| C2-03 (20D) | S-Curve Characteristic at Decel Start | | Default: 0.20 s Min.: 0.00 Max.: 10.00 | 178 |
| C2-04 (20E) | S-Curve Characteristic at Decel End | | Default: 0.00 s Min.: 0.00 Max.: 10.00 | 178 |

◆ C3: Slip Compensation

| No. (Addr. Hex) | Name | Description | Values | Page |
|--------------------|---|---|--|------|
| C3-01 (20F) RUN | Slip Compensation Gain | Sets the gain for the motor slip compensation function used for motor 1. | Default: 0.0 Min.: 0.0 Max.: 2.5 | 179 |
| C3-02 (210) RUN | Slip Compensation Primary Delay Time | Adjusts the slip compensation function delay time used for motor 1. | Default: 2000 ms Min.: 0 Max.: 10000 | 179 |
| C3-03 (211) | Slip Compensation Limit | Sets an upper limit for the slip compensation function as a percentage of motor rated slip for motor 1 (E2-02). | Default: 200% Min.: 0 Max.: 250 | 179 |
| C3-04 (212) | Slip Compensation Selection during Regeneration | 0: Disabled. 1: Enabled above 6 Hz. 2: Enabled whenever slip compensation is possible. | Default: 0 Range: 0 to 2 | 179 |

◆ C4: Torque Compensation

| No. (Addr. Hex) | Name | Description | Values | Page |
|--------------------|--|--|---|------|
| C4-01 (215) RUN | Torque Compensation Gain | Sets the gain for the automatic torque (voltage) boost function and helps to produce better starting torque. Used for motor 1. | Default: 1.00 Min.: 0.00 Max.: 2.50 | 180 |
| C4-02 (216) RUN | Torque Compensation Primary Delay Time 1 | Sets the torque compensation filter time. | Default: 200 ms Min.: 0 ms Max.: 60000 ms | 180 |

◆ C6: Carrier Frequency

















| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|-------------------------------------|---|---|------|
| C6-02 (224) | Carrier Frequency Selection | 1: 2.0 kHz 2: 5.0 kHz 3: 8.0 kHz 4: 10.0 kHz 5: 12.5 kHz 6: 15.0 kHz 7: Swing PWM1 (Audible sound 1) 8: Swing PWM2 (Audible sound 2) 9: Swing PWM3 (Audible sound 3) A: Swing PWM4 (Audible sound 4) B to E: No setting possible F: User-defined (determined by C6-03 through C6-05) | Default: 7 Range: 1 to 9; A, F | 180 |
| C6-03 (225) | Carrier Frequency Upper Limit | Determines the upper and lower limits for the carrier frequency. | Default: <1> Min.: 1.0 kHz Max.: 15.0 kHz | 181 |
| C6-04 (226) | Carrier Frequency Lower Limit | | Default: <1> Min.: 1.0 kHz Max.: 15.0 kHz | 181 |
| C6-05 (227) | Carrier Frequency Proportional Gain | | Default: <1> Min.: 0 Max.: 99 | 181 |

<1> Default setting value is dependent on parameter C6-02, Carrier Frequency Selection.


B.5 d: References

Reference parameters set the various frequency reference values during operation.

◆ d1: Frequency Reference

| No. (Addr. Hex) | Name | Description | Values | Page |
|---|------------------------|--|--|---------------------|
| d1-01 (280)  | Frequency Reference 1 | Sets the frequency reference for the drive. Setting units are determined by parameter o1-03. | Default: 0.00 Hz Min.: 0.00 Max.: 400.00 </> | 182 |
| d1-02 (281)  | Frequency Reference 2 | Sets the frequency reference for the drive. Setting units are determined by parameter o1-03. | Default: 0.00 Hz Min.: 0.00 Max.: 400.00 </> | 182 |
| d1-03 (282)  | Frequency Reference 3 | Sets the frequency reference for the drive. Setting units are determined by parameter o1-03. | Default: 0.00 Hz Min.: 0.00 Max.: 400.00 </> | 182 |
| d1-04 (283)  | Frequency Reference 4 | Sets the frequency reference for the drive. Setting units are determined by parameter o1-03. | Default: 0.00 Hz Min.: 0.00 Max.: 400.00 </> | 182 |
| d1-05 (284)  | Frequency Reference 5 | Sets the frequency reference for the drive. Setting units are determined by parameter o1-03. | Default: 0.00 Hz Min.: 0.00 Max.: 400.00 </> | 182 |
| d1-06 (285)  | Frequency Reference 6 | Sets the frequency reference for the drive. Setting units are determined by parameter o1-03. | Default: 0.00 Hz Min.: 0.00 Max.: 400.00 </> | 182 |
| d1-07 (286)  | Frequency Reference 7 | Sets the frequency reference for the drive. Setting units are determined by parameter o1-03. | Default: 0.00 Hz Min.: 0.00 Max.: 400.00 </> | 182 |
| d1-08 (287)  | Frequency Reference 8 | Sets the frequency reference for the drive. Setting units are determined by parameter o1-03. | Default: 0.00 Hz Min.: 0.00 Max.: 400.00 </> | 182 |
| d1-09 (288)  | Frequency Reference 9 | Sets the frequency reference for the drive. Setting units are determined by parameter o1-03. | Default: 0.00 Hz Min.: 0.00 Max.: 400.00 </> | 182 |
| d1-10 (28B)  | Frequency Reference 10 | Sets the frequency reference for the drive. Setting units are determined by parameter o1-03. | Default: 0.00 Hz Min.: 0.00 Max.: 400.00 </> | 182 |
| d1-11 (28C)  | Frequency Reference 11 | Sets the frequency reference for the drive. Setting units are determined by parameter o1-03. | Default: 0.00 Hz Min.: 0.00 Max.: 400.00 </> | 182 |
| d1-12 (28D)  | Frequency Reference 12 | Sets the frequency reference for the drive. Setting units are determined by parameter o1-03. | Default: 0.00 Hz Min.: 0.00 Max.: 400.00 </> | 182 |
| d1-13 (28E)  | Frequency Reference 13 | Sets the frequency reference for the drive. Setting units are determined by parameter o1-03. | Default: 0.00 Hz Min.: 0.00 Max.: 400.00 </> | 182 |
| d1-14 (28F)  | Frequency Reference 14 | Sets the frequency reference for the drive. Setting units are determined by parameter o1-03. | Default: 0.00 Hz Min.: 0.00 Max.: 400.00 </> | 182 |
| d1-15 (290)  | Frequency Reference 15 | Sets the frequency reference for the drive. Setting units are determined by parameter o1-03. | Default: 0.00 Hz Min.: 0.00 Max.: 400.00 </> | 182 |
| d1-16 (291)  | Frequency Reference 16 | Sets the frequency reference for the drive. Setting units are determined by parameter o1-03. | Default: 0.00 Hz Min.: 0.00 Max.: 400.00 </> | 182 |

B.5 d: References

| No. (Addr. Hex) | Name | Description | Values | Page |
|--|-------------------------|--|--|---------------------|
| d1-17 (292)  | Jog Frequency Reference | Sets the Jog frequency reference. Setting units are determined by parameter o1-03. | Default: 6.00 Hz Min.: 0.00 Max.: 400.00 <1> | 182 |

<1> Range upper limit is determined by parameters d2-01, Frequency Reference Upper Limit, and E1-04, Maximum Output Frequency.



◆ d2: Frequency Upper/Lower Limits





| No. (Addr. Hex.) | Name | Description | Setting | Page |
|------------------|------------------------------------|---|---|---------------------|
| d2-01 (289) | Frequency Reference Upper Limit | Sets the frequency reference upper limit as a percentage of the maximum output frequency. | Default: 100.0% Min.: 0.0 Max.: 110.0 | 184 |
| d2-02 (28A) | Frequency Reference Lower Limit | Sets the frequency reference lower limit as a percentage of the maximum output frequency. | Default: 0.0% Min.: 0.0 Max.: 110.0 | 184 |
| d2-03 (293) | Master Speed Reference Lower Limit | Sets the lower limit for frequency references from analog inputs as a percentage of the maximum output frequency. | Default: 0.0% Min.: 0.0 Max.: 110.0 | 185 |

◆ d3: Jump Frequency

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|----------------------|---|---|---------------------|
| d3-01 (294) | Jump Frequency 1 | Eliminates problems with resonant vibration of the motor/machine by avoiding continuous operation in predefined frequency ranges. The drive accelerates and decelerates the motor through the prohibited frequency ranges. Setting 0.0 disables this function. Parameters must be set so that $d3-01 \geq d3-02 \geq d3-03$. | Default: 0.0 Hz Min.: 0.0 Max.: 400.0 | 185 |
| d3-02 (295) | Jump Frequency 2 | Eliminates problems with resonant vibration of the motor/machine by avoiding continuous operation in predefined frequency ranges. The drive accelerates and decelerates the motor through the prohibited frequency ranges. Setting 0.0 disables this function. Parameters must be set so that $d3-01 \geq d3-02 \geq d3-03$. | Default: 0.0 Hz Min.: 0.0 Max.: 400.0 | 185 |
| d3-03 (296) | Jump Frequency 3 | Eliminates problems with resonant vibration of the motor/machine by avoiding continuous operation in predefined frequency ranges. The drive accelerates and decelerates the motor through the prohibited frequency ranges. Setting 0.0 disables this function. Parameters must be set so that $d3-01 \geq d3-02 \geq d3-03$. | Default: 0.0 Hz Min.: 0.0 Max.: 400.0 | 185 |
| d3-04 (297) | Jump Frequency Width | Sets the dead-band width around each selected prohibited frequency reference point. | Default: 1.0 Hz Min.: 0.0 Max.: 20.0 | 185 |

◆ d4: Frequency Reference Hold and Up/Down 2 Function

| No. (Addr. Hex) | Name | Description | Values | Page |
|--|--|---|---|---------------------|
| d4-01 (298) | Frequency Reference Hold Function Selection | 0: Disabled. Drive starts from zero when the power is switched on. 1: Enabled. At power up, the drive starts the motor at the Hold frequency that was saved. | Default: 0 Range: 0, 1 | 186 |
| d4-03 (2AA)  | Frequency Reference Bias Step (Up/Down 2) | Sets the bias added to the frequency reference when the Up 2 and Down 2 digital inputs are enabled (H1-□□ = 75, 76). | Default: 0.00 Hz Min.: 0.00 Max.: 99.99 | 187 |
| d4-04 (2AB)  | Frequency Reference Bias Accel/Decel (Up/Down 2) | 0: Use selected accel/decel time. 1: Use accel/decel time 4 (C1-07 and C1-08). Note: The functionality of setting 1 is only accessible via MEMOBUS/Modbus communication. | Default: 0 Range: 0, 1 | 188 |

| No. (Addr. Hex) | Name | Description | Values | Page |
|---|---|---|---|---------------------|
| d4-05 (2AC)  | Frequency Reference Bias Operation Mode Selection (Up/Down 2) | 0: Bias value is held if no input Up 2 or Down 2 is active. 1: When the Up 2 reference and Down 2 reference are both on or both off, the applied bias becomes 0. The specified accel/decel times are used for acceleration or deceleration. | Default: 0 Range: 0, 1 | 188 |
| d4-06 (2AD) | Frequency Reference Bias (Up/Down 2) | The Up/Down 2 bias value is saved in d4-06 when the frequency reference is not input by the digital operator. Set as a percentage of the maximum output frequency. | Default: 0.0% Min.: -99.9 Max.: 100.0 | 189 |
| d4-07 (2AE)  | Analog Frequency Reference Fluctuation Limit (Up/Down 2) | Limits how much the frequency reference is allowed to change while an input terminal set for Up 2 or Down 2 is enabled. If the frequency reference changes for more than the set value, then the bias value is held and the drive accelerates or decelerates to the frequency reference. Set as a percentage of the maximum output frequency. | Default: 0.01% Min.: 0.01 Max.: 100.0 | 189 |
| d4-08 (2AF)  | Frequency Reference Bias Upper Limit (Up/Down 2) | Sets the upper limit for the bias and the value that can be saved in d4-06. Set as a percentage of the maximum output frequency. | Default: 1.0% Min.: 0.0 Max.: 100.0 | 189 |
| d4-09 (2B0)  | Frequency Reference Bias Lower Limit (Up/Down 2) | Sets the lower limit for the bias and the value that can be saved in d4-06. Set as a percentage of the maximum output frequency. | Default: 0.0% Min.: -99.9 Max.: 0.0 | 189 |
| d4-10 (2B6) | Up/Down Frequency Reference Limit Selection | 0: The lower limit is determined by d2-02 or an analog input. 1: The lower limit is determined by d2-02. | Default: 0 Range: 0, 1 | 189 |

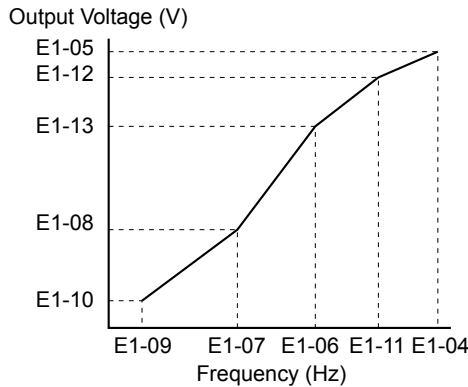
◆ d6: Field Weakening and Field Forcing

| No. (Addr. Hex.) | Name | Description | Values | Page |
|------------------|---------------------------------|--|---|---------------------|
| d6-01 (2A0) | Field Weakening Level | Sets the drive output voltage for the Field Weakening function as a percentage of the maximum output voltage. Enabled when a multi-function input is set for Field Weakening (H1-□□ = 63). | Default: 80% Min.: 0 Max.: 100 | 190 |
| d6-02 (2A1) | Field Weakening Frequency Limit | Sets the lower limit of the frequency range where Field Weakening control is valid. The Field Weakening command is valid only at frequencies above this setting and only when the output frequency matches the frequency reference (speed agree). | Default: 0.0 Hz Min.: 0.0 Max.: 400.0 | 190 |

B.6 E: Motor Parameters

◆ E1: V/f Pattern

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|-----------------------------------|---|--|------|
| E1-01 (300) | Input Voltage Setting | This parameter must be set to the power supply voltage. WARNING! Electrical Shock Hazard. Drive input voltage (not motor voltage) must be set in E1-01 for the protective features of the drive to function properly. Failure to do so may result in equipment damage and/or death or personal injury. | Default: 230 V <1> Min.: 155 Max.: 255 <1> | 191 |
| E1-03 (302) | V/f Pattern Selection | 0: 50 Hz, Constant torque 1 1: 60 Hz, Constant torque 2 2: 60 Hz, Constant torque 3 (50 Hz base) 3: 72 Hz, Constant torque 4 (60 Hz base) 4: 50 Hz, Variable torque 1 5: 50 Hz, Variable torque 2 6: 60 Hz, Variable torque 1 7: 60 Hz, Variable torque 2 8: 50 Hz, High starting torque 1 9: 50 Hz, High starting torque 2 A: 60 Hz, High starting torque 3 B: 60 Hz, High starting torque 4 C: 90 Hz (60 Hz base) D: 120 Hz (60 Hz base) E: 180 Hz (60 Hz base) F: Custom V/f, E1-04 through E1-13 settings define the V/f pattern | Default: F <2> Range: 0 to 9; A to FF | 191 |
| E1-04 (303) | Maximum Output Frequency | These parameters are only applicable when E1-03 is set to F. To set linear V/f characteristics, set the same values for E1-07 and E1-09. In this case, the setting for E1-08 will be disregarded. Ensure that the four frequencies are set according to these rules: $E1-09 \leq E1-07 < E1-06 \leq E1-11 \leq E1-04$ | Default: 60.0 Hz Min.: 40.0 Max.: 400.0 | 194 |
| E1-05 (304) | Maximum Voltage | | Default: 575 V <1> Min.: 0.0 Max.: 255.0 | 194 |
| E1-06 (305) | Base Frequency | | Default: 60.0 Hz Min.: 0.0 Max.: E1-04 | 194 |
| E1-07 (306) | Middle Output Frequency | | Default: 3.0 Hz Min.: 0.0 Max.: E1-04 | 194 |
| E1-08 (307) | Middle Output Frequency Voltage | | Default: 15.0 V <1> Min.: 0.0 V Max.: 255.0 V | 194 |
| E1-09 (308) | Minimum Output Frequency | | Default: 1.5 Hz Min.: 0.0 Max.: E1-04 | 194 |
| E1-10 (309) | Minimum Output Frequency Voltage | | Default: 9.0 V <1> Min.: 0.0 V Max.: 255.0 V | 194 |
| E1-11 (30A) <4> | Middle Output Frequency 2 | | Default: 0.0 Hz Min.: 0.0 Max.: E1-04 | 194 |
| E1-12 (30B) <4> | Middle Output Frequency Voltage 2 | | Default: 0.0 V Min.: 0.0 Max.: 255.0 V <1> | 194 |
| E1-13 (30C) | Base Voltage | | Default: 0.0 V <3> Min.: 0.0 Max.: 255.0 V <1> | 194 |



- <1> Values shown are specific to 200 V class drives. Double the value for 400 V class drives. Multiply the value by 2.875 for 600 V class drives.
- <2> Parameter setting value is not reset to the default value when the drive is initialized.
- <3> When Auto-Tuning is performed, E1-13 and E1-05 will be set to the same value.
- <4> Parameter ignored when E1-11 (Motor 1 Mid Output Frequency 2) and E1-12 (Motor 1 Mid Output Frequency Voltage 2) are set to 0.0.

◆ E2: Motor 1 Parameters





| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|---|---|---|------|
| E2-01 (30E) | Motor Rated Current | Sets the motor nameplate full load current in amps. Automatically set during Auto-Tuning. | Default: <1> Min.: 10% of drive rated current Max.: 200% of drive rated current <2> | 195 |
| E2-02 (30F) | Motor Rated Slip | Sets the motor rated slip. Automatically set during Auto-Tuning. | Default: <1> Min.: 0.00 Hz Max.: 20.00 Hz | 195 |
| E2-03 (310) | Motor No-Load Current | Sets the no-load current for the motor. Automatically set during Auto-Tuning. | Default: <1> Min.: 0 A Max.: E2-01 <2> | 196 |
| E2-04 (311) | Number of Motor Poles | Sets the number of motor poles. Automatically set during Auto-Tuning. | Default: 4 Min.: 2 Max.: 48 | 196 |
| E2-05 (312) | Motor Line-to-Line Resistance | Sets the phase-to-phase motor resistance. Automatically set during Auto-Tuning. | Default: <1> Min.: 0.000 Ω Max.: 65.000 Ω | 196 |
| E2-06 (313) | Motor Leakage Inductance | Sets the voltage drop due to motor leakage inductance as a percentage of motor rated voltage. Automatically set during Auto-Tuning. | Default: <1> Min.: 0.0% Max.: 40.0% | 196 |
| E2-10 (317) | Motor Iron Loss for Torque Compensation | Sets the motor iron loss. | Default: <1> Min.: 0 W Max.: 65535 W | 196 |
| E2-11 (318) | Motor Rated Power | Sets the motor rated power in kilowatts (1 HP = 0.746 kW). Automatically set during Auto-Tuning. | Default: <1> Min.: 0.00 kW Max.: 650.00 kW | 196 |

<1> Default setting is dependent on parameter o2-04, Drive Model Selection.

<2> The number of decimal places in the parameter value depends on the drive model 1. This value has two decimal places (0.01 A) if the drive is set for a maximum applicable motor capacity up to and including 11 kW, and one decimal place (0.1 A) if the maximum applicable motor capacity is higher than 11 kW.

B.7 F: Communication Options

◆ F4: Analog Monitor Card (AO-A3)

| No. (Addr. Hex) | Name | Description | Values | Page |
|--|-------------------------------|---|--|------|
| F4-01 (391) | Terminal V1 Monitor Selection | Sets the monitor signal for output from terminal V1. Set this parameter to the last three digits of the desired U□-□□ monitor. Some U parameters are available only in certain control modes. | Default: 102 Range: 000 to 999 | 198 |
| F4-02 (392)  | Terminal V1 Monitor Gain | Sets the gain for voltage output via terminal V1. | Default: 100.0% Min.: -999.9 Max.: 999.9 | 198 |
| F4-03 (393) | Terminal V2 Monitor Selection | Sets the monitor signal for output from terminal V2. Set this parameter to the last three digits of the desired U□-□□ monitor. Some U parameters are available only in certain control modes. | Default: 103 Range: 000 to 999 | 198 |
| F4-04 (394)  | Terminal V2 Monitor Gain | Sets the gain for voltage output via terminal V2. | Default: 50.0% Min.: -999.9 Max.: 999.9 | 198 |
| F4-05 (395)  | Terminal V1 Monitor Bias | Sets the amount of bias added to the voltage output via terminal V1. | Default: 0.0% Min.: -999.9 Max.: 999.9 | 198 |
| F4-06 (396)  | Terminal V2 Monitor Bias | Sets the amount of bias added to the voltage output via terminal V2. | Default: 0.0% Min.: -999.9 Max.: 999.9 | 198 |
| F4-07 (397) | Terminal V1 Signal Level | 0: 0 to 10 V 1: -10 to 10 V | Default: 0 Range: 0, 1 | 198 |
| F4-08 (398) | Terminal V2 Signal Level | 0: 0 to 10 V 1: -10 to 10 V | Default: 0 Range: 0, 1 | 198 |

◆ F6, F7: Communication Option Card

Parameters F6-01 through F6-03 and F6-06 through F6-08 are used for CC-Link, CANopen, DeviceNet, PROFIBUS-DP, and MECHATROLINK-II options. Other parameters in the F6 group are used for communication-protocol-specific settings. F7 parameters are used for EtherNet/IP, Modbus TCP/IP, and PROFINET options.

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|--|---|--|------|
| F6-01 (3A2) | Communications Error Operation Selection | 0: Ramp to stop. Decelerate to stop using the deceleration time in C1-02. 1: Coast to stop. 2: Fast Stop. Decelerate to stop using the deceleration time in C1-09. 3: Alarm only. 4: Alarm and Run at d1-04 </> 5: Alarm and Ramp to stop (automatic recovery) </> Note: Take proper safety measures, such as installing an emergency stop switch, when setting F6-01 to 3 or 4. | Default: 1 Range: 0 to 5 | 199 |
| F6-02 (3A3) | External Fault from Comm. Option Detection Selection | 0: Always detected. 1: Detection during run only. | Default: 0 Range: 0, 1 | 199 |
| F6-03 (3A4) | External Fault from Comm. Option Operation Selection | 0: Ramp to stop. Decelerate to stop using the deceleration time in C1-02. 1: Coast to stop. 2: Fast Stop. Decelerate to stop using the deceleration time in C1-09. 3: Alarm only. | Default: 1 Range: 0 to 3 | 200 |
| F6-04 (3A5) | bUS Error Detection Time | Sets the delay time for error detection if a bus error occurs. | Default: 2.0 s Min.: 0.0 Max.: 5.0 | 200 |
| F6-07 (3A8) | Multi-Step Speed Enable/Disable Selection when NefRef/ComRef is Selected | 0: Multi-step reference disabled (same as F7) 1: Multi-step reference enabled (same as V7) | Default: 0 Range: 0, 1 | 200 |

| No. (Addr. Hex) | Name | Description | Values | Page |
|------------------|--|--|---|------|
| F6-08 (36A) <v> | Reset Communication Parameters | 0: Communication-related parameters (F6-□□/□□) are not reset when the drive is initialized using A1-03. 1: Reset all communication-related parameters (F6-□□/□□) when the drive is initialized using A1-03. | Default: 0 Range: 0, 1 | 200 |
| F6-10 (3B6) | CC-Link Node Address | Sets the node address if a CC-Link option is installed. | Default: 0 Min.: 0 Max.: 64 | 200 |
| F6-11 (3B7) | CC-Link Communication Speed | 0: 156 Kbps 1: 625 Kbps 2: 2.5 Mbps 3: 5 Mbps 4: 10 Mbps | Default: 0 Range: 0 to 4 | 200 |
| F6-14 (3BB) | bUS Error Auto Reset | 0: Disabled 1: Enabled | Default: 0 Range: 0, 1 | 201 |
| F6-20 (36B) | MECHATROLINK Station Address | Sets the station address when the MECHATROLINK option has been installed. | Default: 21 Min.: 20 <v> Max.: 3F | — |
| F6-21 (36C) | MECHATROLINK Frame Size | 0: 32 byte 1: 17 byte | Default: 0 Range: 0, 1 | — |
| F6-22 (36D) | MECHATROLINK Link Speed | 0: 10 Mbps 1: 4 Mbps | Default: 0 Range: 0, 1 | — |
| F6-23 (36E) | MECHATROLINK Monitor Selection (E) | Sets the MECHATROLINK-II monitor (E). | Default: 0 Min.: 0 Max.: FFFF | — |
| F6-24 (36F) | MECHATROLINK Monitor Selection (F) | Sets the MECHATROLINK-II monitor (F). | Default: 0 Min.: 0 Max.: FFFF | — |
| F6-25 (3C9) | Operation Selection at Watchdog Timer Error (E5) | 0: Ramp to stop. Decelerate using the deceleration time in C1-02. 1: Coast to stop 2: Fast stop. Decelerate using the deceleration time in C1-09. 3: Alarm only | Default: 1 Range: 0 to 3 | — |
| F6-26 (3CA) | MECHATROLINK bUS Errors Detected | Sets the number of option communication errors (bUS). | Default: 2 Min.: 2 Max.: 10 | — |
| F6-30 (3CB) | PROFIBUS-DP Node Address | Sets the node address. | Default: 0 Min.: 0 Max.: 125 | 202 |
| F6-31 (3CC) | PROFIBUS-DP Clear Mode Selection | 0: Resets drive operation with a Clear mode command. 1: Maintains the previous operation state when Clear mode command is given. | Default: 0 Range: 0, 1 | 202 |
| F6-32 (3CD) | PROFIBUS-DP Data Format Selection | 0: PPO Type 1: Conventional 2: PPO (w/bit 0) <v> 3: PPO Type (Auto Enter) <v> 4: Conventional (Auto Enter) <v> 5: PPO (w/bit0, Auto Enter) <v> | Default: 0 Range: 0 to 5 | 202 |
| F6-35 (3D0) | CANopen Node ID Selection | Sets the node address. | Default: 0 Min.: 0 Max.: 126 | 202 |
| F6-36 (3D1) | CANopen Communication Speed | 0: Auto-detection 1: 10 kbps 2: 20 kbps 3: 50 kbps 4: 125 kbps 5: 250 kbps 6: 500 kbps 7: 800 kbps 8: 1 Mbps | Default: 6 Range: 0 to 8 | 202 |
| F6-41 (03D6) <v> | CompoNet Communication Speed | Reserved. | — | — |
| F6-50 (3C1) | DeviceNet MAC Address | Selects the drive MAC address. | Default: 64 Min.: 0 Max.: 64 | 203 |

B.7 F: Communication Options

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------------------|-------------------------------------|---|---|------|
| F6-51 (3C2) | DeviceNet Communication Speed | 0: 125 kbps 1: 250 kbps 2: 500 kbps 3: Adjustable from network 4: Detect automatically | Default: 4 Range: 0 to 4 | 203 |
| F6-52 (3C3) | DeviceNet PCA Setting | Sets the format of the data set from the DeviceNet master to the drive. | Default: 21 Min.: 0 Max.: 255 | 203 |
| F6-53 (3C4) | DeviceNet PPA Setting | Sets the format of the data set from the drive to the DeviceNet master. | Default: 71 Min.: 0 Max.: 255 | 203 |
| F6-54 (3C5) | DeviceNet Idle Mode Fault Detection | 0: Enabled 1: Disabled, no fault detection 2: Vendor Specific </> 3: Forward </> 4: Reverse </> | Default: 0 Range: 0 to 4 | 203 |
| F6-55 (3C6) | DeviceNet Baud Rate Monitor | Verifies the baud rate running on the network. 0: 125 kbps 1: 250 kbps 2: 500 kbps | Default: 0 Range: 0 to 2 | 204 |
| F6-56 (3D7) | DeviceNet Speed Scaling | Sets the scaling factor for the speed monitor in DeviceNet. | Default: 0 Min.: -15 Max.: 15 | 204 |
| F6-57 (3D8) | DeviceNet Current Scaling | Sets the scaling factor for the output current monitor in DeviceNet. | Default: 0 Min.: -15 Max.: 15 | 204 |
| F6-58 (3D9) | DeviceNet Torque Scaling | Sets the scaling factor for the torque monitor in DeviceNet. | Default: 0 Min.: -15 Max.: 15 | 204 |
| F6-59 (3DA) | DeviceNet Power Scaling | Sets the scaling factor for the power monitor in DeviceNet. | Default: 0 Min.: -15 Max.: 15 | 204 |
| F6-60 (3DB) | DeviceNet Voltage Scaling | Sets the scaling factor for the voltage monitor in DeviceNet. | Default: 0 Min.: -15 Max.: 15 | 204 |
| F6-61 (3DC) | DeviceNet Time Scaling | Sets the scaling factor for the time monitor in DeviceNet. | Default: 0 Min.: -15 Max.: 15 | 204 |
| F6-62 (3DD) | DeviceNet Heartbeat Interval | Sets the heartbeat interval for DeviceNet communications. | Default: 0 Min.: 0 Max.: 10 | 204 |
| F6-63 (3DE) | DeviceNet Network MAC ID | Saves and monitors settings 0 to 63 of F6-50 (DeviceNet MAC Address). | Default: 63 Min.: 0 Max.: 63 | 204 |
| F6-64 to F6-71 (3DF to 3C8) | Reserved | Reserved for Dynamic I/O Assembly Parameters. | – | – |
| F6-72 (081B) </> | PowerLink Node Address | Reserved. | – | – |
| F6-75 (0B20) </> | P1-N2 Protocol Select | Selects the protocol for the SI-J3 option card. 1: N2 2: P1 | Default: 2 Range: 1, 2 | – |
| F6-76 (0B20) </> | P1-N2 Comm Fault | 0: Disabled 1: Enabled | Default: 1 Range: 0, 1 | – |
| F6-77 (0B22) </> | P1-N2 Comm Fault Time | Sets the length of time before clearing a communication fault. | Default: 2.0 s Min.: 0.0 Max.: 10.0 | – |
| F6-78 (0B23) </> | P1-N2 Node Address | Sets the network node address. | Default: 1 Range: 0 to 255 | – |

| No. (Addr. Hex) | Name | Description | Values | Page |
|------------------|----------------------------------|---|---|------|
| F6-79 (0B24) <F> | Baud Rate Select | Sets the baud rate for the P1 protocol. 2: 4800 3: 9600 | Default: 3 Range: 2, 3 | – |
| F7-01 (3E5) <F> | IP Address 1 | Sets the most significant octet of network static IP address. | Default: 192 Range: 0 to 255 | – |
| F7-02 (3E6) <F> | IP Address 2 | Sets the second most significant octet of network static IP address. | Default: 168 Range: 0 to 255 | – |
| F7-03 (3E7) <F> | IP Address 3 | Sets the third most significant octet of network static IP address. | Default: 1 Range: 0 to 255 | – |
| F7-04 (3E8) <F> | IP Address 4 | Sets the fourth most significant octet of network static IP address. | Default: 20 Range: 0 to 255 | – |
| F7-05 (3E9) | Subnet Mask 1 | Sets the most significant octet of network static Subnet Mask. | Default: 255 Range: 0 to 255 | – |
| F7-06 (3EA) | Subnet Mask 2 | Sets the second most significant octet of network static Subnet Mask. | Default: 255 Range: 0 to 255 | – |
| F7-07 (3EB) | Subnet Mask 3 | Sets the third most significant octet of network static Subnet Mask. | Default: 255 Range: 0 to 255 | – |
| F7-08 (3EC) | Subnet Mask 4 | Sets the fourth most significant octet of network static Subnet Mask. | Default: 0 Range: 0 to 255 | – |
| F7-09 (3ED) | Gateway Address 1 | Sets the most significant octet of network Gateway address. | Default: 192 Range: 0 to 255 | – |
| F7-10 (3EE) | Gateway Address 2 | Sets the second most significant octet of network Gateway address. | Default: 168 Range: 0 to 255 | – |
| F7-11 (3EF) | Gateway Address 3 | Sets the third most significant octet of network Gateway address. | Default: 1 Range: 0 to 255 | – |
| F7-12 (3E0) | Gateway Address 4 | Sets the fourth most significant octet of network Gateway address. | Default: 1 Range: 0 to 255 | – |
| F7-13 (3F1) | Address Mode at Startup | Select the option address setting method 0: Static <F> 1: BOOTP 2: DHCP | Default: 2 Range: 0 to 2 | – |
| F7-14 (3F2) | Duplex Mode Selection | Selects duplex mode setting. 0: Half duplex forced 1: Auto-negotiate duplex mode and communication speed 2: Full duplex forced 3: Half duplex forced (port 1)/Auto-negotiate duplex mode and communication speed (port 2) <F> 4: Half duplex forced (port 1)/Full duplex forced (port 2) <F> 5: Auto-negotiate duplex mode and communication speed (port 1)/Half duplex forced (port 2) <F> 6: Auto-negotiate duplex mode and communication speed (port 1)/Full duplex forced (port 2) <F> 7: Full duplex forced (port 1)/Half duplex forced (port 2) <F> 8: Full duplex forced (port 1)/Auto-negotiate duplex mode and communication speed (port 2) <F> | Default: 1 Range: 0 to 8 | – |
| F7-15 (3F3) | Communication Speed Selection | Sets the communication speed 10: 10 Mbps 100: 100 Mbps 101: 10 Mbps (port 1)/100 Mbps (port 2) <F> 102: 100 Mbps (port 1)/10 Mbps (port 2) <F> | Default: 10 Range: 10 to 102 | – |
| F7-16 (3F4) | Communication Loss Timeout | Sets the timeout value for communication loss detection in tenths of a second. A value of 0 disables the connection timeout. Example: An entered value of 100 represents 10.0 seconds. | Default: 0.0 s Min.: 0.0 Max.: 30.0 | – |
| F7-17 (3F5) | EtherNet/IP Speed Scaling Factor | Sets the scaling factor for the speed monitor in EtherNet/IP Class ID 2AH Object. | Default: 0 Min.: -15 Max.: 15 | – |

B.7 F: Communication Options

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------------------|------------------------------------|--|-------------------------------------|------|
| F7-18 (3F6) | EtherNet/IP Current Scaling Factor | Sets the scaling factor for the output current monitor in EtherNet/IP Class ID 2AH Object. | Default: 0 Min.: -15 Max.: 15 | – |
| F7-19 (3F7) | EtherNet/IP Torque Scaling Factor | Sets the scaling factor for the torque monitor in EtherNet/IP Class ID 2AH Object. | Default: 0 Min.: -15 Max.: 15 | – |
| F7-20 (3F8) | EtherNet/IP Power Scaling Factor | Sets the scaling factor for the power monitor in EtherNet/IP Class ID 2AH Object. | Default: 0 Min.: -15 Max.: 15 | – |
| F7-21 (3F9) | EtherNet/IP Voltage Scaling Factor | Sets the scaling factor for the voltage monitor in EtherNet/IP Class ID 2AH Object. | Default: 0 Min.: -15 Max.: 15 | – |
| F7-22 (3FA) | EtherNet/IP Time Scaling | Sets the scaling factor for the time monitor in EtherNet/IP Class ID 2AH Object. | Default: 0 Min.: -15 Max.: 15 | – |
| F7-23 to F7-32 (3FB to 374) | Dynamic Output Assembly Parameters | Parameters used in Output Assembly 116. Each parameter contains a MEMOBUS/Modbus address. The value received for Output Assembly 116 will be written to this corresponding MEMOBUS/Modbus address. A MEMOBUS/Modbus address value of 0 means that the value received for Output Assembly 116 will not be written to any MEMOBUS/Modbus register. | Default: 0 | – |
| F7-33 to F7-42 (375 to 37E) | Dynamic Input Assembly Parameters | Parameters used in Input Assembly 166. Each parameter contains a MEMOBUS/Modbus address. The value sent for Input Assembly 166 will be read from this corresponding MEMOBUS/Modbus address. A MEMOBUS/Modbus address value of 0 means that the value sent for Input Assembly 166 is not defined by the user, therefore the option default register value will be returned. | Default: 0 | – |
| F7-60 (0780) </> | PZD1 Write | Sets MEMOBUS/Modbus address for PZD1 Write (PPO Write). Values 0 to 2 enable the PZD1 Write as STW. | Default: 0 Min.: 0 Max.: FFFF | – |
| F7-61 (0781) </> | PZD2 Write | Sets MEMOBUS/Modbus address for PZD2 Write (PPO Write). Values 0 to 2 enable the PZD2 Write as HSW. | Default: 0 Min.: 0 Max.: FFFF | – |
| F7-62 (0782) </> | PZD3 Write | Sets MEMOBUS/Modbus address for PZD3 Write (PPO Write). Values 0 to 2 disable the PZD3 Write. | Default: 0 Min.: 0 Max.: FFFF | – |
| F7-63 (0783) </> | PZD4 Write | Sets MEMOBUS/Modbus address for PZD4 Write (PPO Write). Values 0 to 2 disable the PZD4 Write. | Default: 0 Min.: 0 Max.: FFFF | – |
| F7-64 (0784) </> | PZD5 Write | Sets MEMOBUS/Modbus address for PZD5 Write (PPO Write). Values 0 to 2 disable the PZD5 Write. | Default: 0 Min.: 0 Max.: FFFF | – |
| F7-65 (0785) </> | PZD6 Write | Sets MEMOBUS/Modbus address for PZD6 Write (PPO Write). Values 0 to 2 disable the PZD6 Write. | Default: 0 Min.: 0 Max.: FFFF | – |
| F7-66 (0786) </> | PZD7 Write | Sets MEMOBUS/Modbus address for PZD7 Write (PPO Write). Values 0 to 2 disable the PZD7 Write. | Default: 0 Min.: 0 Max.: FFFF | – |
| F7-67 (0787) </> | PZD8 Write | Sets MEMOBUS/Modbus address for PZD8 Write (PPO Write). Values 0 to 2 disable the PZD8 Write. | Default: 0 Min.: 0 Max.: FFFF | – |
| F7-68 (0788) </> | PZD9 Write | Sets MEMOBUS/Modbus address for PZD9 Write (PPO Write). Values 0 to 2 disable the PZD9 Write. | Default: 0 Min.: 0 Max.: FFFF | – |
| F7-69 (0789) </> | PZD10 Write | Sets MEMOBUS/Modbus address for PZD10 Write (PPO Write). Values 0 to 2 disable the PZD10 Write. | Default: 0 Min.: 0 Max.: FFFF | – |
| F7-70 (078A) </> | PZD1 Read | Sets MEMOBUS/Modbus address for PZD1 Read (PPO Read). Values 0 to 2 enable the PZD1 Read as ZSW. | Default: 0 Min.: 0 Max.: FFFF | – |
| F7-71 (078B) </> | PZD2 Read | Sets MEMOBUS/Modbus address for PZD2 Read (PPO Read). Values 0 to 2 enable the PZD2 Read as HIW. | Default: 0 Min.: 0 Max.: FFFF | – |

| No. (Addr. Hex) | Name | Description | Values | Page |
|------------------|------------|--|-------------------------------------|------|
| F7-72 (078C) <1> | PZD3 Read | Sets MEMOBUS/Modbus address for PZD3 Read (PPO Read). Values 0 to 2 disable the PZD3 Read. | Default: 0 Min.: 0 Max.: FFFF | – |
| F7-73 (078D) <2> | PZD4 Read | Sets MEMOBUS/Modbus address for PZD4 Read (PPO Read). Values 0 to 2 disable the PZD4 Read. | Default: 0 Min.: 0 Max.: FFFF | – |
| F7-74 (078E) <3> | PZD5 Read | Sets MEMOBUS/Modbus address for PZD5 Read (PPO Read). Values 0 to 2 disable the PZD5 Read. | Default: 0 Min.: 0 Max.: FFFF | – |
| F7-75 (078F) <4> | PZD6 Read | Sets MEMOBUS/Modbus address for PZD6 Read (PPO Read). Values 0 to 2 disable the PZD6 Read. | Default: 0 Min.: 0 Max.: FFFF | – |
| F7-76 (0790) <5> | PZD7 Read | Sets MEMOBUS/Modbus address for PZD7 Read (PPO Read). Values 0 to 2 disable the PZD7 Read. | Default: 0 Min.: 0 Max.: FFFF | – |
| F7-77 (0791) <6> | PZD8 Read | Sets MEMOBUS/Modbus address for PZD8 Read (PPO Read). Values 0 to 2 disable the PZD8 Read. | Default: 0 Min.: 0 Max.: FFFF | – |
| F7-78 (0792) <1> | PZD9 Read | Sets MEMOBUS/Modbus address for PZD9 Read (PPO Read). Values 0 to 2 disable the PZD9 Read. | Default: 0 Min.: 0 Max.: FFFF | – |
| F7-79 (0793) <2> | PZD10 Read | Sets MEMOBUS/Modbus address for PZD10 Read (PPO Read). Values 0 to 2 disable the PZD10 Read. | Default: 0 Min.: 0 Max.: FFFF | – |

- <1> Available in drive software versions PRG: 8503 and later.
- <2> Parameter setting value is not reset to the default value when the drive is initialized.
- <3> Available in drive software versions PRG: 8502 and later.
- <4> Values shown are for the MECHATROLINK-II option (SI-T3). Values for MECHATROLINK-III option (SI-ET3) are: Min: 03, Max.: EF
- <5> Cycle power for setting changes to take effect.
- <6> If F7-13 is set to 0, all IP addresses (F7-01 to F7-04) must be unique.

B.8 H Parameters: Multi-Function Terminals

H parameters assign functions to the multi-function input and output terminals.

◆ H1: Multi-Function Digital Inputs

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|---|---|--|------|
| H1-01 (438) | Multi-Function Digital Input Terminal S1 Function Selection | Assigns a function to the multi-function digital inputs. Refer to pages 454 to 456 for descriptions of setting values. Note: Set unused terminals to F. | Default: 40 (F) <1> Min.: 1 Max.: 9F | 205 |
| H1-02 (439) | Multi-Function Digital Input Terminal S2 Function Selection | Assigns a function to the multi-function digital inputs. Refer to pages 454 to 456 for descriptions of setting values. Note: Set unused terminals to F. | Default: 41 (F) <1> Min.: 1 Max.: 9F | 205 |
| H1-03 (400) | Multi-Function Digital Input Terminal S3 Function Selection | Assigns a function to the multi-function digital inputs. Refer to pages 454 to 456 for descriptions of setting values. Note: Set unused terminals to F. | Default: 24 Min.: 0 Max.: 9F | 205 |
| H1-04 (401) | Multi-Function Digital Input Terminal S4 Function Selection | Assigns a function to the multi-function digital inputs. Refer to pages 454 to 456 for descriptions of setting values. Note: Set unused terminals to F. | Default: 14 Min.: 0 Max.: 9F | 205 |
| H1-05 (402) | Multi-Function Digital Input Terminal S5 Function Selection | Assigns a function to the multi-function digital inputs. Refer to pages 454 to 456 for descriptions of setting values. Note: Set unused terminals to F. | Default: 3 (0) <1> Min.: 0 Max.: 9F | 205 |
| H1-06 (403) | Multi-Function Digital Input Terminal S6 Function Selection | Assigns a function to the multi-function digital inputs. Refer to pages 454 to 456 for descriptions of setting values. Note: Set unused terminals to F. | Default: 4 (3) <1> Min.: 0 Max.: 9F | 205 |
| H1-07 (404) | Multi-Function Digital Input Terminal S7 Function Selection | Assigns a function to the multi-function digital inputs. Refer to pages 454 to 456 for descriptions of setting values. Note: Set unused terminals to F. | Default: 6 (4) <1> Min.: 0 Max.: 9F | 205 |
| H1-08 (405) | Multi-Function Digital Input Terminal S8 Function Selection | Assigns a function to the multi-function digital inputs. Refer to pages 454 to 456 for descriptions of setting values. Note: Set unused terminals to F. | Default: 8 (6) <1> Min.: 0 Max.: 9F | 205 |

<1> Value in parenthesis is the default setting when a 3-Wire initialization is performed (A1-03 = 3330).

| H1 Multi-Function Digital Input Selections | | | |
|--|----------------------------------|---|------|
| H1-□□ Setting | Function | Description | Page |
| 0 | 3-Wire sequence | Closed: Reverse rotation (only if the drive is set up for 3-Wire sequence) Terminals S1 and S2 are automatically set up for the Run command and Stop command. | 206 |
| 1 | LOCAL/REMOTE selection | Open: REMOTE (parameter settings determine the source of the frequency Reference 1 or 2 (b1-01, b1-02 or b1-15, b1-16) Closed: LOCAL, Frequency reference and Run command are input from the digital operator. | 206 |
| 2 | External reference 1/2 selection | Open: Run command and frequency reference source 1 (determined by b1-01 and b1-02) Closed: Run command and frequency reference source 2 (determined by b1-15 and b1-16) | 207 |
| 3 | Multi-Step Speed Reference 1 | When input terminals are set to Multi-Step Speed References 1 through 3, switching combinations of those terminals will create a multi-step speed sequence using the frequency references set in d1-01 through d1-08. | 207 |
| 4 | Multi-Step Speed Reference 2 | When input terminals are set to Multi-Step Speed References 1 through 3, switching combinations of those terminals will create a multi-step speed sequence using the frequency references set in d1-01 through d1-08. | 207 |
| 5 | Multi-Step Speed Reference 3 | When input terminals are set to Multi-Step Speed References 1 through 3, switching combinations of those terminals will create a multi-step speed sequence using the frequency references set in d1-01 through d1-08. | 207 |
| 6 | Jog reference selection | Closed: Jog frequency reference (d1-17) selected. Jog has priority over all other reference sources. | 207 |
| 7 | Accel/decel time selection 1 | Used to switch between accel/decel time 1 (set in C1-01, C1-02) and accel/decel time 2 (set in C1-03, C1-04). | 207 |
| 8 | Baseblock command (N.O.) | Closed: No drive output | 207 |

| H1 Multi-Function Digital Input Selections | | | |
|--|---------------------------------|--|------|
| H1-□□ Setting | Function | Description | Page |
| 9 | Baseblock command (N.C.) | Open: No drive output | 207 |
| A | Accel/decel ramp hold | Open: Accel/decel is not held Closed: The drive pauses during acceleration or deceleration and maintains the output frequency. | 207 |
| B | Drive overheat alarm (oH2) | Closed: An external device has triggered an oH2 alarm. Sets Drive Overheat Pre-alarm Multi-Function Digital Output 20h. | 208 |
| C | Analog terminal input selection | Open: Function assigned by H3-14 is disabled. Closed: Function assigned by H3-14 is enabled. | 208 |
| F | Through mode | Select this setting when using the terminal in a pass-through mode. The terminal does not trigger a drive function but can be used as digital input for the controller the drive is connected to. | 208 |
| 10 | Up command | The drive accelerates when the Up command terminal closes, and decelerates when the Down command closes. When both terminals are closed or both are open, the drive holds the frequency reference. The Up and Down commands must always be used in conjunction with one another. | 208 |
| 11 | Down command | The drive accelerates when the Up command terminal closes, and decelerates when the Down command closes. When both terminals are closed or both are open, the drive holds the frequency reference. The Up and Down commands must always be used in conjunction with one another. | 208 |
| 12 | Forward Jog | Closed: Runs forward at the Jog frequency d1-17. | 209 |
| 13 | Reverse Jog | Closed: Runs reverse at the Jog frequency d1-17. | 209 |
| 14 | Fault reset | Closed: Resets faults if the cause is cleared and the Run command is removed. | 209 |
| 15 | Fast Stop (N.O.) | Closed: Decelerates at the Fast Stop time set to C1-09. | 209 |
| 17 | Fast Stop (N.C.) | Open: Decelerates to stop at the Fast Stop time set to C1-09. | 209 |
| 18 | Timer function input | Triggers the timer set up by parameters b4-01 and b4-02. Must be set in conjunction with the timer function output (H2-□□ = 12). | 210 |
| 19 | PID disable | Open: PID control enabled Closed: PID control disabled | 210 |
| 1A <-> | Accel/decel time selection 2 | Used in conjunction with an input terminal set for “Accel/decel time selection 1” (H1-□□ = 7), and allows the drive to switch between accel/decel times 3 and 4. | 210 |
| 1B | Program lockout | Open: Parameters cannot be edited (except for U1-01 if the reference source is assigned to the digital operator). Closed: Parameters can be edited and saved. | 210 |
| 1E | Reference sample hold | Closed: Samples the analog frequency reference and operates the drive at that speed. | 210 |
| 20 to 2F | External fault | 20: N.O., Always detected, ramp to stop 21: N.C., Always detected, ramp to stop 22: N.O., During run, ramp to stop 23: N.C., During run, ramp to stop 24: N.O., Always detected, coast to stop 25: N.C., Always detected, coast to stop 26: N.O., During run, coast to stop 27: N.C., During run, coast to stop 28: N.O., Always detected, Fast Stop 29: N.C., Always detected, Fast Stop 2A: N.O., During run, Fast Stop 2B: N.C., During run, Fast Stop 2C: N.O., Always detected, alarm only (continue running) 2D: N.C., Always detected, alarm only (continue running) 2E: N.O., During run, alarm only (continue running) 2F: N.C., During run, alarm only (continue running) | 211 |
| 30 | PID integral reset | Closed: Resets the PID control integral value. | 211 |
| 31 | PID integral hold | Open: Performs integral operation. Closed: Maintains the current PID control integral value. | 211 |
| 32 | Multi-Step Speed Reference 4 | Used in combination with input terminals set to Multi-Step Speed Reference 1, 2, and 3. Use parameters d1-09 to d1-16 to set reference values. | 211 |
| 34 | PID soft starter cancel | Open: PID soft starter is enabled. Closed: Disables the PID soft starter b5-17. | 211 |
| 35 | PID input level selection | Closed: Inverts the PID input signal. | 211 |

B.8 H Parameters: Multi-Function Terminals

| H1 Multi-Function Digital Input Selections | | | |
|--|---------------------------------------|---|------|
| H1-□□ Setting | Function | Description | Page |
| 40 | Forward run command (2-Wire sequence) | Open: Stop Closed: Forward run Note: Cannot be set together with settings 42 or 43. | 212 |
| 41 | Reverse run command (2-Wire sequence) | Open: Stop Closed: Reverse run Note: Cannot be set together with settings 42 or 43. | 212 |
| 42 | Run command (2-Wire sequence 2) | Open: Stop Closed: Run Note: Cannot be set together with settings 40 or 41. | 212 |
| 43 | FWD/REV command (2-Wire sequence 2) | Open: Forward Closed: Reverse Note: Determines motor direction, but does not issue a Run command. Cannot be set together with settings 40 or 41. | 212 |
| 47 | Node setup | Closed: Node setup for SI-S3 enabled. | 212 |
| 51 | Sequence Timer Disable | Closed: Drive ignores sequence timers and runs normally (based on b1-02/b1-16 source). | 212 |
| 52 | Sequence Timer Cancel | Closed: When the input changes from open to closed, the currently active sequence timer is disabled. Operation will resume with the next scheduled sequence timer. Cycling the Run command after the current sequence timer has been canceled will re-enable the sequence timer. | 212 |
| 60 | DC Injection Braking command | Closed: Triggers DC Injection Braking. | 212 |
| 61 | External Speed Search command 1 | Closed: Activates Current Detection Speed Search from the maximum output frequency (E1-04). | 212 |
| 62 | External Speed Search command 2 | Closed: Activates Current Detection Speed Search from the frequency reference. | 212 |
| 63 | Field weakening | Closed: The drive performs Field Weakening control as set for d6-01 and d6-02. | 213 |
| 65 | KEB Ride-Thru 1 (N.C.) | Open: KEB Ride-Thru 1 enabled. | 213 |
| 66 | KEB Ride-Thru 1 (N.O.) | Closed: KEB Ride-Thru 1 enabled. | 213 |
| 67 | Communications test mode | Tests the MEMOBUS/Modbus RS-422/RS-485 interface. Displays "PASS" if the test completes successfully. | 213 |
| 68 | High Slip Braking (HSB) | Closed: Activates High Slip Braking to stop the drive during a Run command. | 213 |
| 6A | Drive enable | Open: Drive disabled. If this input is opened during run, the drive will stop as specified by b1-03. Closed: Ready for operation. | 213 |
| 75 | Up 2 command | Used to control the bias added to the frequency reference by the Up/Down 2 function. The Up 2 and Down 2 commands must always be used in conjunction with one another. | 213 |
| 76 | Down 2 command | Used to control the bias added to the frequency reference by the Up/Down 2 function. The Up 2 and Down 2 commands must always be used in conjunction with one another. | 213 |
| 7A | KEB Ride-Thru 2 (N.C.) | Open: KEB Ride-Thru 2 enabled. Drive disregards L2-29 and performs Single Drive KEB Ride-Thru 2. | 214 |
| 7B | KEB Ride-Thru 2 (N.O.) | Closed: KEB Ride-Thru 2 enabled. Drive disregards L2-29 and performs Single Drive KEB Ride-Thru 2. | 214 |
| A8 | Secondary PI Disable (N.O.) | Closed: Disables the secondary PI controller. Output behavior depends on the setting of S3-12. | 214 |
| A9 | Secondary PI Disable (N.C.) | Closed: Enables the secondary PI controller. Output behavior depends on the setting of S3-12 when open. | 214 |
| AA | Secondary PI Inverse Operation | Closed: Changes the sign of the secondary PI controller input (reverse acting PI control). | 214 |
| AB | Secondary PI Integral Reset | Closed: Resets the secondary PI controller integral value. | 214 |
| AC | Secondary PI Integral Hold | Closed: Locks the value of the secondary PI controller integral value. | 214 |
| AD | Select Secondary PI Parameters | Closed: Uses the secondary PI controller Proportional and Integral adjustments (S3-06 and S3-07) instead of the primary PI controller Proportional and Integral adjustments (b5-02 and b5-03). Only valid when S3-01 = 0 (secondary PI controller disabled). Note: This multi-function input has no effect on the secondary PI controller. It is only used for the primary PI controller (b5-□□). | 215 |
| AF | Emergency Override Forward Run | Closed: Run the drive forward using the speed set in S6-02. | 215 |
| B0 | Emergency Override Reverse Run | Closed: Run the drive in reverse using the speed set in S6-02. | 215 |

<1> Available in drive software versions PRG: 8502 and earlier.

◆ H2: Multi-Function Digital Outputs

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|---|---|-------------------------------|------|
| H2-01 (40B) | Terminal M1-M2 function selection (relay) | Refer to H2 Multi-Function Digital Output Settings on pages 457 to 458 for descriptions of setting values. | Default: 0 Range: 0 to 192 | 215 |
| H2-02 (40C) | Terminal M3-M4 function selection (relay) | | Default: 1 Range: 0 to 192 | 215 |
| H2-03 (40D) | Terminal MD-ME-MF Function Selection | | Default: 2 Range: 0 to 192 | 215 |
| H2-06 (437) | Watt Hour Output Unit Selection | Outputs a 200 ms pulse signal when the watt-hour counter increases by the units selected. 0: 0.1 kWh units 1: 1 kWh units 2: 10 kWh units 3: 100 kWh units 4: 1000 kWh units | Default: 0 Range: 0 to 4 | 224 |

| H2 Multi-Function Digital Output Settings | | | |
|---|----------------------------|--|------|
| H2-□□ Setting | Function | Description | Page |
| 0 | During run | Closed: A Run command is active or voltage is output. | 216 |
| 1 | Zero speed | Open: Output frequency is above the minimum output frequency set in E1-09. Closed: Output frequency is below the minimum output frequency set in E1-09. | 216 |
| 2 | Speed agree 1 | Closed: Output frequency equals the speed reference (plus or minus the hysteresis set to L4-02). | 216 |
| 3 | User-set speed agree 1 | Closed: Output frequency and speed reference equal L4-01 (plus or minus the hysteresis set to L4-02). | 217 |
| 4 | Frequency detection 1 | Closed: Output frequency is less than or equal to the value in L4-01 with hysteresis determined by L4-02. | 217 |
| 5 | Frequency detection 2 | Closed: Output frequency is greater than or equal to the value in L4-01 with hysteresis determined by L4-02. | 218 |
| 6 | Drive ready | Closed: Power up is complete and the drive is ready to accept a Run command. | 218 |
| 7 | DC bus undervoltage | Closed: DC bus voltage is below the U _v trip level set in L2-05. | 218 |
| 8 | During baseblock (N.O.) | Closed: Drive has entered the baseblock state (no output voltage). | 219 |
| 9 | Frequency reference source | Open: External Reference 1 or 2 supplies the frequency reference (set in b1-01 or b1-15). Closed: Digital operator supplies the frequency reference. | 219 |
| A | Run command source | Open: External Reference 1 or 2 supplies the Run command (set in b1-02 or b1-16). Closed: Digital operator supplies the Run command. | 219 |
| B | Torque detection 1 (N.O.) | Closed: An overtorque or undertorque situation has been detected. | 219 |
| C | Frequency reference loss | Closed: Analog frequency reference has been lost. Frequency reference loss is detected when the frequency reference drops below 10% of the reference within 400 ms. | 219 |
| D | Braking resistor fault | Closed: Braking resistor or transistor is overheated or faulted out. | 219 |
| E | Fault | Closed: Fault occurred. | 219 |
| F | Through mode | Set this value when using the terminal in the pass-through mode. | 219 |
| 10 | Minor fault | Closed: An alarm has been triggered, or the IGBTs have reached 90% of their expected life span. | 219 |
| 11 | Fault reset command active | Closed: A command has been entered to clear a fault via the input terminals or from the serial network. | 219 |
| 12 | Timer output | Closed: Timer output. | 220 |
| 13 | Speed agree 2 | Closed: When drive output frequency equals the frequency reference ±L4-04. | 220 |
| 14 | User-set speed agree 2 | Closed: When the drive output frequency is equal to the value in L4-03 ±L4-04. | 220 |
| 15 | Frequency detection 3 | Closed: When the drive output frequency is less than or equal to the value in L4-03 ±L4-04. | 221 |
| 16 | Frequency detection 4 | Closed: When the output frequency is greater than or equal to the value in L4-03 ±L4-04. | 221 |
| 17 | Torque detection 1 (N.C.) | Open: Overtorque or undertorque has been detected. | 219 |
| 18 | Torque detection 2 (N.O.) | Closed: Overtorque or undertorque has been detected. | |
| 19 | Torque detection 2 (N.C.) | Open: Overtorque or undertorque has been detected. | 219 |
| 1A | During reverse | Closed: Drive is running in the reverse direction. | 221 |
| 1B | During baseblock (N.C.) | Open: Drive has entered the baseblock state (no output voltage). | 222 |







B.8 H Parameters: Multi-Function Terminals

| H2 Multi-Function Digital Output Settings | | | |
|---|--------------------------------------|--|------|
| H2-□□ Setting | Function | Description | Page |
| 1E | Restart enabled | Closed: An automatic restart is performed | 222 |
| 1F | Motor overload alarm (oL1) | Closed: oL1 is at 90% of its trip point or greater. An oH3 situation also triggers this alarm. | 222 |
| 20 | Drive overheat pre-alarm (oH) | Closed: The heatsink temperature exceeds the L8-02 level (while L8-03 = 3 or 4), or an external device has triggered an oH2 alarm via multi-function input H1-□□ = B. | 222 |
| 22 | Mechanical weakening detection | Closed: Mechanical weakening detected. | 222 |
| 2F | Maintenance period | Closed: Cooling fan, electrolytic capacitors, IGBTs, or the soft charge bypass relay may require maintenance. | 222 |
| 37 | During frequency output | Open: Either the drive has stopped or baseblock, DC Injection Braking, or Initial Excitation is being performed. Closed: Drive is running the motor (not in a baseblock state and DC Injection is not being performed). | 222 |
| 38 | Drive enabled | Closed: Multi-function input set for "Drive enable" is closed (H1-□□ = 6A) | 223 |
| 39 | Watt hour pulse output | Output units are determined by H2-06. Outputs a pulse every 200 ms to indicate the kWh count. | 223 |
| 3C | LOCAL/REMOTE status | Open: REMOTE Closed: LOCAL | 223 |
| 3D | During speed search | Closed: Speed Search is being executed. | 223 |
| 3E | PID feedback low | Closed: PID feedback level is too low. | 223 |
| 3F | PID feedback high | Closed: The PID feedback level is too high. | 223 |
| 4A | During KEB Ride-Thru | Closed: KEB Ride-Thru is being performed. | 223 |
| 4C | During fast stop | Closed: A Fast Stop command has been entered from the operator or input terminals. | 223 |
| 4D | oH Pre-alarm time limit | Closed: An oH pre-alarm is present after 10 output frequency reduction cycles have passed (L8-03 = 4). | 223 |
| 4E | Braking transistor fault (rr) | Closed: The built-in dynamic braking transistor failed. | 223 |
| 4F | Braking resistor overheat (oH) | Closed: The dynamic braking resistor has overheated. | 223 |
| 50 | Waiting to Run | Closed: b1-11 Timer is active. | 223 |
| 51 | Sequence timer 1 | Closed: Sequence timer 1 is active. | 223 |
| 52 | Sequence timer 2 | Closed: Sequence timer 2 is active. | 223 |
| 53 | Sequence timer 3 | Closed: Sequence timer 3 is active. | 223 |
| 54 | Sequence timer 4 | Closed: Sequence timer 4 is active. | 223 |
| 58 | Underload detection | Closed: Underload is detected. | 223 |
| 60 | Internal cooling fan alarm | Closed: Internal cooling fan alarm | 224 |
| 71 | Secondary PI Feedback Low | Closed: PI2 feedback level is too low. | 224 |
| 72 | Secondary PI Feedback High | Closed: The PI2 feedback level is too high. | 224 |
| 89 <1> | Output I Lim | Closed: Drive output speed is being limited due to the output current limit or due the single-phase foldback regulator. | 224 |
| 100 to 189 | Function 0 to 89 with inverse output | Inverts the output switching of the multi-function output functions. Set the last two digits of 1□□ to reverse the output signal of that specific function. | 224 |

<1> Available in drive software versions PRG: 8503 and later.

◆ H3: Multi-Function Analog Inputs





| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|------------------------------------|--|------------------------------|------|
| H3-01 (410) | Terminal A1 Signal Level Selection | 0: 0 to 10 V 1: -10 to 10 V 2: 4 to 20 mA 3: 0 to 20 mA Note: Use Jumper S1 to set input terminal A1 for a current or voltage input signal. | Default: 0 Range: 0 to 3 | 225 |
| H3-02 (434) | Terminal A1 Function Selection | Sets the function of terminal A1. | Default: 0 Range: 0 to 26 | 225 |

| No. (Addr. Hex) | Name | Description | Values | Page |
|---|--|---|--|---------------------|
| H3-03 (411)  | Terminal A1 Gain Setting | Sets the level of the input value selected in H3-02 when 10 V is input at terminal A1. | Default: 100.0% Min.: -999.9 Max.: 999.9 | 225 |
| H3-04 (412)  | Terminal A1 Bias Setting | Sets the level of the input value selected in H3-02 when 0 V is input at terminal A1. | Default: 0.0% Min.: -999.9 Max.: 999.9 | 225 |
| H3-05 (413) | Terminal A3 Signal Level Selection | 0: 0 to 10 V 1: -10 to 10 V 2: 4 to 20 mA 3: 0 to 20 mA Note: Use Jumper S1 to set input terminal A3 for a current or voltage input signal. | Default: 0 Range: 0 to 3 | 226 |
| H3-06 (414) | Terminal A3 Function Selection | Sets the function of terminal A3. | Default: 2 Range: 0 to 26 | 226 |
| H3-07 (415)  | Terminal A3 Gain Setting | Sets the level of the input value selected in H3-06 when 10 V is input at terminal A3. | Default: 100.0% Min.: -999.9 Max.: 999.9 | 226 |
| H3-08 (416)  | Terminal A3 Bias Setting | Sets the level of the input value selected in H3-06 when 0 V is input at terminal A3. | Default: 0.0% Min.: -999.9 Max.: 999.9 | 226 |
| H3-09 (417) | Terminal A2 Signal Level Selection | 0: 0 to 10 V 1: -10 to 10 V 2: 4 to 20 mA 3: 0 to 20 mA Note: Use Jumper S1 to set input terminal A2 for a current or voltage input signal. | Default: 2 Range: 0 to 3 | 226 |
| H3-10 (418) | Terminal A2 Function Selection | Sets the function of terminal A2. | Default: 0 Range: 0 to 26 | 227 |
| H3-11 (419)  | Terminal A2 Gain Setting | Sets the level of the input value selected in H3-10 when 10 V (20 mA) is input at terminal A2. | Default: 100.0% Min.: -999.9 Max.: 999.9 | 227 |
| H3-12 (41A)  | Terminal A2 Bias Setting | Sets the level of the input value selected in H3-10 when 0 V (0 or 4 mA) is input at terminal A2. | Default: 0.0% Min.: -999.9 Max.: 999.9 | 227 |
| H3-13 (41B) | Analog Input Filter Time Constant | Sets a primary delay filter time constant for terminals A1, A2, and A3. Used for noise filtering. | Default: 0.03 s Min.: 0.00 Max.: 2.00 | 227 |
| H3-14 (41C) | Analog Input Terminal Enable Selection | Determines which analog input terminals will be enabled when a digital input programmed for “Analog input enable” (H1-□□ = C) is activated. 1: Terminal A1 only 2: Terminal A2 only 3: Terminals A1 and A2 only 4: Terminal A3 only 5: Terminals A1 and A3 6: Terminals A2 and A3 7: All terminals enabled | Default: 7 Range: 1 to 7 | 227 |
| H3-16 (2F0) | Terminal A1 Offset | Adds an offset when the analog signal to terminal A1 is at 0 V. | Default: 0 Min.: -500 Max.: 500 | 227 |
| H3-17 (2F1) | Terminal A2 Offset | Adds an offset when the analog signal to terminal A2 is at 0 V. | Default: 0 Min.: -500 Max.: 500 | 227 |
| H3-18 (2F2) | Terminal A3 Offset | Adds an offset when the analog signal to terminal A3 is at 0 V. | Default: 0 Min.: -500 Max.: 500 | 227 |

B.8 H Parameters: Multi-Function Terminals

| H3 Multi-Function Analog Input Settings | | | |
|---|--|---|------|
| H3-□□ Setting | Function | Description | Page |
| 0 | Frequency bias | 10 V = E1-04 (maximum output frequency) | 228 |
| 1 | Frequency gain | 0 to 10 V signal allows a setting of 0 to 100%. -10 to 0 V signal allows a setting of -100 to 0%. | 228 |
| 2 | Auxiliary frequency reference 1 | 10 V = E1-04 (maximum output frequency) | 228 |
| 3 | Auxiliary frequency reference 2 | 10 V = E1-04 (maximum output frequency) | 228 |
| 4 | Output voltage bias | 10 V = E1-05 (motor rated voltage) | 228 |
| 5 | Accel/decel time gain | 10 V = 100% | 228 |
| 6 | DC Injection Braking current | 10 V = Drive rated current | 229 |
| 7 | Overtorque/undertorque detection level | 10 V = Drive rated current (V/f) | 229 |
| 8 | Stall Prevention level during run | 10 V = Drive rated current | 229 |
| 9 | Output frequency lower limit level | 10 V = E1-04 (maximum output frequency) | 229 |
| B | PID feedback | 10 V = 100% | 229 |
| C | PID setpoint | 10 V = 100% | 229 |
| D | Frequency bias | 10 V = E1-04 (maximum output frequency) | 229 |
| E | Motor Temperature (PTC Input) | 10 V = 100% Note: A 12 kΩ resistor must be connected between one of the terminals A1, A2, or A3 and V+ for PTC functionality. Connect the 12 kΩ resistor to the same terminal as the PTC input. Do not connect terminals V+ to AC, or damage to the drive may result. | 230 |
| 16 | Differential PID feedback | 10 V = 100% | 230 |
| 17 | Motor Thermistor (NTC) | 10 V = -9 °C 0 V = 234 °C | 230 |
| 1F | Through mode | Set this value when using the terminal in the pass-through mode. | 230 |
| 25 | Secondary PI Setpoint | 10 V = S3-02 (maximum output frequency) | 230 |
| 26 | Secondary PI Feedback | 10 V = S3-02 (maximum output frequency) | 230 |

◆ H4: Analog Outputs

| No. (Addr. Hex) | Name | Description | Values | Page |
|---|---|---|--|------|
| H4-01 (41D) | Multi-Function Analog Output Terminal FM Monitor Selection | Selects the data to be output through multi-function analog output terminal FM. Set the desired monitor parameter to the digits available in U□-□□. For example, enter “103” for U1-03. | Default: 102 Range: 000 to 999 | 230 |
| H4-02 (41E)  | Multi-Function Analog Output Terminal FM Gain | Sets the signal level at terminal FM that is equal to 100% of the selected monitor value. | Default: 100.0% Min.: -999.9 Max.: 999.9 | 230 |
| H4-03 (41F)  | Multi-Function Analog Output Terminal FM Bias | Sets the signal level at terminal FM that is equal to 0% of the selected monitor value. | Default: 0.0% Min.: -999.9 Max.: 999.9 | 230 |
| H4-04 (420) | Multi-Function Analog Output Terminal AM Monitor Selection | Selects the data to be output through multi-function analog output terminal AM. Set the desired monitor parameter to the digits available in U□-□□. For example, enter “103” for U1-03. | Default: 103 Range: 000 to 999 | 230 |
| H4-05 (421)  | Multi-Function Analog Output Terminal AM Gain | Sets the signal level at terminal AM that is equal to 100% of the selected monitor value. | Default: 50.0% Min.: -999.9 Max.: 999.9 | 230 |
| H4-06 (422)  | Multi-Function Analog Output Terminal AM Bias | Sets the signal level at terminal AM that is equal to 0% of the selected monitor value. | Default: 0.0% Min.: -999.9 Max.: 999.9 | 230 |
| H4-07 (423) | Multi-Function Analog Output Terminal FM Signal Level Selection | 0: 0 to 10 V 1: -10 to 10 V 2: 4 to 20mA | Default: 0 Range: 0 to 2 | 231 |


| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|---|---|-----------------------------|------|
| H4-08 (424) | Multi-Function Analog Output Terminal AM Signal Level Selection | 0: 0 to 10 V 1: -10 to 10 V 2: 4 to 20 mA | Default: 0 Range: 0 to 2 | 231 |

◆ H5: MEMOBUS/Modbus Serial Communication




| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|--|--|---|------|
| H5-01 (425) <I> | Drive Node Address | Selects drive station node number (address) for MEMOBUS/Modbus terminals R+, R-, S+, S-. Cycle power for the setting to take effect. | Default: 1F (Hex) Min.: 0 Max.: FF | 511 |
| H5-02 (426) | Communication Speed Selection | 0: 1200 bps 1: 2400 bps 2: 4800 bps 3: 9600 bps 4: 19200 bps 5: 38400 bps 6: 57600 bps 7: 76800 bps 8: 115200 bps Cycle power for the setting to take effect. | Default: 3 Range: 0 to 8 | 511 |
| H5-03 (427) | Communication Parity Selection | 0: No parity 1: Even parity 2: Odd parity Cycle power for the setting to take effect. | Default: 0 Range: 0 to 2 | 511 |
| H5-04 (428) | Stopping Method after Communication Error (CE) | 0: Ramp to stop 1: Coast to stop 2: Fast Stop 3: Alarm only | Default: 3 Range: 0 to 3 | 511 |
| H5-05 (429) | Communication Fault Detection Selection | 0: Disabled 1: Enabled. If communication is lost for more than two seconds, a CE fault will occur. | Default: 1 Range: 0, 1 | 511 |
| H5-06 (42A) | Drive Transmit Wait Time | Set the wait time between receiving and sending data. | Default: 5 ms Min.: 5 Max.: 65 | 512 |
| H5-07 (42B) | RTS Control Selection | 0: Disabled. RTS is always on. 1: Enabled. RTS turns on only when sending. | Default: 1 Range: 0, 1 | 512 |
| H5-09 (435) | CE Detection Time | Sets the time required to detect a communications error. Adjustment may be needed when networking several drives. | Default: 2.0 s Min.: 0.0 Max.: 10.0 | 512 |
| H5-10 (436) | Unit Selection for MEMOBUS/Modbus Register 0025H | 0: 0.1 V units 1: 1 V units | Default: 0 Range: 0, 1 | 512 |
| H5-11 (43C) | Communications ENTER Function Selection | 0: Drive requires an Enter command before accepting any changes to parameter settings. 1: Parameter changes are activated immediately without the Enter command. | Default: 0 Range: 0, 1 | 513 |
| H5-12 (43D) | Run Command Method Selection | 0: FWD/Stop, REV/Stop 1: Run/Stop, FWD/REV | Default: 0 Range: 0, 1 | 513 |

<I> If this parameter is set to 0, the drive will be unable to respond to MEMOBUS/Modbus commands.

◆ H6: Pulse Train Input

| No. (Addr. Hex) | Name | Description | Values | Page |
|---|--|---|--|------|
| H6-01 (42C) | Pulse Train Input Terminal RP Function Selection | 0: Frequency reference 1: PID feedback value 2: PID setpoint value | Default: 0 Range: 0 to 2 | 232 |
| H6-02 (42D)  | Pulse Train Input Scaling | Sets the terminal RP input signal frequency that is equal to 100% of the value selected in H6-01. | Default: 1440 Hz Min.: 100 Max.: 32000 | 232 |

B.8 H Parameters: Multi-Function Terminals

| No. (Addr. Hex) | Name | Description | Values | Page |
|---|-------------------------------------|---|--|---------------------|
| H6-03 (42E)  | Pulse Train Input Gain | Sets the level of the value selected in H6-01 when a frequency with the value set in H6-02 is input. | Default: 100.0% Min.: 0.0 Max.: 1000.0 | 232 |
| H6-04 (42F)  | Pulse Train Input Bias | Sets the level of the value selected in H6-01 when 0 Hz is input. | Default: 0.0% Min.: -100.0 Max.: 100.0 | 232 |
| H6-05 (430)  | Pulse Train Input Filter Time | Sets the pulse train input filter time constant. | Default: 0.10 s Min.: 0.00 Max.: 2.00 | 232 |
| H6-08 (43F) | Pulse Train Input Minimum Frequency | Sets the minimum frequency for the pulse train input to be detected. Enabled when H6-01 = 0, 1, or 2. | Default: 0.5 Hz Min.: 0.1 Max.: 1000.0 | 233 |

B.9 L: Protection Function

L parameters provide protection to the drive and motor, including control during momentary power loss, Stall Prevention, frequency detection, fault restarts, overtorque detection, and other types of hardware protection.

◆ L1: Motor Protection

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|--|--|--|------|
| L1-01 (480) | Motor Overload Protection Selection | 0: Disabled 1: General purpose motor (standard fan cooled) 2: Drive dedicated motor with a speed range of 1:10 3: Vector motor with a speed range of 1:100 6: General purpose motor (50 Hz) The drive may not be able to provide protection when using multiple motors, even if overload is enabled in L1-01. Set L1-01 to 0 and install separate thermal relays to each motor. | Default: 1 Range: 0 to 6 | 234 |
| L1-02 (481) | Motor Overload Protection Time | Sets the motor thermal overload protection (oL1) time. | Default: 1.0 min Min.: 0.1 Max.: 5.0 | 236 |
| L1-03 (482) | Motor Overheat Alarm Operation Selection (PTC input) | Sets operation when the motor temperature analog input (H3-02, H3-10, or H3-06 = E) exceeds the oH3 alarm level. 0: Ramp to stop 1: Coast to stop 2: Fast Stop (decelerate to stop using the deceleration time in C1-09) 3: Alarm only ("oH3" will flash) | Default: 3 Range: 0 to 3 | 237 |
| L1-04 (483) | Motor Overheat Fault Operation Selection (PTC input) | Sets stopping method when the motor temperature analog input (H3-02, H3-10, or H3-06 = E) exceeds the oH4 fault level. 0: Ramp to stop 1: Coast to stop 2: Fast Stop (decelerate to stop using the deceleration time in C1-09) | Default: 1 Range: 0 to 2 | 237 |
| L1-05 (484) | Motor Temperature Input Filter Time (PTC input) | Adjusts the filter for the motor temperature analog input (H3-02, H3-10, or H3-06 = E). | Default: 0.20 s Min.: 0.00 Max.: 10.00 | 238 |
| L1-13 (46D) | Continuous Electrothermal Operation Selection | 0: Disabled 1: Enabled 2: Enabled (RTC) | Default: 1 Range: 0 to 2 | 238 |

◆ L2: Momentary Power Loss Ride-Thru

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|---|--|---|------|
| L2-01 (485) | Momentary Power Loss Operation Selection | 0: Disabled. Drive trips on Uv1 fault when power is lost. 1: Recover within the time set in L2-02. Uv1 will be detected if power loss is longer than L2-02. 2: Recover as long as CPU has power. Uv1 is not detected. 3: KEB deceleration for the time set to L2-02. 4: KEB deceleration as long as CPU has power. 5: KEB deceleration to stop. | Default: 2 Range: 0 to 5 | 240 |
| L2-02 (486) | Momentary Power Loss Ride-Thru Time | Sets the Power Loss Ride-Thru time. Enabled only when L2-01 = 1 or 3. | Default: </> Min.: 0.0 s Max.: 25.5 s | 245 |
| L2-03 (487) | Momentary Power Loss Minimum Baseblock Time | Sets the minimum wait time for residual motor voltage decay before the drive output reenergizes after performing Power Loss Ride-Thru. Increasing the time set to L2-03 may help if overcurrent or overvoltage occur during Speed Search or during DC Injection Braking. | Default: </> Min.: 0.1 s Max.: 5.0 s | 245 |
| L2-04 (488) | Momentary Power Loss Voltage Recovery Ramp Time | Sets the time for the output voltage to return to the preset V/f pattern during Speed Search. | Default: </> Min.: 0.0 s Max.: 5.0 s | 246 |

B.9 L: Protection Function

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|---------------------------------------|---|--|------|
| L2-05 (489) | Undervoltage Detection Level (Uv1) | Sets the DC bus undervoltage trip level. | Default: 190 Vdc <2> <3> Min.: 150 Vdc Max.: 210 Vdc <3> | 246 |
| L2-06 (48A) | KEB Deceleration Time | Sets the time required to decelerate from the speed when KEB was activated to zero speed. | Default: 0.00 s Min.: 0.00 Max.: 6000.0 <4> | 246 |
| L2-07 (48B) | KEB Acceleration Time | Sets the time to accelerate to the frequency reference when momentary power loss is over. If set to 0.0, the active acceleration time is used. | Default: 0.00 s Min.: 0.00 Max.: 6000.0 <4> | 246 |
| L2-08 (48C) | Frequency Gain at KEB Start | Sets the percentage of output frequency reduction at the beginning of deceleration when the KEB Ride-Thru function is started. Reduction = (slip frequency before KEB) × L2-08 × 2 | Default: 100% Min.: 0 Max.: 300 | 246 |
| L2-10 (48E) | KEB Detection Time (Minimum KEB Time) | Sets the time to perform KEB Ride-Thru. | Default: 50 ms Min.: 0 Max.: 2000 | 246 |
| L2-11 (461) | DC Bus Voltage Setpoint during KEB | Sets the desired value of the DC bus voltage during KEB Ride-Thru. | Default: <2> [E1-01] × 1.22 Min.: 150 Vdc Max.: 400 Vdc <5> | 246 |
| L2-29 (475) | KEB Method Selection | 0: Single Drive KEB Ride-Thru 1 1: Single Drive KEB Ride-Thru 2 2: System KEB Ride-Thru 1 3: System KEB Ride-Thru 2 | Default: 0 Range: 0 to 3 | 247 |

<1> Default setting is dependent on parameter o2-04, Drive Model Selection.

<2> Default setting is dependent on parameter E1-01, Input voltage Setting.

<3> Values shown are specific to 200 V class drives. Double the value for 400 V class drives. Multiply the value by 2.875 for 600 V class drives.

<4> Setting range value is dependent on parameter C1-10, Accel/Decel Time Setting Units. When C1-10 = 0 (units of 0.01 seconds), the setting range becomes 0.00 to 600.00 seconds.

<5> Values shown are specific to 200 V class drives. Double the value for 400 V class drives. Multiply the value by 2.875 for 600 V class drives, but set the value below 1040 Vdc (overvoltage protection level).

◆ L3: Stall Prevention

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|--|--|--|------|
| L3-01 (48F) | Stall Prevention Selection during Acceleration | 0: Disabled. 1: General purpose. Acceleration is paused as long as the current is above the L3-02 setting. 2: Intelligent. Accelerate in the shortest possible time without exceeding the L3-02 level. | Default: 1 Range: 0 to 2 | 247 |
| L3-02 (490) | Stall Prevention Level during Acceleration | Used when L3-01 = 1 or 2. 100% is equal to the drive rated current. | Default: <1> Min.: 0% Max.: 150% <1> | 248 |
| L3-03 (491) | Stall Prevention Limit during Acceleration | Sets Stall Prevention lower limit during acceleration when operating in the constant power range. Set as a percentage of drive rated current. | Default: 50% Min.: 0 Max.: 100 | 248 |
| L3-04 (492) | Stall Prevention Selection during Deceleration | 0: Disabled. Deceleration at the active deceleration rate. An ov fault may occur. 1: General purpose. Deceleration is paused when the DC bus voltage exceeds the Stall Prevention level. 2: Intelligent. Decelerate as fast as possible while avoiding ov faults. 3: Stall Prevention with braking resistor. Stall Prevention during deceleration is enabled in coordination with dynamic braking. 4: Overexcitation Deceleration. Decelerates while increasing the motor flux. 5: Overexcitation Deceleration 2. Adjust the deceleration rate according to the DC bus voltage. | Default: 1 Range: 0 to 5 | 249 |

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|--|--|---|------|
| L3-05 (493) | Stall Prevention Selection during Run | 0: Disabled. Drive runs at a set frequency. A heavy load may cause speed loss. 1: Decel time 1. Uses the deceleration time set to C1-02 while Stall Prevention is performed. 2: Decel time 2. Uses the deceleration time set to C1-04 while Stall Prevention is performed. | Default: 1 Range: 0 to 2 | 250 |
| L3-06 (494) | Stall Prevention Level during Run | Enabled when L3-05 is set to 1 or 2. 100% is equal to the drive rated current. | Default: <1> Min.: 30% Max.: 150% <2> | 250 |
| L3-11 (4C7) | Overvoltage Suppression Function Selection | Enables or disables the ov suppression function, which allows the drive to change the output frequency as the load changes to prevent an ov fault. 0: Disabled 1: Enabled | Default: 0 Range: 0, 1 | 250 |
| L3-17 (462) | Target DC Bus Voltage for Overvoltage Suppression and Stall Prevention | Sets the desired value for the DC bus voltage during overvoltage suppression and Stall Prevention during deceleration. | Default: 375 Vdc <2> <3> Min.: 150 Max.: 400 <3> | 251 |
| L3-20 (465) | DC Bus Voltage Adjustment Gain | Sets the proportional gain for KEB Ride-Thru, Stall Prevention, and overvoltage suppression. | Default: 1.00 Min.: 0.00 Max.: 5.00 | 251 |
| L3-21 (466) | Accel/Decel Rate Calculation Gain | Sets the proportional gain used to calculate the deceleration rate during KEB Ride-Thru, ov suppression function, and Stall Prevention during deceleration (L3-04 = 2). | Default: 1.00 Min.: 0.10 Max.: 10.00 | 251 |
| L3-23 (4FD) | Automatic Reduction Selection for Stall Prevention during Run | 0: Sets the Stall Prevention level set in L3-04 that is used throughout the entire frequency range. 1: Automatic Stall Prevention level reduction in the constant output range. The lower limit value is 40% of L3-06. | Default: 0 Range: 0, 1 | 251 |
| L3-24 (46E) | Motor Acceleration Time for Inertia Calculations | Sets the time needed to accelerate the uncoupled motor at rated torque from stop to the maximum frequency. | Default: <4> <5> Min: 0.001 s Max: 10.000 s | 252 |
| L3-25 (46F) | Load Inertia Ratio | Sets the ratio between the motor and machine inertia. | Default: 1.0 Min.: 1.0 Max.: 1000.0 | 252 |
| L3-26 (455) | Additional DC Bus Capacitors | When DC bus capacitors have been added externally, be sure to add those values to the internal capacitor table for proper DC bus calculations. | Default: 0 µF Min: 0 Max: 65000 | 252 |
| L3-27 (456) | Stall Prevention Detection Time | Sets the time the current must exceed the Stall Prevention level to activate Stall Prevention. | Default: 50 ms Min.: 0 Max.: 5000 | 252 |

<1> Upper limit is dependent on parameter L8-38, Frequency Reduction Selection.

<2> Default setting is dependent on parameter E1-01, Input voltage Setting.

<3> Values shown are specific to 200 V class drives. Double the value for 400 V class drives. Multiply the value by 2.875 for 600 V class drives, but set the value below 1040 Vdc (overvoltage protection level).

<4> Parameter value changes automatically if E2-11 is manually changed or changed by Auto-Tuning.

<5> Default setting is dependent on parameter o2-04, Drive Model Selection.

◆ L4: Speed Detection

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|---------------------------------------|--|--|------|
| L4-01 (499) | Speed Agreement Detection Level | L4-01 sets the frequency detection level for digital output functions H2-□□ = 2, 3, 4, 5. | Default: 0.0 Hz Min.: 0.0 Max.: 400.0 | 253 |
| L4-02 (49A) | Speed Agreement Detection Width | L4-02 sets the hysteresis or allowable margin for speed detection. | Default: 2.0 Min.: 0.0 Max.: 20.0 | 253 |
| L4-03 (49B) | Speed Agreement Detection Level (+/-) | L4-03 sets the frequency detection level for digital output functions H2-□□ = 13, 14, 15, 16. | Default: 0.0 Hz Min.: -400.0 Max.: 400.0 | 253 |

B.9 L: Protection Function

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|--|---|--|------|
| L4-04 (49C) | Speed Agreement Detection Width (+/-) | L4-04 sets the hysteresis or allowable margin for speed detection. | Default: 2.0 Min.: 0.0 Max.: 20.0 | 253 |
| L4-05 (49D) | Frequency Reference Loss Detection Selection | 0: Stop. Drive stops when the frequency reference is lost. 1: Run. Drive runs at a reduced speed when the frequency reference is lost. | Default: 0 Range: 0, 1 | 253 |
| L4-06 (4C2) | Frequency Reference at Reference Loss | Sets the percentage of the frequency reference that the drive should run with when the frequency reference is lost. | Default: 80.0% Min.: 0.0 Max.: 100.0 | 254 |
| L4-07 (470) | Speed Agreement Detection Selection | 0: No detection during baseblock. 1: Detection always enabled. | Default: 0 Range: 0, 1 | 254 |

◆ L5: Fault Restart

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|---|--|---|------|
| L5-01 (49E) | Number of Auto Restart Attempts | Sets the number of times the drive may attempt to restart after the following faults occur: GF, LF, oC, ov, PF, rH, rr, oL1, oL2, oL3, oL4, STo, Uv1. | Default: 0 Min.: 0 Max.: 10 | 254 |
| L5-02 (49F) | Auto Restart Fault Output Operation Selection | 0: Fault output not active. 1: Fault output active during restart attempt. | Default: 0 Range: 0, 1 | 255 |
| L5-04 (46C) | Fault Reset Interval Time | Sets the amount of time to wait between performing fault restarts. | Default: 10.0 s Min.: 0.5 Max.: 600.0 | 255 |
| L5-05 (467) | Fault Reset Operation Selection | 0: Continuously attempt to restart while incrementing restart counter only at a successful restart (same as F7 and G7). 1: Attempt to restart with the interval time set in L5-04 and increment the restart counter with each attempt (same as V7). | Default: 0 Range: 0, 1 | 255 |

◆ L6: Torque Detection

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|------------------------------|--|--|------|
| L6-01 (4A1) | Torque Detection Selection 1 | 0: Disabled 1: oL3 detection only active during speed agree, operation continues after detection 2: oL3 detection always active during run, operation continues after detection 3: oL3 detection only active during speed agree, output shuts down on an oL3 fault 4: oL3 detection always active during run, output shuts down on an oL3 fault 5: UL3 detection only active during speed agree, operation continues after detection 6: UL3 detection always active during run, operation continues after detection 7: UL3 detection only active during speed agree, output shuts down on an oL3 fault 8: UL3 detection always active during run, output shuts down on an oL3 fault 9: UL6 Alarm at Speed Agree 10: UL6 Alarm during Run 11: UL6 Fault at Speed Agree 12: UL6 Fault during Run | Default: 0 Range: 0 to 12 | 256 |
| L6-02 (4A2) | Torque Detection Level 1 | Sets the overtorque and undertorque detection level. | Default: 15% Min.: 0 Max.: 300 | 257 |
| L6-03 (4A3) | Torque Detection Time 1 | Sets the time an overtorque or undertorque condition must exist to trigger torque detection 1. | Default: 10.0 s Min.: 0.0 Max.: 10.0 | 257 |

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|---|---|---|------|
| L6-04 (4A4) | Torque Detection Selection 2 | 0: Disabled 1: oL4 detection only active during speed agree, operation continues after detection 2: oL4 detection always active during run, operation continues after detection 3: oL4 detection only active during speed agree, output shuts down on an oL4 fault 4: oL4 detection always active during run, output shuts down on an oL4 fault 5: UL4 detection only active during speed agree, operation continues after detection 6: UL4 detection always active during run, operation continues after detection 7: UL4 detection only active during speed agree, output shuts down on an oL4 fault 8: UL4 detection always active during run, output shuts down on an oL4 fault | Default: 0 Range: 0 to 8 | 256 |
| L6-05 (4A5) | Torque Detection Level 2 | Sets the overtorque and undertorque detection level. | Default: 150% Min.: 0 Max.: 300 | 257 |
| L6-06 (4A6) | Torque Detection Time 2 | Sets the time an overtorque or undertorque condition must exist to trigger torque detection 2. | Default: 0.1 s Min.: 0.0 Max.: 10.0 | 257 |
| L6-13 (62E) | Motor Underload Protection Selection | Sets the motor underload protection (UL6) based on motor load. 0: Base frequency enable 1: Max frequency enable | Default: 0 Range: 0, 1 | 256 |
| L6-14 (62F) | Motor Underload Protection Level at Minimum Frequency | Sets the UL6 detection level at minimum frequency by percentage of drive rated current. | Default: 15% Min.: 0 Max.: 300 | 256 |

◆ L8: Drive Protection

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|---|---|---|------|
| L8-01 (4AD) | Internal Dynamic Braking Resistor Protection Selection (ERF type) | 0: Resistor overheat protection disabled 1: Resistor overheat protection enabled | Default: 0 Range: 0, 1 | 257 |
| L8-02 (4AE) | Overheat Alarm Level | An overheat alarm occurs when heatsink temperature exceeds the L8-02 level. | Default: </> Min.: 50 °C Max.: 150 °C | 258 |
| L8-03 (4AF) | Overheat Pre-Alarm Operation Selection | 0: Ramp to stop. A fault is triggered. 1: Coast to stop. A fault is triggered. 2: Fast Stop. Decelerate to stop using the deceleration time in C1-09. A fault is triggered. 3: Continue operation. An alarm is triggered. 4: Continue operation at reduced speed as set in L8-19. | Default: 3 Range: 0 to 4 | 258 |
| L8-05 (4B1) | Input Phase Loss Protection Selection | Selects the detection of input current phase loss, power supply voltage imbalance, or main circuit electrolytic capacitor deterioration. 0: Disabled 1: Enabled | Default: 1 Range: 0, 1 | 259 |
| L8-07 (4B3) | Output Phase Loss Protection Selection | 0: Disabled 1: Enabled (triggered by a single phase loss) 2: Enabled (triggered when two phases are lost) | Default: 1 Range: 0 to 2 | 259 |
| L8-09 (4B5) | Output Ground Fault Detection Selection | 0: Disabled 1: Enabled | Default: 1 Range: 0, 1 | 260 |
| L8-10 (4B6) | Heatsink Cooling Fan Operation Selection | 0: During run only. Fan operates only during run for L8-11 seconds after stop. 1: Fan always on. Cooling fan operates whenever the drive is powered up. | Default: 0 Range: 0, 1 | 260 |
| L8-11 (4B7) | Heatsink Cooling Fan Off Delay Time | Sets a delay time to shut off the cooling fan after the Run command is removed when L8-10 = 0. | Default: 60 s Min.: 0 Max.: 300 | 260 |
| L8-12 (4B8) | Ambient Temperature Setting | Enter the ambient temperature. This value adjusts the oL2 detection level. | Default: 40 °C Min.: -10 Max.: 50 | 260 |
| L8-15 (4BB) | oL2 Characteristics Selection at Low Speeds | 0: No oL2 level reduction below 6 Hz. 1: oL2 level is reduced linearly below 6 Hz. It is halved at 0 Hz. | Default: 1 Range: 0, 1 | 260 |
| L8-18 (4BE) | Software Current Limit Selection | 0: Disabled 1: Enabled | Default: 0 Range: 0, 1 | 261 |

B.9 L: Protection Function

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|---|--|--|------|
| L8-19 (4BF) | Frequency Reduction Rate during Overheat Pre-Alarm | Specifies the frequency reference reduction gain at overheat pre-alarm when L8-03 = 4. | Default: 0.8 Min.: 0.1 Max.: 0.9 | 259 |
| L8-32 (4E2) | Main Contactor and Cooling Fan Power Supply Failure Selection | Determines drive response when a fault occurs with the internal cooling fan. 0: Ramp to stop 1: Coast to stop 2: Fast stop (Decelerate to stop using the deceleration time set to C1-09) 3: Alarm only ("FAN" will flash) 4: Continue operation at reduced speed as set to L8-19. | Default: 1 Range: 0 to 4 | 261 |
| L8-35 (4EC) | Installation Method Selection | 0: IP00/Open-Chassis enclosure 1: Side-by-Side mounting 2: IP20/NEMA Type 1 enclosure 3: External heatsink installation | Default: <2> <3> Range: 0 to 3 | 261 |
| L8-38 (4EF) | Carrier Frequency Reduction | 0: Disabled 1: Enabled below 6 Hz 2: Enabled for the entire speed range | Default: 2 Range: 0 to 2 | 262 |
| L8-40 (4F1) | Carrier Frequency Reduction Off Delay Time | Sets the time that the drive continues running with reduced carrier frequency after the carrier reduction condition is gone. Setting 0.00 s disables the carrier frequency reduction time. | Default: 0.5 s Min.: 0.00 Max.: 2.00 | 262 |
| L8-41 (4F2) | High Current Alarm Selection | 0: Disabled 1: Enabled. An alarm is triggered at output currents above 150% of drive rated current. | Default: 0 Range: 0, 1 | 262 |
| L8-55 (45F) | Internal Braking Transistor Protection | 0: Disabled. Disable when using a regen converter or optional braking unit. 1: Protection enabled. | Default: 1 Range: 0, 1 | 262 |
| L8-93 (73C) | LSO Detection Time at Low Speed | Sets the amount of time until baseblock is executed after detecting pull-out at low speed. | Default: 1.0 s Min.: 0.0 Max.: 10.0 | 263 |
| L8-94 (73D) | LSO Detection Level at Low Speed | Determines the detection level of pull-out at low speed. | Default: 3% Min.: 0 Max.: 10 | 263 |
| L8-95 (73D) | Average LSO Frequency at Low Speed | Sets the average number of times pull-out can occur at low speed. | Default: 10 times Min.: 1 Max.: 50 | 263 |

<1> Default setting is dependent on parameter o2-04, Drive Model Selection.

<2> Parameter setting value is not reset to the default value when the drive is initialized.

<3> Default setting is determined by the drive model:

Setting 2: Model code CIMR-P□2A0004 to 2A0211, 4A0002 to 4A0165, and 5A0003 to 5A0242

Setting 0: Model code CIMR-P□2A0250 to 2A0415 and 4A0208 to 4A0675

B.10 n: Special Adjustment

The n parameters adjust more advanced performance characteristics such as Hunting Prevention, High Slip Braking, and Overexcitation Braking.

◆ n1: Hunting Prevention

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|--|---|--|------|
| n1-01 (580) | Hunting Prevention Selection | 0: Disabled 1: Enabled | Default: 1 Range: 0, 1 | 264 |
| n1-02 (581) | Hunting Prevention Gain Setting | If the motor vibrates while lightly loaded, increase the gain by 0.1 until vibration ceases. If the motor stalls, decrease the gain by 0.1 until the stalling ceases. | Default: 1.00 Min.: 0.00 Max.: 2.50 | 264 |
| n1-03 (582) | Hunting Prevention Time Constant | Sets the time constant used for Hunting Prevention. | Default: <1> Min.: 0 ms Max.: 500 ms | 264 |
| n1-05 (530) | Hunting Prevention Gain while in Reverse | Sets the gain used for Hunting Prevention. If set to 0, the gain set to n1-02 is used for operation in reverse. | Default: 0.00 Min.: 0.00 Max.: 2.50 | 264 |

<1> Default setting is dependent on parameter o2-04, Drive Model Selection.

◆ n3: High Slip Braking (HSB) and Overexcitation Braking




| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|---|--|---|------|
| n3-01 (588) | High-Slip Braking Deceleration Frequency Width | Sets the output frequency reduction step width for when the drive stops the motor using HSB. Set as a percentage of the maximum output frequency. Increase this setting if overvoltage occurs during HSB. | Default: 5% Min.: 1 Max.: 20 | 265 |
| n3-02 (589) | High-Slip Braking Current Limit | Sets the current limit during HSB as a percentage of the motor rated current. | Default: <1> Min.: 100% Max.: 200% | 265 |
| n3-03 (58A) | High-Slip Braking Dwell Time at Stop | Sets the time the drive will run with minimum frequency (E1-09) at the end of deceleration. If this time is set too low, the machine inertia can cause the motor to rotate slightly after HSB. | Default: 1.0 s Min.: 0.0 Max.: 10.0 | 265 |
| n3-04 (58B) | High-Slip Braking Overload Time | Sets the time required for an HSB overload fault (oL7) to occur when the drive output frequency does not change during an HSB stop. This parameter does not typically require adjustment. | Default: 40 s Min.: 30 Max.: 1200 | 265 |
| n3-13 (531) | Overexcitation Deceleration Gain | Sets the gain applied to the V/f pattern during Overexcitation Deceleration (L3-04 = 4). | Default: 1.10 Min.: 1.00 Max.: 1.40 | 266 |
| n3-14 (532) | High Frequency Injection during Overexcitation Deceleration | 0: Disabled 1: Enabled | Default: 0 Range: 0, 1 | 266 |
| n3-21 (579) | High-Slip Suppression Current Level | Sets output current level at which the drive will start reducing the overexcitation gain in order to prevent a too high motor slip during Overexcitation Deceleration. Set as a percentage of the drive rated current. | Default: 100% Min.: 0 Max.: 150 | 266 |
| n3-23 (57B) | Overexcitation Operation Selection | 0: Enabled in both directions 1: Enabled only when rotating forward 2: Enabled only when in reverse | Default: 0 Range: 0 to 2 | 266 |

<1> Default setting is dependent on parameter L8-38, Frequency Reduction Selection.

B.11 o: Operator-Related Settings

The o parameters set up the digital operator displays.

◆ o1: Digital Operator Display Selection


| No. (Addr. Hex) | Name | Description | Values | Page |
|---|--|---|---|------|
| o1-01 (500)  | Drive Mode Unit Monitor Selection | Selects the content of the last monitor that is shown when scrolling through Drive Mode display. Enter the last three digits of the monitor parameter number to be displayed: U□-□□. | Default: 106 (Monitor U1-06) Range: 104 to 809 | 267 |
| o1-02 (501)  | User Monitor Selection after Power Up | 1: Frequency reference (U1-01) 2: Direction 3: Output frequency (U1-02) 4: Output current (U1-03) 5: User-selected monitor (set by o1-01) | Default: 1 Range: 1 to 5 | 267 |
| o1-03 (502) | Digital Operator Display Selection | Sets the units the drive should use to display the frequency reference and motor speed monitors. 0: 0.01 Hz 1: 0.01% (100% = E1-04) 2: r/min (calculated using the number of motor poles setting in E2-04) 3: User-selected units (set by o1-09, o1-10 and o1-11) | Default: 0 Range: 0 to 3 | 267 |
| o1-05 (0504)  <2> | LCD Contrast Control | Sets the contrast of the LCD operator. | Default: 3 Min.: 0 Max.: 5 | 268 |
| o1-06 (517) | User Monitor Selection Mode | Selects the monitors displayed on the second and third lines of the digital operator display. 0: 3 Monitor Sequential (displays the next two sequential monitors) 1: 3 Monitor Selectable (set by o1-07 and o1-08) | Default: 0 Range: 0, 1 | 267 |
| o1-07 (518) | Second Line Monitor Selection | Selects the monitor that is shown in the second line. Enter the last three digits of the monitor parameter number to be displayed: U□-□□. For example, set "403" to display monitor parameter U4-03. Note: Parameter is effective only when o1-06 is set to 1. | Default: 102 Range: 101 to 799 | 267 |
| o1-08 (519) | Third Line Monitor Selection | Selects the monitor that is shown in the third line. Enter the last three digits of the monitor parameter number to be displayed: U□-□□. For example, set "403" to display monitor parameter U4-03. Note: Parameter is effective only when o1-06 is set to 1. | Default: 103 Range: 101 to 799 | 267 |
| o1-09 (51C) | Frequency Reference Display Units | Sets unit display for the frequency reference parameters and frequency related monitors when o1-03 = 3. 0: WC (Inch of water) 1: PSI (Pounds per square inch) 2: GPM (Gallons per minute) 3: F (Degrees Fahrenheit) 4: CFM (Cubic feet per minute) 5: CMH (Cubic meters per hour) 6: LPH (Liters per hour) 7: LPS (Liters per second) 8: Bar (Bar) 9: Pa (Pascal) 10: C (Degrees Celsius) 11: Mtr (Meters) 12: Ft (Feet) 13: LPM (Liters per minute) 14: CMM (Cubic meters per minute) 15: "Hg (inches of mercury) 24: Custom units (determined by o1-13 to o1-15) 25: None | Default: 25 Range: 0 to 15; 24, 25 | 267 |
| o1-10 (520) | User-Set Display Units Maximum Value | These settings define the display values when o1-03 is set to 3. o1-10 sets the display value that is equal to the maximum output frequency. | Default: <2> Range: 1 to 60000 | 269 |
| o1-11 (521) | User-Set Display Units Decimal Display | o1-11 sets the position of the decimal position. | Default: <2> Range: 0 to 3 | 269 |
| o1-13 (3105) | Frequency Reference and Frequency Related Monitor Custom Units 1 | Sets the first character of the customer-specified unit display when o1-03 is set to 3 and o1-09 is set to 24. | Default: 41 Range: 30 to 7A | 269 |

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|--|---|--------------------------------|------|
| o1-14 (3106) | Frequency Reference and Frequency Related Monitor Custom Units 2 | Sets the second character of the customer-specified unit display when o1-03 is set to 3 and o1-09 is set to 24. | Default: 41 Range: 30 to 7A | 269 |
| o1-15 (3107) | Frequency Reference and Frequency Related Monitor Custom Units 3 | Sets the third character of the customer-specified unit display when o1-03 is set to 3 and o1-09 is set to 24. | Default: 41 Range: 30 to 7A | 269 |

<1> Default setting is dependent on parameter o1-03, Digital Operator Display Selection.

<2> Available in drive software versions PRG: 8503 and later.

◆ o2: Digital Operator Keypad Functions

| No. (Addr. Hex) | Name | Description | Values | Page |
|---|---|---|---------------------------------------|------|
| o2-01 (505) | LO/RE Key Function Selection | 0: Disabled 1: Enabled. LO/RE key switches between LOCAL and REMOTE operation. | Default: 1 Range: 0, 1 | 270 |
| o2-02 (506) | STOP Key Function Selection | 0: Disabled. STOP key is disabled in REMOTE operation. 1: Enabled. STOP key is always enabled. | Default: 1 Range: 0, 1 | 270 |
| o2-03 (507) | User Parameter Default Value | 0: No change. 1: Set defaults. Saves parameter settings as default values for a User Initialization. 2: Clear all. Clears the default settings that have been saved for a User Initialization. | Default: 0 Range: 0 to 2 | 270 |
| o2-04 (508) | Drive Model Selection | Enter the drive model. Setting required only if installing a new control board. | Default: Determined by drive capacity | 271 |
| o2-05 (509) | Frequency Reference Setting Method Selection | 0: ENTER key must be pressed to enter a frequency reference. 1: ENTER key is not required. The frequency reference can be adjusted using the up and down arrow keys only. | Default: 0 Range: 0, 1 | 271 |
| o2-06 (50A) | Operation Selection when Digital Operator is Disconnected | 0: The drive continues operating if the digital operator is disconnected. 1: An oPr fault is triggered and the motor coasts to stop. | Default: 1 Range: 0, 1 | 271 |
| o2-07 (527) | Motor Direction at Power Up when Using Operator | This parameter requires assigning drive operation to the digital operator. 0: Forward 1: Reverse | Default: 0 Range: 0, 1 | 271 |
| o2-20 (81E)  | Operator RUN Save at Power Loss | When running during a power loss, the Run command is issued via the digital operator and the Run state is saved to the EEPROM. When power is restored, the Run command is automatically applied if the LOCAL/REMOTE or FREF conditions have not changed in the drive. 0: Disabled 1: Enabled | Default: 0 Range: 0, 1 | 271 |

◆ o3: Copy Function

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|-------------------------|---|-----------------------------|------|
| o3-01 (515) | Copy Function Selection | 0: No action 1: Read parameters from the drive, saving them onto the digital operator. 2: Copy parameters from the digital operator, writing them to the drive. 3: Verify parameter settings on the drive to check if they match the data saved on the operator. | Default: 0 Range: 0 to 3 | 272 |
| o3-02 (516) | Copy Allowed Selection | 0: Read operation prohibited 1: Read operation allowed | Default: 0 Range: 0, 1 | 272 |

◆ o4: Maintenance Monitor Settings

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|---|--|-------------------------------------|---------------------|
| o4-01 (50B) | Cumulative Operation Time Setting | Sets the value for the cumulative operation time of the drive in units of 10 h. | Default: 0 Min.: 0 Max.: 9999 | 272 |
| o4-02 (50C) | Cumulative Operation Time Selection | 0: Logs power-on time 1: Logs operation time when the drive output is active (output operation time). | Default: 0 Range: 0, 1 | 273 |
| o4-03 (50E) | Cooling Fan Operation Time Setting | Sets the value of the fan operation time monitor U4-03 in units of 10 h. | Default: 0 Min.: 0 Max.: 9999 | 273 |
| o4-05 (51D) | Capacitor Maintenance Setting | Sets the value of the Maintenance Monitor for the capacitors. See U4-05 to check when the capacitors may need to be replaced. | Default: 0% Min.: 0 Max.: 150 | 273 |
| o4-07 (523) | DC Bus Pre-Charge Relay Maintenance Setting | Sets the value of the Maintenance Monitor for the soft charge bypass relay. See U4-06 to check when the bypass relay may need to be replaced. | Default: 0% Min.: 0 Max.: 150 | 273 |
| o4-09 (525) | IGBT Maintenance Setting | Sets the value of the Maintenance Monitor for the IGBTs. See U4-07 for IGBT replacement times. | Default: 0% Min.: 0 Max.: 150 | 273 |
| o4-11 (510) | U2, U3 Initialization | 0: U2-□□ and U3-□□ monitor data is not reset when the drive is initialized (A1-03). 1: U2-□□ and U3-□□ monitor data is reset when the drive is initialized (A1-03). | Default: 0 Range: 0, 1 | 273 |
| o4-12 (512) | kWh Monitor Initialization | 0: U4-10 and U4-11 monitor data is not reset when the drive is initialized (A1-03). 1: U4-10 and U4-11 monitor data is reset when the drive is initialized (A1-03). | Default: 0 Range: 0, 1 | 274 |
| o4-13 (528) | Number of Run Commands Counter Initialization | 0: Number of Run commands counter is not reset when the drive is initialized (A1-03). 1: Number of Run commands counter is reset when the drive is initialized (A1-03). | Default: 0 Range: 0, 1 | 274 |
| o4-17 (3100) | Set/Reset Real-Time Clock | Sets the current date and time for the Real-Time Clock. 0: - - 1: Set 2: Reset | Default: 0 Range: 0 to 2 | 116 |
| o4-20 (81F) | Time Display Format | Sets the time display format. 0: 12-hour 1: 24-hour | Default: 0 Range: 0, 1 | 274 |

B.12 S: Special Application

◆ S1: Dynamic Noise Control Function

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|---|---|---|------|
| S1-01 (3200) | Dynamic Audible Noise Control Function Selection | 0: Disabled 1: Enabled | Default: 0 Range: 0, 1 | 275 |
| S1-02 (3201) | Voltage Reduction Rate | Sets the rate at which the output voltage will be reduced as a percentage of the V/f pattern when operating with no load. | Default: 50.0% Min.: 50.0 Max.: 100.0 | 275 |
| S1-03 (3202) | Voltage Restoration Level | Sets the level when the drive should start restoring the voltage as a percentage of the drive rated torque. | Default: 20.0% Min.: 0.0 Max.: 90.0 | 275 |
| S1-04 (3203) | Voltage Restoration Complete Level | Sets the level at which voltage restoration for the V/f pattern is complete as a percentage of the drive rated torque. If the output torque rises above the value of S1-04, then the voltage will be controlled in a manner specified by the V/f pattern setting. | Default: 50.0% Min.: S1-03 + 10.0 Max.: 100.0 | 276 |
| S1-05 (3204) | Voltage Restoration Sensitivity Time Constant | Sets the level of sensitivity of the output torque and LPF time constants for the voltage reduction rate. The level of sensitivity can be adjusted in accordance with the load response. | Default: 1.000 s Min.: 0.000 Max.: 3.000 | 276 |
| S1-06 (3205) | Voltage Restoration Time Constant at Impact | Sets the voltage restoration time constant if an impact load is added. | Default: 0.050 s Min.: 0.000 Max.: 1.000 | 276 |
| S1-07 (323C) | Output Phase Loss Level for Dynamic Noise Control | Reduces the output phase loss level when Dynamic Noise Control is active. | Default: 100.0% Min.: 10.0 Max.: 100.0 | 276 |

◆ S2: Programmable Run Timers

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|-----------------------------------|---|--|------|
| S2-01 (3206) | Sequence Timer 1 Start Time | Sets the start time for timer 1. The value must be set less than or equal to S2-02. | Default: 00:00 Min.: 00:00 Max.: 24:00 <I> | 279 |
| S2-02 (3207) | Sequence Timer 1 Stop Time | Sets the stop time for timer 1. The value must be set greater than or equal to S2-01. | Default: 00:00 Min.: 00:00 Max.: 24:00 <I> | 280 |
| S2-03 (3208) | Sequence Timer 1 Day Selection | Sets the days for which sequence timer 1 is active. 0: Timer disabled 1: Daily 2: Mon - Fri 3: Sat - Sun 4: Monday 5: Tuesday 6: Wednesday 7: Thursday 8: Friday 9: Saturday 10: Sunday 10: Sunday | Default: 0 Range: 0 to 10 | 280 |
| S2-04 (3209) | Sequence Timer 1 Selection | Sets the action that occurs when sequence timers 1 is active. 0: Digital output only 1: Run 2: Run - PI disable | Default: 0 Range: 0 to 2 | 280 |
| S2-05 (320A) | Sequence Timer 1 Reference Source | Selects the frequency reference source used for running the drive when sequence timer 1 is active (only applicable when S2-04 is set to 1 or 2). 0: Operator (d1-01) 1: Operator (d1-02) 2: Operator (d1-03) 3: Operator (d1-04) 4: Terminals 5: Serial communication 6: Option card 7: Pulse input | Default: 0 Range: 0 to 7 | 281 |




B.12 S: Special Application

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------------|-----------------------------------|---|--|------|
| S2-06 (320B) | Sequence Timer 2 Start Time | Sets the start time for timer 2. The value must be set less than or equal to S2-07. | Default: 00:00 Min.: 00:00 Max.: 24:00 <I> | 279 |
| S2-07 (320C) | Sequence Timer 2 Stop Time | Sets the stop time for timer 2. The value must be set greater than or equal to S2-06. | Default: 00:00 Min.: 00:00 Max.: 24:00 <I> | 280 |
| S2-08 (320D) | Sequence Timer 2 Day Selection | Sets the days for which sequence timer 2 is active. 0: Timer disabled 1: Daily 2: Mon - Fri 3: Sat - Sun 4: Monday 5: Tuesday 6: Wednesday 7: Thursday 8: Friday 9: Saturday 10: Sunday | Default: 0 Range: 0 to 10 | 280 |
| S2-09 (320E) | Sequence Timer 2 Selection | Sets the action that occurs when sequence timer 2 is active. 0: Digital output only 1: Run 2: Run - PI disable | Default: 0 Range: 0 to 2 | 280 |
| S2-10 (320F) | Sequence Timer 2 Reference Source | Selects the frequency reference source used for running the drive when sequence timer 2 is active (only applicable when S2-09 is set to 1 or 2). 0: Operator (d1-01) 1: Operator (d1-02) 2: Operator (d1-03) 3: Operator (d1-04) 4: Terminals 5: Serial communication 6: Option card 7: Pulse input | Default: 0 Range: 0 to 7 | 281 |
| S2-11 (3210) | Sequence Timer 3 Start Time | Sets the start time for timer 3. The value must be set less than or equal to S2-12. | Default: 00:00 Min.: 00:00 Max.: 24:00 <I> | 279 |
| S2-12 (3211) | Sequence Timer 3 Stop Time | Sets the stop time for timer 3. The value must be set greater than or equal to S2-11. | Default: 00:00 Min.: 00:00 Max.: 24:00 <I> | 280 |
| S2-13 (3212) | Sequence Timer 3 Day Selection | Sets the days for which sequence timer 3 is active. 0: Timer disabled 1: Daily 2: Mon - Fri 3: Sat - Sun 4: Monday 5: Tuesday 6: Wednesday 7: Thursday 8: Friday 9: Saturday 10: Sunday | Default: 0 Range: 0 to 10 | 280 |
| S2-14 (3213) | Sequence Timer 3 Selection | Sets the action that occurs when sequence timer 3 is active. 0: Digital output only 1: Run 2: Run - PI disable | Default: 0 Range: 0 to 2 | 280 |
| S2-15 (3214) | Sequence Timer 3 Reference Source | Selects the frequency reference source used for running the drive when sequence timer 3 is active (only applicable when S2-14 is set to 1 or 2). 0: Operator (d1-01) 1: Operator (d1-02) 2: Operator (d1-03) 3: Operator (d1-04) 4: Terminals 5: Serial communication 6: Option card 7: Pulse input | Default: 0 Range: 0 to 7 | 281 |
| S2-16 (3215) | Sequence Timer 4 Start Time | Sets the start time for timer 4. The value must be set less than or equal to S2-17. | Default: 00:00 Min.: 00:00 Max.: 24:00 <I> | 279 |















| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|-----------------------------------|---|--|------|
| S2-17 (3216) | Sequence Timer 4 Stop Time | Sets the stop time for timer 4. The value must be set greater than or equal to S2-16. | Default: 00:00 Min.: 00:00 Max.: 24:00 <I> | 280 |
| S2-18 (3217) | Sequence Timer 4 Day Selection | Sets the days for which sequence timer 4 is active. 0: Timer disabled 1: Daily 2: Mon - Fri 3: Sat - Sun 4: Monday 5: Tuesday 6: Wednesday 7: Thursday 8: Friday 9: Saturday 10: Sunday | Default: 0 Range: 0 to 10 | 280 |
| S2-19 (3218) | Sequence Timer 4 Selection | Sets the action that occurs when sequence timer 4 is active. 0: Digital output only 1: Run 2: Run - PI disable | Default: 0 Range: 0 to 2 | 280 |
| S2-20 (3219) | Sequence Timer 4 Reference Source | Selects the frequency reference source used for running the drive when sequence timer 4 is active (only applicable when S2-19 is set to 1 or 2). 0: Operator (d1-01) 1: Operator (d1-02) 2: Operator (d1-03) 3: Operator (d1-04) 4: Terminals 5: Serial communication 6: Option card 7: Pulse input | Default: 0 Range: 0 to 7 | 281 |

<I> Setting the sequence timer start time to a higher value than the sequence timer stop time disables that sequence timer.

◆ S3: Secondary PI (PI2) Control

| No. (Addr. Hex) | Name | Description | Values | Page |
|--|-------------------------------|--|--|------|
| S3-01 (321A)  | Secondary PI Enable Selection | Determines when the secondary PI controller is enabled. 0: Disabled 1: Always 2: Drive running 3: Motor running Note: Setting 3 does not run the motor at zero speed, baseblock, or in DC injection. | Default: 0 Range: 0 to 3 | 281 |
| S3-02 (321B)  | Secondary PI User Display | Sets the scale value of 100% PI input. | Default: 10000 Min.: 0 Max.: 60000 | 282 |
| S3-03 (321C)  | Secondary PI Display Digits | Sets the decimal place display for secondary PI units. 0: No decimal places 1: One decimal place 2: Two decimal places 3: Three decimal places | Default: 2 Range: 0 to 3 | 282 |

B.12 S: Special Application

| No. (Addr. Hex) | Name | Description | Values | Page |
|--|---|---|---|------|
| S3-04 (321D)  | Secondary PI Unit Selection | Sets the units for the secondary PI control function. 0: Inch of water (WC) 1: Pounds per square inch (PSI) 2: Gallons per minute (GPM) 3: Degrees Fahrenheit (F) 4: Cubic feet per minute (CFM) 5: Cubic meters per hour (CMH) 6: Liters per hour (LPH) 7: Liters per second (LPS) 8: Bar (Bar) 9: Pascals (Pa) 10: Degrees Celsius (C) 11: Meters (Mtr) (Ft: Feet) 12: Liters per minute (LPM) 13: Cubic meters per minute (CMM) 14: No unit 15: Percentage (%) | Default: 15 Range: 0 to 15 | 282 |
| S3-05 (321E)  | Secondary PI Setpoint Value | Sets the secondary PI controller target value. | Default: 0.00 <1> Min.: 0.00 Max.: 600.00 <2> | 282 |
| S3-06 (321F)  | Secondary PI Proportional Gain Setting | Sets the proportional gain of the secondary PI controller. A setting of 0.00 disables P control. | Default: 1.00 Min.: 0.00 Max.: 25.00 | 283 |
| S3-07 (3220)  | Secondary PI Integral Time Setting | Sets the integral time for the secondary PI controller. A setting of 0.0 s disables integral control. | Default: 1.0 s Min.: 0.0 Max.: 360.0 | 283 |
| S3-08 (3221)  | Secondary PI Integral Limit Setting | Sets the maximum output possible from the integrator. | Default: 100.0% Min.: 0.0 Max.: 100.0 | 283 |
| S3-09 (3222)  | Secondary PI Output Upper Limit | Sets the maximum output possible from the secondary PI controller. | Default: 100.0% Min.: 0.0 Max.: 100.0 | 283 |
| S3-10 (3223)  | Secondary PI Output Lower Limit | Sets the minimum output possible from the secondary PI controller. | Default: 0.00% Min.: -100.00 Max.: 100.00 | 283 |
| S3-11 (3224)  | Secondary PI Output Level Selection | Sets the secondary PI controller output direction. 0: Normal Output (direct acting) 1: Reverse Output (reverse acting) | Default: 0 Range: 0, 1 | 283 |
| S3-12 (3225)  | Secondary PI Disable Mode | Selects the secondary PI controller output when disabled. 0: No output (0%) 1: Lower Limit (S3-10) 2: Setpoint | Default: 0 Range: 0 to 2 | 283 |
| S3-13 (3226)  | Secondary PI Low Feedback Detection Level | Sets the secondary PI low feedback detection level. | Default: 0.00 <1> Min.: 0.00 Max.: 600.00 <2> | 283 |
| S3-14 (3227)  | Secondary PI Low Feedback Detection Time | Sets the secondary PI low feedback detection delay time in seconds. | Default: 1.0 s Min.: 0.0 Max.: 25.5 | 284 |
| S3-15 (3228)  | Secondary PI High Feedback Level | Sets the secondary PI high feedback detection level. | Default: 100.00 <1> Min.: 0.00 Max.: 600.00 <2> | 284 |
| S3-16 (3229)  | Secondary PI High Feedback Detection Time | Sets the secondary PI high feedback detection delay time in seconds. | Default: 1.0 s Min.: 0.0 Max.: 25.5 | 284 |
| S3-17 (322A)  | Secondary PI Feedback Detection Selection | Selects when secondary PI controller low and high feedback detection are active. 0: Secondary PI enabled 1: Always | Default: 0 Range: 0, 1 | 284 |

<1> Unit is determined by S3-04.

<2> Upper limit is S3-02, decimal placeholder is determined by S3-03.

◆ S6: P1000 Protection

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|---|--|--|------|
| S6-01 (3236) | Emergency Override Speed | Sets the speed command used in emergency override mode when S6-02 = 0. | Default: 0.00 Hz Min.: 0.00 Max.: 240.00 | 284 |
| S6-02 (3237) | Emergency Override Reference Selection | Selects the emergency override speed source. 0: Use S6-01 Reference 1: Use Frequency Reference | Default: 0 Range: 0, 1 | 284 |
| S6-07 (323C) | Output Phase Loss Level for Dynamic Noise Control | Reduces the output phase loss level when Dynamic Noise Control is active. | Default: 100.0% Min.: 10.0 Max.: 100.0 | 285 |

◆ S7: Output Current Limit

| No. (Addr. Hex) | Name | Description | Values | Page |
|------------------|---------------------------------|--|---|------|
| S7-01 (324B) <1> | Output Current Limit Select | Sets the function to enable and disable the output current regulator. 0: Disabled 1: Enabled | Default: 0 Range: 0, 1 | – |
| S7-02 (324C) <1> | Current Limit | Sets the current limit. The value is internally limited to 300% of drive rated current. | Default: 0.0 A Min.: 0.0 Max.: 1000.0 | – |
| S7-10 (3250) <1> | Single Phase Foldback Selection | Sets the function to enable and disable the single-phase ripple regulator. 0: Disabled 1: Enabled | Default: 1 Range: 0, 1 | – |
| S7-11 (3251) <1> | Ripple Regulator Setpoint | Set as a percentage of the maximum amount of ripple allowed before the drive will detect and input phase loss fault. | Default: 95.0% Min.: 0.0 Max.: 200.0 | – |

<1> Available in drive software versions PRG: 8503 and later.

B.13 T: Motor Tuning

Enter data into the following parameters to tune the motor and drive for optimal performance.

◆ T1: Induction Motor Auto-Tuning

| No. (Addr. Hex) | Name | Description | Values | Page |
|-----------------|----------------------------|---|---|------|
| T1-01 (701) | Auto-Tuning Mode Selection | 2: Stationary Auto-Tuning for Line-to-Line Resistance 3: Rotational Auto-Tuning for V/f Control (necessary for Energy Savings and Speed Estimation Speed Search) | Default: 2 Range: 2, 3 | 132 |
| T1-02 (702) | Motor Rated Power | Sets the motor rated power as specified on the motor nameplate. Note: Use the following formula to convert horsepower into kilowatts: 1HP = 0.746 kW. | Default: <1> Min.: 0.00 kW Max.: 650.00 kW | 132 |
| T1-03 (703) | Motor Rated Voltage | Sets the motor rated voltage as specified on the motor nameplate. | Default: 200.0 V <2> Min: 0.0 Max: 255.0 <2> | 132 |
| T1-04 (704) | Motor Rated Current | Sets the motor rated current as specified on the motor nameplate. | Default: <1> Min.: 10% of drive rated current Max.: 200% of drive rated current | 133 |
| T1-05 (705) | Motor Base Frequency | Sets the rated frequency of the motor as specified on the motor nameplate. | Default: 60.0 Hz Min.: 0.0 Max.: 400.0 | 133 |
| T1-06 (706) | Number of Motor Poles | Sets the number of motor poles as specified on the motor nameplate. | Default: 4 Min.: 2 Max.: 48 | 133 |
| T1-07 (707) | Motor Base Speed | Sets the rated speed of the motor as specified on the motor nameplate. | Default: 1750 r/min Min.: 0 Max.: 24000 | 133 |
| T1-11 (70B) | Motor Iron Loss | Sets the iron loss for determining the Energy Saving coefficient. The value is set to E2-10 (motor iron loss) set when the power is cycled. If T1-02 is changed, a default value appropriate for the motor capacity that was entered will appear. | Default: 14 W <3> Min.: 0 Max.: 65535 | 133 |

<1> Default setting is dependent on parameter o2-04, Drive Model Selection.

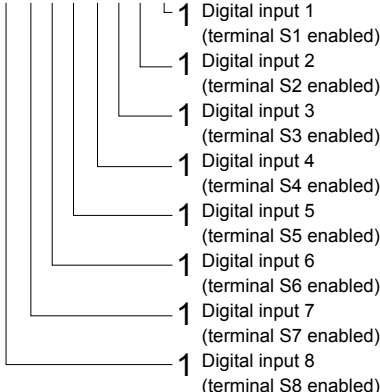
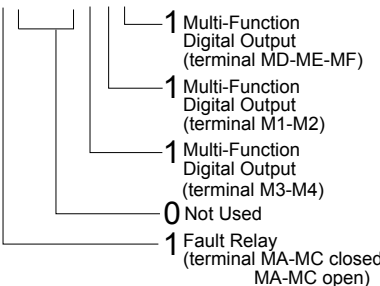
<2> Values shown are specific to 200 V class drives. Double the value for 400 V class drives. Multiply the value by 2.875 for 600 V class drives.

<3> Default setting value differs depending on the motor code value and motor parameter settings.

B.14 U: Monitors

Monitor parameters allow the user to view drive status, fault information, and other data concerning drive operation.

◆ U1: Operation Status Monitors

| No. (Addr. Hex) | Name | Description | Analog Output Level | Unit |
|-----------------|--------------------------|--|--|---------|
| U1-01 (40) | Frequency Reference | Monitors the frequency reference. Display units are determined by o1-03. | 10 V: Max frequency | 0.01 Hz |
| U1-02 (41) | Output Frequency | Displays the output frequency. Display units are determined by o1-03. | 10 V: Max frequency | 0.01 Hz |
| U1-03 (42) | Output Current | Displays the output current. | 10 V: Drive rated current | <1> <2> |
| U1-04 (43) | Control Method | 0: V/f Control | No signal output available | - |
| U1-06 (45) | Output Voltage Reference | Displays the output voltage. | 10 V: 200 Vrms <3> | 0.1 Vac |
| U1-07 (46) | DC Bus Voltage | Displays the DC bus voltage. | 10 V: 400 V <3> | 1 Vdc |
| U1-08 (47) | Output Power | Displays the output power (this value is calculated internally). | 10 V: Drive capacity (motor capacity) kW | <4> |
| U1-10 (49) | Input Terminal Status | Displays the input terminal status. U1 - 10 = 00000000  <ul style="list-style-type: none"> 1 Digital input 1 (terminal S1 enabled) 1 Digital input 2 (terminal S2 enabled) 1 Digital input 3 (terminal S3 enabled) 1 Digital input 4 (terminal S4 enabled) 1 Digital input 5 (terminal S5 enabled) 1 Digital input 6 (terminal S6 enabled) 1 Digital input 7 (terminal S7 enabled) 1 Digital input 8 (terminal S8 enabled) | No signal output available | - |
| U1-11 (4A) | Output Terminal Status | Displays the output terminal status. U1 - 11 = 00000000  <ul style="list-style-type: none"> 1 Multi-Function Digital Output (terminal MD-ME-MF) 1 Multi-Function Digital Output (terminal M1-M2) 1 Multi-Function Digital Output (terminal M3-M4) 0 Not Used 1 Fault Relay (terminal MA-MC closed MA-MC open) | No signal output available | - |

B.14 U: Monitors

| No. (Addr. Hex) | Name | Description | Analog Output Level | Unit |
|-----------------|-------------------------------------|---|----------------------------|---------|
| U1-12 (4B) | Drive Status | Verifies the drive operation status. U1 - 12=00000000 | No signal output available | – |
| U1-13 (4E) | Terminal A1 Input Level | Displays the signal level to analog input terminal A1. | 10 V: 100% | 0.1% |
| U1-14 (4F) | Terminal A2 Input Level | Displays the signal level to analog input terminal A2. | 10 V: 100% | 0.1% |
| U1-15 (50) | Terminal A3 Input Level | Displays the signal level to analog input terminal A3. | 10 V: 100% | 0.1% |
| U1-16 (53) | Output Frequency after Soft Starter | Displays output frequency with ramp time and S-curves. Units determined by o1-03. | 10 V: Max frequency | 0.01 Hz |
| U1-18 (61) | oPE Fault Parameter | Displays the parameter number that caused the oPE02 operation error. | No signal output available | – |
| U1-19 (66) | MEMOBUS/Modbus Error Code | Displays the contents of a MEMOBUS/Modbus error. U1 - 19=00000000 | No signal output available | – |
| U1-24 (7D) | Input Pulse Monitor | Displays the frequency to pulse train input terminal RP. | Determined by H6-02 | 1 Hz |
| U1-25 (4D) | Software Number (Flash) | FLASH ID | No signal output available | – |
| U1-26 (5B) | Software No. (ROM) | ROM ID | No signal output available | – |
| U1-29 (7AA) | Software No. (PWM) | PWM ID | No signal output available | – |
| U1-75 (851) | Time-Hour/Minute | Displays the current time (Hours and Minutes). | No signal output available | – |
| U1-76 (852) | Date – Year | Displays the current year. | No signal output available | – |
| U1-77 (853) | Date – Month/Day | Displays the current date (Month and Date). | No signal output available | – |
| U1-78 (854) | Date – Week Day | Displays the current date of the week. 0: Sunday 1: Monday 2: Tuesday 3: Wednesday 4: Thursday 5: Friday 6: Saturday | No signal output available | – |

<1> The number of decimal places in the parameter value depends on the drive model and the ND selection. This value has two decimal places (0.01 A) if the drive is set for a maximum applicable motor capacity up to and including 11 kW, and one decimal place (0.1 A) if the maximum applicable motor capacity is higher than 11 kW.

<2> When reading the value of this monitor via MEMOBUS/Modbus, a value of 8192 is equal to 100% of the drive rated output current.

- <3> Values shown are specific to 200 V class drives. Double the value for 400 V class drives. Multiply the value by 2.875 for 600 V class drives.
- <4> The display resolution depends on the ND selection. This value has two decimal places (0.01 kW) if the drive is set for a maximum applicable motor capacity up to and including 11 kW, and one decimal place (0.1 kW) if the maximum applicable motor capacity is higher than 11 kW.

◆ U2: Fault Trace

| No. (Addr. Hex) | Name | Description | Analog Output Level | Unit |
|-----------------|--|--|----------------------------|---------|
| U2-01 (80) | Current Fault | Displays the current fault. | No signal output available | – |
| U2-02 (81) | Previous Fault | Displays the previous fault. | No signal output available | – |
| U2-03 (82) | Frequency Reference at Previous Fault | Displays the frequency reference at the previous fault. | No signal output available | 0.01 Hz |
| U2-04 (83) | Output Frequency at Previous Fault | Displays the output frequency at the previous fault. | No signal output available | 0.01 Hz |
| U2-05 (84) | Output Current at Previous Fault | Displays the output current at the previous fault. | No signal output available | <1> <2> |
| U2-07 (86) | Output Voltage at Previous Fault | Displays the output voltage at the previous fault. | No signal output available | 0.1 Vac |
| U2-08 (87) | DC Bus Voltage at Previous Fault | Displays the DC bus voltage at the previous fault. | No signal output available | 1 Vdc |
| U2-09 (88) | Output Power at Previous Fault | Displays the output power at the previous fault. | No signal output available | 0.1 kW |
| U2-11 (8A) | Input Terminal Status at Previous Fault | Displays the input terminal status at the previous fault. Displayed as in U1-10. | No signal output available | – |
| U2-12 (8B) | Output Terminal Status at Previous Fault | Displays the output status at the previous fault. Displays the same status displayed in U1-11. | No signal output available | – |
| U2-13 (8C) | Drive Operation Status at Previous Fault | Displays the operation status of the drive at the previous fault. Displays the same status displayed in U1-12. | No signal output available | – |
| U2-14 (8D) | Cumulative Operation Time at Previous Fault | Displays the cumulative operation time at the previous fault. | No signal output available | 1 h |
| U2-15 (7E0) | Soft Starter Speed Reference at Previous Fault | Displays the speed reference for the soft starter at the previous fault. | No signal output available | 0.01 Hz |
| U2-20 (8E) | Heatsink Temperature at Previous Fault | Displays the temperature of the heatsink when the most recent fault occurred. | No signal output available | 1 °C |
| U2-27 (7FA) | Motor Temperature at Previous Fault (NTC) | Displays the temperature of the motor when the most recent fault occurred. | No signal output available | 1 °C |
| U2-30 (3008) | Date Year at Previous Fault | Displays the year when the most recent fault occurred. | No signal output available | – |
| U2-31 (3009) | Date Month and Day at Previous Fault | Displays the date and day when the most recent fault occurred. | No signal output available | – |
| U2-32 (300A) | Time Hours and Minutes at Previous Fault | Displays the time when the most recent fault occurred. | No signal output available | – |

- <1> The number of decimal places in the parameter value depends on the drive model and the ND selection. This value has two decimal places (0.01 A) if the drive is set for a maximum applicable motor capacity up to and including 11 kW, and one decimal place (0.1 A) if the maximum applicable motor capacity is higher than 11 kW.
- <2> When reading the value of this monitor via MEMOBUS/Modbus, a value of 8192 is equal to 100% of the drive rated output current.

◆ U3: Fault History

| No. (Addr. Hex) | Name | Description | Analog Output Level | Unit |
|--|--|--|-------------------------------|------|
| U3-01 to U3-04 (90 to 93 (800 to 803)) | First to 4th Most Recent Fault | Displays the first to the fourth most recent faults. | No signal output available | – |
| U3-05 to U3-10 (804 to 809) | 5th to 10th Most Recent Fault | Displays the fifth to the tenth most recent faults. After ten faults, data for the oldest fault is deleted. The most recent fault appears in U3-01, with the next most recent fault appearing in U3-02. The data is moved to the next monitor parameter each time a fault occurs. | No signal output available | – |
| U3-11 to U3-14 (94 to 97 (80A to 80D)) | Cumulative Operation Time at 1st to 4th Most Recent Fault | Displays the cumulative operation time when the first to the fourth most recent faults occurred. | No signal output available | 1 h |
| U3-15 to U3-20 (80E to 813) | Cumulative Operation Time at 5th to 10th Most Recent Fault | Displays the cumulative operation time when the fifth to the tenth most recent faults occurred. | No signal output available | 1 h |
| U3-21 (300B) | Date Year at Most Recent Fault | Displays the year when the most recent fault occurred. | No signal output available | – |
| U3-22 (300C) | Date Month and Day at Most Recent Fault | Displays the date and day when the most recent faults occurred. | No signal output available | – |
| U3-23 (300D) | Time Hours and Minutes at Most Recent Fault | Displays the time when the most recent fault occurred. | No signal output available | – |
| U3-24 (300E) | Date Year at 2nd Most Recent Fault | Displays the year when the second most recent fault occurred. | No signal output available | – |
| U3-25 (300F) | Date Month and Day at 2nd Most Recent Fault | Displays the date and day when the second most recent fault occurred. | No signal output available | – |
| U3-26 (3010) | Time Hours and Minutes at 2nd Most Recent Fault | Displays the time when the second most recent fault occurred. | No signal output available | – |
| U3-27 (3011) | Date Year at 3rd Most Recent Fault | Displays the year when the most third recent fault occurred. | No signal output available | – |
| U3-28 (3012) | Date Month and Day at 3rd Most Recent Fault | Displays the date and day when the third most recent fault occurred. | No signal output available | – |
| U3-29 (3013) | Time Hours and Minutes at 3rd Most Recent Fault | Displays the time when the third most recent fault occurred. | No signal output available | – |
| U3-30 (3014) | Date Year at 4th Most Recent Fault | Displays the year when the fourth most recent fault occurred. | No signal output available | – |
| U3-31 (3015) | Date Month and Day at 4th Most Recent Fault | Displays the date and day when the fourth most recent fault occurred. | No signal output available | – |
| U3-32 (3016) | Time Hours and Minutes at 4th Most Recent Fault | Displays the time when the fourth most recent fault occurred. | No signal output available | – |
| U3-33 (3017) | Date Year at 5th Most Recent Fault | Displays the year when the fifth most recent fault occurred. | No signal output available | – |
| U3-34 (3018) | Date Month and Day at 5th Most Recent Fault | Displays the date and day when the fifth most recent fault occurred. | No signal output available | – |
| U3-35 (3019) | Time Hours and Minutes at 5th Most Recent Fault | Displays the time when the fifth most recent fault occurred. | No signal output available | – |
| U3-36 (301A) | Date Year at 6th Most Recent Fault | Displays the year when the sixth most recent fault occurred. | No signal output available | – |
| U3-37 (301B) | Date Month and Day at 6th Most Recent Fault | Displays the date and day when the sixth most recent fault occurred. | No signal output available | – |
| U3-38 (301C) | Time Hours and Minutes at 6th Most Recent Fault | Displays the time when the most sixth recent fault occurred. | No signal output available | – |
| U3-39 (301D) | Date Year at 7th Most Recent Fault | Displays the year when the most seventh recent fault occurred. | No signal output available | – |
| U3-40 (301E) | Date Month and Day at 7th Most Recent Fault | Displays the date and day when the seventh most recent fault occurred. | No signal output available | – |

| No. (Addr. Hex) | Name | Description | Analog Output Level | Unit |
|-----------------|---|---|----------------------------|------|
| U3-41 (301F) | Time Hours and Minutes at 7th Most Recent Fault | Displays the time when the seventh most recent fault occurred. | No signal output available | – |
| U3-42 (3020) | Date Year at 8th Most Recent Fault | Displays the year when the eighth most recent fault occurred. | No signal output available | – |
| U3-43 (3021) | Date Month and Day 8th at Most Recent Fault | Displays the date and day when the eighth most recent fault occurred. | No signal output available | – |
| U3-44 (3022) | Time Hours and Minutes at 8th Most Recent Fault | Displays the time when the eighth most recent fault occurred. | No signal output available | – |
| U3-45 (3023) | Date Year at 9th Most Recent Fault | Displays the year when the ninth most recent fault occurred. | No signal output available | – |
| U3-46 (3024) | Date Month and Day at 9th Most Recent Fault | Displays the date and day when the ninth most recent fault occurred. | No signal output available | – |
| U3-47 (3025) | Time Hours and Minutes at 9th Most Recent Fault | Displays the time when the ninth most recent fault occurred. | No signal output available | – |
| U3-48 (3026) | Date Year at 10th Most Recent Fault | Displays the year when the tenth most recent fault occurred. | No signal output available | – |
| U3-49 (3027) | Date Month and Day at 10th Most Recent Fault | Displays the date and day when the tenth most recent fault occurred. | No signal output available | – |
| U3-50 (3028) | Time Hours and Minutes at 10th Most Recent | Displays the time when the tenth most recent fault occurred. | No signal output available | – |

◆ U4: Maintenance Monitors

| No. (Addr. Hex) | Name | Description | Analog Output Level | Unit |
|-----------------|--------------------------------------|---|----------------------------|--------|
| U4-01 (4C) | Cumulative Operation Time | Displays the cumulative operation time of the drive. The value for the cumulative operation time counter can be reset in parameter o4-01. Use parameter o4-02 to determine if the operation time should start as soon as the power is switched on or only while the Run command is present. The maximum number displayed is 99999, after which the value is reset to 0. | No signal output available | 1 h |
| U4-02 (75) | Number of Run Commands | Displays the number of times the Run command is entered. Reset the number of Run commands using parameter o4-13. This value will reset to 0 and start counting again after reaching 65535. | No signal output available | 1 Time |
| U4-03 (67) | Cooling Fan Operation Time | Displays the cumulative operation time of the cooling fan. The default value for the fan operation time is reset in parameter o4-03. This value will reset to 0 and start counting again after reaching 99999. | No signal output available | 1 h |
| U4-04 (7E) | Cooling Fan Maintenance | Displays main cooling fan usage time as a percentage of its expected performance life. Parameter o4-03 can be used to reset this monitor. Replace the fan when this monitor reaches 90%. | No signal output available | 1% |
| U4-05 (7C) | Capacitor Maintenance | Displays main circuit capacitor usage time as a percentage of their expected performance life. Parameter o4-05 can be used to reset this monitor. Replace the capacitor when this monitor reaches 90%. | No signal output available | 1% |
| U4-06 (7D6) | Soft Charge Bypass Relay Maintenance | Displays the soft charge bypass relay maintenance time as a percentage of its estimated performance life. Parameter o4-07 can be used to reset this monitor. Replace the soft charge bypass relay when this monitor reaches 90%. | No signal output available | 1% |
| U4-07 (7D7) | IGBT Maintenance | Displays IGBT usage time as a percentage of the expected performance life. Parameter o4-09 can be used to reset this monitor. Replace the IGBT when this monitor reaches 90%. | No signal output available | 1% |
| U4-08 (68) | Heatsink Temperature | Displays the heatsink temperature. | 10 V: 100 °C | 1 °C |
| U4-09 (5E) | LED Check | Lights all segments of the LED to verify that the display is working properly. | No signal output available | – |
| U4-10 (5C) | kWh, Lower 4 Digits | Monitors the drive output power. The value is shown as a 9-digit number displayed across two monitor parameters, U4-10 and U4-11. | No signal output available | 1 kWh |
| U4-11 (5D) | kWh, Upper 5 Digits | Example: 12345678.9 kWh is displayed as: U4-10: 678.9 kWh U4-11: 12345 MWh | No signal output available | 1 MWh |

Parameter List

B

B.14 U: Monitors

| No. (Addr. Hex) | Name | Description | Analog Output Level | Unit |
|-----------------|---|--|----------------------------|---------------|
| U4-13 (7CF) | Peak Hold Current | Displays the highest current value that occurred during run. | No signal output available | 0.01 A </> |
| U4-14 (7D0) | Peak Hold Output Frequency | Displays the output frequency when the current value shown in U4-13 occurred. | No signal output available | 0.01 Hz |
| U4-16 (7D8) | Motor Overload Estimate (oL1) | Shows the value of the motor overload detection accumulator. 100% is equal to the oL1 detection level. | 10 V: 100% | 0.1% |
| U4-18 (7DA) | Frequency Reference Source Selection | Displays the source for the frequency reference as XY-nn. X: indicates which reference is used: 1 = Reference 1 (b1-01) 2 = Reference 2 (b1-15) Y-nn: indicates the reference source 0-01 = Digital operator 1-01 = Analog (terminal A1) 1-02 = Analog (terminal A2) 1-03 = Analog (terminal A3) 2-02 to 17 = Multi-step speed (d1-02 to 17) 3-01 = MEMOBUS/Modbus communications 4-01 = Communication option card 5-01 = Pulse input | No signal output available | – |
| U4-19 (7DB) | Frequency Reference from MEMOBUS/Modbus Comm. | Displays the frequency reference provided by MEMOBUS/Modbus (decimal). | No signal output available | 0.01% |
| U4-20 (7DC) | Option Frequency Reference | Displays the frequency reference input by an option card (decimal). | No signal output available | – |
| U4-21 (7DD) | Run Command Source Selection | Displays the source for the Run command as XY-nn. X: Indicates which Run source is used: 1 = Reference 1 (b1-02) 2 = Reference 2 (b1-16) Y: Input power supply data 0 = Digital operator 1 = External terminals 3 = MEMOBUS/Modbus communications 4 = Communication option card nn: Run command limit status data 00: No limit status. 01: Run command was left on when stopped in the PRG mode 02: Run command was left on when switching from LOCAL to REMOTE operation 03: Waiting for soft charge bypass contactor after power up (Uv or Uv1 flashes after 10 s) 04: Waiting for “Run command prohibited” time period to end 05: Fast Stop (digital input, digital operator) 06: b1-17 (Run command given at power-up) 07: During baseblock while coast to stop with timer 08: Frequency reference is below minimal reference during baseblock 09: Waiting for Enter command | No signal output available | – |
| U4-22 (7DE) | MEMOBUS/Modbus Communications Reference | Displays the drive control data set by MEMOBUS/Modbus communications register no. 0001H as a four-digit hexadecimal number. | No signal output available | – |
| U4-23 (7DF) | Communication Option Card Reference | Displays drive control data set by an option card as a four-digit hexadecimal number. | No signal output available | – |
| U4-32 (7FB) | Motor Temperature (NTC) | Displays the motor temperature (NTC). U4-32 will display “20 °C” when a multi-function analog input is not set for motor thermistor input (H1-□□ = 17H). | 200 °C | 1 °C |
| U4-37 (1044) | oH Alarm Location Monitor | Displays the module where the oH alarm occurred as a binary number. | No signal output available | – |
| U4-38 (1045) | FAn Alarm Location Monitor | Displays the module where the FAn alarm occurred as a binary number. | No signal output available | – |
| U4-39 (1046) | voF Alarm Location Monitor | Displays the module where the voF alarm occurred as a binary number. | No signal output available | – |

</> When reading the value of this monitor via MEMOBUS/Modbus, a value of 8192 is equal to 100% of the drive rated output current.

◆ U5: PID Monitors

| No. (Addr. Hex) | Name | Description | Analog Output Level | Unit |
|-----------------|----------------------------|--|----------------------------|--------------|
| U5-01 (57) | PID Feedback 1 | Displays the PID feedback value. | 10 V: 100% | 0.01% <1> |
| U5-02 (63) | PID Input | Displays the amount of PID input (deviation between PID setpoint and feedback). | 10 V: 100% | 0.01% |
| U5-03 (64) | PID Output | Displays PID control output. | 10 V: 100% | 0.01% |
| U5-04 (65) | PID Setpoint | Displays the PID setpoint. | 10 V: 100% | 0.01% <1> |
| U5-05 (7D2) | PID Differential Feedback | Displays the 2nd PID feedback value if differential feedback is used (H3-□□ = 16). | 10 V: 100% | 0.01% |
| U5-06 (7D3) | PID Adjusted Feedback | Displays the difference of both feedback values if differential feedback is used (U5-01 - U5-05). If differential feedback is not used, then U5-01 and U5-06 will be the same. | 10 V: 100% | 0.01% |
| U5-14 (86B) | PI Output 2 Upper 4 Digits | Displays the custom PI output. U5-14 shows the upper 4 digits while U5-15 shows the lower 4 digits. Monitors are scaled by b5-43 and b5-44 | No signal output available | 1 <2> |
| U5-15 (86C) | PI Output 2 Lower 4 Digits | Displays the custom PI output. U5-14 shows the upper 4 digits while U5-15 shows the lower 4 digits. Monitors are scaled by b5-43 and b5-44. | No signal output available | 0.01 <2> |
| U5-17 (86E) | PI2 Setpoint | Displays the secondary PI setpoint. | Dependent upon S3-02 | <3> |
| U5-18 (86F) | PI2 Feedback | Displays the secondary PI feedback value. | Dependent upon S3-02 | <3> |
| U5-19 (870) | PI2 Input | Displays the secondary PI input (deviation between PI target and feedback). | Dependent upon S3-02 | <3> |
| U5-20 (871) | PI2 Output | Displays the secondary PI control output. | Dependent upon S3-02 | <3> |
| U5-30 (3000) | Time Hr Min HHMM | Displays the current time (Hours and Minutes). | No signal output available | 1 |
| U5-31 (3001) | Date Year | Displays the current year. | No signal output available | 1 |
| U5-32 (3002) | Date Mo Day MMDD | Displays the current date (Month and Day). | No signal output available | 1 |
| U5-33 (3003) | Date Week 000W | Displays the current date of the week. 0: Sunday 1: Monday 2: Tuesday 3: Wednesday 4: Thursday 5: Friday 6: Saturday | No signal output available | 1 |
| U5-99 (1599) | PID Setpoint Command | Displays the PID Setpoint commanded by the source. | No signal output available | 0.01% <1> |

<1> Unit, range and resolution is determined by b5-20, b5-38, b5-39, and b5-46

<2> Unit is determined by b5-41

<3> Unit is determined by S3-04.

◆ U6: Operation Status Monitors

| No. (Addr. Hex) | Name | Description | Analog Output Level | Unit |
|-----------------|------------------------------|--|-------------------------------------|------|
| U6-01 (51) | Motor Secondary Current (Iq) | Displays the value of the motor secondary current (Iq). Motor rated secondary current is 100%. | 10 V: Motor secondary rated current | 0.1% |

Note: Fault histories are not kept when CPF00, CPF01, CPF06, CPF24, oFA00, oFb00, oFC00, Uv1, Uv2, or Uv3 occur.

B.15 V/f Pattern Default Values

The following tables show the V/f pattern setting default values depending on the V/f pattern selection (E1-03).

Table B.3 E1-03 V/f Pattern Settings for Drive Capacity: 2A0004 to 2A0021, 4A0002 to 4A0011, and 5A0003 to 5A0009

| No. | Unit | V/f Control | | | | | | | | | | | | | | | |
|-----------|------|-------------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|
| | | 0 | 1 | 2 | 3 | 4 | 5 | 6 | 7 | 8 | 9 | A | B | C | D | E | F |
| E1-03 | - | 0 | 1 | 2 | 3 | 4 | 5 | 6 | 7 | 8 | 9 | A | B | C | D | E | F |
| E1-04 | Hz | 50.0 | 60.0 | 60.0 | 72.0 | 50.0 | 50.0 | 60.0 | 60.0 | 50.0 | 50.0 | 60.0 | 60.0 | 90.0 | 120.0 | 180.0 | 60.0 |
| E1-05 <1> | V | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 230.0 |
| E1-06 | Hz | 50.0 | 60.0 | 50.0 | 60.0 | 50.0 | 50.0 | 60.0 | 60.0 | 50.0 | 50.0 | 60.0 | 60.0 | 60.0 | 60.0 | 60.0 | 60.0 |
| E1-07 | Hz | 2.5 | 3.0 | 3.0 | 3.0 | 25.0 | 25.0 | 30.0 | 30.0 | 2.5 | 2.5 | 3.0 | 3.0 | 3.0 | 3.0 | 3.0 | 3.0 |
| E1-08 <2> | V | 15.0 | 15.0 | 15.0 | 15.0 | 35.0 | 50.0 | 35.0 | 50.0 | 19.0 | 24.0 | 19.0 | 24.0 | 15.0 | 15.0 | 15.0 | 17.3 |
| E1-09 | Hz | 1.3 | 1.5 | 1.5 | 1.5 | 1.3 | 1.3 | 1.5 | 1.5 | 1.3 | 1.3 | 1.5 | 1.5 | 1.5 | 1.5 | 1.5 | 1.5 |
| E1-10 <2> | V | 9.0 | 9.0 | 9.0 | 9.0 | 8.0 | 9.0 | 8.0 | 9.0 | 11.0 | 13.0 | 11.0 | 15.0 | 9.0 | 9.0 | 9.0 | 10.2 |

<2> Values shown here are specific to 200 V class drives. Double the value for 400 V class drives. Multiply the value by 2.875 for 600 V class drives.

Table B.4 E1-03 V/f Pattern Settings for Drive Capacity: 2A0030 to 2A0211, 4A0018 to 4A0103, and 5A0011 to 5A0077

| No. | Unit | V/f Control | | | | | | | | | | | | | | | |
|-----------|------|-------------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|
| | | 0 | 1 | 2 | 3 | 4 | 5 | 6 | 7 | 8 | 9 | A | B | C | D | E | F <1> |
| E1-03 | - | 0 | 1 | 2 | 3 | 4 | 5 | 6 | 7 | 8 | 9 | A | B | C | D | E | F <1> |
| E1-04 | Hz | 50.0 | 60.0 | 60.0 | 72.0 | 50.0 | 50.0 | 60.0 | 60.0 | 50.0 | 50.0 | 60.0 | 60.0 | 90.0 | 120.0 | 180.0 | 60.0 |
| E1-05 <2> | V | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 230.0 |
| E1-06 | Hz | 50.0 | 60.0 | 50.0 | 60.0 | 50.0 | 50.0 | 60.0 | 60.0 | 50.0 | 50.0 | 60.0 | 60.0 | 60.0 | 60.0 | 60.0 | 60.0 |
| E1-07 | Hz | 2.5 | 3.0 | 3.0 | 3.0 | 25.0 | 25.0 | 30.0 | 30.0 | 2.5 | 2.5 | 3.0 | 3.0 | 3.0 | 3.0 | 3.0 | 3.0 |
| E1-08 <2> | V | 14.0 | 14.0 | 14.0 | 14.0 | 35.0 | 50.0 | 35.0 | 50.0 | 18.0 | 23.0 | 18.0 | 23.0 | 14.0 | 14.0 | 14.0 | 16.1 |
| E1-09 | Hz | 1.3 | 1.5 | 1.5 | 1.5 | 1.3 | 1.3 | 1.5 | 1.5 | 1.3 | 1.3 | 1.5 | 1.5 | 1.5 | 1.5 | 1.5 | 1.5 |
| E1-10 <2> | V | 7.0 | 7.0 | 7.0 | 7.0 | 6.0 | 7.0 | 6.0 | 7.0 | 9.0 | 11.0 | 9.0 | 13.0 | 7.0 | 7.0 | 7.0 | 8.1 |

<1> This value determines the default values for E1-04 through E1-10.

<2> Values shown here are specific to 200 V class drives. Double the value for 400 V class drives. Multiply the value by 2.875 for 600 V class drives.

Table B.5 E1-03 V/f Pattern Settings for Drive Capacity: 2A0250 to 2A0415, 4A0139 to 4A1200, and 5A0099 to 5A0242

| No. | Unit | V/f Control | | | | | | | | | | | | | | | |
|-----------|------|-------------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|
| | | 0 | 1 | 2 | 3 | 4 | 5 | 6 | 7 | 8 | 9 | A | B | C | D | E | F <1> |
| E1-03 | - | 0 | 1 | 2 | 3 | 4 | 5 | 6 | 7 | 8 | 9 | A | B | C | D | E | F <1> |
| E1-04 | Hz | 50.0 | 60.0 | 60.0 | 72.0 | 50.0 | 50.0 | 60.0 | 60.0 | 50.0 | 50.0 | 60.0 | 60.0 | 90.0 | 120.0 | 180.0 | 60.0 |
| E1-05 <2> | V | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 200.0 | 230.0 |
| E1-06 | Hz | 50.0 | 60.0 | 50.0 | 60.0 | 50.0 | 50.0 | 60.0 | 60.0 | 50.0 | 50.0 | 60.0 | 60.0 | 60.0 | 60.0 | 60.0 | 60.0 |
| E1-07 | Hz | 2.5 | 3.0 | 3.0 | 3.0 | 25.0 | 25.0 | 30.0 | 30.0 | 2.5 | 2.5 | 3.0 | 3.0 | 3.0 | 3.0 | 3.0 | 3.0 |
| E1-08 <2> | V | 12.0 | 12.0 | 12.0 | 12.0 | 35.0 | 50.0 | 35.0 | 50.0 | 15.0 | 20.0 | 15.0 | 20.0 | 12.0 | 12.0 | 12.0 | 13.8 |
| E1-09 | Hz | 1.3 | 1.5 | 1.5 | 1.5 | 1.3 | 1.3 | 1.5 | 1.5 | 1.3 | 1.3 | 1.5 | 1.5 | 1.5 | 1.5 | 1.5 | 1.5 |
| E1-10 <2> | V | 6.0 | 6.0 | 6.0 | 6.0 | 5.0 | 6.0 | 5.0 | 6.0 | 7.0 | 9.0 | 7.0 | 11.0 | 6.0 | 6.0 | 6.0 | 6.9 |

<1> This value determines the default values for E1-04 through E1-10.

<2> Values shown here are specific to 200 V class drives. Double the value for 400 V class drives. Multiply the value by 2.875 for 600 V class drives.

B.16 Defaults by Drive Model

The following tables show parameters and default settings that change with the drive model selection (o2-04).

Table B.6 200 V Class Drives Default Settings by Drive Model Selection and ND settings

| No. | Name | Unit | Default Settings | | | |
|--------------|---|------------------|------------------------|--------------------|--------------------|--------------------|
| | | | 2A0004 | 2A0006 | 2A0008 | 2A0010 |
| – | Model CIMR-P□ | – | 2A0004 | 2A0006 | 2A0008 | 2A0010 |
| o2-04 | Drive Model Selection | Hex. | 62 | 63 | 64 | 65 |
| E2-11 | Motor Rated Output | kW (HP) | 0.75 (0.75) | 1.1 (1) | 1.5 (2) | 2.2 (3) |
| b3-04 | V/f Gain during Speed Search | % | 100 | 100 | 100 | 100 |
| b3-06 | Output Current 1 during Speed Search | – | 1 | 0.5 | 0.5 | 0.5 |
| b3-07 | Output Current 2 during Speed Search (Speed Estimation Type) | – | – | – | – | – |
| b3-26 | Start Speed Search Select | – | – | – | – | – |
| b8-03 | Energy Saving Control Filter Time Constant | s | 0.50 | 0.50 | 0.50 | 0.50 |
| b8-04 | Energy Saving Coefficient Value | – | 223.7 | 196.6 | 169.4 | 156.8 |
| C5-17 | Motor Inertia | kgm ² | 0.0028 | 0.0068 | 0.0068 | 0.0088 |
| C6-02 | Carrier Frequency Selection | – | 7 | 7 | 7 | 7 |
| E2-01 | Motor Rated Current | A | 3.3 | 4.9 | 6.2 | 8.5 |
| E2-02 | Motor Rated Slip | Hz | 2.5 | 2.6 | 2.6 | 2.9 |
| E2-03 | Motor No-Load Current | A | 1.8 | 2.3 | 2.8 | 3 |
| E2-05 | Motor Line-to-Line Resistance | Ω | 5.156 | 3.577 | 1.997 | 1.601 |
| E2-06 | Motor Leakage Inductance | % | 13.8 | 18.5 | 18.5 | 18.4 |
| E2-10 | Motor Iron Loss for Torque Compensation | W | 26 | 38 | 53 | 77 |
| L2-02 | Momentary Power Loss Ride-Thru Time | s | 0.1 | 0.2 | 0.3 | 0.3 |
| L2-03 | Momentary Power Loss Minimum Baseblock Time | s | 0.3 | 0.4 | 0.4 | 0.5 |
| L2-04 | Momentary Power Loss Voltage Recovery Time | s | 0.3 | 0.3 | 0.3 | 0.3 |
| L3-24 | Motor Acceleration Time for Inertia Calculations | s | 0.142 | 0.142 | 0.166 | 0.145 |
| L8-02 | Overheat Alarm Level | °C | 115 | 115 | 115 | 115 |
| L8-35 | Installation Method Selection | – | 2 | 2 | 2 | 2 |
| L8-38 | Carrier Frequency Reduction Selection | – | 2 | 2 | 2 | 2 |
| n1-03 | Hunting Prevention Time Constant | ms | 10 | 10 | 10 | 10 |

B.16 Defaults by Drive Model

| No. | Name | Unit | Default Settings | | | |
|--------------|---|------------------|--------------------|--------------------|----------------------|---------------------|
| | | | 2A0012 | 2A0018 | 2A0021 | 2A0030 |
| – | Model CIMR-P□ | – | 2A0012 | 2A0018 | 2A0021 | 2A0030 |
| o2-04 | Drive Model Selection | Hex. | 66 | 67 | 68 | 6A |
| E2-11 | Motor Rated Output | kW (HP) | 3.0 (3) | 3.7 (5) | 5.5 (7.5) | 7.5 (10) |
| b3-04 | V/f Gain during Speed Search | % | 100 | 100 | 100 | 100 |
| b3-06 | Output Current 1 during Speed Search | – | 0.5 | 0.5 | 0.5 | 0.5 |
| b3-07 | Output Current 2 during Speed Search (Speed Estimation Type) | – | – | – | – | – |
| b3-26 | Start Speed Search Select | – | – | – | – | – |
| b8-03 | Energy Saving Control Filter Time Constant | s | 0.50 | 0.50 | 0.50 | 0.50 |
| b8-04 | Energy Saving Coefficient Value | – | 136.4 | 122.9 | 94.75 | 72.69 |
| C5-17 | Motor Inertia | kgm ² | 0.0158 | 0.0158 | 0.0255 | 0.037 |
| C6-02 | Carrier Frequency Selection | – | 7 | 7 | 7 | 7 |
| E2-01 | Motor Rated Current | A | 11.4 | 14 | 19.6 | 26.6 |
| E2-02 | Motor Rated Slip | Hz | 2.7 | 2.73 | 1.5 | 1.3 |
| E2-03 | Motor No-Load Current | A | 3.7 | 4.5 | 5.1 | 8 |
| E2-05 | Motor Line-to-Line Resistance | Ω | 1.034 | 0.771 | 0.399 | 0.288 |
| E2-06 | Motor Leakage Inductance | % | 19 | 19.6 | 18.2 | 15.5 |
| E2-10 | Motor Iron Loss for Torque Compensation | W | 91 | 112 | 172 | 262 |
| L2-02 | Momentary Power Loss Ride-Thru Time | s | 0.5 | 1 | 1 | 1 |
| L2-03 | Momentary Power Loss Minimum Baseblock Time | s | 0.5 | 0.6 | 0.7 | 0.8 |
| L2-04 | Momentary Power Loss Voltage Recovery Time | s | 0.3 | 0.3 | 0.3 | 0.3 |
| L3-24 | Motor Acceleration Time for Inertia Calculations | s | 0.145 | 0.154 | 0.168 | 0.175 |
| L8-02 | Overheat Alarm Level | °C | 125 | 110 | 110 | 120 |
| L8-35 | Installation Method Selection | – | 2 | 2 | 2 | 2 |
| L8-38 | Carrier Frequency Reduction Selection | – | 2 | 2 | 2 | 2 |
| n1-03 | Hunting Prevention Time Constant | ms | 10 | 10 | 10 | 10 |

| No. | Name | Unit | Default Settings | | | |
|--------------|--|------------------|------------------|----------------|------------------|----------------|
| | | | 2A0040 | 2A0056 | 2A0069 | 2A0081 |
| – | Model CIMR-P□ | – | 2A0040 | 2A0056 | 2A0069 | 2A0081 |
| o2-04 | Drive Model Selection | Hex. | 6B | 6D | 6E | 6F |
| E2-11 | Motor Rated Power | kW (HP) | 11 (15) | 15 (20) | 18.5 (25) | 22 (30) |
| b3-04 | V/f Gain during Speed Search | % | 100 | 100 | 100 | 100 |
| b3-06 | Output Current 1 during Speed Search | – | 0.5 | 0.5 | 0.5 | 0.5 |
| b3-07 | Output Current 2 during Speed Search (Speed Estimation Type) | – | – | – | – | – |
| b3-26 | Start Speed Search Select | – | – | – | – | – |
| b8-03 | Energy Saving Control Filter Time Constant | s | 0.50 | 0.50 | 0.50 | 0.50 |
| b8-04 | Energy Saving Coefficient Value | – | 70.44 | 63.13 | 57.87 | 51.79 |
| C5-17 | Motor Inertia | kgm ² | 0.053 | 0.076 | 0.138 | 0.165 |
| C6-02 | Carrier Frequency Selection | – | 7 | 7 | 7 | 7 |
| E2-01 | Motor Rated Current | A | 39.7 | 53 | 65.8 | 77.2 |
| E2-02 | Motor Rated Slip | Hz | 1.7 | 1.6 | 1.67 | 1.7 |
| E2-03 | Motor No-Load Current | A | 11.2 | 15.2 | 15.7 | 18.5 |
| E2-05 | Motor Line-to-Line Resistance | Ω | 0.23 | 0.138 | 0.101 | 0.079 |
| E2-06 | Motor Leakage Inductance | % | 19.5 | 17.2 | 15.7 | 19.5 |
| E2-10 | Motor Iron Loss for Torque Compensation | W | 245 | 272 | 505 | 538 |
| L2-02 | Momentary Power Loss Ride-Thru Time | s | 1 | 2 | 2 | 2 |
| L2-03 | Momentary Power Loss Minimum Baseblock Time | s | 0.9 | 1 | 1 | 1 |
| L2-04 | Momentary Power Loss Voltage Recovery Time | s | 0.3 | 0.6 | 0.6 | 0.6 |
| L3-24 | Motor Acceleration Time for Inertia Calculations | s | 0.265 | 0.244 | 0.317 | 0.355 |
| L8-02 | Overheat Alarm Level | °C | 125 | 120 | 120 | 125 |
| L8-35 | Installation Method Selection | – | 2 | 2 | 2 | 2 |
| L8-38 | Carrier Frequency Reduction Selection | – | 2 | 2 | 2 | 2 |
| n1-03 | Hunting Prevention Time Constant | ms | 10 | 10 | 10 | 10 |

B.16 Defaults by Drive Model

| No. | Name | Unit | Default Settings | | | |
|--------------|---|------------------|--------------------|--------------------|--------------------|--------------------|
| | | | 2A0110 | 2A0138 | 2A0169 | 2A0211 |
| – | Model CIMR-P□ | – | 2A0110 | 2A0138 | 2A0169 | 2A0211 |
| o2-04 | Drive Model Selection | Hex. | 70 | 72 | 73 | 74 |
| E2-11 | Motor Rated Power | kW (HP) | 30 (40) | 37 (50) | 45 (60) | 55 (75) |
| b3-04 | V/f Gain during Speed Search | % | 80 | 80 | 80 | 80 |
| b3-06 | Output Current 1 during Speed Search | – | 0.5 | 0.5 | 0.5 | 0.5 |
| b3-07 | Output Current 2 during Speed Search (Speed Estimation Type) | – | – | – | – | – |
| b3-26 | Start Speed Search Select | – | – | – | – | – |
| b8-03 | Energy Saving Control Filter Time Constant | s | 0.50 | 0.50 | 0.50 | 2.00 |
| b8-04 | Energy Saving Coefficient Value | – | 46.27 | 38.16 | 35.78 | 31.35 |
| C5-17 | Motor Inertia | kgm ² | 0.220 | 0.273 | 0.333 | 0.490 |
| C6-02 | Carrier Frequency Selection | – | 7 | 7 | 7 | 7 |
| E2-01 | Motor Rated Current | A | 105 | 131 | 160 | 190 |
| E2-02 | Motor Rated Slip | Hz | 1.8 | 1.33 | 1.6 | 1.43 |
| E2-03 | Motor No-Load Current | A | 21.9 | 38.2 | 44 | 45.6 |
| E2-05 | Motor Line-to-Line Resistance | Ω | 0.064 | 0.039 | 0.03 | 0.022 |
| E2-06 | Motor Leakage Inductance | % | 20.8 | 18.8 | 20.2 | 20.5 |
| E2-10 | Motor Iron Loss for Torque Compensation | W | 699 | 823 | 852 | 960 |
| L2-02 | Momentary Power Loss Ride-Thru Time | s | 2 | 2 | 2 | 2 |
| L2-03 | Momentary Power Loss Minimum Baseblock Time | s | 1.1 | 1.1 | 1.2 | 1.3 |
| L2-04 | Momentary Power Loss Voltage Recovery Ramp Time | s | 0.6 | 0.6 | 1 | 1 |
| L3-24 | Motor Acceleration Time for Inertia Calculations | s | 0.323 | 0.32 | 0.387 | 0.317 |
| L8-02 | Overheat Alarm Level | °C | 130 | 130 | 130 | 125 |
| L8-35 | Installation Method Selection | – | 0 | 0 | 0 | 0 |
| L8-38 | Carrier Frequency Reduction Selection | – | 2 | 2 | 2 | 2 |
| n1-03 | Hunting Prevention Time Constant | ms | 10 | 10 | 10 | 10 |

| No. | Name | Unit | Default Settings | | | |
|--------------|---|------------------|---------------------|---------------------|---------------------|---------------------|
| | | | 2A0250 | 2A0312 | 2A0360 | 2A0415 |
| – | Model CIMR-P□ | – | 2A0250 | 2A0312 | 2A0360 | 2A0415 |
| o2-04 | Drive Model Selection | Hex. | 75 | 76 | 77 | 78 |
| E2-11 | Motor Rated Power | kW (HP) | 30 (100) | 37 (125) | 45 (150) | 55 (175) |
| b3-04 | V/f Gain during Speed Search | % | 80 | 80 | 80 | 80 |
| b3-06 | Output Current 1 during Speed Search | – | 0.7 | 0.7 | 0.7 | 0.7 |
| b3-07 | Output Current 2 during Speed Search (Speed Estimation Type) | – | – | – | – | – |
| b3-26 | Start Speed Search Select | – | – | – | – | – |
| b8-03 | Energy Saving Control Filter Time Constant | s | 2.00 | 2.00 | 2.00 | 2.00 |
| b8-04 | Energy Saving Coefficient Value | – | 23.1 | 20.65 | 18.12 | 18.12 |
| C5-17 | Motor Inertia | kgm ² | 0.90 | 1.10 | 1.90 | 1.90 |
| C6-02 | Carrier Frequency Selection | – | 7 | 7 | 7 | 7 |
| E2-01 | Motor Rated Current | A | 260 | 260 | 260 | 260 |
| E2-02 | Motor Rated Slip | Hz | 1.39 | 1.39 | 1.39 | 1.39 |
| E2-03 | Motor No-Load Current | A | 72 | 72 | 72 | 72 |
| E2-05 | Motor Line-to-Line Resistance | Ω | 0.023 | 0.023 | 0.023 | 0.023 |
| E2-06 | Motor Leakage Inductance | % | 20 | 20 | 20 | 20 |
| E2-10 | Motor Iron Loss for Torque Compensation | W | 1200 | 1200 | 1200 | 1200 |
| L2-02 | Momentary Power Loss Ride-Thru Time | s | 2 | 2 | 2 | 2 |
| L2-03 | Momentary Power Loss Minimum Baseblock Time | s | 1.5 | 1.5 | 1.7 | 1.7 |
| L2-04 | Momentary Power Loss Voltage Recovery Ramp Time | s | 1 | 1 | 1 | 1 |
| L3-24 | Motor Acceleration Time for Inertia Calculations | s | 0.533 | 0.592 | 0.646 | 0.646 |
| L8-02 | Overheat Alarm Level | °C | 115 | 120 | 120 | 120 |
| L8-35 | Installation Method Selection | – | 0 | 0 | 0 | 0 |
| L8-38 | Carrier Frequency Reduction Selection | – | 2 | 2 | 2 | 2 |
| n1-03 | Hunting Prevention Time Constant | ms | 10 | 10 | 100 | 100 |

B.16 Defaults by Drive Model

Table B.7 400 V Class Drives Default Settings by Drive Model

| No. | Name | Unit | Default Settings | | | |
|--------------|---|------------------|------------------------|--------------------|--------------------|--------------------|
| | | | 4A0002 | 4A0004 | 4A0005 | 4A0007 |
| – | Model CIMR-P□ | – | 92 | 93 | 94 | 95 |
| o2-04 | Drive Model Selection | Hex. | 92 | 93 | 94 | 95 |
| E2-11 | Motor rated power | kW (HP) | 0.75 (0.75) | 1.5 (2) | 2.2 (3) | 3.0 (3) |
| b3-04 | V/f Gain during Speed Search | % | 100 | 100 | 100 | 100 |
| b3-06 | Output Current 1 during Speed Search | – | 0.5 | 0.5 | 0.5 | 0.5 |
| b3-07 | Output Current 2 during Speed Search (Speed Estimation Type) | – | – | – | – | – |
| b3-26 | Start Speed Search Select | – | – | – | – | – |
| b8-03 | Energy Saving Control Filter Time Constant | s | 0.50 | 0.50 | 0.50 | 0.50 |
| b8-04 | Energy Saving Coefficient Value | – | 447.4 | 338.8 | 313.6 | 265.7 |
| C5-17 | Motor Inertia | kgm ² | 0.0028 | 0.0068 | 0.0088 | 0.0158 |
| C6-02 | Carrier Frequency Selection | – | 7 | 7 | 7 | 7 |
| E2-01 | Motor Rated Current | A | 1.6 | 3.1 | 4.2 | 5.7 |
| E2-02 | Motor Rated Slip | Hz | 2.6 | 2.5 | 3 | 2.7 |
| E2-03 | Motor No-Load Current | A | 0.8 | 1.4 | 1.5 | 1.9 |
| E2-05 | Motor Line-to-Line Resistance | Ω | 22.459 | 10.1 | 6.495 | 4.360 |
| E2-06 | Motor Leakage Inductance | % | 14.3 | 18.3 | 18.7 | 19 |
| E2-10 | Motor Iron Loss for Torque Compensation | W | 26 | 53 | 77 | 105 |
| L2-02 | Momentary Power Loss Ride-Thru Time | s | 0.1 | 0.2 | 0.3 | 0.5 |
| L2-03 | Momentary Power Loss Min. Baseblock Time | s | 0.3 | 0.4 | 0.5 | 0.5 |
| L2-04 | Momentary Power Loss Voltage Recovery Time | s | 0.3 | 0.3 | 0.3 | 0.3 |
| L3-24 | Motor Acceleration Time for Inertia Calculations | s | 0.142 | 0.166 | 0.145 | 0.145 |
| L8-02 | Overheat Alarm Level | °C | 110 | 110 | 110 | 110 |
| L8-35 | Installation Method Selection | – | 2 | 2 | 2 | 2 |
| L8-38 | Carrier Frequency Reduction Selection | – | 2 | 2 | 2 | 2 |
| n1-03 | Hunting Prevention Time Constant | ms | 10 | 10 | 10 | 10 |

| No. | Name | Unit | Default Settings | | | |
|--------------|---|------------------|--------------------|----------------------|---------------------|--------------------|
| | | | 4A0009 | 4A0011 | 4A0018 | 4A0023 |
| – | Model CIMR-P□ | – | 96 | 97 | 9A | 9A |
| o2-04 | Drive Model Selection | Hex. | 96 | 97 | | 9A |
| E2-11 | Motor Rated Power | kW (HP) | 3.7 (5) | 5.5 (7.5) | 7.5 (10) | 11 (15) |
| b3-04 | V/f Gain during Speed Search | % | 100 | 100 | 100 | 100 |
| b3-06 | Output Current 1 during Speed Search | – | 0.5 | 0.5 | 0.5 | 0.5 |
| b3-07 | Output Current 2 during Speed Search (Speed Estimation Type) | – | – | – | – | – |
| b3-26 | Start Speed Search Select | – | – | – | – | – |
| b8-03 | Energy Saving Control Filter Time Constant | s | 0.50 | 0.50 | 0.50 | 0.50 |
| b8-04 | Energy Saving Coefficient Value | – | 245.8 | 189.5 | 145.38 | 140.88 |
| C5-17 | Motor Inertia | kgm ² | 0.0158 | 0.0255 | 0.037 | 0.053 |
| C6-02 | Carrier Frequency Selection | – | 7 | 7 | 7 | 7 |
| E2-01 | Motor Rated Current | A | 7 | 9.8 | 13.3 | 19.9 |
| E2-02 | Motor Rated Slip | Hz | 2.7 | 1.5 | 1.3 | 1.7 |
| E2-03 | Motor No-Load Current | A | 2.3 | 2.6 | 4 | 5.6 |
| E2-05 | Motor Line-to-Line Resistance | Ω | 3.333 | 1.595 | 1.152 | 0.922 |
| E2-06 | Motor Leakage Inductance | % | 19.3 | 18.2 | 15.5 | 19.6 |
| E2-10 | Motor Iron Loss for Torque Compensation | W | 130 | 193 | 263 | 385 |
| L2-02 | Momentary Power Loss Ride-Thru Time | s | 0.5 | 0.5 | 0.8 | 1 |
| L2-03 | Momentary Power Loss Min. Baseblock Time | s | 0.6 | 0.7 | 0.8 | 0.9 |
| L2-04 | Momentary Power Loss Voltage Recovery Time | s | 0.3 | 0.3 | 0.3 | 0.3 |
| L3-24 | Motor Acceleration Time for Inertia Calculations | s | 0.154 | 0.168 | 0.175 | 0.265 |
| L8-02 | Overheat Alarm Level | °C | 110 | 110 | 110 | 115 |
| L8-35 | Installation Method Selection | – | 2 | 2 | 2 | 2 |
| L8-38 | Carrier Frequency Reduction Selection | – | 2 | 2 | 2 | 2 |
| n1-03 | Hunting Prevention Time Constant | ms | 10 | 10 | 10 | 10 |

B.16 Defaults by Drive Model

| No. | Name | Unit | Default Settings | | | |
|-------|---|------------------|------------------|--------------|------------|------------|
| | | | 4A0031 | 4A0038 | 4A0044 | 4A0058 |
| – | Model CIMR-P□ | – | 4A0031 | 4A0038 | 4A0044 | 4A0058 |
| o2-04 | Drive Model Selection | Hex. | 9C | 9D | 9E | 9F |
| E2-11 | Motor Rated Power | kW (HP) | 15 (20) | 18.5 (25) | 22 (30) | 30 (40) |
| b3-04 | V/f Gain during Speed Search | % | 100 | 100 | 100 | 100 |
| b3-06 | Output Current 1 during Speed Search | – | 0.5 | 0.5 | 0.5 | 0.5 |
| b3-07 | Output Current 2 during Speed Search (Speed Estimation Type) | – | – | – | – | – |
| b3-26 | Start Speed Search Select | – | – | – | – | – |
| b8-03 | Energy Saving Control Filter Time Constant | s | 0.50 | 0.50 | 0.50 | 0.50 |
| b8-04 | Energy Saving Coefficient Value | – | 126.26 | 115.74 | 103.58 | 92.54 |
| C5-17 | Motor Inertia | kgm ² | 0.076 | 0.138 | 0.165 | 0.220 |
| C6-02 | Carrier Frequency Selection | – | 7 | 7 | 7 | 7 |
| E2-01 | Motor Rated Current | A | 26.5 | 32.9 | 38.6 | 52.3 |
| E2-02 | Motor Rated Slip | Hz | 1.6 | 1.67 | 1.7 | 1.8 |
| E2-03 | Motor No-Load Current | A | 7.6 | 7.8 | 9.2 | 10.9 |
| E2-05 | Motor Line-to-Line Resistance | Ω | 0.55 | 0.403 | 0.316 | 0.269 |
| E2-06 | Motor Leakage Inductance | % | 17.2 | 20.1 | 23.5 | 20.7 |
| E2-10 | Motor Iron Loss for Torque Compensation | W | 440 | 508 | 586 | 750 |
| L2-02 | Momentary Power Loss Ride-Thru Time | s | 2 | 2 | 2 | 2 |
| L2-03 | Momentary Power Loss Minimum Baseblock Time | s | 1 | 1 | 1 | 1.1 |
| L2-04 | Momentary Power Loss Voltage Recovery Time | s | 0.6 | 0.6 | 0.6 | 0.6 |
| L3-24 | Motor Acceleration Time for Inertia Calculations | s | 0.244 | 0.317 | 0.355 | 0.323 |
| L8-02 | Overheat Alarm Level | °C | 120 | 120 | 115 | 120 |
| L8-35 | Installation Method Selection | – | 2 | 2 | 2 | 0 |
| L8-38 | Carrier Frequency Reduction Selection | – | 2 | 2 | 2 | 2 |
| n1-03 | Hunting Prevention Time Constant | ms | 10 | 10 | 10 | 10 |

| No. | Name | Unit | Default Settings | | | |
|--------------|---|------------------|--------------------|--------------------|--------------------|---------------------|
| | | | 4A0072 | 4A0088 | 4A0103 | 4A0139 |
| – | Model CIMR-P□ | – | 4A0072 | 4A0088 | 4A0103 | 4A0139 |
| o2-04 | Drive Model Selection | Hex. | A1 | A2 | A3 | A4 |
| E2-11 | Motor rated power | kW (HP) | 37 (50) | 45 (60) | 55 (75) | 75 (100) |
| b3-04 | V/f Gain during Speed Search | % | 100 | 100 | 80 | 60 |
| b3-06 | Output Current 1 during Speed Search | – | 0.5 | 0.5 | 0.5 | 0.7 |
| b3-07 | Output Current 2 during Speed Search (Speed Estimation Type) | – | – | – | – | – |
| b3-26 | Start Speed Search Select | – | – | – | – | – |
| b8-03 | Energy Saving Control Filter Time Constant | s | 0.50 | 0.50 | 2.00 | 2.00 |
| b8-04 | Energy Saving Coefficient Value | – | 76.32 | 71.56 | 67.2 | 46.2 |
| C5-17 | Motor Inertia | kgm ² | 0.273 | 0.333 | 0.490 | 0.90 |
| C6-02 | Carrier Frequency Selection | – | 7 | 7 | 7 | 7 |
| E2-01 | Motor Rated Current | A | 65.6 | 79.7 | 95 | 130 |
| E2-02 | Motor Rated Slip | Hz | 1.33 | 1.6 | 1.46 | 1.39 |
| E2-03 | Motor No-Load Current | A | 19.1 | 22 | 24 | 36 |
| E2-05 | Motor Line-to-Line Resistance | Ω | 0.155 | 0.122 | 0.088 | 0.092 |
| E2-06 | Motor Leakage Inductance | % | 18.8 | 19.9 | 20 | 20 |
| E2-10 | Motor Iron Loss for Torque Compensation | W | 925 | 1125 | 1260 | 1600 |
| L2-02 | Momentary Power Loss Ride-Thru Time | s | 2 | 2 | 2 | 2 |
| L2-03 | Momentary Power Loss Min. Basebl. Time | s | 1.1 | 1.2 | 1.2 | 1.3 |
| L2-04 | Momentary Power Loss Volt. Recov. Time | s | 0.6 | 0.6 | 1 | 1 |
| L3-24 | Motor Acceleration Time for Inertia Calculations | s | 0.32 | 0.387 | 0.317 | 0.533 |
| L8-02 | Overheat Alarm Level | °C | 120 | 110 | 120 | 130 |
| L8-35 | Installation Method Selection | – | 0 | 0 | 0 | 0 |
| L8-38 | Carrier Frequency Reduction Selection | – | 2 | 2 | 2 | 2 |
| n1-03 | Hunting Prevention Time Constant | ms | 10 | 10 | 10 | 30 |

B.16 Defaults by Drive Model

| No. | Name | Unit | Default Settings | | | |
|--------------|---|------------------|---------------------|----------------------|----------------------|----------------------|
| | | | 4A0165 | 4A0208 | 4A0250 | 4A0296 |
| – | Model CIMR-P□ | – | 4A0165 | 4A0208 | 4A0250 | 4A0296 |
| o2-04 | Drive Model Selection | Hex. | A5 | A6 | A7 | A8 |
| E2-11 | Motor rated power | kW (HP) | 90 (125) | 110 (150) | 132 (200) | 160 (250) |
| b3-04 | V/f Gain during Speed Search | % | 60 | 60 | 60 | 60 |
| b3-06 | Output Current 1 during Speed Search | – | 0.7 | 0.7 | 0.7 | 0.7 |
| b3-07 | Output Current 2 during Speed Search (Speed Estimation Type) | – | – | – | – | – |
| b3-26 | Start Speed Search Select | – | – | – | – | – |
| b8-03 | Energy Saving Control Filter Time Constant | s | 2.00 | 2.00 | 2.00 | 2.00 |
| b8-04 | Energy Saving Coefficient Value | – | 38.91 | 36.23 | 32.79 | 30.13 |
| C5-17 | Motor Inertia | kgm ² | 1.10 | 1.90 | 2.10 | 3.30 |
| C6-02 | Carrier Frequency Selection | – | 7 | 7 | 7 | 7 |
| E2-01 | Motor Rated Current | A | 156 | 190 | 223 | 270 |
| E2-02 | Motor Rated Slip | Hz | 1.4 | 1.4 | 1.38 | 1.35 |
| E2-03 | Motor No-Load Current | A | 40 | 49 | 58 | 70 |
| E2-05 | Motor Line-to-Line Resistance | Ω | 0.056 | 0.046 | 0.035 | 0.029 |
| E2-06 | Motor Leakage Inductance | % | 20 | 20 | 20 | 20 |
| E2-10 | Motor Iron Loss for Torque Compensation | W | 1760 | 2150 | 2350 | 2850 |
| L2-02 | Momentary Power Loss Ride-Thru Time | s | 2 | 2 | 2 | 2 |
| L2-03 | Momentary Power Loss Min. Basebl. Time | s | 1.5 | 1.7 | 1.7 | 1.8 |
| L2-04 | Momentary Power Loss Volt. Recov. Time | s | 1 | 1 | 1 | 1 |
| L3-24 | Motor Acceleration Time for Inertia Calculations | s | 0.592 | 0.646 | 0.673 | 0.777 |
| L8-02 | Overheat Alarm Level | °C | 130 | 120 | 120 | 125 |
| L8-35 | Installation Method Selection | – | 0 | 0 | 0 | 0 |
| L8-38 | Carrier Frequency Reduction Selection | – | 2 | 2 | 2 | 2 |
| n1-03 | Hunting Prevention Time Constant | ms | 30 | 30 | 30 | 30 |

| No. | Name | Unit | Default Settings | | |
|--------------|---|------------------|----------------------|----------------------|-------------------------------|
| | | | 4A0362 | 4A0414 | 4A0515 |
| – | Model CIMR-P□ | – | 4A0362 | 4A0414 | 4A0515 |
| o2-04 | Drive Model Selection | Hex. | A9 | AA | AC |
| E2-11 | Motor rated power | kW (HP) | 185 (300) | 220 (350) | 250 (400 -450) |
| b3-04 | V/f Gain during Speed Search | % | 60 | 60 | 60 |
| b3-06 | Output Current 1 during Speed Search | – | 0.7 | 0.7 | 0.7 |
| b3-07 | Output Current 2 during Speed Search (Speed Estimation Type) | – | – | – | – |
| b3-26 | Start Speed Search Select | – | – | – | – |
| b8-03 | Energy Saving Control Filter Time Constant | s | 2.00 | 2.00 | 2.00 |
| b8-04 | Energy Saving Coefficient Value | – | 30.57 | 27.13 | 21.76 |
| C5-17 | Motor Inertia | kgm ² | 3.60 | 4.10 | 6.50 |
| C6-02 | Carrier Frequency Selection | – | 7 | 7 | 7 |
| E2-01 | Motor Rated Current | A | 310 | 370 | 500 |
| E2-02 | Motor Rated Slip | Hz | 1.3 | 1.3 | 1.25 |
| E2-03 | Motor No-Load Current | A | 81 | 96 | 130 |
| E2-05 | Motor Line-to-Line Resistance | Ω | 0.025 | 0.02 | 0.014 |
| E2-06 | Motor Leakage Inductance | % | 20 | 20 | 20 |
| E2-10 | Motor Iron Loss for Torque Compensation | W | 3200 | 3700 | 4700 |
| L2-02 | Momentary Power Loss Ride-Thru Time | s | 2 | 2 | 2 |
| L2-03 | Momentary Power Loss Min. Basebl. Time | s | 1.9 | 2 | 2.1 |
| L2-04 | Momentary Power Loss Volt. Recov. Time | s | 1 | 1 | 1 |
| L3-24 | Motor Acceleration Time for Inertia Calculations | s | 0.864 | 0.91 | 1.392 |
| L8-02 | Overheat Alarm Level | °C | 130 | 140 | 140 |
| L8-35 | Installation Method Selection | – | 0 | 0 | 0 |
| L8-38 | Carrier Frequency Reduction Selection | – | 2 | 2 | 2 |
| n1-03 | Hunting Prevention Time Constant | ms | 30 | 100 | 100 |

B.16 Defaults by Drive Model

| No. | Name | Unit | Default Settings | | |
|--------------|---|------------------|-------------------------------|----------------------|-----------------------|
| | | | 4A0675 | 4A0930 | 4A1200 |
| – | Model CIMR-P□ | – | 4A0675 | 4A0930 | 4A1200 |
| o2-04 | Drive Model Selection | Hex. | AE | B0 | B2 |
| E2-11 | Motor rated power | kW (HP) | 355 (500 -550) | 500 (750) | 630 (1000) |
| b3-04 | V/f Gain during Speed Search | % | 60 | 60 | 60 |
| b3-06 | Output Current 1 during Speed Search | – | 0.7 | 0.7 | 0.7 |
| b3-07 | Output Current 2 during Speed Search (Speed Estimation Type) | – | – | 2.0 | 2.0 |
| b3-26 | Start Speed Search Select | – | – | 1000 | 1000 |
| b8-03 | Energy Saving Control Filter Time Constant | s | 2.00 | 2.00 | 2.00 |
| b8-04 | Energy Saving Coefficient Value | – | 23.84 | 20.26 | 17.06 |
| C5-17 | Motor Inertia | kgm ² | 12.00 | 14.00 | 18.00 |
| C6-02 | Carrier Frequency Selection | – | 7 | 7 | 7 |
| E2-01 | Motor Rated Current | A | 650 | 900 | 1200 |
| E2-02 | Motor Rated Slip | Hz | 1 | 0.9 | 0.7 |
| E2-03 | Motor No-Load Current | A | 130 | 180 | 240 |
| E2-05 | Motor Line-to-Line Resistance | Ω | 0.012 | 0.009 | 0.006 |
| E2-06 | Motor Leakage Inductance | % | 20 | 20 | 20 |
| E2-10 | Motor Iron Loss for Torque Compensation | W | 5560 | 7833 | 11123 |
| L2-02 | Momentary Power Loss Ride-Thru Time | s | 2 | 2 | 2 |
| L2-03 | Momentary Power Loss Min. Basebl. Time | s | 2.3 | 3.1 | 4.6 |
| L2-04 | Momentary Power Loss Volt. Recov. Time | s | 1 | 3 | 4.5 |
| L3-24 | Motor Acceleration Time for Inertia Calculations | s | 1.667 | 2.222 | 3.333 |
| L8-02 | Overheat Alarm Level | °C | 140 | 140 | 140 |
| L8-35 | Installation Method Selection | – | 0 | 0 | 0 |
| L8-38 | Carrier Frequency Reduction Selection | – | 2 | 2 | 2 |
| n1-03 | Hunting Prevention Time Constant | ms | 100 | 100 | 100 |

Table B.8 600 V Class Drives Default Settings by Drive Model

| No. | Name | Unit | Default Settings | | | | |
|--------------|---|--------------------|--------------------|--------------------|--------------------|----------------------|---------------------|
| | | | 5A0003 | 5A0004 | 5A0006 | 5A0009 | 5A0011 |
| – | Model CIMR-P□ | – | 5A0003 | 5A0004 | 5A0006 | 5A0009 | 5A0011 |
| o2-04 | Drive Model Selection | Hex. | C3 | C4 | C5 | C7 | |
| E2-11 | Motor Rated Power | kW (HP) | 1.5 (2) | 2.2 (3) | 3.7 (5) | 5.5 (7.5) | 7.5 (10) |
| b3-04 | V/f Gain during Speed Search | % | 100 | 100 | 100 | 100 | 100 |
| b3-06 | Output Current 1 during Speed Search | – | 0.5 | 0.5 | 0.5 | 0.5 | 0.5 |
| b3-07 | Output Current 2 during Speed Search (Speed Estimation Type) | – | – | – | – | – | – |
| b3-26 | Start Speed Search Select | – | – | – | – | – | – |
| b8-03 | Energy Saving Control Filter Time Constant | s | 0.50 | 0.50 | 0.50 | 0.50 | 0.50 |
| b8-04 | Energy Saving Coefficient Value | – | 494.4 | 415.3 | 320.2 | 239.95 | 199.86 |
| C5-17 | Motor Inertia | kgm ² | 0.0068 | 0.0088 | 0.0158 | 0.0255 | 0.037 |
| C6-02 | Carrier Frequency Selection | – | 7 | 7 | 7 | 7 | 7 |
| E2-01 | Motor Rated Current | A | 2.7 | 3.9 | 6.1 | 9 | 11 |
| E2-02 | Motor Rated Slip | Hz | 2.5 | 3.0 | 2.7 | 1.5 | 1.3 |
| E2-03 | Motor No-Load Current | A | 0.8 | 1.2 | 1.8 | 2.7 | 3.3 |
| E2-05 | Motor Line-to-Line Resistance | Ω | 13.72 | 8.825 | 4.936 | 2.601 | 1.446 |
| E2-06 | Motor Leakage Inductance | % | 18.3 | 18.7 | 19.3 | 18.2 | 15.5 |
| E2-10 | Motor Iron Loss for Torque Compensation | W | 53 | 77 | 130 | 193 | 263 |
| L2-02 | Momentary Power Loss Ride-Thru Time | s | 0.2 | 0.3 | 0.5 | 0.5 | 0.8 |
| L2-03 | Momentary Power Loss Minimum Baseblock Time | s | 0.5 | 0.5 | 0.8 | 0.8 | 1 |

| No. | Name | Unit | | | | | |
|-------|--|------------|------------|------------|------------|--------------|-------------|
| – | Model CIMR-P□ | – | 5A0003 | 5A0004 | 5A0006 | 5A0009 | 5A0011 |
| o2-04 | Drive Model Selection | Hex. | C3 | C4 | C5 | C7 | |
| E2-11 | Motor Rated Power | kW (HP) | 1.5 (2) | 2.2 (3) | 3.7 (5) | 5.5 (7.5) | 7.5 (10) |
| L2-04 | Momentary Power Loss Voltage Recovery Time | s | 0.5 | 0.5 | 0.6 | 0.7 | 0.8 |
| L3-24 | Motor Acceleration Time for Inertia Calculations | s | 0.166 | 0.145 | 0.154 | 0.168 | 0.175 |
| L8-02 | Overheat Alarm Level | °C | 110 | 110 | 110 | 110 | 115 |
| L8-35 | Installation Method Selection | – | 2 | 2 | 2 | 2 | 2 |
| L8-38 | Carrier Frequency Reduction Selection | – | 2 | 2 | 2 | 2 | 2 |
| n1-03 | Hunting Prevention Time Constant | ms | 10 | 10 | 10 | 10 | 10 |

B.16 Defaults by Drive Model

| No. | Name | Unit | Default Settings | | | |
|--------------|---|------------------|--------------------|--------------------|----------------------|--------------------|
| | | | 5A0017 | 5A0022 | 5A0027 | 5A0032 |
| – | Model CIMR-P□ | – | 5A0017 | 5A0022 | 5A0027 | 5A0032 |
| o2-04 | Drive Model Selection | Hex. | CA | CC | CD | CE |
| E2-11 | Motor Rated Power | kW (HP) | 11 (15) | 15 (20) | 18.5 (25) | 22 (30) |
| b3-04 | V/f Gain during Speed Search | % | 100 | 100 | 100 | 100 |
| b3-06 | Output Current 1 during Speed Search | – | 0.5 | 0.5 | 0.5 | 0.5 |
| b3-07 | Output Current 2 during Speed Search (Speed Estimation Type) | – | – | – | – | – |
| b3-26 | Start Speed Search Select | – | – | – | – | – |
| b8-03 | Energy Saving Control Filter Time Constant | s | 0.5 | 0.5 | 0.5 | 0.5 |
| b8-04 | Energy Saving Coefficient Value | – | 172 | 154 | 140 | 129 |
| C5-17 | Motor Inertia | kgm ² | 0.053 | 0.076 | 0.138 | 0.165 |
| C6-02 | Carrier Frequency Selection | – | 7 | 7 | 7 | 7 |
| E2-01 | Motor Rated Current | A | 17 | 22 | 27 | 32 |
| E2-02 | Motor Rated Slip | Hz | 1.7 | 1.6 | 1.67 | 1.7 |
| E2-03 | Motor No-Load Current | A | 5.1 | 6.6 | 8.1 | 9.6 |
| E2-05 | Motor Line-to-Line Resistance | Ω | 1.17 | 0.9 | 0.66 | 0.52 |
| E2-06 | Motor Leakage Inductance | % | 19.6 | 17.2 | 20.1 | 23.5 |
| E2-10 | Motor Iron Loss for Torque Compensation | W | 385 | 440 | 508 | 586 |
| L2-02 | Momentary Power Loss Ride-Thru Time | s | 1 | 2 | 2 | 2 |
| L2-03 | Momentary Power Loss Minimum Baseblock Time | s | 1 | 1.2 | 1.2 | 1.2 |
| L2-04 | Momentary Power Loss Voltage Recovery Time | s | 0.9 | 1 | 1 | 1 |
| L3-24 | Motor Acceleration Time for Inertia Calculations | s | 0.27 | 0.24 | 0.32 | 0.36 |
| L8-02 | Overheat Alarm Level | °C | 120 | 120 | 115 | 115 |
| L8-35 | Installation Method Selection | – | 2 | 2 | 2 | 2 |
| L8-38 | Carrier Frequency Reduction Selection | – | 2 | 2 | 2 | 2 |
| n1-03 | Hunting Prevention Time Constant | ms | 10 | 10 | 10 | 10 |

| No. | Name | Unit | Default Settings | | |
|-------|---|------------------|------------------|------------|------------|
| – | Model CIMR-P□ | – | 5A0041 | 5A0052 | 5A0062 |
| o2-04 | Drive Model Selection | Hex. | CF | D1 | D2 |
| E2-11 | Motor Rated Power | kW (HP) | 30 (40) | 37 (50) | 45 (60) |
| b3-04 | V/f Gain during Speed Search | % | 80 | 80 | 80 |
| b3-06 | Output Current 1 during Speed Search | – | 0.5 | 0.5 | 0.5 |
| b3-07 | Output Current 2 during Speed Search (Speed Estimation Type) | – | – | – | – |
| b3-26 | Start Speed Search Select | – | – | – | – |
| b8-03 | Energy Saving Control Filter Time Constant | s | 0.5 | 0.5 | 0.5 |
| b8-04 | Energy Saving Coefficient Value | – | 115.57 | 97.01 | 90.07 |
| C5-17 | Motor Inertia | kgm ² | 0.220 | 0.273 | 0.333 |
| C6-02 | Carrier Frequency Selection | – | 7 | 7 | 7 |
| E2-01 | Motor Rated Current | A | 41 | 52 | 62 |
| E2-02 | Motor Rated Slip | Hz | 1.8 | 1.33 | 1.6 |
| E2-03 | Motor No-Load Current | A | 12.3 | 15.6 | 18.8 |
| E2-05 | Motor Line-to-Line Resistance | Ω | 0.438 | 0.267 | 0.21 |
| E2-06 | Motor Leakage Inductance | % | 20.7 | 18.8 | 19.9 |
| E2-10 | Motor Iron Loss for Torque Compensation | W | 750 | 925 | 1125 |
| L2-02 | Momentary Power Loss Ride-Thru Time | s | 2 | 2 | 2 |
| L2-03 | Momentary Power Loss Minimum Baseblock Time | s | 1.2 | 1.2 | 1.5 |
| L2-04 | Momentary Power Loss Voltage Recovery Time | s | 1.1 | 1.2 | 1.3 |
| L3-24 | Motor Acceleration Time for Inertia Calculations | s | 0.323 | 0.32 | 0.387 |
| L8-02 | Overheat Alarm Level | °C | 110 | 110 | 110 |
| L8-35 | Installation Method Selection | – | 2 | 2 | 2 |
| L8-38 | Carrier Frequency Reduction Selection | – | 2 | 2 | 2 |
| n1-03 | Hunting Prevention Time Constant | ms | 10 | 10 | 10 |

B.16 Defaults by Drive Model

| No. | Name | Unit | Default Settings | |
|--------------|---|------------------|--------------------|---------------------|
| | | | 5A0077 | 5A0099 |
| – | Model CIMR-P□ | – | 5A0077 | 5A0099 |
| o2-04 | Drive Model Selection | Hex. | D3 | D4 |
| E2-11 | Motor Rated Power | kW (HP) | 55 (75) | 75 (100) |
| b3-04 | V/f Gain during Speed Search | % | 80 | 80 |
| b3-06 | Output Current 1 during Speed Search | – | 0.5 | 0.5 |
| b3-07 | Output Current 2 during Speed Search (Speed Estimation Type) | – | – | – |
| b3-26 | Start Speed Search Select | – | – | – |
| b8-03 | Energy Saving Control Filter Time Constant | s | 2 | 2 |
| b8-04 | Energy Saving Coefficient Value | – | 80.87 | 70.07 |
| C5-17 | Motor Inertia | kgm ² | 0.490 | 0.90 |
| C6-02 | Carrier Frequency Selection | – | 7 | 7 |
| E2-01 | Motor Rated Current | A | 77 | 99 |
| E2-02 | Motor Rated Slip | Hz | 1.46 | 1.39 |
| E2-03 | Motor No-Load Current | A | 23.1 | 29.7 |
| E2-05 | Motor Line-to-Line Resistance | Ω | 0.15 | 0.099 |
| E2-06 | Motor Leakage Inductance | % | 20 | 20 |
| E2-10 | Motor Iron Loss for Torque Compensation | W | 1260 | 1600 |
| L2-02 | Momentary Power Loss Ride-Thru Time | s | 2 | 2 |
| L2-03 | Momentary Power Loss Minimum Baseblock Time | s | 1.8 | 1.8 |
| L2-04 | Momentary Power Loss Voltage Recovery Time | s | 1.5 | 1.6 |
| L3-24 | Motor Acceleration Time for Inertia Calculations | s | 0.317 | 0.533 |
| L8-02 | Overheat Alarm Level | °C | 110 | 110 |
| L8-35 | Installation Method Selection | – | 2 | 2 |
| L8-38 | Carrier Frequency Reduction Selection | – | 2 | 2 |
| n1-03 | Hunting Prevention Time Constant | ms | 10 | 30 |

| No. | Name | Unit | Default Settings | | | |
|--------------|---|------------------|---------------------|----------------------|----------------------|----------------------|
| | | | 5A0125 | 5A0145 | 5A0192 | 5A0242 |
| – | Model CIMR-P□ | – | 5A0125 | 5A0145 | 5A0192 | 5A0242 |
| o2-04 | Drive Model Selection | Hex. | D5 | D6 | D7 | D9 |
| E2-11 | Motor Rated Power | kW (HP) | 90 (125) | 110 (150) | 160 (200) | 185 (250) |
| b3-04 | V/f Gain during Speed Search | % | 80 | 80 | 80 | 80 |
| b3-06 | Output Current 1 during Speed Search | – | 0.5 | 0.5 | 0.5 | 0.5 |
| b3-07 | Output Current 2 during Speed Search (Speed Estimation Type) | – | – | – | – | – |
| b3-26 | Start Speed Search Select | – | – | – | – | – |
| b8-03 | Energy Saving Control Filter Time Constant | s | 2.00 | 2.00 | 2.00 | 2.00 |
| b8-04 | Energy Saving Coefficient Value | – | 61.50 | 58.67 | 49.90 | 42.90 |
| C5-17 | Motor Inertia | kgm ² | 1.10 | 1.90 | 2.10 | 4.10 |
| C6-02 | Carrier Frequency Selection | – | 7 | 7 | 7 | 7 |
| E2-01 | Motor Rated Current | A | 125 | 145 | 192 | 242 |
| E2-02 | Motor Rated Slip | Hz | 1.39 | 1.40 | 1.35 | 1.35 |
| E2-03 | Motor No-Load Current | A | 37.5 | 43.2 | 57.6 | 57.6 |
| E2-05 | Motor Line-to-Line Resistance | Ω | 0.079 | 0.060 | 0.037 | 0.037 |
| E2-06 | Motor Leakage Inductance | % | 20.0 | 20.0 | 20.0 | 20.0 |
| E2-10 | Motor Iron Loss for Torque Compensation | W | 2150 | 2150 | 2850 | 2850 |
| L2-02 | Momentary Power Loss Ride-Thru Time | s | 2.0 | 2.0 | 2.0 | 2.0 |
| L2-03 | Momentary Power Loss Minimum Baseblock Time | s | 2.0 | 2.0 | 2.0 | 2.0 |
| L2-04 | Momentary Power Loss Voltage Recovery Time | s | 1.7 | 1.8 | 2.0 | 2.0 |
| L3-24 | Motor Acceleration Time for Inertia Calculations | s | 0.592 | 0.646 | 0.673 | 0.864 |
| L8-02 | Overheat Alarm Level | °C | 110 | 110 | 110 | 110 |
| L8-35 | Installation Method Selection | – | 0 | 0 | 0 | 0 |
| L8-38 | Carrier Frequency Reduction Selection | – | 2 | 2 | 2 | 2 |
| n1-03 | Hunting Prevention Time Constant | ms | 30 | 30 | 30 | 30 |

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Appendix: C

MEMOBUS/Modbus Communications

| | | |
|-------------|--|------------|
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C.1 MEMOBUS/Modbus Configuration

Drives can be controlled from a PLC or other master device via serial communications using the MEMOBUS/Modbus protocol. MEMOBUS/Modbus communications can be configured using one master (PLC) and up to 255 slaves. The drive has slave functionality only, and serial communication is normally initiated from the master and responded to by the slaves.

The master communicates with the specified slave drive. The address or node for each slave must be set prior so the master can communicate with the slave at that address. A slave that receives a command from the master will perform the specified function and send a response back to the master.

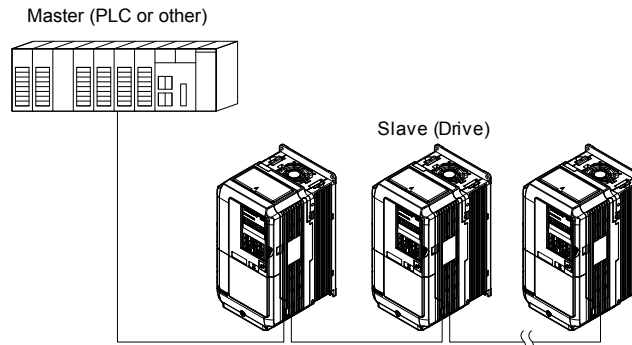


Figure C.1 Connecting Multiple Drives to a PLC

C.2 Communication Specifications

MEMOBUS/Modbus specifications appear in *Table C.1*:

Table C.1 MEMOBUS/Modbus Communications Specifications

| Item | Specifications | |
|--------------------------|---|--|
| Interface | RS-422, RS-485 | |
| Communications Cycle | Asynchronous (Start-stop synchronization) | |
| Communication Parameters | Communication Speeds Available | 1.2; 2.4; 4.8; 9.6; 19.2; 38.4; 57.6; 76.8; 115.2 kbps |
| | Data length | 8-bit (fixed) |
| | Parity | Select even, odd, or none |
| | Stop bit | 1-bit (fixed) |
| Protocol | MEMOBUS/Modbus (using RTU mode only) | |
| Maximum Number of Slaves | 31 drives (RS-485) | |

C.3 Connecting to a Network

This section explains how to connect the drive to a MEMOBUS/Modbus network and the network termination required for a connection.

◆ Network Cable Connection

Follow the instructions below to connect the drive to a MEMOBUS/Modbus network.

1. With the power shut off, connect the communications cable to the drive and the master. Use terminals TB5 for MEMOBUS/Modbus.

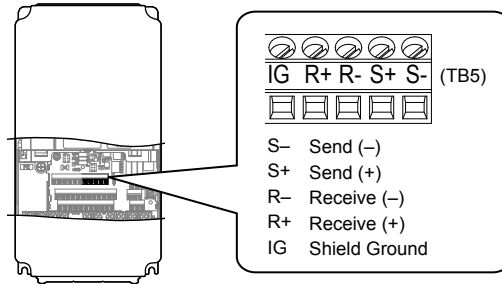


Figure C.2 Serial Communications Cable Connection Terminals (TB5)

Note: Separate the communications cables from the main circuit cables and other wiring and power cables. Use shielded cables for the communications cables, and properly shielded clamps to prevent problems with noise. When using RS-485 communications, connect S+ to R+, and S- to R- as shown in the diagram below.

2. Check or set the termination resistor selection at all slaves. Use the description in [Network Termination](#) on page 510 for slaves that are P1000 drives.
3. Switch the power on.
4. Set the parameters needed for serial communications (H5-01 through H5-12) using the digital operator.
5. Shut the power off and wait until the display on the digital operator goes out completely.
6. Turn the power back on.
7. The drive is now ready to begin communicating with the master.

◆ Wiring Diagram for Multiple Connections

Figure C.3 and *Figure C.4* explain the wiring diagrams for multiple connections using MEMOBUS/Modbus communication.

■ RS-485 Interface

Note: The isolated ground (IG) connection is optional but strongly recommended to improve network immunity to electrical interference.

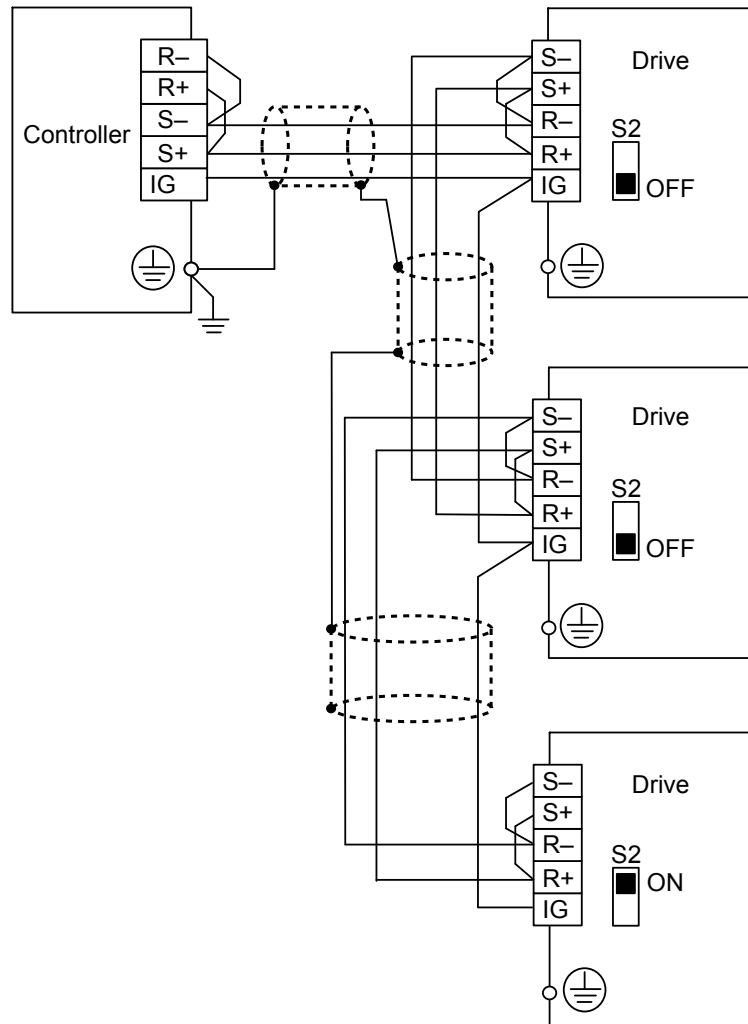


Figure C.3 RS-485 Interface

- Note:**
1. Set DIP switch S2 to the ON position on the drive located at the end of the network. Set DIP switch S2 to the OFF positions on all other slave devices.
 2. Set H5-07 to 1 when using the RS-485 interface.

■ RS-422 Interface

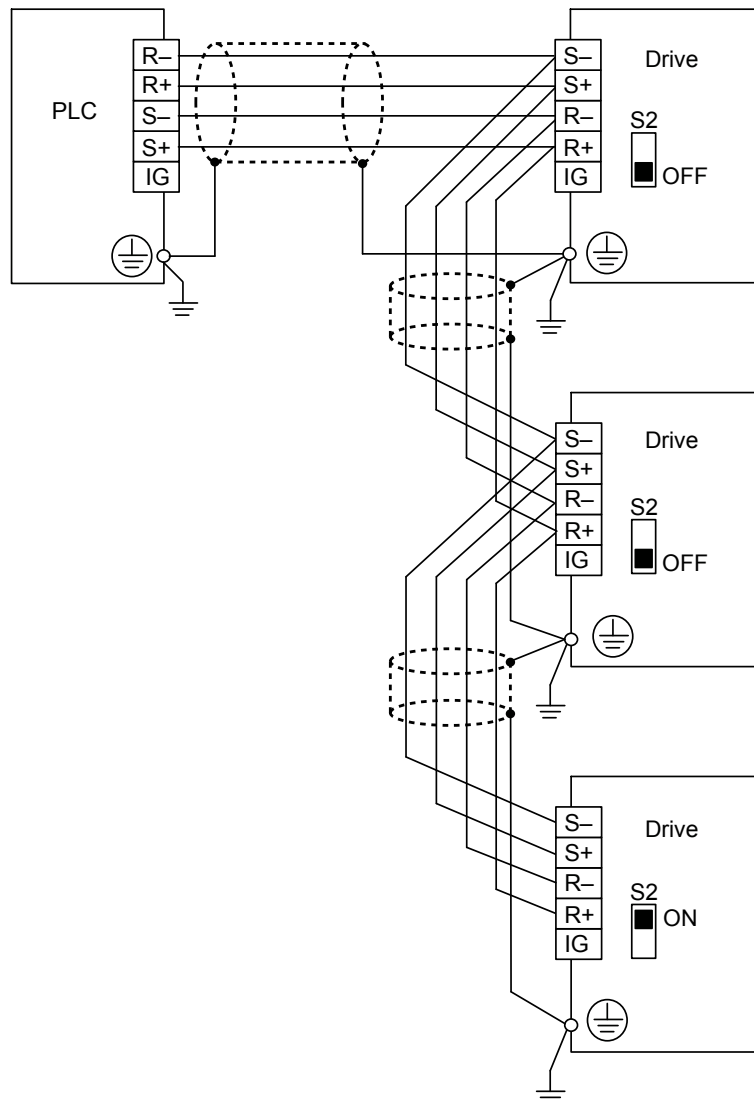


Figure C.4 RS-422 Interface

- Note:**
1. Set DIP switch S2 to the ON position on the drive located at the end of the network. Set DIP switch S2 to the OFF positions on all other slave devices.
 2. Set H5-07 to 1 when using the RS-422 interface in a multi-drop circuit.
Set H5-07 to 0 when using the RS-422 interface in a point-to-point circuit.

◆ Network Termination

The two ends of the MEMOBUS/Modbus network line have to be terminated. The drive has a built in termination resistor that can be enabled or disabled using DIP switch S2. If a drive is located at the end of a network line, enable the termination resistor by setting DIP switch S2 to the ON position. Disable the termination resistor on all slaves that are not located at the network line end.

C.4 MEMOBUS/Modbus Setup Parameters

◆ MEMOBUS/Modbus Serial Communication

Changes to MEMOBUS/Modbus communications settings become effective after restarting the drive.

■ H5-01: Drive Node Address

Sets the drive station node number (address) for MEMOBUS/Modbus terminals R+, R-, S+, S- . .

Note: Cycle the power after changing this parameter to enable the new setting.

| No. | Name | Setting Range | Default |
|-------|---------------------|---------------|----------|
| H5-01 | Drive Slave Address | | 1F (Hex) |

■ H5-02: Communication Speed Selection

Sets the MEMOBUS/Modbus communications speed.

Note: Cycle the power after changing this parameter to enable the new setting.

| No. | Name | Setting Range | Default |
|-------|-------------------------------|---------------|---------|
| H5-02 | Communication Speed Selection | 0 to 8 | 3 |

| H5-02 | Communication Speed | H5-02 | Communication Speed |
|-------|---------------------|-------|---------------------|
| 0 | 1200 bps | 5 | 38400 bps |
| 1 | 2400 bps | 6 | 57600 bps |
| 2 | 4800 bps | 7 | 76800 bps |
| 3 | 9600 bps | 8 | 115200 bps |
| 4 | 19200 bps | | |

■ H5-03: Communication Parity Selection

Sets the parity used for communications.

Note: Cycle power for the setting to take effect.

| No. | Name | Setting Range | Default |
|-------|--------------------------------|---------------|---------|
| H5-03 | Communication Parity Selection | 0 to 2 | 0 |

Setting 0: No parity

Setting 1: Even parity

Setting 2: Odd parity

■ H5-04: Stopping Method after Communication Error

Selects the stopping method after a communications error (CE) has occurred.

| No. | Name | Setting Range | Default |
|-------|--------------------------|---------------|---------|
| H5-04 | Stopping Method after CE | 0 to 3 | 3 |

Setting 0: Ramp to stop (uses the deceleration time currently enabled)

Setting 1: Coast to stop

Setting 2: Fast Stop

Setting 3: Alarm only (continue operation)

■ H5-05: Communication Fault Detection Selection

Enables or disables the CE detection for communications.

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------|
| H5-05 | Communication Fault Detection Selection | 0 or 1 | 1 |

Setting 0: Disabled

No communication error detection. The drive continues operation.

C.4 MEMOBUS/Modbus Setup Parameters

Setting 1: Enabled

If the drive does not receive data from the master for longer than the time set to H5-09, then a CE fault will be triggered and the drive will operate as determined by parameter H5-04.

■ H5-06: Drive Transmit Wait Time

Sets the time the drive waits after receiving data from a master until responding data.

Note: Cycle power for the setting to take effect.

| No. | Name | Setting Range | Default |
|-------|--------------------------|---------------|---------|
| H5-06 | Drive Transmit Wait Time | 5 to 65 ms | 5 ms |

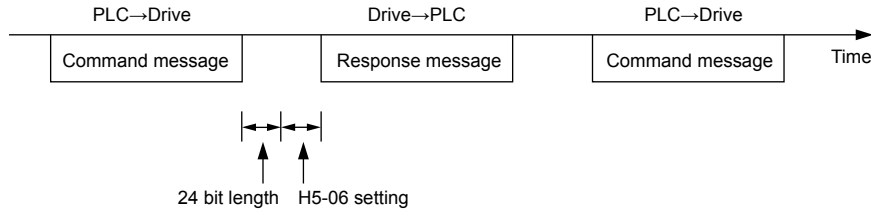


Figure C.5 Drive Transmit Wait Time Setting

■ H5-07: RTS Control Selection

Enables or disables RTS control.

Note: Cycle power for the setting to take effect.

| No. | Name | Setting Range | Default |
|-------|-----------------------|---------------|---------|
| H5-07 | RTS Control Selection | 0 or 1 | 1 |

Setting 0: Disabled. RTS is always on.

Use this setting with point-to-point RS-422 communications.

Setting 1: Enabled. RTS switches while sending.

Use this setting with RS-485 communications or when using multi-drop RS-422 communications.

■ H5-09: Communications Fault Detection Time

Sets the time the communications must be lost before the drive triggers a CE fault.

| No. | Name | Setting Range | Default |
|-------|-------------------------------------|---------------|---------|
| H5-09 | Communications Fault Detection Time | 0.0 to 10.0 s | 2.0 s |

■ H5-10: Unit Selection for MEMOBUS/Modbus Register 0025H

Sets the unit for the output voltage monitor value in MEMOBUS/Modbus register 0025H.

| No. | Name | Setting Range | Default |
|-------|--|---------------|---------|
| H5-10 | Unit Selection for MEMOBUS/Modbus Register 0025H | 0 or 1 | 0 |

Setting 0: 0.1 V units

Setting 1: 1 V units

■ H5-11: Communications Enter Function Selection

Selects whether an Enter command is necessary to change parameter values via MEMOBUS/Modbus communications. *Refer to Enter Command on page 536.*

| No. | Name | Setting Range | Default |
|-------|---|---------------|---------|
| H5-11 | Communications Enter Function Selection | 0 or 1 | 0 |

Setting 0: Enter command necessary

Parameter changes become effective after an Enter command. An Enter command must only be sent after the last parameter change, not for each single parameter.

Setting 1: Enter command not necessary

Parameter value changes become effective immediately without the need to send an Enter command.

■ H5-12: Run Command Method Selection

Selects the type of sequence used when the Run command source is set to MEMOBUS/Modbus communications (b1-02, b1-16 = 2).

| No. | Name | Setting Range | Default |
|-------|------------------------------|---------------|---------|
| H5-12 | Run Command Method Selection | 0 or 1 | 0 |

Setting 0: FWD/Stop, REV/Stop

Setting bit 0 of MEMOBUS/Modbus register 0001H will start and stop the drive in the forward direction. Setting bit 1 will start and stop the drive in reverse.

Setting 1: Run/Stop, FWD/REV

Setting bit 0 of MEMOBUS/Modbus register 0001H will start and stop the drive. Setting bit 1 changes the direction.

C.5 Drive Operations by MEMOBUS/Modbus

The drive operations that can be performed by MEMOBUS/Modbus communication depend on drive parameter settings. This section explains the functions that can be used and related parameter settings.

◆ Observing the Drive Operation

PLCs can perform the following actions with MEMOBUS/Modbus communications:

- observe drive status and drive control terminal status
- read and write parameters (not H5-□□)
- reset faults
- set multi-function inputs

Note: Input settings from the input terminals (S1 to S8) and from MEMOBUS/Modbus communications are both linked by a logical OR operation.

◆ Controlling the Drive

Select an external reference and adjust the parameters in [Table C.2](#) accordingly to start and stop the drive or set the frequency reference using MEMOBUS/Modbus communications.

Table C.2 Setting Parameters for Drive Control from MEMOBUS/Modbus

| Reference Source | Parameter | Name | Required Setting |
|----------------------|-----------|---------------------------------|------------------|
| External Reference 1 | b1-01 | Frequency Reference Selection 1 | 2 |
| | b1-02 | Run Command Selection 1 | 2 |
| External Reference 2 | b1-15 | Frequency Reference Selection 2 | 2 |
| | b1-16 | Run Command Selection 2 | 2 |

Refer to b1-01: Frequency Reference Selection 1 on page 147 and Refer to b1-02: Run Command Selection 1 on page 148 for details on external reference parameter selections. Refer to Setting 2: External Reference 1/2 Selection on page 207 for instructions on selecting external references 1 and 2.

C.6 Communications Timing

To prevent a communications overrun in the slave drive, the master should wait a certain time between sending messages to the same drive. In the same way, the slave drive must wait before sending response messages to prevent an overrun in the master. This section explains the message timing.

◆ Command Messages from Master to Drive

The master must wait for a specified time between receiving a response and resending the same type of command to the same slave drive to prevent overrun and data loss. The minimum wait time depends on the command as shown in [Table C.3](#).

Table C.3 Minimum Wait Time for Sending Messages

| Command Type | Example | Minimum Wait Time |
|--------------|---|--|
| 1 | <ul style="list-style-type: none"> Control command (Run, Stop) Set inputs/outputs Read monitors and parameter values | 5 ms </> |
| 2 | Write parameters | H5-06 = 0: 50 ms H5-06 = 1: 200 ms </> |
| 3 | Save changes using an Enter command | 200 ms to 2 s, depending on the number of parameters that were changed </> |
| 4 | Enter with storage to drive EEPROM after initialization | 5 s |

</> If the drive receives command type 1 data during the minimum wait time, it will perform the command and then respond. However, if it receives a command type 2 or 3 during that time, either a communication error will result or the command will be ignored.

Set a timer in the master to check how long it takes for the slave drive(s) to respond to the master. If no response is received within a certain amount of time, the master should try resending the message.

◆ Response Messages from Drive to Master

If the drive receives a command from the master, it will process the data received and wait for the time set in H5-06 until it responds. Increase H5-06 if the drive response causes overrun in the master.

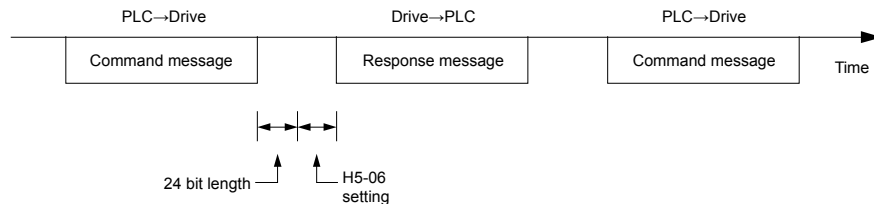


Figure C.6 Minimum Response Wait Time

C.7 Message Format

◆ Message Content

In MEMOBUS/Modbus communications, the master sends commands to the slave, and the slave responds. The message format is configured for both sending and receiving as shown below, and the length of data packets depends on the command (function) content.

| |
|---------------|
| SLAVE ADDRESS |
| FUNCTION CODE |
| DATA |
| ERROR CHECK |

◆ Slave Address

The slave address in the message defines the note the message is sent to. Use addresses between 0 and FF (hex). If a message with slave address 0 is sent (broadcast), the command from the master will be received by all slaves. The slaves do not provide a response to a broadcast type message.

◆ Function Code

The three types of function codes are shown in the table below.

| Function Code | Function Name | Data Length (bytes) | | | |
|---------------|--|---------------------|---------|------------------|---------|
| | | Command Message | | Response Message | |
| | | Minimum | Maximum | Minimum | Maximum |
| 03H | Read MEMOBUS/Modbus registers | 8 | 8 | 7 | 37 |
| 08H | Loopback test | 8 | 8 | 8 | 8 |
| 10H | Write to multiple MEMOBUS/Modbus registers | 11 | 41 | 8 | 8 |

◆ Data

Configure consecutive data by combining the MEMOBUS/Modbus register address (test code in case of a loopback test) and the data the register contains. The data length changes depending on the command details.

A drive MEMOBUS/Modbus register always has a data length of two bytes. Data written into drive registers must also always have a length of two bytes. Register data read out from the drive will always consist of two bytes.

◆ Error Check

The drive uses a CRC-16 (cyclic redundancy check, checksum method) for checking data validity. Use the procedure described below when calculating the CRC-16 checksum for command data or when verifying response data.

■ Command Data

When the drive receives data, it calculates the CRC-16 checksum from the data and compares it to the CRC-16 value received within the message. Both must match before a command is processed.

An initial value of FFFFH (i.e., all 16 bits equal 1) must be used for CRC-16 calculations in the MEMOBUS/Modbus protocol.

Calculate the CRC-16 checksum using the following steps:

1. The starting value is FFFFH.
2. Perform an XOR operation of this value and the slave address.
3. Right shift the result.
4. When the overflow bit of the shift operation becomes 1, perform an XOR operation of the result from step 3 above and the fix value A001H.
5. Repeat steps 3 and 4 until eight shift operations have been performed.
6. After eight shift operations, perform an XOR operation with the result and the next data in the message (function code, register address, data). Continue with steps 3 to 5 until the last data has been processed.
7. The result of the last shift or XOR operation is the checksum.

The example in *Table C.4* shows the CRC-16 calculation of the slave address 02H and the function code 03H, yielding the result D140H.

Note: This example does not show the calculation for a complete MEMOBUS/Modbus command. Normally data would follow in the calculation.

Table C.4 CRC-16 Checksum Calculation Example

| Description | Calculation | Overflow | Description | Calculation | Overflow |
|---|---------------------|----------|------------------------------------|----------------------------|----------|
| Initial Value (FFFFH) | 1111 1111 1111 1111 | | Function Code 03H | 0000 0000 0000 0011 | |
| Address 02H | 0000 0000 0000 0010 | | XOR w result | 1000 0001 0011 1101 | |
| XOR w initial value | 1111 1111 1111 1101 | | Shift 1 | 0100 0000 1001 1110 | 1 |
| Shift 1 | 0111 1111 1111 1110 | 1 | XOR w A001H | 1010 0000 0000 0001 | |
| XOR w A001H | 1010 0000 0000 0001 | | XOR result | 1110 0000 1001 1111 | |
| XOR result | 1101 1111 1111 1111 | | Shift 2 | 0111 0000 0100 1111 | 1 |
| Shift 2 | 0110 1111 1111 1111 | 1 | XOR w A001H | 1010 0000 0000 0001 | |
| XOR w A001H | 1010 0000 0000 0001 | | XOR result | 1101 0000 0100 1110 | |
| XOR result | 1100 1111 1111 1110 | | Shift 3 | 0110 1000 0010 0111 | 0 |
| Shift 3 | 0110 0111 1111 1111 | 0 | Shift 4 | 0011 0100 0001 0011 | 1 |
| Shift 4 | 0011 0011 1111 1111 | 1 | XOR w A001H | 1010 0000 0000 0001 | |
| XOR w A001H | 1010 0000 0000 0001 | | XOR result | 1001 0100 0001 0010 | |
| XOR result | 1001 0011 1111 1110 | | Shift 5 | 0100 1010 0000 1001 | 0 |
| Shift 5 | 0100 1001 1111 1111 | 0 | Shift 6 | 0010 0101 0000 0100 | 1 |
| Shift 6 | 0010 0100 1111 1111 | 1 | XOR w A001H | 1010 0000 0000 0001 | |
| XOR w A001H | 1010 0000 0000 0001 | | XOR result | 1000 0101 0000 0101 | |
| XOR result | 1000 0100 1111 1110 | | Shift 7 | 0100 0010 1000 0010 | 1 |
| Shift 7 | 0100 0010 0111 1111 | 0 | XOR w A001H | 1010 0000 0000 0001 | |
| Shift 8 | 0010 0001 0011 1111 | 1 | XOR result | 1110 0010 1000 0011 | |
| XOR w A001H | 1010 0000 0000 0001 | | Shift 8 | 0111 0001 0100 0001 | 1 |
| XOR result | 1000 0001 0011 1110 | | XOR w A001H | 1010 0000 0000 0001 | |
| Perform operations with next data (function code) | | | XOR result | 1101 0001 0100 0000 | |
| | | | CRC-16 | 1101 0001 0100 0000 | |
| | | | | D 1 4 0 (Lower) (Upper) | |
| | | | Continue from here with next data. | | |

■ Response Data

Perform a CRC-16 calculation on the response message data as described above as a validation check. The result should match the CRC-16 checksum received within the response message.

C.8 Message Examples

Below are some examples of command and response messages.

◆ Reading Drive MEMOBUS/Modbus Register Contents

Using the function code 03H (Read), a maximum of 16 MEMOBUS/Modbus registers can be read out at a time.

The following table shows message examples when reading status signals, error details, data link status, and frequency references from the slave 2 drive.

| Command Message | | | Response Message (normal) | | | Response Message (fault) | | |
|-----------------|--------|-------|---------------------------|-----------------------|-------|--------------------------|-------|-----|
| Slave Address | | 02H | Slave Address | | 02H | Slave Address | | 02H |
| Function Code | | 03H | Function Code | | 03H | Function Code | | 83H |
| Starting No. | Upper | 00H | Data Quantity | | 08H | Error Code | | 03H |
| | Lower | 20H | 1st storage register | Upper | 00H | CRC-16 | Upper | F1H |
| Data Quantity | Upper | 00H | | Lower | 65H | | Lower | 31H |
| | CRC-16 | Upper | 45H | Next storage register | Upper | 00H | | |
| Lower | | 04H | Lower | | 00H | | | |
| CRC-16 | Upper | 45H | Next storage register | Upper | 00H | | | |
| | Lower | F0H | | Lower | 00H | | | |
| CRC-16 | Upper | 45H | Next storage register | Upper | 01H | | | |
| | Lower | F0H | | Lower | F4H | | | |
| CRC-16 | Upper | 45H | CRC-16 | Upper | AFH | | | |
| | Lower | F0H | | Lower | 82H | | | |

◆ Loopback Test

Function code 08H performs a loopback test that returns a response message with exactly the same content as the command message. The response message can be used to check communications between the master and slave. User-defined test code and data values can also be set.

The following table shows a message example when performing a loopback test with the slave 1 drive.

| Command Message | | | Response Message | | |
|-----------------|-------|-----|------------------|-------|-----|
| Slave Address | | 01H | Slave Address | | 01H |
| Function Code | | 08H | Function Code | | 08H |
| Test Code | Upper | 00H | Test Code | Upper | 00H |
| | Lower | 00H | | Lower | 00H |
| Data | Upper | A5H | Data | Upper | A5H |
| | Lower | 37H | | Lower | 37H |
| CRC-16 | Upper | DAH | CRC-16 | Upper | DAH |
| | Lower | 8DH | | Lower | 8DH |

◆ Writing to Multiple Registers

Function code 10H allows the user to write multiple drive MEMOBUS/Modbus registers with one message. This process works similar to reading registers, in that the address of the first register to be written and the data quantity are set in the command message. The data to be written must be consecutive so that the register addresses are in order, starting from the specified address in the command message. The data order must be high byte then lower byte.

The following table shows an example of a message where a forward operation has been set with a frequency reference of 60.00 Hz for the slave 1 drive.

If parameter values are changed using the Write command, an Enter command may be necessary to activate or save the data depending on the setting of H5-11. [Refer to H5-11: Communications Enter Function Selection on page 513](#) and [Refer to Enter Command on page 536](#) for detailed descriptions.

| Command Message | | | Response Message (normal) | | | Response Message (fault) | | |
|-----------------|-----------|-------|---------------------------|-------|-----|--------------------------|-------|-----|
| Slave Address | | 01H | Slave Address | | 01H | Slave Address | | 01H |
| Function Code | | 10H | Function Code | | 10H | Function Code | | 90H |
| Starting No. | Upper | 00H | Starting No. | Upper | 00H | Error Code | | 02H |
| | Lower | 01H | | Lower | 01H | CRC-16 | Upper | CDH |
| Data Quantity | Upper | 00H | Data Quantity | Upper | 00H | | Lower | C1H |
| | Lower | 02H | | Lower | 02H | | | |
| Number of Bytes | | 04H | CRC-16 | Upper | 10H | | | |
| Starting Data | Upper | 00H | | Lower | 08H | | | |
| | Next Data | Upper | 17H | | | | | |
| Lower | | 70H | | | | | | |
| CRC-16 | Upper | 63H | | | | | | |
| | Lower | 39H | | | | | | |

Note: Double the number of the data quantity for the number of bytes in the command message.

C.9 MEMOBUS/Modbus Data Table

The tables below list all MEMOBUS/Modbus data.

The MEMOBUS register hex addresses for parameters are listed beginning on page [433](#).

◆ Command Data

It is possible to both read and write command data.

Note: Bits that are not used should be set to 0. Refrain from writing to reserved registers.

| Register No. | Contents | |
|----------------|---|---|
| 0000H | Reserved | |
| 0001H | Operation Commands and Multi-function Inputs | |
| | bit 0 | H5-12 = 0: Forward Run Command (0 = Stop, 1 = Forward Run) H5-12 = 1: Run Command (0 = Stop, 1 = Run) |
| | bit 1 | H5-12 = 0: Reverse Run Command (0 = Stop, 1 = Reverse Run) H5-12 = 1: Forward/Reverse (0 = Forward, 1 = Reverse) |
| | bit 2 | External Fault (EF0) |
| | bit 3 | Fault Reset |
| | bit 4 | Multi-Function Input 1 Function is ComRef when H1-01 = 40 (Forward/Stop). <i>Refer to d: Reference Settings on page 182 for ComRef explanations.</i> |
| | bit 5 | Multi-Function Input 2 Function is ComCtrl when H1-02 = 41 (Reverse/Stop). |
| | bit 6 | Multi-Function Input 3 |
| | bit 7 | Multi-Function Input 4 |
| | bit 8 | Multi-Function Input 5 |
| | bit 9 | Multi-Function Input 6 |
| | bit A | Multi-Function Input 7 |
| | bit B | Multi-Function Input 8 |
| | bit C to F | Reserved |
| 0002H | Frequency Reference | Units are determined by parameter o1-03. |
| 0003H | Output voltage gain/ Unit: 0.1% Range: 20 (2.0%) to 2000 (200.0%), Default when power on: 1000 (100.0%) | |
| 0004H to 0005H | Reserved | |
| 0006H | PID Target, 0.01% units, signed | |
| 0007H | Analog Output Terminal FM Setting (10 V / 4000 H) | |
| 0008H | Analog Output Terminal AM Setting (10 V / 4000 H) | |
| 0009H | Settings for Multi-Function Digital Outputs | |
| | bit 0 | Multi-Function Contact Output (Terminal M1-M2) |
| | bit 1 | Multi-Function Contact Output (Terminal M3-M4) |
| | bit 2 | Multi-Function Contact Output (Terminal MD-MF) |
| | bit 3 to 5 | Reserved |
| | bit 6 | Enables the function in bit 7 |
| | bit 7 | Fault Contact Output (terminal MA/MB-MC) |
| bit 8 to F | Reserved | |
| 000AH to 000CH | Reserved | |
| 000DH | PI2 Setpoint | |
| 000EH | Reserved | |

| Register No. | Contents | |
|----------------|--|---|
| 000FH | Control Selection Setting | |
| | bit 0 | Reserved |
| | bit 1 | PID Setpoint Input |
| | bit 2, 3 | Reserved |
| | bit 4 | PI2 Target Input |
| | bit 5 to B | Reserved |
| | bit C | Enable Terminal S5 Input for Broadcast Data |
| | bit D | Enable Terminal S6 Input for Broadcast Data |
| | bit E | Enable Terminal S7 Input for Broadcast Data |
| bit F | Enable Terminal S8 Input for Broadcast Data | |
| 0010H to 001AH | Reserved | |
| 001BH | Analog Monitor Option AO-A3 Analog Output 1 (10 V/4000 H) | |
| 001CH | Analog Monitor Option AO-A3 Analog Output 2 (10 V/4000 H) | |
| 001DH to 001FH | Reserved | |
| 3004H | Set Time – Hours/Minutes (HHmm) | |
| 3005H | Set Date – Year/Day of Week (YYdd) | |
| 3006H | Set Date – Month/Day (MMDD) | |
| 3007H | RTC Set Command/Status 0 = Complete 1 = Set RTC data using registers 3004H to 3006H 8 = failed | |
| 302FH | RTC Enter 0 = Overwrite RTC data using registers 3004H to 3006H. Only effective when 3030H bit 1 (RTC Enter Enable) is set. | |
| 3030H | bit 1 | RTC Enter Enable |
| | bit 2 | RTC TIE Fault Enable |

◆ Monitor Data

Monitor data can be read only.

| Register No. | Contents | |
|--------------|----------------|--|
| 0020H | Drive Status 1 | |
| | bit 0 | During Run |
| | bit 1 | During Reverse |
| | bit 2 | Drive Ready |
| | bit 3 | Fault |
| | bit 4 | Data Setting Error |
| | bit 5 | Multi-Function Contact Output (terminal M1-M2) |
| | bit 6 | |
| | bit 7 | |
| | bit 8 to bit D | Reserved |
| | bit E | ComRef status |
| | bit F | ComCtrl status |

C.9 MEMOBUS/Modbus Data Table

| Register No. | Contents | |
|----------------|---|---|
| 0021H | Fault Contents 1 | |
| | bit 0 | Overcurrent (oC), Ground fault (GF) |
| | bit 1 | Overvoltage (ov) |
| | bit 2 | Drive Overload (oL2) |
| | bit 3 | Overheat 1 (oH1), Drive Overheat Warning (oH2) |
| | bit 4 | Dynamic Braking Transistor Fault (rr), Braking Resistor Overheat (rH) |
| | bit 5 | Reserved |
| | bit 6 | PID Feedback Loss (FbL / FbH) |
| | bit 7 | EF to EF8: External Fault |
| | bit 8 | CPF□□: Hardware Fault (includes oFx) |
| | bit 9 | Motor Overload (oL1), Overtorque Detection 1/2 (oL3/oL4), Undertorque Detection 1/2 (UL3/UL4) |
| | bit A | Reserved |
| | bit B | Main Circuit Undervoltage (Uv) |
| | bit C | Undervoltage (Uv1), Control Power Supply Undervoltage (Uv2), Soft Charge Circuit Fault (Uv3) |
| | bit D | Output Phase Loss (LF), Input Phase Loss (PF) |
| bit E | MEMOBUS/Modbus Communication Error (CE), Option Communication Error (bUS) | |
| bit F | Operator Connection Fault (oPr) | |
| 0022H | Data Link Status | |
| | bit 0 | Writing data or switching motors |
| | bit 1 | Reserved |
| | bit 2 | |
| | bit 3 | Upper or lower limit error |
| | bit 4 | Data conformity error |
| | bit 5 | Writing to EEPROM |
| | bit 6 to bit F | Reserved |
| 0023H | Frequency Reference </> | |
| 0024H | Output Frequency </> | |
| 0025H | Output Voltage Reference, 0.1 V units (units are determined by parameter H5-10) | |
| 0026H | Output Current, 0.1 A units | |
| 0027H | Output Power | |
| 0028H | Reserved | |
| 0029H | Fault Contents 2 | |
| | bit 0 | IGBT Short Circuit (SC) |
| | bit 1 | Ground Fault (GF) |
| | bit 2 | Input Phase Loss (PF) |
| | bit 3 | Output Phase Loss (LF) |
| | bit 4 | Braking Resistor Overheat (rH) |
| | bit 5 | Reserved |
| | bit 6 | Motor Overheat 2 (PTC input) (oH4) |
| bit 7 to bit F | Reserved | |

| Register No. | Contents | |
|----------------|--|---|
| 002AH | Alarm Contents 1 | |
| | bit 0, 1 | Reserved |
| | bit 2 | Run Command Input Error (EF) |
| | bit 3 | Drive Baseblock (bb) |
| | bit 4 | Overtorque Detection 1 (oL3) |
| | bit 5 | Heatsink Overheat (oH) |
| | bit 6 | Overvoltage (ov) |
| | bit 7 | Undervoltage (Uv) |
| | bit 8 | Cooling Fan Error (FAn) |
| | bit 9 | MEMOBUS/Modbus Communication Error (CE) |
| | bit A | Option Communication Error (bUS) |
| | bit B | Undertorque Detection 1/2 (UL3/UL4) |
| | bit C | Motor Overheat (oH3) |
| | bit D | PID Feedback Loss (FbL, FbH) |
| | bit E | Reserved |
| bit F | Serial Communication Transmission Error (CALL) | |
| 002BH | Input Terminal Status | |
| | bit 0 | Terminal S1 Closed |
| | bit 1 | Terminal S2 Closed |
| | bit 2 | Terminal S3 Closed |
| | bit 3 | Terminal S4 Closed |
| | bit 4 | Terminal S5 Closed |
| | bit 5 | Terminal S6 Closed |
| | bit 6 | Terminal S7 Closed |
| | bit 7 | Terminal S8 Closed |
| bit 8 to bit F | Reserved | |
| 002CH | Drive Status 2 | |
| | bit 0 | During Run |
| | bit 1 | Zero Speed |
| | bit 2 | Speed Agree |
| | bit 3 | User Speed Agree |
| | bit 4 | Frequency Detection 1 |
| | bit 5 | Frequency Detection 2 |
| | bit 6 | Drive Ready |
| | bit 7 | During Undervoltage |
| | bit 8 | During Baseblock |
| | bit 9 | Frequency Reference from Operator Keypad |
| | bit A | Run Command from Operator Keypad |
| | bit B | Over/Undertorque 1, 2 |
| | bit C | Frequency Reference Loss |
| | bit D | During Fault Restart |
| bit E | Fault | |
| bit F | Communication Timeout | |
| 002DH | Output Terminal Status | |
| | bit 0 | Multi-Function Contact Output 1 (terminal MD-ME-MF) |
| | bit 1 | Multi-Function Contact Output 2 (terminal M1-M2) |
| | bit 2 | Multi-Function Contact Output 3 (terminal M3-M4) |
| | bit 3 to 6 | Reserved |
| | bit 7 | Fault Contact Output (terminal MA/MB-MC) |
| bit 8 to F | Reserved | |

C.9 MEMOBUS/Modbus Data Table

| Register No. | Contents | | |
|----------------|---|---------------------------------|--|
| 002EH | Reserved | | |
| 002FH | Frequency Reference Bias (from Up/Down 2 Function), 0.1% units | | |
| 0030H | Reserved | | |
| 0031H | DC Bus Voltage, 1 Vdc units | | |
| 0032H to 0033H | Reserved | | |
| 0034H | Product Code 1 [ASCII], Product Type | | |
| 0035H | Product Code 2 [ASCII], Region Code | | |
| 0036H, 0037H | Reserved | | |
| 0038H | PID Feedback, 0.1% units, unsigned, 100% / max. output frequency | | |
| 0039H | PID Input, 0.1% units, signed, 100% / max. output frequency | | |
| 003AH | PID Output, 0.1% units, signed, 100% / max. output frequency | | |
| 003BH, 003CH | Reserved | | |
| 003DH | Communications Error Contents <3> | | |
| | bit 0 | CRC Error | |
| | bit 1 | Data Length Error | |
| | bit 2 | Reserved | |
| | bit 3 | Parity Error | |
| | bit 4 | Overrun Error | |
| | bit 5 | Framing Error | |
| | bit 6 | Timeout | |
| bit 7 to bit F | Reserved | | |
| 003EH | Output Frequency | r/min <4> | |
| 003FH | | 0.01% units | |
| 0040H to 004AH | Used for various monitors U1-□□. <i>Refer to U: Monitors on page 479</i> for parameter details. | | |
| 004BH | Drive status (U1-12) | | |
| | bit 0 | During Run | |
| | bit 1 | During Zero Speed | |
| | bit 2 | During Reverse Run | |
| | bit 3 | During Fault Reset Signal Input | |
| | bit 4 | During Speed Agree | |
| | bit 5 | Drive Ready | |
| | bit 6 | Alarm | |
| | bit 7 | Fault | |
| | bit 8 | During Operation Error (oPE□□) | |
| | bit 9 | During Momentary Power Loss | |
| | bit A to B | Reserved | |
| | bit E | ComRef status, NetRef status | |
| bit F | ComCtrl status, NetCtrl status | | |
| 004CH to 007EH | Used for various monitors U1-□□, U4-□□, U5-□□ and U6-□□. <i>Refer to U2: Fault Trace on page 481</i> and <i>Refer to U3: Fault History on page 482</i> for parameter details. | | |
| 007FH | Alarm Code, <i>Refer to Alarm Register Contents on page 535</i> for alarm codes. | | |
| 0080H to 0097H | Used for monitors U2-□□, U3-□□. <i>Refer to U: Monitors on page 479</i> for parameter details and <i>Refer to Fault Trace Contents on page 533</i> for register value descriptions. | | |
| 0098H | High Word of Accumulated Operation Time Monitor, 10 h units (U4-01) | | |
| 0099H | Low Word of Accumulated Operation Time Monitor, 1 h units (U4-01) | | |
| 009AH | High Word of Cooling Fan Operation Time Monitor (U4-03) | | |
| 009BH | Low Word of Cooling Fan Operation Time Monitor (U4-03) | | |
| 009CH to 00AAH | Reserved | | |
| 00ABH | Drive Rated Current <2> | | |
| 00ACH to 00AFH | Reserved | | |

| Register No. | Contents | |
|----------------|--|---|
| 00B0H | Option Code Connected to CN5-A | Register contains ASCII code of the option card. AO-A3 = 0004H Communication Option: Register contains ASCII code of first and third digit of the option card type number. Example: Register value is 5343H for “SC” if an SI-C3 option card is installed. |
| 00B1H | Reserved | |
| 00B2H | Option Code Connected to CN5-B | |
| 00B3H | Option Code Connected to CN5-C | |
| 00B4H | Reserved | |
| 00B5H | Frequency Reference After Soft-starter (U1-16) | r/min units <4> |
| 00B6H | | 0.01% units |
| 00B7H | Frequency Reference | r/min <4> |
| 00B8H | | 0.01% units |
| 00B9H to 00BEH | Reserved | |
| 00BFH | Lists the last two digits of operation error code oPE□□. | |
| 00C0H | Fault Contents 3 | |
| | bit 1 | Undervoltage (Uv1) |
| | bit 2 | Control Power Supply Undervoltage (Uv2) |
| | bit 3 | Soft Charge Circuit Fault (Uv3) |
| | bit 4 | IGBT Short Circuit (SC) |
| | bit 5 | Ground Fault (GF) |
| | bit 6 | Overcurrent (oC) |
| | bit 7 | Overvoltage (ov) |
| | bit 8 | Heatsink Overheat (oH) |
| | bit 9 | Heatsink Overheat (oH1) |
| | bit A | Motor Overload (oL1) |
| | bit B | Drive Overload (oL2) |
| | bit C | Overtorque Detection 1 (oL3) |
| | bit D | Overtorque Detection 2 (oL4) |
| 00C1H | Fault Contents 4 | |
| | bit 0 | External Fault at input terminal S3 (EF3) |
| | bit 1 | External Fault at input terminal S4 (EF4) |
| | bit 2 | External Fault at input terminal S5 (EF5) |
| | bit 3 | External Fault at input terminal S6 (EF6) |
| | bit 4 | External Fault at input terminal S7 (EF7) |
| | bit 5 | External Fault at input terminal S8 (EF8) |
| | bit 6 | Cooling Fan Error (FAn) |
| | bit 7 to 9 | Reserved |
| | bit A | Input Phase Loss (PF) |
| | bit B | Output Phase Loss (LF) |
| | bit C | Motor Overheat (PTC input) (oH3) |
| | bit D | Digital Operator Connection Fault (oPr) |
| | bit E | EEPROM Write Error (Err) |
| bit F | Motor Overheat Fault (PTC input) (oH4) | |

C.9 MEMOBUS/Modbus Data Table

| Register No. | Contents | |
|----------------|-------------------------------|---|
| 00C2H | Fault Contents 5 | |
| | bit 0 | MEMOBUS/Modbus Communication Error (CE) |
| | bit 1 | Option Communication Error (bUS) |
| | bit 2 to 5 | Reserved |
| | bit 6 | Option External Fault (EF0) |
| | bit 7 | PID Feedback Loss (FbL) |
| | bit 8 | Undertorque Detection 1 (UL3) |
| | bit 9 | Undertorque Detection 2 (UL4) |
| | bit A | High Slip Braking Overload (oL7) |
| | bit B to E | Reserved |
| | bit F | Hardware Fault (includes oFx) |
| 00C3H | Fault Contents 6 | |
| | bit 0 to 4 | Reserved |
| | bit 5 | Current Imbalance (LF2) |
| | bit 6 | Pullout Detection (STo) |
| | bit 7 | Reserved |
| | bit 8 | SI-T3 Watchdog Error (E5) |
| | bit 9 | Reserved |
| | bit A | Too many speed search restarts (SEr) |
| | bit B to F | Reserved |
| 00C4H | Fault Contents 7 | |
| | bit 0 | PID Feedback Loss (FbH) |
| | bit 1 | External Fault 1, input terminal S1 (EF1) |
| | bit 2 | External Fault 2, input terminal S2 (EF2) |
| | bit 3, 4 | Reserved |
| | bit 5 | Current Offset Fault (CoF) |
| | bit 6 to B | Reserved |
| | bit C | Output Voltage Detection Fault (voF) |
| | bit D | Braking Resistor Fault (rF) |
| | bit E | Braking Transistor Overload Fault (boL) |
| | bit F | Motor Overheat (NTC Input) (oH5) |
| 00C5H | Fault Contents 8 | |
| | | |
| | | |
| | bit 0 | Reserved |
| | bit 1 | Node Setup Fault (nSE) |
| | bit 2 | Thermistor Disconnect (THo) |
| | bit 3 | Variable Torque Overload (VToL) |
| | bit 4 to 8 | Reserved |
| | bit 9 | Underload Detection 6 (UL6) |
| | bit A, B | Reserved |
| | bit C | HOA Time Not Set (TIM) |
| | bit D | HOA Battery Low (bAT) |
| bit E | HOA Time Data Error (TdE) | |
| bit F | HOA Time Interval Error (TIE) | |
| 00C6H to 00C7H | Reserved | |

| Register No. | Contents | |
|--------------|-------------------------------------|--|
| 00C8H | Alarm Contents 2 | |
| | bit 0 | Undervoltage (Uv) |
| | bit 1 | Overvoltage (ov) |
| | bit 2 | Heatsink Overheat (oH) |
| | bit 3 | Drive Overheat (oH2) |
| | bit 4 | Overtorque 1 (oL3) |
| | bit 5 | Overtorque 2 (oL4) |
| | bit 6 | Run Commands Input Error (EF) |
| | bit 7 | Drive Baseblock (bb) |
| | bit 8 | External Fault 3, input terminal S3 (EF3) |
| | bit 9 | External Fault 4, input terminal S4 (EF4) |
| | bit A | External Fault 5, input terminal S5 (EF5) |
| | bit B | External Fault 6, input terminal S6 (EF6) |
| | bit C | External Fault 7, input terminal S7 (EF7) |
| | bit D | External Fault 8, input terminal S8 (EF8) |
| | bit E | Cooling Fan Error (FAn) |
| bit F | Reserved | |
| 00C9H | Alarm Contents 3 | |
| | bit 0, 1 | Reserved |
| | bit 2 | Digital Operator Connection Fault (oPr) |
| | bit 3 | MEMOBUS/Modbus Communication Error (CE) |
| | bit 4 | Option Communication Error (bUS) |
| | bit 5 | Serial Communication Transmission Error (CALL) |
| | bit 6 | Motor Overload (oL1) |
| | bit 7 | Drive Overload (oL2) |
| | bit 8 | Reserved |
| | bit 9 | Option Card External fault (EF0) |
| | bit A, B | Reserved |
| | bit C | Serial Communication Transmission Error (CALL) |
| | bit D | Undertorque Detection 1 (UL3) |
| | bit E | Undertorque Detection 2 (UL4) |
| bit F | MEMOBUS/Modbus Test Mode Fault (SE) | |
| 00CAH | Alarm Contents 4 | |
| | bit 0 | Reserved |
| | bit 1 | Motor Overheat 1 (PTC Input) (oH3) |
| | bit 2 to 5 | Reserved |
| | bit 6 | PID Feedback Loss (FbL) |
| | bit 7 | PID Feedback Loss (FbH) |
| | bit 9 | Drive Disabled (dnE) |
| bit A to F | Reserved | |

C.9 MEMOBUS/Modbus Data Table

| Register No. | Contents | |
|--------------|------------------|--|
| 00CBH | Alarm Contents 5 | |
| | bit 0 | SI-T3 Watchdog Error (E5) |
| | bit 1 | SI-T3 Station Address Setting Error (AEr) |
| | bit 2 | SI-T3 Comm. Cycle Setting Error (CyC) |
| | bit 3 | High Current Alarm (HCA) |
| | bit 4 | Cooling Fan Maintenance Time (LT-1) |
| | bit 5 | Soft Charge Bypass Relay Maintenance Time (LT-2) |
| | bit 6 | Reserved |
| | bit 7 | SI-S EEPROM Error (EEP) |
| | bit 8 | External Fault 1 (input terminal S1) (EF1) |
| | bit 9 | External Fault 2 (input terminal S2) (EF2) |
| bit A to F | Reserved | |
| 00CCH | Alarm Contents 6 | |
| | bit 0 | Output Voltage Detection Fault (VoF) |
| | bit 1 | IGBT Maintenance Time (90%) (TrPC) |
| | bit 2 | Capacitor Maintenance Time (LT-3) |
| | bit 3 | IGBT Maintenance Time (50%) (LT-4) |
| | bit 4 | Braking Transistor Overload Fault (boL) |
| | bit 5 to 6 | Reserved |
| | bit 7 | Motor Overheat (NTC Input) (oH5) |
| | bit 8 to B | Reserved |
| | bit C | Thermistor Disconnect (THo) |
| | bit D | Underload Detection 6 (UL6) |
| | bit E | Waiting for Run (wRUn) |
| bit F | Reserved | |
| 00CDH | Reserved | |
| 00CEH | bit 0, 1 | Reserved |
| | bit 2 | Time Not Set (TIM) |
| | bit 3 | Battery Low (bAT) |
| | bit 4 | Time Deviation Error (TdE) |
| | bit 5 | Reserved |
| | bit 6 | Emergency Override FWD (EoF) |
| | bit 7 | Emergency Override REV (Eor) |
| 00CFH | Reserved | |
| 00D0H | CPF Contents 1 | |
| | bit 0, 1 | Reserved |
| | bit 2 | A/D Conversion Error (CPF02) |
| | bit 3 | PWM Data Fault (CPF03) |
| | bit 4, 5 | Reserved |
| | bit 6 | EEPROM Memory Data Error (CPF06) |
| | bit 7 | Terminal Board Connection Error (CPF07) |
| | bit 8 | EEPROM Serial Communications Fault (CPF08) |
| | bit 9, A | Reserved |
| | bit B | RAM Fault (CPF11) |
| | bit C | FLASH Memory Fault (CPF12) |
| | bit D | Watchdog Circuit Exception (CPF13) |
| | bit E | Control Circuit Fault (CPF14) |
| bit F | Reserved | |

| Register No. | Contents | |
|----------------|-------------------------------|--|
| 00D1H | CPF Contents 2 | |
| | bit 0 | Clock Fault (CPF16) |
| | bit 1 | Timing Fault (CPF17) |
| | bit 2 | Control Circuit Fault (CPF18) |
| | bit 3 | Control Circuit Fault (CPF19) |
| | bit 4 | Hardware fault at power up (CPF20) |
| | bit 5 | Hardware fault at communication start up (CPF21) |
| | bit 6 | A/D Conversion Fault (CPF22) |
| | bit 7 | PWM Feedback Fault (CPF23) |
| | bit 8 | Drive Unit Signal Fault (CPF24) |
| | bit 9 | Terminal board is not properly connected. (CPF25) |
| | bit A | ASIC BB Circuit Error (CPF26) |
| | bit B | ASIC PWM Setting Register Error (CPF27) |
| | bit C | ASIC PWM Pattern Error (CPF28) |
| | bit D | ASIC On-delay Error (CPF29) |
| | bit E | ASIC BBON Error (CPF30) |
| bit F | ASIC Code Error (CPF31) | |
| 00D2H | bit 0 | ASIC Start-up Error (CPF32) |
| | bit 1 | Watch-dog Error (CPF33) |
| | bit 2 | ASIC Power/Clock Error (CPF34) |
| | bit 3 | External A/D Converter Error (CPF35) |
| | bit 4 to 7 | Reserved |
| | bit 8 | Control Circuit Error (CPF40) |
| | bit 9 | Control Circuit Error (CPF41) |
| | bit A | Control Circuit Error (CPF42) |
| | bit B | Control Circuit Error (CPF43) |
| | bit C | Control Circuit Error (CPF44) |
| bit D | Control Circuit Error (CPF45) | |
| bit E, F | Reserved | |
| 00D3H to 00D7H | oFA0x Contents (CN5-A) | |
| 00D8H | oFA0x Contents (CN5-A) | |
| | bit 0 | Option Compatibility Error (oFA00) |
| | bit 1 | Option not properly connected (oFA01) |
| | bit 2 | Same type of option card already connected (oFA02) |
| | bit 3, 4 | Reserved |
| | bit 5 | A/D Conversion Error (oFA05) |
| | bit 6 | Option Response Error (oFA06) |
| | bit 7 to F | Reserved |
| 00D9H | oFA1x Contents (CN5-A) | |
| | bit 0 | Option RAM Fault (oFA10) |
| | bit 1 | Option Operation Mode Fault (SLMOD) (oFA11) |
| | bit 2 | Drive Receive CRC Error (oFA12) |
| | bit 3 | Drive Receive Frame Error (oFA13) |
| | bit 4 | Drive Receive Abort Error (oFA14) |
| | bit 5 | Option Receive CRC Error (oFA15) |
| | bit 6 | Option Receive Frame Error (oFA16) |
| | bit 7 | Option Receive Abort Error (oFA17) |
| bit 8 to F | Reserved | |
| 00DAH to 00DBH | Reserved | |

C.9 MEMOBUS/Modbus Data Table

| Register No. | Contents | |
|----------------|------------------------|--|
| 00DBH | oFA3x Contents (CN5-A) | |
| | bit 0 | Comm. ID Error (oFA30) |
| | bit 1 | Model Code Error (oFA31) |
| | bit 2 | Sumcheck Error (oFA32) |
| | bit 3 | Comm. option timeout waiting for response (oFA33) |
| | bit 4 | MEMOBUS Timeout (oFA34) |
| | bit 5 | Drive timeout waiting for response (oFA35) |
| | bit 6 | CI Check Error (oFA36) |
| | bit 7 | Drive timeout waiting for response (oFA37) |
| | bit 8 | Control Command Selection Error (oFA38) |
| | bit 9 | Drive timeout waiting for response (oFA39) |
| | bit A | Control Response Selection 1 Error (oFA40) |
| | bit B | Drive timeout waiting for response (oFA41) |
| | bit C | Control Response Selection 2 Error (oFA42) |
| | bit D | Control Response Selection Error (oFA43) |
| bit E, F | Reserved | |
| 00DCH | oFb0x Contents (CN5-B) | |
| | bit 0 | Option compatibility error (oFb00) |
| | bit 1 | Option not properly connected (oFb01) |
| | bit 2 | Same type of option card already connected (oFb02) |
| | bit 3, 4 | Reserved |
| | bit 5 | A/D Conversion Fault (oFb05) |
| | bit 6 | Option Response Error (oFb06) |
| | bit 7 to F | Reserved |
| 00DDH | oFb1x Contents (CN5-B) | |
| | bit 0 | Option RAM Fault (oFb10) |
| | bit 1 | Option Operation Mode Fault (SLMOD) (oFb11) |
| | bit 2 | Drive Receive CRC Error (oFb12) |
| | bit 3 | Drive Receive Frame Error (oFb13) |
| | bit 4 | Drive Receive Abort Error (oFb14) |
| | bit 5 | Option Receive CRC Error (oFb15) |
| | bit 6 | Option Receive Frame Error (oFb16) |
| | bit 7 | Option Receive Abort Error (oFb17) |
| bit 8 to F | Reserved | |
| 00DEH to 00DFH | Reserved | |

| Register No. | Contents | |
|--------------|------------------------|--|
| 00E0H | oFb3x Contents (CN5-B) | |
| | bit 0 | Comm. ID Error (oFb30) |
| | bit 1 | Model Code Error (oFb31) |
| | bit 2 | Sumcheck Error (oFb32) |
| | bit 3 | Comm. option timeout waiting for response (oFb33) |
| | bit 4 | MEMOBUS Timeout (oFb34) |
| | bit 5 | Drive timeout waiting for response (oFb35) |
| | bit 6 | CI Check Error (oFb36) |
| | bit 7 | Drive timeout waiting for response (oFb37) |
| | bit 8 | Control Command Selection Error (oFb38) |
| | bit 9 | Drive timeout waiting for response (oFb39) |
| | bit A | Control Response Selection 1 Error (oFb40) |
| | bit B | Drive timeout waiting for response (oFb41) |
| | bit C | Control Response Selection 2 Error (oFb42) |
| | bit D | Control Response Selection Error (oFb43) |
| bit E, F | Reserved | |
| 00E1H | oFC0x Contents (CN5-C) | |
| | bit 0 | Option compatibility error (oFC00) |
| | bit 1 | Option not properly connected (oFC01) |
| | bit 2 | Same type of option card already connected (oFC02) |
| | bit 3, 4 | Reserved |
| | bit 5 | A/D Conversion Fault (oFC05) |
| | bit 6 | Option Response Error (oFC06) |
| | bit 7 to F | Reserved |
| 00E2H | oFC1x Contents (CN5-C) | |
| | bit 0 | Option RAM Fault (oFC10) |
| | bit 1 | Option Operation Mode Fault (SLMOD) (oFC11) |
| | bit 2 | Drive Receive CRC Error (oFC12) |
| | bit 3 | Drive Receive Frame Error (oFC13) |
| | bit 4 | Drive Receive Abort Error (oFC14) |
| | bit 5 | Option Receive CRC Error (oFC15) |
| | bit 6 | Option Receive Frame Error (oFC16) |
| | bit 7 | Option Receive Abort Error (oFC17) |
| bit 8 to F | Reserved | |
| 00E3H, 00E4H | Reserved | |

C.9 MEMOBUS/Modbus Data Table

| Register No. | Contents | |
|----------------|------------------------|---|
| 00E5H | oFC3x Contents (CN5-C) | |
| | bit 0 | Comm. ID Error (oFC30) |
| | bit 1 | Model Code Error (oFC31) |
| | bit 2 | Sumcheck Error (oFC32) |
| | bit 3 | Comm. option timeout waiting for response (oFC33) |
| | bit 4 | MEMOBUS Timeout (oFC34) |
| | bit 5 | Drive timeout waiting for response (oFC35) |
| | bit 6 | CI Check Error (oFC36) |
| | bit 7 | Drive timeout waiting for response (oFC37) |
| | bit 8 | Control Command Selection Error (oFC38) |
| | bit 9 | Drive timeout waiting for response (oFC39) |
| | bit A | Control Response Selection 1 Error (oFC40) |
| | bit B | Drive timeout waiting for response (oFC41) |
| | bit C | Control Response Selection 2 Error (oFC42) |
| | bit D | Control Response Selection Error (oFC43) |
| bit E, F | Reserved | |
| 00E6H to 00FFH | Reserved | |

- <1> Parameter o1-03, Digital Operator Display Selection, determines the units.
- <2> The number of decimal places in the parameter value depends on the drive model. This value has two decimal places (0.01 A) if the drive is set for a maximum applicable motor capacity up to and including 11 kW, and one decimal place (0.1 A) if the maximum applicable motor capacity is higher than 11 kW. *Refer to Power Ratings on page 394.*
- <3> Communication error contents are saved until the fault is reset.
- <4> Set the number of motor poles to parameter E2-04.

◆ Broadcast Messages

Data can be written from the master to all slave devices at the same time.

The slave address in a broadcast command message must be set to 00H. All slaves will receive the message, but will not respond.

| Register No. | Contents | |
|--------------|-----------------------|--|
| 0001H | Digital Input Command | |
| | bit 0 | Forward Run (0: Stop 1: Run) |
| | bit 1 | Direction Command (0: Forward, 1: Reverse) |
| | bit 2, 3 | Reserved |
| | bit 4 | External Fault |
| | bit 5 | Fault Reset |
| | bit 6 to B | Reserved |
| | bit C | Multi-Function Digital Input S5 |
| | bit D | Multi-Function Digital Input S6 |
| | bit E | Multi-Function Digital Input S7 |
| | bit F | Multi-Function Digital Input S8 |
| 0002H | Frequency Reference | 30000/100% |

◆ Fault Trace Contents

The table below shows the fault codes that can be read out by MEMOBUS/Modbus commands from the U2-□□ monitor parameters.

Table C.5 Fault Trace / History Register Contents

| Fault Code | Fault Name | Fault Code | Fault Name |
|------------|---|------------|---|
| 0002H | Undervoltage (Uv1) | 004EH | Braking Resistor Transistor Fault (rF) |
| 0003H | Control Power Supply Undervoltage (Uv2) | 004FH | Braking Transistor Overload Fault (boL) |
| 0004H | Soft Charge Circuit Fault (Uv3) | 0050H | Motor Overheat (NTC Input) (oH5) |
| 0005H | IGBT Short Circuit (SC) | 0052H | Node Setup Fault (nSE) |
| 0006H | Ground Fault (GF) | 0053H | Thermistor Disconnect (THo) |
| 0007H | Overcurrent (oC) | 005AH | Underload Detection 6 (UL6) |
| 0008H | Overvoltage (ov) | 005DH | HOA Time Not Set (TIM) |
| 0009H | Heatsink Overheat (oH) | 005EH | HOA Battery Low (bAT) |
| 000AH | Heatsink Overheat (oH1) | 005FH | HOA Time Deviation Error (TdE) |
| 000BH | Motor Overload (oL1) | 0060H | HOA Time Interval Error (TIE) |
| 000CH | Drive Overload (oL2) | 0083H | A/D Conversion Error (CPF02) |
| 000DH | Overtorque Detection 1 (oL3) | 0084H | PWM Data Fault (CPF03) |
| 000EH | Overtorque Detection 2 (oL4) | 0087H | EEPROM Memory Data Error (CPF06) |
| 000FH | Dynamic Braking Transistor (rr) | 0088H | Terminal Board Connection Error (CPF07) |
| 0010H | Braking Resistor Overheat (rH) | 0089H | EEPROM Serial Communication Fault (CPF08) |
| 0011H | External Fault at Input Terminal S3 (EF3) | 008CH | RAM Fault (CPF11) |
| 0012H | External Fault at Input Terminal S4 (EF4) | 008DH | Flash Memory Circuit Exception (CPF12) |
| 0013H | External Fault at Input Terminal S5 (EF5) | 008EH | Watchdog Circuit Exception (CPF13) |
| 0014H | External Fault at Input Terminal S6 (EF6) | 008FH | Control Circuit Fault (CPF14) |
| 0015H | External Fault at Input Terminal S7 (EF7) | 0091H | Clock Fault (CPF16) |
| 0016H | External Fault at Input Terminal S8 (EF8) | 0092H | Timing Fault (CPF17) |
| 001BH | Input Phase Loss (PF) | 0093H | Control Circuit Fault (CPF18) |
| 001CH | Output Phase Loss (LF) | 0094H | Control Circuit Fault (CPF19) |
| 001DH | Motor Overheat (PTC input) (oH3) | 0095H | Hardware Fault at Power Up (CPF20) |
| 001EH | Digital Operator Connection (oPr) | 0096H | Hardware Fault at Communication Start Up (CPF21) |
| 001FH | EEPROM Write Error (Err) | 0097H | A/D Conversion Fault (CPF22) |
| 0020H | Motor Overheat (PTC input) (oH4) | 0098H | PWM Feedback Fault (CPF23) |
| 0021H | MEMOBUS/Modbus Communication Error (CE) | 0099H | Drive Unit Signal Fault (CPF24) |
| 0022H | Option Communication Error (bUS) | 009AH | Terminal Board is Not Properly Connected. (CPF25) |
| 0027H | Option External Fault (EF0) | 009BH | ASIC BB Circuit Error (CPF26) |
| 0028H | PID Feedback Loss (FbL) | 009CH | ASIC PWM Setting Register Error (CPF27) |
| 0029H | Undertorque Detection 1 (UL3) | 009DH | ASIC PWM Pattern Error (CPF28) |
| 002AH | Undertorque Detection 2 (UL4) | 009EH | ASIC On-delay Error (CPF29) |
| 002BH | High Slip Braking Overload (oL7) | 009FH | ASIC BBON Error (CPF30) |
| 0030H | Hardware Fault (including oFx) | 00A0H | ASIC Code Error (CPF31) |
| 0036H | Output Current Imbalance (LF2) | 00A1H | ASIC Start-up Error (CPF32) |
| 0037H | Pullout Detection (Sto) | 00A2H | Watch-dog Error (CPF33) |
| 003BH | Too Many Speed Search Restarts (SEr) | 00A3H | ASIC Power/Clock Error (CPF34) |
| 0041H | PID Feedback Loss (FbH) | 00A4H | External A/D Converter Error (CPF35) |
| 0042H | External Fault 1, Input Terminal S1 (EF1) | 00A9H | Control Circuit Error (CPF40) |
| 0043H | External Fault 2, Input Terminal S2 (EF2) | 00AAH | Control Circuit Error (CPF41) |
| 0046H | Current Offset Fault (CoF) | 00ABH | Control Circuit Error (CPF42) |
| 0047H | PLC Detection Error 1 (PE1) | 00ACH | Control Circuit Error (CPF43) |
| 0048H | PLC Detection Error 2 (PE2) | 00ADH | Control Circuit Error (CPF44) |
| 004DH | Output Voltage Detection Fault (voF) | 00AEH | Control Circuit Error (CPF45) |

C.9 MEMOBUS/Modbus Data Table

| Fault Code | Fault Name |
|------------|--|
| 0101H | Option Compatibility Error (oFA00) |
| 0102H | Option Not Properly Connected (oFA01) |
| 0103H | Same Type of Option Card Already Connected (oFA02) |
| 0106H | A/D Conversion Error (oFA05) |
| 0107H | Option Response Error (oFA06) |
| 0111H | Option RAM Fault (oFA10) |
| 0112H | Option Operation Mode Fault (SLMOD) (oFA11) |
| 0113H | Drive Receive CRC Error (oFA12) |
| 0114H | Drive Receive Frame Error (oFA13) |
| 0115H | Drive Receive Abort Error (oFA14) |
| 0116H | Option Receive CRC Error (oFA15) |
| 0117H | Option Receive Frame Error (oFA16) |
| 0118H | Option Receive Abort Error (oFA17) |
| 0131H | Comm. ID Error (oFA30) |
| 0132H | Model Code Error (oFA31) |
| 0133H | Sumcheck Error (oFA32) |
| 0134H | Comm. Option Timeout Waiting for Response (oFA33) |
| 0135H | MEMOBUS Timeout (oFA34) |
| 0136H | Drive Timeout Waiting for Response (oFA35) |
| 0137H | CI Check Error (oFA36) |
| 0138H | Drive Timeout Waiting for Response (oFA37) |
| 0139H | Control Command Selection Error (oFA38) |
| 013AH | Drive Timeout Waiting for Response (oFA39) |
| 013BH | Control Response Selection 1 Error (oFA40) |
| 013CH | Drive Timeout Waiting for Response (oFA41) |
| 013DH | Control Response Selection 2 Error (oFA42) |
| 013EH | Control Response Selection Error (oFA43) |
| 0200H | Option Compatibility Error (oFb00) |
| 0202H | Option Connection Error (oFb01) |
| 0203H | Same Type of Option Card Already Connected (oFb02) |
| 0206H | A/D Conversion Error (oFb05) |
| 0207H | Option Response Error (oFb06) |
| 0211H | Option RAM Fault (oFb10) |
| 0212H | Option Operation Mode Fault (SLMOD) (oFb11) |
| 0213H | Drive Receive CRC Error (oFb12) |
| 0214H | Drive Receive Frame Error (oFb13) |
| 0215H | Drive Receive Abort Error (oFb14) |
| 0216H | Option Receive CRC Error (oFb15) |
| 0217H | Option Receive Frame Error (oFb16) |
| 0218H | Option Receive Abort Error (oFb17) |
| 0231H | Comm. ID Error (oFb30) |

| Fault Code | Fault Name |
|------------|--|
| 0232H | Model Code Error (oFb31) |
| 0233H | Sumcheck Error (oFb32) |
| 0234H | Comm. option Timeout Waiting for Response (oFb33) |
| 0235H | MEMOBUS Timeout (oFb34) |
| 0236H | Drive Timeout Waiting for Response (oFb35) |
| 0237H | CI Check Error (oFb36) |
| 0238H | Drive Timeout Waiting for Response (oFb37) |
| 0239H | Control Command Selection Error (oFb38) |
| 023AH | Drive Timeout Waiting for Response (oFb39) |
| 023BH | Control Response Selection 1 Error (oFb40) |
| 023CH | Drive Timeout Waiting for Response (oFb41) |
| 023DH | Control Response Selection 2 Error (oFb42) |
| 023EH | Control Response Selection Error (oFb43) |
| 0301H | Option Compatibility Error (oFc00) |
| 0302H | Option Not Properly Connected (oFc01) |
| 0303H | Same Type of Option Card Already Connected (oFc02) |
| 0306H | A/D Conversion Error (oFc05) |
| 0307H | Option Response Error (oFc06) |
| 0311H | Option RAM Fault (oFc10) |
| 0312H | Option Operation Mode Fault (SLMOD) (oFc11) |
| 0313H | Drive Receive CRC Error (oFc12) |
| 0314H | Drive Receive Frame Error (oFc13) |
| 0315H | Drive Receive Abort Error (oFc14) |
| 0316H | Option Receive CRC Error (oFc15) |
| 0317H | Option Receive Frame Error (oFc16) |
| 0318H | Option Receive Abort Error (oFc17) |
| 0331H | Comm. ID Error (oFc30) |
| 0332H | Model Code Error (oFc31) |
| 0333H | Sumcheck Error (oFc32) |
| 0334H | Comm. Option Timeout Waiting for Response (oFc33) |
| 0335H | MEMOBUS Timeout (oFc34) |
| 0336H | Drive Timeout Waiting for Response (oFc35) |
| 0337H | CI Check Error (oFc36) |
| 0338H | Drive Timeout Waiting for Response (oFc37) |
| 0339H | Control Command Selection Error (oFc38) |
| 033AH | Drive Timeout Waiting for Response (oFc39) |
| 033BH | Control Response Selection 1 Error (oFc40) |
| 033CH | Drive Timeout Waiting for Response (oFc41) |
| 033DH | Control Response Selection 2 Error (oFc42) |
| 033EH | Control Response Selection Error (oFc43) |

◆ Alarm Register Contents

The table below shows the alarm codes that can be read out from MEMOBUS/Modbus register 007FH.

Table C.6 Alarm Register 007FH Contents

| Fault Code | Fault Name | Fault Code | Fault Name |
|------------|--|------------|--|
| 0001H | Undervoltage (Uv) | 0027H | PID Feedback Loss (FbL) |
| 0002H | Overvoltage (ov) | 0028H | PID Feedback Loss (FbH) |
| 0003H | Heatsink Overheat (oH) | 002AH | Drive Disabled (dnE) |
| 0004H | Drive Overheat (oH2) | 0031H | SI-T3 Watchdog Error (E5) |
| 0005H | Overtorque 1 (oL3) | 0032H | SI-T3 Station Address Setting Error (AEr) |
| 0006H | Overtorque 2 (oL4) | 0033H | SI-T3 Comm. Cycle Setting Error (CyC) |
| 0007H | Run commands input error (EF) | 0034H | High Current Alarm (HCA) |
| 0008H | Drive Baseblock (bb) | 0035H | Cooling Fan Maintenance Time (LT-1) |
| 0009H | External Fault 3, input terminal S3 (EF3) | 0036H | Capacitor Maintenance Time (LT-2) |
| 000AH | External Fault 4, input terminal S4 (EF4) | 0038H | SI-S EEPROM Error (EEP) |
| 000BH | External Fault 5, input terminal S5 (EF5) | 0039H | External Fault (input terminal S1) (EF1) |
| 000CH | External Fault 6, input terminal S6 (EF6) | 003AH | External Fault (input terminal S2) (EF2) |
| 000DH | External Fault 7, input terminal S7 (EF7) | 003FH | PLC Alarm (PA1) |
| 000EH | External Fault 8, input terminal S8 (EF8) | 0040H | PLC Alarm (PA2) |
| 000FH | Cooling Fan Error (FAn) | 0041H | Output Voltage Detection Fault (voF) |
| 0014H | MEMOBUS/Modbus Communication Error (CE) | 0042H | IGBT Maintenance Time (90%) (TrPC) |
| 0015H | Option Communication Error (bUS) | 0043H | Soft Charge Bypass Relay Maintenance Time (LT-3) |
| 0016H | Serial Communication Transmission Error (CALL) | 0044H | IGBT Maintenance Time (50%) (LT-4) |
| 0017H | Motor Overload (oL1) | 0045H | Braking Transistor Overload (boL) |
| 0018H | Drive Overload (oL2) | 0048H | Motor Overheat (NTC Input) (oH5) |
| 001AH | Option Card External Fault (EF0) | 004EH | Underload Detection 6 (UL6) |
| 001BH | Motor Switch command input during run (rUn) | 004FH | Waiting for Run (wRUn) |
| 001DH | Serial Communication Transmission Error (CALL) | 0063H | HOA Time Not Set (TIM) |
| 001EH | Undertorque Detection 1 (UL3) | 0064H | HOA Battery Low (bAT) |
| 001FH | Undertorque Detection 2 (UL4) | 0065H | HOA Time Deviation Error (TdE) |
| 0020H | MEMOBUS/Modbus Test Mode Fault (SE) | 0067H | Emergency Override FWD (EoF) |
| 0022H | Motor Overheat (oH3) | 0068H | Emergency Override REV (Eor) |

C.10 Enter Command

When writing parameters to the drive from the PLC using MEMOBUS/Modbus communication, parameter H5-11 determines whether an Enter command must be issued to enable these parameters. This section describes the types and functions of the Enter commands.

◆ Enter Command Types

The drive supports two types of Enter commands as shown in *Table C.7*. An Enter command is enabled by writing 0 to register numbers 0900H or 0910H. It is only possible to write to these registers; attempting to read from these registers will cause an error.

Table C.7 Enter Command Types

| Register No. | Description |
|--------------|--|
| 0900H | Simultaneously writes data into the EEPROM (non-volatile memory) of the drive and enables the data in RAM. Parameter changes remain after cycling power. |
| 0910H | Writes data in the RAM only. Parameter changes are lost when the drive is shut off. |

Note: The EEPROM can only be written to 100,000 times, so it is recommended to limit the number of times writing to the EEPROM. The Enter command registers are write-only and if these registers are read, the register address will be invalid (Error code: 02H). An Enter command is not required when reference or broadcast data are sent to the drive.

◆ Enter Command Settings when Upgrading the Drive

When replacing previous Yaskawa drive models with the P1000 and keeping the MEMOBUS/Modbus communications settings, set parameter H5-11 in accordance with the Enter command configuration in the older drive. H5-11 determines whether an Enter command is necessary to activate parameter changes in the drive.

- If upgrading from a G7, F7, or P7 series drive to a P1000, set parameter H5-11 to 0.
- If upgrading from a V7 series drive to a P1000, set parameter H5-11 to 1.

■ H5-11 and the Enter Command

An enter command is not required when writing registers 0000H to 001FH. Changes to those registers take effect immediately, independent of the setting in parameter H5-11.

| H5-11 Settings | H5-11 = 0 | H5-11 = 1 |
|---|--|--|
| Drive being replaced | G7, F7, P7 | V7 |
| How parameter settings are enabled | When the Enter command is received from the master. | As soon as the value is changed. |
| Upper/lower limit check | Upper/lower limit check is performed, taking the settings of related parameters into account. | Checks only the upper/lower limits of the parameters that were changed. |
| Default value of related parameters | Not affected. The settings of related parameters remain unchanged. They must be changed manually if needed. | Default settings of related parameters are changed automatically. |
| Error handling when setting multiple parameters | Data is accepted even if one setting is invalid. The invalid setting will be discarded. No error message occurs. | Error occurs if only one setting is invalid. All data that was sent are discarded. |

C.11 Communication Errors

◆ MEMOBUS/Modbus Error Codes

A list of MEMOBUS/Modbus errors appears below.

When an error occurs, remove whatever caused the error and restart communications.

| Error Code | Error Name |
|------------|--|
| | Cause |
| 01H | Function Code Error |
| | Attempted to set a function code from a PLC other than 03H, 08H, and 10H. |
| 02H | Register Number Error |
| | <ul style="list-style-type: none"> A register number specified in the command message does not exist. Attempted to send a broadcast message using other register numbers than 0001H or 0002H. |
| 03H | Bit Count Error |
| | <ul style="list-style-type: none"> Read data or write data is greater than 16 bits. Invalid command message quantity. In a write message, the “Number of Data Items” contained within the message does not equal twice the amount of data words (i.e., the total of Data 1+ Data 2, etc.). |
| 21H | Data Setting Error |
| | <ul style="list-style-type: none"> Control data or parameter write data is outside the allowable setting range. Attempted to write a contradictory parameter setting. |
| 22H | Write Mode Error |
| | <ul style="list-style-type: none"> During run, the user attempted to write a parameter that cannot be written to during run. During an EEPROM memory data error (CPF06), the master attempted to write to a parameter other than A1-00 to A1-05, E1-03, or o2-04. Attempted to write to read-only data. |
| 23H | DC Bus Undervoltage Write Error |
| | During an undervoltage situation, the master attempted to write to parameters that cannot be written to during undervoltage. |
| 24H | Write Error During Parameter Process |
| | Master attempted writing to the drive while the drive was processing parameter data. |
| 25H | Writing into EEPROM Disabled |
| | An attempt was made to write data into EEPROM by MEMOBUS/Modbus communications when writing EEPROM is not possible. (When this error code occurs, an error message is displayed and the drive continues operation.) |

◆ Slave Not Responding

In the following situations, the slave drive will ignore the command message sent from the master, and not send a response message:

- When a communications error (overrun, framing, parity, or CRC-16) is detected in the command message.
- When the slave address in the command message and the slave address in the drive do not match (remember to set the slave address for the drive using H5-01).
- When the gap between two blocks (8-bit) of a message exceeds 24 bits.
- When the command message data length is invalid.

Note: If the slave address specified in the command message is 00H, all slaves execute the write function, but do not return response messages to the master.

C.12 Self-Diagnostics

The drive has a built-in self-diagnosing function of the serial communication interface circuits. To perform the self-diagnosis function, use the following procedure.

DANGER! Electrical Shock Hazard. Do not connect or disconnect wiring while the power is on. Failure to comply will result in death or serious injury. Before servicing, disconnect all power to the equipment. The internal capacitor remains charged even after the power supply is turned off. The charge indicator LED will extinguish when the DC bus voltage is below 50 Vdc. To prevent electric shock, wait at least one minute after all indicators are OFF and measure the DC bus voltage level to confirm safe level.

1. Turn on the power to the drive.
2. Note the present terminal S6 function selection setting (H1-06) and set it for the communications test mode (H1-06 = 67).
3. Turn off the power to the drive.
4. With the power off, wire the drive as shown in **Figure C.7**, connecting terminals R+ and S+, R- and S-, and S6 and SC.

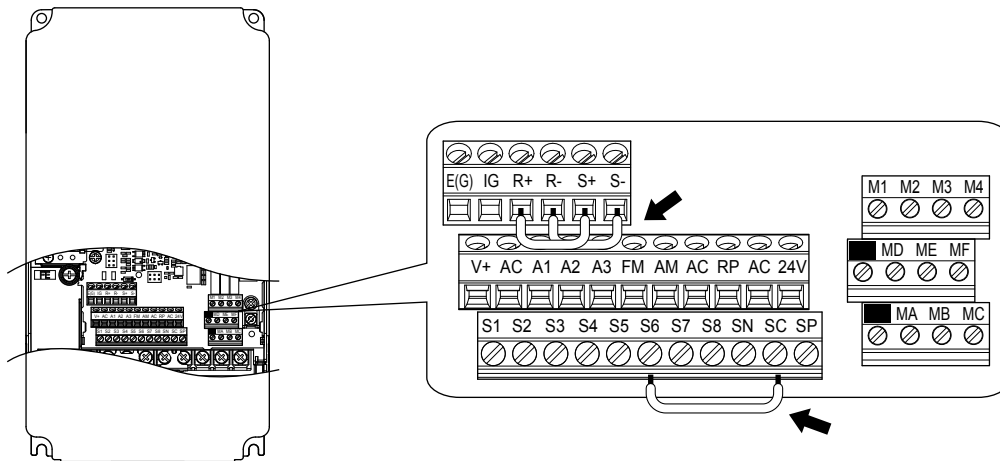


Figure C.7 Terminal Connections for Communication Self-Diagnostics

5. Set jumper S3 to source mode (internal power supply).
6. Turn the power to the drive back on.
7. During normal operation, the drive will display “Pass” to indicate that the communications test mode is operating normally.
When a fault occurs, the drive will display “CE” on the keypad display.
8. Turn off the power supply.
9. Remove the wire jumpers from terminal R+, R-, S+, S-, and S6-SC. Reset jumper S3 to its original position and set terminal S6 to its original function.
10. Return to normal operation.

Appendix: D

Standards Compliance

This appendix explains the guidelines and criteria for maintaining CE and UL standards.

| | | |
|------------|----------------------------------|------------|
| D.1 | SECTION SAFETY..... | 540 |
| D.2 | EUROPEAN STANDARDS..... | 542 |
| D.3 | UL AND CSA STANDARDS..... | 550 |

D.1 Section Safety

DANGER

Electrical Shock Hazard

Before servicing, disconnect all power to the equipment. The internal capacitor remains charged even after the power supply is turned off. The charge indicator LED will extinguish when the DC bus voltage is below 50 Vdc. To prevent electric shock, wait for at least the time specified on the warning label, once all indicators are OFF, measure for unsafe voltages to confirm the drive is safe prior to servicing.

Failure to comply will result in death or serious injury.

WARNING

Electrical Shock Hazard

Do not operate equipment with covers removed.

Failure to comply could result in death or serious injury.

The diagrams in this section may show drives without covers or safety shields to show details. Be sure to reinstall covers or shields before operating the drives and run the drives according to the instructions described in this manual.

Always ground the motor-side grounding terminal.

Improper equipment grounding could result in death or serious injury by contacting the motor case.

Do not touch any terminals before the capacitors have fully discharged.

Failure to comply could result in death or serious injury.

Before wiring terminals, disconnect all power to the equipment. The internal capacitor remains charged even after the power supply is turned off. After shutting off the power, wait for at least the amount of time specified on the drive before touching any components.

Do not allow unqualified personnel to perform work on the drive.

Failure to comply could result in death or serious injury.

Installation, maintenance, inspection, and servicing must be performed only by authorized personnel familiar with installation, adjustment and maintenance of AC drives.

Do not perform work on the drive while wearing loose clothing, jewelry or without eye protection.

Failure to comply could result in death or serious injury.

Remove all metal objects such as watches and rings, secure loose clothing, and wear eye protection before beginning work on the drive.

Do not remove covers or touch circuit boards while the power is on.

Failure to comply could result in death or serious injury.

Fire Hazard

Tighten all terminal screws to the specified tightening torque.

Loose electrical connections could result in death or serious injury by fire due to overheating of electrical connections.

Do not use an improper voltage source.

Failure to comply could result in death or serious injury by fire.

Verify that the rated voltage of the drive matches the voltage of the incoming power supply before applying power.

Do not use improper combustible materials.

Failure to comply could result in death or serious injury by fire.

Attach the drive to metal or other noncombustible material.

NOTICE

Observe proper electrostatic discharge procedures (ESD) when handling the drive and circuit boards.

Failure to comply may result in ESD damage to the drive circuitry.

Never connect or disconnect the motor from the drive while the drive is outputting voltage.

Improper equipment sequencing could result in damage to the drive.

Do not use unshielded wire for control wiring.

Failure to comply may cause electrical interference resulting in poor system performance. Use shielded twisted-pair wires and ground the shield to the ground terminal of the drive.

Do not modify the drive circuitry.

Failure to comply could result in damage to the drive and will void warranty.

Yaskawa is not responsible for modification of the product made by the user. This product must not be modified.

Check all the wiring to ensure that all connections are correct after installing the drive and connecting other devices.

Failure to comply could result in damage to the drive.

If a fuse is blown or a Ground Fault Circuit Interrupter (GFCI) is tripped, check the wiring and the selection of the peripheral devices.

Contact your supplier if the cause cannot be identified after checking the above.

Do not restart the drive immediately operate the peripheral devices if a fuse is blown or a GFCI is tripped.

Check the wiring and the selection of peripheral devices to identify the cause. Contact your supplier before restarting the drive or the peripheral devices if the cause cannot be identified.

D.2 European Standards



Figure D.1 CE Mark

The CE mark indicates compliance with European safety and environmental regulations. It is required for engaging in business and commerce in Europe.

European standards include the Machinery Directive for machine manufacturers, the Low Voltage Directive for electronics manufacturers, and the EMC guidelines for controlling noise.

This drive displays the CE mark based on the EMC guidelines and the Low Voltage Directive.

- **Low Voltage Directive:** 2014/35/EU
- **EMC Guidelines:** 2014/30/EU

Devices used in combination with this drive must also be CE certified and display the CE mark. When using drives displaying the CE mark in combination with other devices, it is ultimately the responsibility of the user to ensure compliance with CE standards. After setting up the device, verify that conditions meet European standards.

Note: 600 V class drives (models 5□□□□□□) are not compliant with European Standards.

◆ CE Low Voltage Directive Compliance

This drive has been tested according to European standard IEC/EN 61800-5-1:2007, and it fully complies with the Low Voltage Directive.

To comply with the Low Voltage Directive, be sure to meet the following conditions when combining this drive with other devices:

■ Area of Use

Do not use drives in areas with pollution higher than degree 2 and overvoltage category 3 in accordance with IEC/EN 60664.

■ Factory Recommended Branch Circuit Protection

Yaskawa recommends installing one of the following types of branch circuit protection to maintain compliance with UL508C. Semiconductor protective type fuses are preferred. Alternate branch circuit protection devices are also listed in [Table D.1](#).

NOTICE: If a fuse is blown or a Ground Fault Circuit Interrupter (GFCI) is tripped, check the wiring and the selection of peripheral devices to identify the cause. Contact Yaskawa before restarting the drive or the peripheral devices if the cause cannot be identified.

Table D.1 Factory Recommended Drive Branch Circuit Protection

| Drive Model | Fuse Type | |
|--------------------------------|------------------------|------------------------|
| | Manufacturer: Bussmann | |
| | Model | Fuse Ampere Rating (A) |
| Three-Phase 200 V Class | | |
| 2A0004 | FWH-70B | 70 |
| 2A0006 | FWH-70B | 70 |
| 2A0008 | FWH-70B | 70 |
| 2A0010 | FWH-70B | 70 |
| 2A0012 | FWH-70B | 70 |
| 2A0018 | FWH-90B | 90 |
| 2A0021 | FWH-90B | 90 |
| 2A0030 | FWH-100B | 100 |
| 2A0040 | FWH-200B | 200 |
| 2A0056 | FWH-200B | 200 |
| 2A0069 | FWH-200B | 200 |
| 2A0081 | FWH-300A | 300 |
| 2A0110 | FWH-300A | 300 |

| Drive Model | Fuse Type | |
|--------------------------------|------------------------|------------------------|
| | Manufacturer: Bussmann | |
| | Model | Fuse Ampere Rating (A) |
| 2A0138 | FWH-350A | 350 |
| 2A0169 | FWH-400A | 400 |
| 2A0211 | FWH-400A | 400 |
| 2A0250 | FWH-600A | 600 |
| 2A0312 | FWH-700A | 700 |
| 2A0360 | FWH-800A | 800 |
| 2A0415 | FWH-1000A | 1000 |
| Three-Phase 400 V Class | | |
| 4A0002 | FWH-40B | 40 |
| 4A0004 | FWH-50B | 50 |
| 4A0005 | FWH-70B | 70 |
| 4A0007 | FWH-70B | 70 |
| 4A0009 | FWH-90B | 90 |
| 4A0011 | FWH-90B | 90 |
| 4A0018 | FWH-80B | 80 |
| 4A0023 | FWH-100B | 100 |
| 4A0031 | FWH-125B | 125 |
| 4A0038 | FWH-200B | 200 |
| 4A0044 | FWH-250A | 250 |
| 4A0058 | FWH-250A | 250 |
| 4A0072 | FWH-250A | 250 |
| 4A0088 | FWH-250A | 250 |
| 4A0103 | FWH-250A | 250 |
| 4A0139 | FWH-350A | 350 |
| 4A0165 | FWH-400A | 400 |
| 4A0208 | FWH-500A | 500 |
| 4A0250 | FWH-600A | 600 |
| 4A0296 | FWH-700A | 700 |
| 4A0362 | FWH-800A | 800 |
| 4A0414 | FWH-800A | 800 |
| 4A0515 | FWH-1000A | 1000 |
| 4A0675 | FWH-1200A | 1200 |
| 4A0930 | FWH-1200A | 1200 |
| 4A1200 | FWH-1600A | 1600 |
| Three-Phase 600 V Class | | |
| 5A0003 </> | FWP-50B | 50 |
| 5A0004 </> | FWP-50B | 50 |
| 5A0006 </> | FWP-60B | 60 |
| 5A0009 </> | FWP-60B | 60 |
| 5A0011 </> | FWP-70B | 70 |
| 5A0017 </> | FWP-100B | 100 |
| 5A0022 </> | FWP-100B | 100 |
| 5A0027 </> | FWP-125A | 125 |
| 5A0032 </> | FWP-125A | 125 |
| 5A0041 </> | FWP-175A | 175 |
| 5A0052 </> | FWP-175A | 175 |

D.2 European Standards

| Drive Model | Fuse Type | |
|-------------|------------------------|------------------------|
| | Manufacturer: Bussmann | |
| | Model | Fuse Ampere Rating (A) |
| 5A0062 <1> | FWP-250A | 250 |
| 5A0077 <1> | FWP-250A | 250 |
| 5A0099 <1> | FWP-250A | 250 |
| 5A0125 <1> | FWP-350A | 350 |
| 5A0145 <1> | FWP-350A | 350 |
| 5A0192 <1> | FWP-600A | 600 |
| 5A0242 <1> | FWP-600A | 600 |

<1> 600 V class drives are not compliant with European Standards.

■ Guarding Against Harmful Materials

When installing IP00/Open Type enclosure drives, use an enclosure that prevents foreign material from entering the drive from above or below.

■ Grounding

The drive is designed to be used in T-N (grounded neutral point) networks. If installing the drive in other types of grounded systems, contact your Yaskawa representative for instructions.

◆ EMC Guidelines Compliance

This drive is tested according to European standards IEC/EN 61800-3: 2004.

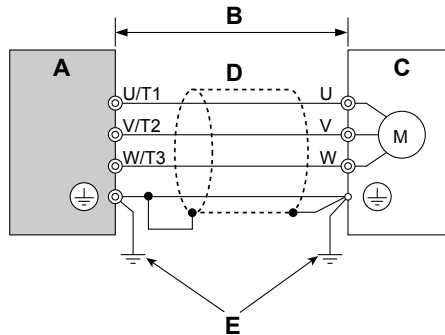
■ EMC Filter Installation

The following conditions must be met to ensure continued compliance with guidelines. [Refer to EMC Filters on page 547](#) for EMC filter selection.

Installation Method

Verify the following installation conditions to ensure that other devices and machinery used in combination with this drive also comply with EMC guidelines.

1. Install an EMC noise filter to the input side specified by Yaskawa for compliance with European standards.
2. Place the drive and EMC noise filter in the same enclosure.
3. Use braided shield cable for the drive and motor wiring, or run the wiring through a metal conduit.
4. Keep wiring as short as possible. Ground the shield on both the drive side and the motor side.



A – Drive

B – 10 m max cable length between drive and motor

C – Motor

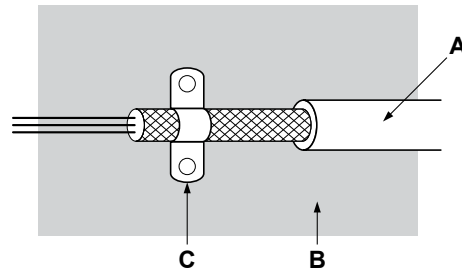
D – Metal conduit

E – Ground wire should be as short as possible.

Figure D.2 Installation Method

5. Make sure the protective earthing conductor complies with technical standards and local safety regulations.

WARNING! *Electrical Shock Hazard. Because the leakage current exceeds 3.5 mA in models 4A0414 to 4A1200, IEC/EN 61800-5-1 states that either the power supply must be automatically disconnected in case of discontinuity of the protective earthing conductor, or a protective earthing conductor with a cross-section of at least 10 mm² (Cu) or 16 mm² (Al) must be used. Failure to comply may result in death or serious injury.*



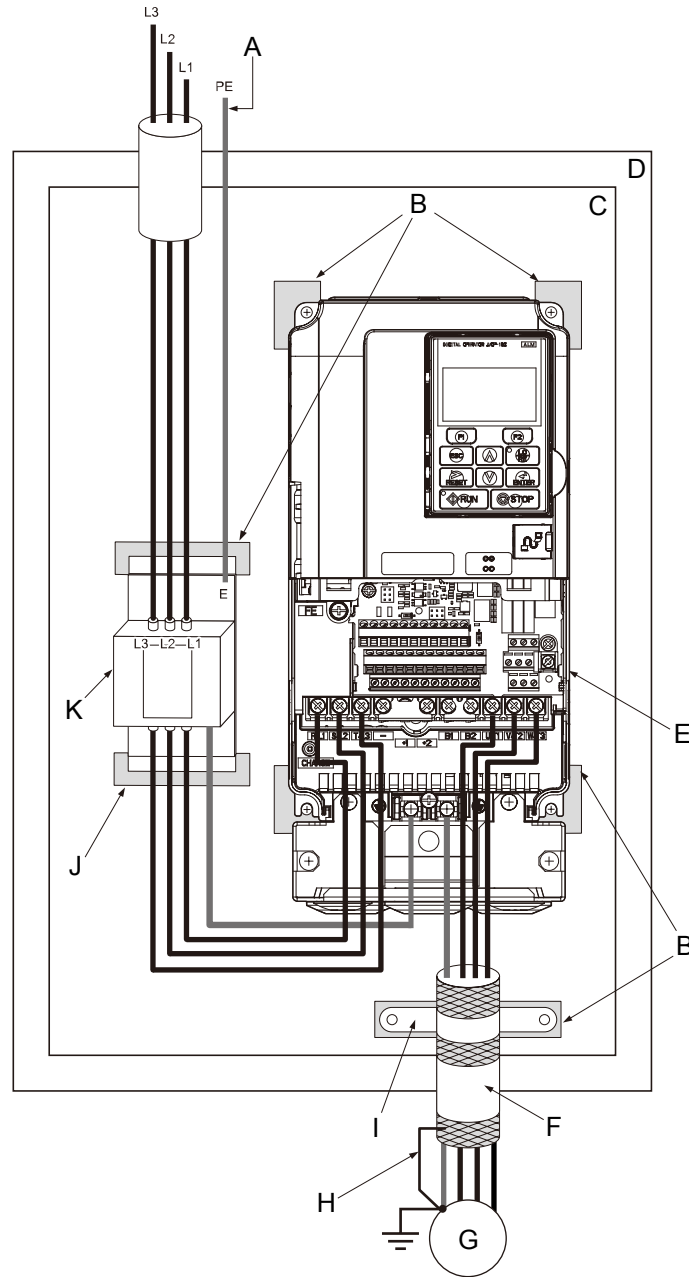
A – Braided shield cable
B – Metal panel

C – Cable clamp (conductive)

Figure D.3 Ground Area

6. Connect a DC link choke to minimize harmonic distortion.

Three-Phase 200 V / 400 V Class



- | | |
|--|--|
| A – Make sure the ground wire is grounded | G – Motor |
| B – Grounding surface (remove any paint or sealant) | H – Cable shield ground |
| C – Metal plate | I – Cable clamp |
| D – Enclosure panel | J – Ground plate (scrape off any visible paint) |
| E – Drive | K – EMC noise filter |
| F – Motor cable (braided shield cable, max. 10 m) | |

Figure D.4 EMC Filter and Drive Installation for CE Compliance (Three-Phase 200 V / 400 V Class)

■ EMC Filters

Install the drive with the EMC filters listed in [Table D.2](#) to comply with the EN61800-3 requirements.

Table D.2 EN61800-3 Filters

| Drive Model | Filter Data (Manufacturer: Schaffner) | | | | | Figure |
|--------------------------------|---------------------------------------|-------------------|-------------|-----------------------------|------------|--------|
| | Type | Rated Current (A) | Weight (lb) | Dimensions [W x D x H] (in) | Y x X (in) | |
| Three-Phase 200 V Class | | | | | | |
| 2A0004 | FS5972-10-07 | 10 | 2.6 | 5.6 × 1.8 × 13.0 | 4.5 × 12.3 | 1 |
| 2A0006 | | | | | | |
| 2A0008 | | | | | | |
| 2A0010 | FS5972-18-07 | 18 | 2.9 | 5.6 × 1.8 × 13.0 | 4.5 × 12.3 | |
| 2A0012 | | | | | | |
| 2A0018 | | | | | | |
| 2A0021 | FS5972-35-07 | 35 | 4.6 | 8.1 × 2.0 × 14.0 | 6.9 × 13.2 | |
| 2A0030 | | | | | | |
| 2A0040 | | | | | | |
| 2A0056 | FS5972-60-07 | 60 | 8.8 | 9.3 × 2.6 × 16.1 | 8.1 × 15.4 | |
| 2A0069 | FS5972-100-35 | 100 | 7.5 | 3.5 × 5.9 × 13.0 | 2.6 × 10.0 | 2 |
| 2A0081 | | | | | | |
| 2A0110 | | | | | | |
| 2A0138 | FS5972-170-40 | 170 | 13.2 | 4.7 × 6.7 × 17.8 | 4.0 × 14.4 | |
| 2A0169 | | | | | | |
| 2A0211 | | | | | | |
| 2A0250 | FS5972-250-37 | 250 | 25.8 | 5.1 × 9.5 × 24.0 | 3.5 × 19.6 | |
| 2A0312 | | | | | | |
| 2A0360 | | | | | | |
| 2A0415 | FS5972-410-99 | 410 | 23.1 | 10.2 × 4.5 × 15.2 | 9.3 × 4.7 | 3 |
| | FS5972-600-99 | 600 | 24.3 | 10.2 × 5.3 × 15.2 | 9.3 × 4.7 | |
| | | | | | | |
| Three-Phase 400 V Class | | | | | | |
| 4A0002 | FS5972-10-07 | 10 | 2.7 | 5.6 × 1.8 × 13.0 | 4.5 × 12.3 | 1 |
| 4A0004 | | | | | | |
| 4A0005 | | | | | | |
| 4A0007 | | | | | | |
| 4A0009 | FS5972-18-07 | 18 | 2.9 | 5.6 × 1.8 × 13.0 | 4.5 × 12.3 | |
| 4A0011 | | | | | | |
| 4A0018 | | | | | | |
| 4A0023 | FS5972-35-07 | 35 | 4.6 | 8.1 × 2.0 × 14.0 | 6.9 × 13.2 | |
| 4A0031 | | | | | | |
| 4A0038 | | | | | | |
| 4A0044 | FS5972-60-07 | 60 | 8.8 | 9.3 × 2.6 × 16.1 | 8.0 × 15.4 | |
| 4A0058 | | | | | | |
| 4A0072 | | | | | | |
| 4A0088 | FS5972-100-35 | 100 | 16.5 | 3.5 × 5.9 × 13.0 | 2.6 × 10.0 | 2 |
| 4A0103 | | | | | | |
| 4A0139 | | | | | | |
| 4A0165 | FS5972-170-35 | 170 | 10.4 | 4.7 × 6.7 × 17.8 | 4.0 × 14.4 | |
| 4A0208 | | | | | | |
| 4A0250 | | | | | | |
| 4A0296 | FS5972-250-37 | 250 | 25.8 | 5.1 × 9.5 × 24.0 | 3.5 × 19.6 | |
| 4A0362 | | | | | | |
| 4A0414 | | | | | | |
| 4A0515 | FS5972-410-99 | 410 | 23.1 | 10.2 × 4.5 × 15.2 | 9.3 × 4.7 | 3 |
| 4A0675 | | | | | | |
| | | | | | | |
| | FS5972-600-99 | 600 | 24.3 | 10.2 × 5.3 × 15.2 | 9.3 × 4.7 | |
| | | | | | | |
| | FS5972-800-99 | 800 | 69.4 | 11.8 × 6.3 × 28.2 | 10.8 × 8.3 | |

D.2 European Standards

| Drive Model | Filter Data (Manufacturer: Schaffner) | | | | | Figure |
|-------------|---------------------------------------|-------------------|-------------|-----------------------------|------------|--------|
| | Type | Rated Current (A) | Weight (lb) | Dimensions [W x D x H] (in) | Y x X (in) | |
| 4A0930 | FS5972-600-99 <1> | 600 | 24.3 | 10.2 × 5.3 × 15.2 | 9.3 × 4.7 | - |
| 4A1200 | FS5972-800-99 <1> | 800 | 69.4 | 11.8 × 6.3 × 28.2 | 10.8 × 8.3 | |

<1> Connect two of the same filters in parallel.

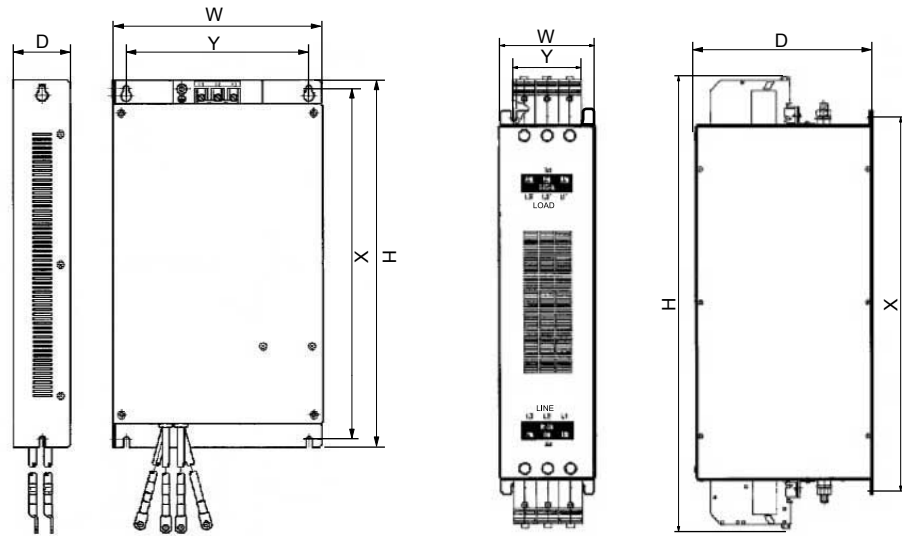


Figure 1

Figure 2

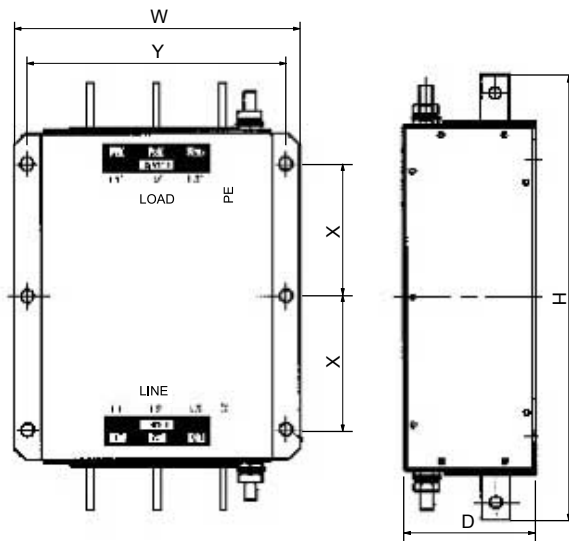


Figure 3

Figure D.5 EMC Filter Dimensions

■ DC Link Chokes for IEC/EN 61000-3-2 Compliance

Table D.3 DC Link Chokes for Harmonic Reduction

| Drive Model | DC Link Chokes | |
|--------------------------------|----------------|---------------|
| | Model | Rating |
| 200 V Three-Phase Units | | |
| 2A0004 | UZDA-B | 5.4 A 8 mH |
| 2A0006 | | |

| Drive Model | DC Link Chokes | |
|--------------------------------|----------------|----------------|
| | Model | Rating |
| 400 V Three-Phase Units | | |
| 4A0002 | UZDA-B | 3.2 A 28 mH |
| 4A0004 | | |

Note: DC link chokes are not required for other models to comply with EMC.

D.3 UL and CSA Standards

◆ UL Standards Compliance

The UL/cUL mark applies to products in the United States and Canada. It indicates that UL has performed product testing and evaluation, and determined that their stringent standards for product safety have been met. For a product to receive UL certification, all components inside that product must also receive UL certification.



Figure D.6 UL/cUL Mark

This drive is tested in accordance with UL standard UL508C and complies with UL requirements. The conditions described below must be met to maintain compliance when using this drive in combination with other equipment:

■ Installation Area

Do not install the drive to an area greater than pollution degree 2 (UL standard).

■ Main Circuit Terminal Wiring

Yaskawa recommends using closed-loop crimp terminals on all drive models. To maintain UL/cUL approval, UL Listed closed-loop crimp terminals are specifically required when wiring the drive main circuit terminals on models 2A0110 to 2A0415, 4A0058 to 4A1200, and 5A0041 to 5A0242. Use only the tools recommended by the terminal manufacturer for crimping. *Refer to Closed-Loop Crimp Terminal Size on page 558* for closed-loop crimp terminal recommendations.

The wire gauges listed in the following tables are Yaskawa recommendations. Refer to local codes for proper wire gauge selections.

Note: The ⊕ mark indicates the terminals for protective ground connection as defined in IEC60417-5019.
 Grounding impedance:
 200 V: 100 Ω or less
 400 V: 10 Ω or less
 600 V: 10 Ω or less

Wire Gauges and Tightening Torques

Table D.4 Wire Gauge and Torque Specifications (Three-Phase 200 V Class)

| Drive Model | Terminal | Recomm. Gauge AWG, kcmil | Wire Range AWG, kcmil | Screw Size | Tightening Torque N·m (lb.in.) |
|--------------------------------------|------------------|-----------------------------|--------------------------|---------------|-----------------------------------|
| 2A0004 2A0006 2A0008 2A0010 | R/L1, S/L2, T/L3 | 14 | 14 to 10 | M4 | 1.2 to 1.5 (10.6 to 13.3) |
| | U/T1, V/T2, W/T3 | 14 | 14 to 10 | | |
| | ⊖, ⊕1, ⊕2 | – | 14 to 10 | | |
| | B1, B2 | – | 14 to 10 | | |
| | ⊕ | 10 </> | 14 to 10 | | |
| 2A0012 | R/L1, S/L2, T/L3 | 12 | 14 to 10 | M4 | 1.2 to 1.5 (10.6 to 13.3) |
| | U/T1, V/T2, W/T3 | 14 | 14 to 10 | | |
| | ⊖, ⊕1, ⊕2 | – | 14 to 10 | | |
| | B1, B2 | – | 14 to 10 | | |
| | ⊕ | 10 </> | 14 to 10 | | |
| 2A0018 | R/L1, S/L2, T/L3 | 10 | 12 to 10 | M4 | 1.2 to 1.5 (10.6 to 13.3) |
| | U/T1, V/T2, W/T3 | 10 | 14 to 10 | | |
| | ⊖, ⊕1, ⊕2 | – | 14 to 10 | | |
| | B1, B2 | – | 14 to 10 | | |
| | ⊕ | 10 </> | 14 to 10 | | |

| Drive Model | Terminal | Recomm. Gauge AWG, kcmil | Wire Range AWG, kcmil | Screw Size | Tightening Torque N·m (lb.in.) |
|-------------|------------------|--------------------------|-----------------------|------------|--------------------------------|
| 2A0021 | R/L1, S/L2, T/L3 | 10 | 12 to 10 | M4 | 1.2 to 1.5 (10.6 to 13.3) |
| | U/T1, V/T2, W/T3 | 10 | 12 to 10 | | |
| | ⊖, ⊕1, ⊕2 | – | 12 to 10 | | |
| | B1, B2 | – | 14 to 10 | | |
| | ⊕ | 10 <2> | 12 to 10 | | |
| 2A0030 | R/L1, S/L2, T/L3 | 8 | 10 to 6 | M4 | 2.1 to 2.3 (18.6 to 20.4) |
| | U/T1, V/T2, W/T3 | 8 | 10 to 6 | | |
| | ⊖, ⊕1, ⊕2 | – | 10 to 6 | | |
| | B1, B2 | – | 14 to 10 | | |
| | ⊕ | 8 <2> | 10 to 8 | M5 | 2.0 to 2.5 (17.7 to 22.1) |
| 2A0040 | R/L1, S/L2, T/L3 | 6 | 8 to 6 | M4 | 2.1 to 2.3 (18.6 to 20.4) |
| | U/T1, V/T2, W/T3 | 8 | 8 to 6 | | |
| | ⊖, ⊕1, ⊕2 | – | 6 | | |
| | B1, B2 | – | 12 to 10 | | |
| | ⊕ | 8 <2> | 10 to 8 | M5 | 2.0 to 2.5 (17.7 to 22.1) |
| 2A0056 | R/L1, S/L2, T/L3 | 4 | 6 to 4 | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| | U/T1, V/T2, W/T3 | 4 | 6 to 4 | | |
| | ⊖, ⊕1, ⊕2 | – | 6 to 4 | | |
| | B1, B2 | – | 10 to 6 | M5 | 2.7 to 3.0 (23.9 to 26.6) |
| | ⊕ | 6 | 8 to 6 | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| 2A0069 | R/L1, S/L2, T/L3 | 3 | 4 to 3 | M8 | 9.9 to 11.0 (87.6 to 97.4) |
| | U/T1, V/T2, W/T3 | 3 | 4 to 3 | | |
| | ⊖, ⊕1, ⊕2 | – | 4 to 3 | | |
| | B1, B2 | – | 8 to 6 | M5 | 2.7 to 3.0 (23.9 to 26.6) |
| | ⊕ | 6 | 6 to 4 | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| 2A0081 | R/L1, S/L2, T/L3 | 2 | 3 to 2 | M8 | 9.9 to 11.0 (87.6 to 97.4) |
| | U/T1, V/T2, W/T3 | 2 | 3 to 2 | | |
| | ⊖, ⊕1, ⊕2 | – | 3 to 2 | | |
| | B1, B2 | – | 6 | M5 | 2.7 to 3.0 (23.9 to 26.6) |
| | ⊕ | 6 | 6 to 4 | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| 2A0110 | R/L1, S/L2, T/L3 | 1/0 | 3 to 1/0 | M8 | 9 to 11 (79.7 to 97.4) |
| | U/T1, V/T2, W/T3 | 1/0 | 3 to 1/0 | | |
| | ⊖, ⊕1 | – | 2 to 1/0 | | |
| | B1, B2 | – | 6 to 1/0 | | |
| | ⊕ | 6 | 6 to 4 | | |
| 2A0138 | R/L1, S/L2, T/L3 | 2/0 | 1 to 2/0 | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 2/0 | 1 to 2/0 | | |
| | ⊖, ⊕1 | – | 1/0 to 3/0 | | |
| | B1, B2 | – | 4 to 2/0 | | |
| | ⊕ | 4 | 4 | M8 | 9 to 11 (79.7 to 97.4) |
| 2A0169 | R/L1, S/L2, T/L3 | 4/0 | 2/0 to 4/0 | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 4/0 | 3/0 to 4/0 | | |
| | ⊖, ⊕1 | – | 1 to 4/0 | | |
| | ⊕3 | – | 1/0 to 4/0 | | |
| | ⊕ | 4 | 4 to 2 | | |

D.3 UL and CSA Standards

| Drive Model | Terminal | Recomm. Gauge AWG, kcmil | Wire Range AWG, kcmil | Screw Size | Tightening Torque N·m (lb.in.) |
|-------------|------------------|-----------------------------|--------------------------|---------------|-----------------------------------|
| 2A0211 | R/L1, S/L2, T/L3 | 1/0 × 2P | 1/0 to 2/0 | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 1/0 × 2P | 1/0 to 2/0 | | |
| | ⊖, ⊕1 | – | 1 to 4/0 | | |
| | ⊕3 | – | 1/0 to 4/0 | | |
| | ⊕ | 4 | 4 to 1/0 | | |
| 2A0250 | R/L1, S/L2, T/L3 | 3/0 × 2P | 3/0 to 300 | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 3/0 × 2P | 3/0 to 300 | | |
| | ⊖, ⊕1 | – | 3/0 to 300 | | |
| | ⊕3 | – | 2 to 300 | M10 | 18 to 23 (159 to 204) |
| | ⊕ | 3 | 3 to 300 | M12 | 32 to 40 (283 to 354) |
| 2A0312 | R/L1, S/L2, T/L3 | 4/0 × 2P | 3/0 to 300 | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 3/0 × 2P | 3/0 to 300 | | |
| | ⊖, ⊕1 | – | 3/0 to 300 | | |
| | ⊕3 | – | 3/0 to 300 | M10 | 18 to 23 (159 to 204) |
| | ⊕ | 2 | 2 to 300 | M12 | 32 to 40 (283 to 354) |
| 2A0360 | R/L1, S/L2, T/L3 | 250 × 2P | 4/0 to 600 | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 4/0 × 2P | 4/0 to 600 | | |
| | ⊖, ⊕1 | – | 250 to 600 | | |
| | ⊕3 | – | 3/0 to 600 | M10 | 18 to 23 (159 to 204) |
| | ⊕ | 1 | 1 to 350 | M12 | 32 to 40 (283 to 354) |
| 2A0415 | R/L1, S/L2, T/L3 | 350 × 2P | 250 to 600 | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 300 × 2P | 300 to 600 | | |
| | ⊖, ⊕1 | – | 300 to 600 | | |
| | ⊕3 | – | 3/0 to 600 | M10 | 18 to 23 (159 to 204) |
| | ⊕ | 1 | 1 to 350 | M12 | 32 to 40 (283 to 354) |

<1> Install a GFCI when using this wire gauge in accordance with IEC/EN 61800-5-1.

<2> Install a GFCI, or use 10 mm² (AWG 8) copper wire when using this wire gauge in accordance with IEC/EN 61800-5-1.

Table D.5 Wire Gauge and Torque Specifications (Three-Phase 400 V Class)

| Drive Model | Terminal | Recomm. Gauge AWG, kcmil | Wire Range AWG, kcmil | Screw Size | Tightening Torque N·m (lb.in.) |
|----------------------------|------------------|-----------------------------|--------------------------|---------------|-----------------------------------|
| 4A0002 4A0004 | R/L1, S/L2, T/L3 | 14 | 14 to 10 | M4 | 1.2 to 1.5 (10.6 to 13.3) |
| | U/T1, V/T2, W/T3 | 14 | 14 to 10 | | |
| | ⊖, ⊕1, ⊕2 | – | 14 to 10 | | |
| | B1, B2 | – | 14 to 10 | | |
| | ⊕ | 12 <?> | 14 to 12 | | |
| 4A0005 4A0007 4A0009 | R/L1, S/L2, T/L3 | 14 | 14 to 10 | M4 | 1.2 to 1.5 (10.6 to 13.3) |
| | U/T1, V/T2, W/T3 | 14 | 14 to 10 | | |
| | ⊖, ⊕1, ⊕2 | – | 14 to 10 | | |
| | B1, B2 | – | 14 to 10 | | |
| | ⊕ | 10 <?> | 14 to 10 | | |
| 4A0011 | R/L1, S/L2, T/L3 | 12 | 14 to 10 | M4 | 1.2 to 1.5 (10.6 to 13.3) |
| | U/T1, V/T2, W/T3 | 14 | 14 to 10 | | |
| | ⊖, ⊕1, ⊕2 | – | 14 to 10 | | |
| | B1, B2 | – | 14 to 10 | | |
| | ⊕ | 10 <?> | 14 to 10 | | |
| 4A0018 | R/L1, S/L2, T/L3 | 10 | 12 to 6 | M4 | 2.1 to 2.3 (18.6 to 20.4) |
| | U/T1, V/T2, W/T3 | 10 | 12 to 6 | | |
| | ⊖, ⊕1, ⊕2 | – | 12 to 6 | | |
| | B1, B2 | – | 12 to 10 | | |
| | ⊕ | 10 <?> | 14 to 10 | M5 | 2.0 to 2.5 (17.7 to 22.1) |
| 4A0023 | R/L1, S/L2, T/L3 | 10 | 10 to 6 | M4 | 2.1 to 2.3 (18.6 to 20.4) |
| | U/T1, V/T2, W/T3 | 10 | 10 to 6 | | |
| | ⊖, ⊕1, ⊕2 | – | 12 to 6 | | |
| | B1, B2 | – | 12 to 10 | | |
| | ⊕ | 10 <?> | 12 to 10 | M5 | 2.0 to 2.5 (17.7 to 22.1) |
| 4A0031 | R/L1, S/L2, T/L3 | 8 | 8 to 6 | M5 | 3.6 to 4.0 (31.8 to 35.4) |
| | U/T1, V/T2, W/T3 | 8 | 10 to 6 | | |
| | ⊖, ⊕1, ⊕2 | – | 10 to 6 | | |
| | B1, B2 | – | 10 to 8 | | |
| | ⊕ | 8 <?> | 10 to 8 | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| 4A0038 | R/L1, S/L2, T/L3 | 6 | 8 to 6 | M5 | 3.6 to 4.0 (31.8 to 35.4) |
| | U/T1, V/T2, W/T3 | 8 | 8 to 6 | | |
| | ⊖, ⊕1, ⊕2 | – | 6 | | |
| | B1, B2 | – | 10 to 8 | | |
| | ⊕ | 6 | 10 to 6 | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| 4A0044 | R/L1, S/L2, T/L3 | 6 | 6 to 4 | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| | U/T1, V/T2, W/T3 | 6 | 6 to 4 | | |
| | ⊖, ⊕1, ⊕2 | – | 6 to 4 | | |
| | B1, B2 | – | 10 to 8 | M5 | 2.7 to 3.0 (23.9 to 26.6) |
| | ⊕ | 6 | 8 to 6 | M6 | 5.4 to 6.0 (47.8 to 53.1) |

D.3 UL and CSA Standards

| Drive Model | Terminal | Recomm. Gauge AWG, kcmil | Wire Range AWG, kcmil | Screw Size | Tightening Torque N-m (lb.in.) |
|-------------|------------------|-----------------------------|--------------------------|---------------|-----------------------------------|
| 4A0058 | R/L1, S/L2, T/L3 | 4 | 6 to 4 | M8 | 9 to 11 (79.7 to 97.4) |
| | U/T1, V/T2, W/T3 | 4 | 6 to 4 | | |
| | ⊖, ⊕1 | – | 6 to 1 | | |
| | B1, B2 | – | 8 to 4 | | |
| | ⊕ | 6 | 8 to 6 | | |
| 4A0072 | R/L1, S/L2, T/L3 | 3 | 4 to 3 | M8 | 9 to 11 (79.7 to 97.4) |
| | U/T1, V/T2, W/T3 | 3 | 4 to 3 | | |
| | ⊖, ⊕1 | – | 4 to 1 | | |
| | B1, B2 | – | 6 to 3 | | |
| | ⊕ | 6 | 6 | | |
| 4A0088 | R/L1, S/L2, T/L3 | 2 | 3 to 1/0 | M8 | 9 to 11 (79.7 to 97.4) |
| | U/T1, V/T2, W/T3 | 2 | 3 to 1/0 | | |
| | ⊖, ⊕1 | – | 3 to 1/0 | | |
| | ⊕3 | – | 6 to 1/0 | | |
| | ⊕ | 4 | 6 to 4 | | |
| 4A0103 | R/L1, S/L2, T/L3 | 1/0 | 2 to 1/0 | M8 | 9 to 11 (79.7 to 97.4) |
| | U/T1, V/T2, W/T3 | 1 | 2 to 1/0 | | |
| | ⊖, ⊕1 | – | 3 to 1/0 | | |
| | ⊕3 | – | 4 to 1/0 | | |
| | ⊕ | 4 | 6 to 4 | | |
| 4A0139 | R/L1, S/L2, T/L3 | 3/0 | 1/0 to 4/0 | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 2/0 | 1/0 to 4/0 | | |
| | ⊖, ⊕1 | – | 1/0 to 4/0 | | |
| | ⊕3 | – | 3 to 4/0 | | |
| | ⊕ | 4 | 4 | | |
| 4A0165 | R/L1, S/L2, T/L3 | 4/0 | 3/0 to 4/0 | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 4/0 | 3/0 to 4/0 | | |
| | ⊖, ⊕1 | – | 1 to 4/0 | | |
| | ⊕3 | – | 1/0 to 4/0 | | |
| | ⊕ | 4 | 4 to 2 | | |
| 4A0208 | R/L1, S/L2, T/L3 | 300 | 2 to 300 | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 300 | 2 to 300 | | |
| | ⊖, ⊕1 | – | 1 to 250 | | |
| | ⊕3 | – | 3 to 3/0 | | |
| | ⊕ | 4 | 4 to 300 | | |
| 4A0250 | R/L1, S/L2, T/L3 | 400 | 1 to 600 | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 400 | 1/0 to 600 | | |
| | ⊖, ⊕1 | – | 3/0 to 600 | | |
| | ⊕3 | – | 1 to 325 | | |
| | ⊕ | 2 | 2 to 350 | | |
| 4A0296 | R/L1, S/L2, T/L3 | 500 | 2/0 to 600 | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 500 | 2/0 to 600 | | |
| | ⊖, ⊕1 | – | 3/0 to 600 | M10 | 18 to 23 (159 to 204) |
| | ⊕3 | – | 1 to 325 | | |
| | ⊕ | 2 | 2 to 350 | | |

| Drive Model | Terminal | Recomm. Gauge AWG, kcmil | Wire Range AWG, kcmil | Screw Size | Tightening Torque N·m (lb.in.) |
|-------------|---|-----------------------------|--------------------------|---------------|-----------------------------------|
| 4A0362 | R/L1, S/L2, T/L3 | 4/0 × 2P | 3/0 to 600 | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 4/0 × 2P | 3/0 to 600 | | |
| | ⊖, ⊕1 | – | 4/0 to 600 | | |
| | ⊕3 | – | 3/0 to 600 | M10 | 18 to 23 (159 to 204) |
| | ⊕ | 1 | 1 to 350 | M12 | 32 to 40 (283 to 354) |
| 4A0414 | R/L1, S/L2, T/L3 | 300 × 2P | 4/0 to 300 | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 300 × 2P | 4/0 to 300 | | |
| | ⊖, ⊕1 | – | 3/0 to 300 | | |
| | ⊕3 | – | 3/0 to 300 | | |
| | ⊕ | 1 | 1 to 3/0 | | |
| 4A0515 | R/L1, S/L2, T/L3 | 3/0 × 4P | 3/0 to 300 | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 4/0 × 4P | 3/0 to 300 | | |
| | ⊖, ⊕1 | – | 1/0 to 300 | | |
| | ⊕3 | – | 1/0 to 300 | | |
| | ⊕ | 1/0 | 1/0 to 300 | | |
| 4A0675 | R/L1, S/L2, T/L3 | 300 × 4P | 4/0 to 300 | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 300 × 4P | 4/0 to 300 | | |
| | ⊖, ⊕1 | – | 1/0 to 300 | | |
| | ⊕3 | – | 1/0 to 300 | | |
| | ⊕ | 2/0 | 2/0 to 300 | | |
| 4A0930 | R/L1, S/L2, T/L3, R1/L11, S1/L21, T1/L31 | 4/0 × 4P×2 | 3/0 to 300 | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 4/0 × 4P×2 | 3/0 to 300 | | |
| | ⊖, ⊕1 | – | 4/0 to 300 | | |
| | ⊕3 | – | 4/0 to 300 | | |
| | ⊕ | 3/0 | 3/0 to 250 | | |
| 4A1200 | R/L1, S/L2, T/L3, R1/L11, S1/L21, T1/L31 | 300 × 4P×2 | 4/0 to 300 | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 300 × 4P×2 | 4/0 to 300 | | |
| | ⊖, ⊕1 | – | 250 to 300 | | |
| | ⊕3 | – | 4/0 to 300 | | |
| | ⊕ | 4/0 | 4/0 to 250 | | |

<1> Install a GFCI when using this wire gauge in accordance with IEC/EN 61800-5-1.

<2> Install a GFCI or use 10 mm² (AWG 8) copper wire when using this wire gauge in accordance with IEC/EN 61800-5-1.

D.3 UL and CSA Standards

Table D.6 Wire Gauge and Torque Specifications (Three-Phase 600 V Class)

| Drive Model | Terminal | Recomm. Gauge mm ² (AWG, kcmil) | Wire Range mm ² (AWG, kcmil) | Screw Size | Tightening Torque N·m (lb.in.) |
|----------------------------|------------------|---|--|---------------|-----------------------------------|
| 5A0003 5A0004 5A0006 | R/L1, S/L2, T/L3 | 2.5 (14) | 2.5 to 6.0 (14 to 10) | M4 | 1.2 to 1.5 (10.6 to 13.3) |
| | U/T1, V/T2, W/T3 | 2.5 (14) | 2.5 to 6.0 (14 to 10) | | |
| | ⊖, ⊕1, ⊕2 | – | 2.5 to 6.0 (14 to 10) | | |
| | B1, B2 | – | 2.5 to 6.0 (14 to 10) | | |
| | ⊕ | 6.0 (10) | 2.5 to 6.0 (14 to 10) | | |
| 5A0009 | R/L1, S/L2, T/L3 | 2.5 (14) | 2.5 to 6.0 (14 to 10) | M4 | 1.2 to 1.5 (10.6 to 13.3) |
| | U/T1, V/T2, W/T3 | 2.5 (14) | 2.5 to 6.0 (14 to 10) | | |
| | ⊖, ⊕1, ⊕2 | – | 2.5 to 6.0 (14 to 10) | | |
| | B1, B2 | – | 2.5 to 6.0 (14 to 10) | | |
| | ⊕ | 6.0 (10) | 4.0 to 6.0 (12 to 10) | | |
| 5A0011 | R/L1, S/L2, T/L3 | 6.0 (10) | 2.5 to 16 (14 to 6) | M4 | 2.1 to 2.3 (18.6 to 20.4) |
| | U/T1, V/T2, W/T3 | 2.5 (14) | 2.5 to 16 (14 to 6) | | |
| | ⊖, ⊕1, ⊕2 | – | 2.5 to 16 (14 to 6) | | |
| | B1, B2 | – | 2.5 to 6.0 (14 to 10) | | |
| | ⊕ | 10 (8) | 4.0 to 6.0 (12 to 8) | M5 | 2.0 to 2.5 (17.7 to 22.1) |
| 5A0017 | R/L1, S/L2, T/L3 | 6.0 (10) | 6.0 to 16 (10 to 6) | M5 | 3.6 to 4.0 (31.8 to 35.4) |
| | U/T1, V/T2, W/T3 | 6.0 (10) | 6.0 to 16 (10 to 6) | | |
| | ⊖, ⊕1, ⊕2 | – | 6.0 to 16 (10 to 6) | | |
| | B1, B2 | – | 6.0 to 10 (10 to 8) | | |
| | ⊕ | 10 (8) | 6.0 to 10 (12 to 8) | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| 5A0022 | R/L1, S/L2, T/L3 | 10 (8) | 6.0 to 16 (10 to 6) | M5 | 3.6 to 4.0 (31.8 to 35.4) |
| | U/T1, V/T2, W/T3 | 6.0 (10) | 6.0 to 16 (10 to 6) | | |
| | ⊖, ⊕1, ⊕2 | – | 6.0 to 16 (10 to 6) | | |
| | B1, B2 | – | 6.0 to 10 (10 to 8) | | |
| | ⊕ | 10 (8) | 6.0 to 10 (10 to 6) | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| 5A0027 5A0032 | R/L1, S/L2, T/L3 | 16 (6) | 16 to 25 (6 to 4) | M6 | 5.4 to 6.0 (47.8 to 53.1) |
| | U/T1, V/T2, W/T3 | 16 (6) | 16 to 25 (6 to 4) | | |
| | ⊖, ⊕1, ⊕2 | – | 16 to 25 (6 to 4) | | |
| | B1, B2 | – | 6.0 to 10 (10 to 8) | M5 | 2.7 to 3.0 (23.9 to 26.6) |
| | ⊕ | 16 (6) | 10 to 16 (10 to 6) | M6 | 5.4 to 6.0 (47.8 to 53.1) |

| Drive Model | Terminal | Recomm. Gauge mm ² (AWG, kcmil) | Wire Range mm ² (AWG, kcmil) | Screw Size | Tightening Torque N·m (lb.in.) |
|-------------|------------------|---|--|---------------|-----------------------------------|
| 5A0041 | R/L1, S/L2, T/L3 | 16 (6) | 6.0 to 25 (10 to 3) | M8 | 9.0 to 11 (79.7 to 97.4) |
| | U/T1, V/T2, W/T3 | 16 (6) | 6.0 to 25 (10 to 3) | | |
| | ⊖, ⊕1 | – | (6 to 1) | | |
| | B1, B2 | – | 4.0 to 25 (12 to 3) | | |
| | ⊕ | 16 (6) | 10 to 16 (6) | | |
| 5A0052 | R/L1, S/L2, T/L3 | 25 (4) | 6.0 to 25 (10 to 3) | M8 | 9.0 to 11 (79.7 to 97.4) |
| | U/T1, V/T2, W/T3 | 16 (6) | 6.0 to 25 (10 to 3) | | |
| | ⊖, ⊕1 | – | 16 to 35 (6 to 1) | | |
| | B1, B2 | – | 10 to 25 (8 to 3) | | |
| | ⊕ | 16 (6) | 10 to 16 (6) | | |
| 5A0062 | R/L1, S/L2, T/L3 | 25 (4) | 6.0 to 95 (10 to 4/0) | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 25 (4) | 6.0 to 95 (10 to 4/0) | | |
| | ⊖, ⊕1 | – | 25 to 95 (4 to 4/0) | | |
| | ⊕3 | – | 16 to 95 (6 to 4/0) | | |
| | ⊕ | 25 (4) | 25 (4) | | |
| 5A0077 | R/L1, S/L2, T/L3 | 25 (3) | 6.0 to 95 (10 to 4/0) | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 25 (3) | 6.0 to 95 (10 to 4/0) | | |
| | ⊖, ⊕1 | – | 25 to 95 (3 to 4/0) | | |
| | ⊕3 | – | 16 to 95 (6 to 4/0) | | |
| | ⊕ | 25 (4) | 25 (4) | | |
| 5A0099 | R/L1, S/L2, T/L3 | 70 (1/0) | 6.0 to 95 (10 to 4/0) | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 50 (1) | 6.0 to 95 (10 to 4/0) | | |
| | ⊖, ⊕1 | – | 35 to 95 (2 to 4/0) | | |
| | ⊕3 | – | 25 to 95 (4 to 4/0) | | |
| | ⊕ | 25 (4) | 25 (4) | | |
| 5A0125 | R/L1, S/L2, T/L3 | 70 (2/0) | 35 to 150 (1 to 300) | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 70 (2/0) | 35 to 150 (1 to 300) | | |
| | ⊖, ⊕1 | – | 70 (2/0 to 3/0) | | |
| | ⊕3 | – | 35 to 50 (1 to 1/0) | | |
| | ⊕ | 35 (3) | 35 to 150 (3 to 300) | | |

D.3 UL and CSA Standards

| Drive Model | Terminal | Recomm. Gauge mm ² (AWG, kcmil) | Wire Range mm ² (AWG, kcmil) | Screw Size | Tightening Torque N·m (lb.in.) |
|-------------|------------------|---|--|---------------|-----------------------------------|
| 5A0145 | R/L1, S/L2, T/L3 | 95 (3/0) | 95 to 150 (2/0 to 300) | M10 | 18 to 23 (159 to 204) |
| | U/T1, V/T2, W/T3 | 95 (3/0) | 95 to 150 (2/0 to 300) | | |
| | ⊖, ⊕1 | – | 70 to 95 (3/0 to 4/0) | | |
| | ⊕3 | – | 70 to 95 (1/0 to 2/0) | | |
| | ⊕ | 35 (3) | 35 to 150 (3 to 300) | | |
| 5A0192 | R/L1, S/L2, T/L3 | 185 (300) | 95 to 300 (2/0 to 600) | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 150 (250) | 95 to 300 (2/0 to 600) | | |
| | ⊖, ⊕1 | – | 95 to 185 (2/0 to 400) | | |
| | ⊕3 | – | 95 to 120 (2/0 to 250) | M10 | 18 to 23 (159 to 204) |
| | ⊕ | 50 (1) | 35 to 300 (1 to 350) | M12 | 32 to 40 (283 to 354) |
| 5A0242 | R/L1, S/L2, T/L3 | 240 (400) | 95 to 300 (2/0 to 600) | M12 | 32 to 40 (283 to 354) |
| | U/T1, V/T2, W/T3 | 185 (350) | 95 to 300 (2/0 to 600) | | |
| | ⊖, ⊕1 | – | 95 to 240 (2/0 to 500) | | |
| | ⊕3 | – | 150 (250 to 300) | M10 | 18 to 23 (159 to 204) |
| | ⊕ | 50 (1) | 35 to 300 (1 to 350) | M12 | 32 to 40 (283 to 354) |

Closed-Loop Crimp Terminal Recommendations

To maintain UL/cUL approval, UL Listed closed-loop crimp terminals are specifically required when wiring the drive main circuit terminals on models 2A0110 to 2A0415, 4A0058 to 4A1200, and 5A0041 to 5A0242. Use only the tools recommended by the terminal manufacturer for crimping. Yaskawa recommends crimp terminals made by JST and Tokyo DIP (or equivalent) for the insulation cap. [Table D.7](#) matches the wire gauges and terminal screw sizes with Yaskawa-recommended crimp terminals, tools, and insulation caps. Refer to the appropriate Wire Gauge and Torque Specifications table for the wire gauge and screw size for your drive model. Place orders with a Yaskawa representative or the Yaskawa sales department.

Wire gauge values shown in ***bold italic*** are the recommended values. Refer to local codes for proper selections.

Table D.7 Closed-Loop Crimp Terminal Size

| Drive Model | Wire Gauge (AWG, kcmil) | | Screw Size | Crimp Terminal Model Number | Tool | | Insulation Cap Model No. | Code <1> |
|--------------------------------------|-------------------------|------------------|------------|-----------------------------|-------------|---------|--------------------------|-------------|
| | R/L1, S/L2, T/L3 | U/T1, V/T2, W/T3 | | | Machine No. | Die Jaw | | |
| 200 V Class | | | | | | | | |
| 2A0004 2A0006 2A0008 2A0010 | 14 | | M4 | R2-4 | YA-4 | AD-900 | TP-003 | 100-054-028 |
| | 12 | | | R5.5-4 | | | TP-005 | 100-054-029 |
| | 10 | | | | | | | |
| 2A0012 | 14 | 14 | M4 | R2-4 | YA-4 | AD-900 | TP-003 | 100-054-028 |
| | 12 | 12 | | R5.5-4 | | | TP-005 | 100-054-029 |
| | 10 | | | | | | | |
| 2A0018 | – | 14 | M4 | R2-4 | YA-4 | AD-900 | TP-003 | 100-054-028 |
| | 12 | | | R5.5-4 | | | TP-005 | 100-054-029 |
| | 10 | | | | | | | |
| 2A0021 | 12 | | M4 | R5.5-4 | YA-4 | AD-900 | TP-005 | 100-054-029 |
| | 10 | | | | | | | |

| Drive Model | Wire Gauge (AWG, kcmil) | | Screw Size | Crimp Terminal Model Number | Tool | | Insulation Cap Model No. | Code <1> |
|-------------|-------------------------|------------------|------------|-----------------------------|-------------------|-------------------|--------------------------|-------------|
| | R/L1, S/L2, T/L3 | U/T1, V/T2, W/T3 | | | Machine No. | Die Jaw | | |
| 2A0030 | 10 | | M4 | R5.5-4 | YA-4 | AD-900 | TP-005 | 100-054-029 |
| | 8 | | | 8-4 | | AD-901 | TP-008 | 100-054-031 |
| | 6 | | | 14-NK4 | | AD-902 | TP-014 | 100-054-033 |
| 2A0040 | 8 | 8 | M4 | 8-4 | YA-4 | AD-901 | TP-008 | 100-054-031 |
| | 6 | 6 | | 14-NK4 | | AD-902 | TP-014 | 100-054-033 |
| 2A0056 | 6 | | M6 | R14-6 | YA-5 | AD-952 | TP-014 | 100-051-261 |
| | 4 | | | R22-6 | | AD-953 | TP-022 | 100-051-262 |
| 2A0069 | 4 | | M8 | R22-8 | YA-5 | AD-953 | TP-022 | 100-051-263 |
| | 3 | | | R38-8 | | AD-954 | TP-038 | 100-051-264 |
| 2A0081 | 3 | | M8 | R38-8 | YA-5 | AD-954 | TP-038 | 100-051-264 |
| | 2 | | | | | | | |
| 2A0110 | 3 | | M8 | R38-8 | YA-5 | AD-954 | TP-038 | 100-051-264 |
| | 2 | | | | | | | |
| | 1 | | | | | | | |
| | 1/0 | | | | | | | |
| 2A0138 | 1 | | M10 | R38-10 | YF-1 YET-300-1 | TD-321, TD-311 | TP-060 | 100-061-114 |
| | 1/0 | | | R60-10 | | | | 100-051-266 |
| | 2/0 | | | 70-10 | | TD-323, TD-312 | TP-080 | 100-054-036 |
| 2A0169 | 2/0 | - | M10 | 70-10 | YF-1 YET-300-1 | TD-323, TD-312 | TP-080 | 100-054-036 |
| | 3/0 | | | 80-10 | | | | 100-051-267 |
| | 4/0 | | | R100-10 | | TD-324, TD-312 | TP-100 | 100-051-269 |
| 2A0211 | 1/0 × 2P | | M10 | R60-10 | YF-1 YET-300-1 | TD-321, TD-311 | TP-060 | 100-051-266 |
| | 2/0 × 2P | | | 70-10 | | TD-323, TD-312 | TP-080 | 100-054-036 |
| 2A0250 | 3/0 × 2P | | M12 | 80-L12 | YF-1 YET-300-1 | TD-323, TD-312 | TP-080 | 100-051-558 |
| | 4/0 × 2P | | | 100-L12 | | TD-324, TD-312 | TP-100 | 100-051-560 |
| | - | 250 × 2P | | 150-L12 | | TD-325, TD-313 | TP-150 | 100-051-562 |
| | 250 | - | | R150-12 | | | TP-150 | 100-051-273 |
| | 300 | | | | | | | |
| 2A0312 | 3/0 × 2P | 3/0 × 2P | M12 | 80-L12 | YF-1 YET-300-1 | TD-323, TD-312 | TP-080 | 100-051-558 |
| | 4/0 × 2P | 4/0 × 2P | | 100-L12 | | TD-324, TD-312 | TP-100 | 100-051-560 |
| | 250 × 2P | | | 150-L12 | | TD-325, TD-313 | TP-150 | 100-051-562 |
| | 300 × 2P | | | | | | | |
| 2A0360 | 4/0 × 2P | 4/0 × 2P | M12 | 100-L12 | YF-1 YET-300-1 | TD-324, TD-312 | TP-100 | 100-051-560 |
| | 250 × 2P | 250 × 2P | | 150-L12 | | TD-325, TD-313 | TP-150 | 100-051-562 |
| | 300 × 2P | | | 180-L12 | | TD-327, TD-314 | TP-200 | 100-066-688 |
| | 350 × 2P | | | | | | | |
| | 400 × 2P | | | 325-12 | | TD-328, TD-315 | TP-325 | 100-051-277 |
| | 500 × 2P | | | | | | | |
| | 600 | 600 × 2P | | | | | | |

D.3 UL and CSA Standards

| Drive Model | Wire Gauge (AWG, kcmil) | | Screw Size | Crimp Terminal Model Number | Tool | | Insulation Cap Model No. | Code <?> | |
|--|-------------------------|------------------|------------|-----------------------------|-------------------|-------------------|--------------------------|-------------|-------------|
| | R/L1, S/L2, T/L3 | U/T1, V/T2, W/T3 | | | Machine No. | Die Jaw | | | |
| 2A0415 | 250 × 2P | – | M12 | 150-L12 | YF-1 YET-300-1 | TD-325, TD-313 | TP-150 | 100-051-562 | |
| | 300 × 2P | 300 × 2P | | 180-L12 | | TD-327, TD-314 | TP-200 | 100-066-688 | |
| | 350 × 2P | 350 × 2P | | 200-L12 | | TD-328, TD-315 | TP-325 | 100-051-564 | |
| | 400 × 2P | | | 325-12 | | | | 100-051-277 | |
| | 500 × 2P | | | | | | | | |
| | 600 × 2P | | | | | | | | |
| 400 V Class | | | | | | | | | |
| 4A0002 4A0004 4A0005 4A0007 4A0009 | 14 | | M4 | R2-4 | YA-4 | AD-900 | TP-003 | 100-054-028 | |
| | 12 | | | R5.5-4 | | | TP-005 | 100-054-029 | |
| | 10 | | | | | | | | |
| 4A0011 | 14 | 14 | M4 | R2-4 | YA-4 | AD-900 | TP-003 | 100-054-028 | |
| | 12 | 12 | | R5.5-4 | | | TP-005 | 100-054-029 | |
| | 10 | | | | | | | | |
| 4A0018 | 12 | | M4 | R5.5-4 | YA-4 | AD-900 | TP-005 | 100-054-029 | |
| | 10 | | | 8-4 | | | AD-901 | TP-008 | 100-054-031 |
| | 8 | | | 14-NK4 | | | AD-902 | TP-014 | 100-054-033 |
| | 6 | | | | | | | | |
| 4A0023 | 10 | | M4 | R5.5-4 | YA-4 | AD-900 | TP-005 | 100-054-029 | |
| | 8 | | | 8-4 | | | AD-901 | TP-008 | 100-054-031 |
| | 6 | | | 14-NK4 | | | AD-902 | TP-014 | 100-054-033 |
| 4A0031 | – | 10 | M5 | R5.5-5 | YA-4 | AD-900 | TP-005 | 100-054-030 | |
| | 8 | | | R8-5 | | | AD-901 | TP-008 | 100-054-032 |
| | 6 | | | R14-5 | | | AD-902 | TP-014 | 100-054-034 |
| 4A0038 | 8 | 8 | M5 | R8-5 | YA-4 | AD-901 | TP-008 | 100-054-032 | |
| | 6 | 6 | | R14-5 | | | AD-902 | TP-014 | 100-054-034 |
| 4A0044 | 6 | | M6 | R14-6 | YA-5 | AD-952 | TP-014 | 100-051-261 | |
| | 4 | | | R22-6 | | | AD-953 | TP-022 | 100-051-262 |
| 4A0058 | 6 | | M8 | R14-8 | YA-5 | AD-952 | TP-014 | 100-054-035 | |
| | 4 | | | R22-8 | | | AD-953 | TP-022 | 100-051-263 |
| 4A0072 | 4 | | M8 | R22-8 | YA-5 | AD-953 | TP-022 | 100-051-263 | |
| | 3 | | | R38-8 | | | AD-954 | TP-038 | 100-051-264 |
| 4A0088 | 3 | | M8 | R38-8 | YA-5 | AD-954 | TP-038 | 100-051-264 | |
| | 2 | | | | | | R60-8 | AD-955 | TP-060 |
| | 1 | | | | | | | | |
| | 1/0 | | | | | | | | |
| 4A0103 | 2 | | M8 | R38-8 | YA-5 | AD-954 | TP-038 | 100-051-264 | |
| | 1 | 1 | | | | | R60-8 | AD-955 | TP-060 |
| | 1/0 | 1/0 | | | | | | | |
| 4A0139 | 1/0 | | M10 | R60-10 | YF-1 YET-300-1 | TD-321, TD-311 | TP-060 | 100-051-266 | |
| | 2/0 | 2/0 | | 70-10 | | TD-323, TD-312 | TP-080 | 100-054-036 | |
| | 3/0 | 3/0 | | 80-10 | | | 100-051-267 | | |
| | 4/0 | | | R100-10 | | TD-324, TD-312 | TP-100 | 100-051-269 | |
| 4A0165 | 3/0 | | M10 | 80-10 | YF-1 YET-300-1 | TD-323, TD-312 | TP-080 | 100-051-267 | |
| | 4/0 | | | R100-10 | | TD-324, TD-312 | TP-100 | 100-051-269 | |

| Drive Model | Wire Gauge (AWG, kcmil) | | Screw Size | Crimp Terminal Model Number | Tool | | Insulation Cap Model No. | Code <1> | | |
|-------------|-------------------------|------------------|-------------------|-----------------------------|-------------------|-------------------|--------------------------|-------------|-------------|--|
| | R/L1, S/L2, T/L3 | U/T1, V/T2, W/T3 | | | Machine No. | Die Jaw | | | | |
| 4A0208 | 2 × 2P | | M10 | 38-L10 | YF-1 YET-150-1 | TD-224, TD-212 | TP-038 | 100-051-556 | | |
| | 1 × 2P | | | 80-L10 | | TD-227, TD-214 | TP-080 | 100-051-557 | | |
| | 3/0 × 2P | | | R100-10 | | TD-228, TD-214 | TP-100 | 100-051-269 | | |
| | 4/0 | | | R150-10 | | TD-229, TD-215 | TP-150 | 100-051-272 | | |
| | 250 | | | | | | | | | |
| | 300 | | | | | | | | | |
| 4A0250 | 1 × 2P | – | M10 | 38-L10 | YF-1 YET-150-1 | TD-224, TD-212 | TP-038 | 100-051-556 | | |
| | 3/0 × 2P | | | 80-L10 | | TD-227, TD-214 | TP-080 | 100-051-557 | | |
| | 4/0 × 2P | | | 100-L10 | | TD-228, TD-214 | TP-100 | 100-051-559 | | |
| | 250 × 2P | | | 150-L10 | | TD-229, TD-215 | TP-150 | 100-051-561 | | |
| | 300 | | | R150-10 | | TP-150 | 100-051-272 | | | |
| | 350 | | | 180-10 | | TD-327, TD-314 | TP-200 | 100-066-687 | | |
| | 400 | | | 200-10 | | | 100-051-563 | | | |
| | 500 | | | 325-10 | YF-1 YET-300-1 | TD-328, TD-315 | TP-325 | 100-051-565 | | |
| | 600 | | | | | | | | | |
| | 4A0296 | 3/0 × 2P | | M12 | 80-L12 | YF-1 YET-300-1 | TD-323, TD-312 | TP-080 | 100-051-558 | |
| 4/0 × 2P | | 100-L12 | TD-324, TD-312 | | TP-100 | | 100-051-560 | | | |
| 250 × 2P | | 150-L12 | TD-325, TD-313 | | TP-150 | | 100-051-562 | | | |
| 300 × 2P | | 180-L12 | TD-327, TD-314 | | TP-200 | | 100-066-688 | | | |
| – | | 350 × 2P | | | | | 180-12 | 100-066-689 | | |
| 350 | | – | | | | | R200-12 | 100-051-275 | | |
| 400 | | 325-12 | YF-1 YET-300-1 | | TD-328, TD-315 | | TP-325 | 100-051-277 | | |
| 500 | | | | | | | | | | |
| 600 | | | | | | | | | | |
| 4A0362 | 3/0 × 2P | | M12 | 80-L12 | YF-1 YET-300-1 | TD-323, TD-312 | TP-080 | 100-051-558 | | |
| | 4/0 × 2P | | | 100-L12 | | TD-324, TD-312 | TP-100 | 100-051-560 | | |
| | 250 × 2P | | | 150-L12 | | TD-325, TD-313 | TP-150 | 100-051-562 | | |
| | 300 × 2P | | | 180-L12 | | TD-327, TD-314 | TP-200 | 100-066-688 | | |
| | 350 × 2P | | | 200-L12 | | | | 100-051-564 | | |
| | 400 × 2P | | | 325-12 | | YF-1 YET-300-1 | TD-328, TD-315 | TP-325 | 100-051-277 | |
| | 500 | | | | | | | | | |
| | 600 | | | | | | | | | |
| 4A0414 | 4/0 × 2P | | M12 | 100-L12 | YF-1 YET-300-1 | TD-324, TD-312 | TP-100 | 100-051-560 | | |
| | 250 × 2P | | | 150-L12 | | TD-325, TD-313 | TP-150 | 100-051-562 | | |
| | 300 × 2P | | | | | | | | | |
| 4A0515 | 3/0 × 4P | 3/0 × 4P | M12 | 80-L12 | YF-1 YET-300-1 | TD-323, TD-312 | TP-080 | 100-051-558 | | |
| | 4/0 × 4P | 4/0 × 4P | | 100-L12 | | TD-324, TD-312 | TP-100 | 100-051-560 | | |
| | 250 × 4P | | | 150-L12 | | YF-1 YET-300-1 | TD-325, TD-313 | TP-150 | 100-051-562 | |
| | 300 × 2P | | | | | | | | | |

D.3 UL and CSA Standards

| Drive Model | Wire Gauge (AWG, kcmil) | | Screw Size | Crimp Terminal Model Number | Tool | | Insulation Cap Model No. | Code <1> |
|-------------|-------------------------|------------------|------------|-----------------------------|-------------------|-------------------|--------------------------|-------------|
| | R/L1, S/L2, T/L3 | U/T1, V/T2, W/T3 | | | Machine No. | Die Jaw | | |
| 4A0675 | 4/0 × 4P | | M12 | 100-L12 | YF-1 YET-300-1 | TD-324, TD-312 | TP-100 | 100-051-560 |
| | 250 × 4P | | | 150-L12 | | TD-325, TD-313 | TP-150 | 100-051-562 |
| | 300 × 4P | | | | | | | |
| 4A0930 | 3/0 × 8P | | M12 | 80-L12 | YF-1 YET-300-1 | TD-323, TD-312 | TP-080 | 100-051-558 |
| | 4/0 × 8P | | | 100-L12 | | TD-324, TD-312 | TP-100 | 100-051-560 |
| | 250 × 8P | | | 150-L12 | | TD-325, TD-313 | TP-150 | 100-051-562 |
| | 300 × 8P | | | | | | | |
| 4A1200 | 4/0 × 8P | | M12 | 100-L12 | YF-1 YET-300-1 | TD-324, TD-312 | TP-100 | 100-051-560 |
| | 250 × 8P | | | 150-L12 | | TD-325, TD-313 | TP-150 | 100-051-562 |
| | 300 × 8P | | | | | | | |

<1> Codes refer to a set of three crimp terminals and three insulation caps. Prepare input and output wiring using two sets for each connection.

Example 1: Models with 300 kcmil for both input and output require one set for input terminals and one set for output terminals, so the user should order two sets of [100-051-272].

Example 2: Models with 4/0 AWG × 2P for both input and output require two sets for input terminals and two sets for output terminals, so the user should order four sets of [100-051-560].

Note: Use crimp insulated terminals or insulated shrink tubing for wiring connections. Wires should have a continuous maximum allowable temperature of 75 °C 600 Vac UL-approved vinyl-sheathed insulation.

Input Fuse Installation

Yaskawa recommends installing one of the following types of branch circuit protection to maintain compliance with UL508C. Semiconductor protective type fuses are preferred. Alternate branch circuit protection devices are also listed in [Table 8.3](#).

Table D.8 Factory Recommended AC Drive Branch Circuit Protection (Normal Duty)

| Drive Model | Nominal Output Power HP | AC Drive Input Amps | MCCB Rating Amps <1> | Time Delay Fuse Rating Amps <2> | Non-time Delay Fuse Rating Amps <3> | Bussman Semiconductor Fuse Rating (Fuse Ampere) <4> |
|--------------------|-------------------------|---------------------|----------------------|---------------------------------|-------------------------------------|---|
| 200 V Class | | | | | | |
| 2A0004 | 0.75 | 3.9 | 15 | 6.25 | 10 | FWH-70B (70) |
| 2A0006 | 1 - 1.5 | 7.3 | 15 | 12 | 20 | FWH-70B (70) |
| 2A0008 | 2 | 8.8 | 15 | 15 | 25 | FWH-70B (70) |
| 2A0010 | 3 | 10.8 | 20 | 17.5 | 30 | FWH-70B (70) |
| 2A0012 | 3 | 13.9 | 25 | 20 | 40 | FWH-70B (70) |
| 2A0018 | 5 | 18.5 | 35 | 30 | 50 | FWH-90B (90) |
| 2A0021 | 7.5 | 24 | 45 | 40 | 70 | FWH-90B (90) |
| 2A0030 | 10 | 37 | 60 | 60 | 110 | FWH-100B (100) |
| 2A0040 | 15 | 52 | 100 | 90 | 150 | FWH-200B (200) |
| 2A0056 | 20 | 68 | 125 | 110 | 200 | FWH-200B (200) |
| 2A0069 | 25 | 80 | 150 | 125 | 225 | FWH-200B (200) |
| 2A0081 | 30 | 96 | 175 | 150 | 275 | FWH-300A (300) |
| 2A0110 | 40 | 111 | 200 | 175 | 300 | FWH-300A (300) |
| 2A0138 | 50 | 136 | 250 | 225 | 400 | FWH-350A (350) |
| 2A0169 | 60 | 164 | 300 | 250 | 450 | FWH-400A (400) |
| 2A0211 | 75 | 200 | 400 | 350 | 600 | FWH-400A (400) |
| 2A0250 | 100 | 271 | 500 | 450 | 800 | FWH-600A (600) |
| 2A0312 | 125 | 324 | 600 | 500 | 800 | FWH-700A (700) |
| 2A0360 | 150 | 394 | 700 | 600 | 1000 <5> | FWH-800A (800) |
| 2A0415 | 175 | 471 | 900 | 800 | 1400 <5> | FWH-1000A (1000) |

| Drive Model | Nominal Output Power HP | AC Drive Input Amps | MCCB Rating Amps <1> | Time Delay Fuse Rating Amps <2> | Non-time Delay Fuse Rating Amps <3> | Bussman Semi-conductor Fuse Rating (Fuse Ampere) <4> |
|--------------------|-------------------------|---------------------|----------------------|---------------------------------|-------------------------------------|--|
| 400 V Class | | | | | | |
| 4A0002 | 1 | 2.1 | 15 | 3.5 | 6 | FWH-40B (40) |
| 4A0004 | 2 | 4.3 | 15 | 7.5 | 12 | FWH-50B (50) |
| 4A0005 | 3 | 5.9 | 15 | 10 | 17.5 | FWH-70B (70) |
| 4A0007 | 3 | 8.1 | 15 | 12 | 20 | FWH-70B (70) |
| 4A0009 | 5 | 9.4 | 15 | 15 | 25 | FWH-90B (90) |
| 4A0011 | 7.5 | 14 | 25 | 20 | 40 | FWH-90B (90) |
| 4A0018 | 10 | 20 | 40 | 35 | 60 | FWH-80B (80) |
| 4A0023 | 15 | 24 | 45 | 40 | 70 | FWH-100B (100) |
| 4A0031 | 20 | 38 | 75 | 60 | 110 | FWH-125B (125) |
| 4A0038 | 25 | 44 | 75 | 75 | 125 | FWH-200B (200) |
| 4A0044 | 30 | 52 | 100 | 90 | 150 | FWH-250A (250) |
| 4A0058 | 40 | 58 | 100 | 100 | 150 | FWH-250A (250) |
| 4A0072 | 50 | 71 | 125 | 110 | 200 | FWH-250A (250) |
| 4A0088 | 60 | 86 | 150 | 150 | 250 | FWH-250A (250) |
| 4A0103 | 75 | 105 | 200 | 175 | 300 | FWH-250A (250) |
| 4A0139 | 100 | 142 | 250 | 225 | 400 | FWH-350A (350) |
| 4A0165 | 125 | 170 | 300 | 250 | 500 | FWH-400A (400) |
| 4A0208 | 150 | 207 | 400 | 350 | 600 | FWH-500A (500) |
| 4A0250 | 200 | 248 | 450 | 400 | 700 | FWH-600A (600) |
| 4A0296 | 250 | 300 | 600 | 500 | 800 | FWH-700A (700) |
| 4A0362 | 300 | 346 | 600 | 600 | 1000 <5> | FWH-800A (800) |
| 4A0414 | 350 | 410 | 800 | 700 | 1200 <5> | FWH-800A (800) |
| 4A0515 | 400 - 450 | 465 | 900 | 800 | 1350 <5> | FWH-1000A (1000) |
| 4A0675 | 500 - 600 | 657 | 1200 | 1100 <5> | 1800 <5> | FWH-1200A (1200) |
| 4A0930 | 700 - 800 | 922 | Not Applicable | | | FWH-1200A (1200) |
| 4A1200 | 900 - 1000 | 1158 | | | | FWH-1600A (1600) |
| 600 V Class | | | | | | |
| 5A0003 | 2 | 3.6 | 15 | 6.25 | 10 | FWP-50B (50) |
| 5A0004 | 3 | 5.1 | 15 | 8 | 15 | FWP-50B (50) |
| 5A0006 | 5 | 8.3 | 15 | 12 | 20 | FWP-60B (60) |
| 5A0009 | 7.5 | 12 | 20 | 20 | 35 | FWP-60B (60) |
| 5A0011 | 10 | 16 | 30 | 25 | 45 | FWP-70B (70) |
| 5A0017 | 15 | 23 | 40 | 40 | 60 | FWP-100B (100) |
| 5A0022 | 20 | 31 | 60 | 50 | 90 | FWP-100B (100) |
| 5A0027 | 25 | 38 | 75 | 60 | 110 | FWP-125A (125) |
| 5A0032 | 30 | 45 | 75 | 75 | 125 | FWP-125A (125) |
| 5A0041 | 40 | 44 | 75 | 75 | 125 | FWP-175A (175) |
| 5A0052 | 50 | 54 | 100 | 90 | 150 | FWP-175A (175) |
| 5A0062 | 60 | 66 | 125 | 110 | 175 | FWP-250A (250) |
| 5A0077 | 75 | 80 | 150 | 125 | 225 | FWP-250A (250) |
| 5A0099 | 100 | 108 | 175 | 175 | 300 | FWP-250A (250) |
| 5A0125 | 125 | 129 | 225 | 225 | 350 | FWP-350A (350) |
| 5A0145 | 150 | 158 | 300 | 275 | 450 | FWP-350A (350) |
| 5A0192 | 200 | 228 | 400 | 350 | 600 | FWP-600A (600) |
| 5A0242 | 250 | 263 | 500 | 450 | 700 | FWP-600A (600) |

<1> Maximum MCCB Rating is 15 A, or 200 % of drive input current rating, whichever is larger. MCCB voltage rating must be 600 VAC or greater.
 <2> Maximum Time Delay fuse is 175% of drive input current rating. This covers any Class CC, J or T class fuse.

D.3 UL and CSA Standards

- <3> Maximum Non-time Delay fuse is 300% of drive input current rating. This covers any CC, J or T class fuse.
- <4> When using semiconductor fuses, Bussman FWH and FWP are required for UL compliance. Select FWH for 200 V Class and 400 V Class models and FWP fuses for 600 V models.
- <5> Class L fuse is also approved for this rating.

■ Low Voltage Wiring for Control Circuit Terminals

Wire low voltage wires with NEC Class 1 circuit conductors. Refer to national state or local codes for wiring. The external power supply shall be a UL listed Class 2 power supply source or equivalent only.

Table D.9 Control Circuit Terminal Power Supply

| Input / Output | Terminal Signal | Power Supply Specifications |
|-------------------------|----------------------------|---|
| Digital inputs | S1 to S8, SC | Use the internal LVLC power supply of the drive. Use class 2 for external power supply. |
| Analog inputs / outputs | +V, A1, A2, A3, AC, AM, FM | Use the internal LVLC power supply of the drive. Use class 2 for external power supply. |

■ Drive Short Circuit Rating

The drive is suitable for use on a circuit capable of delivering not more than 100,000 RMS symmetrical Amperes, 240 Vac maximum (200 V Class), 480 Vac maximum (400 V Class), and 600 Vac maximum (600 V Class) when protected by Bussmann Type FWH or FWP fuses as specified in [Factory Recommended Branch Circuit Protection](#) on page 542.

◆ CSA Standards Compliance



Figure D.7 CSA Mark

■ CSA for Industrial Control Equipment

The drive is CSA-certified as Industrial Control Equipment Class 3211.

Specifically, the drive is certified to: CAN/CSA C22.2 No. 04-04 and CAN/CSA C22.2 No.14-05.

◆ Drive Motor Overload Protection

Set parameter E2-01 (motor rated current) to the appropriate value to enable motor overload protection. The internal motor overload protection is UL Listed and in accordance with the NEC and CEC.

■ E2-01: Motor Rated Current

Setting Range: Model-dependent

Default Setting: Model-dependent

Parameter E2-01 protects the motor when parameter L1-01 is not set to 0. The default for L1-01 is 1, which enables protection for standard induction motors.

If Auto-Tuning has been performed successfully, the motor data entered to T1-04 is automatically written to parameter E2-01. If Auto-Tuning has not been performed, manually enter the correct motor rated current to parameter E2-01.

■ L1-01: Motor Overload Protection Selection

The drive has an electronic overload protection function (oL1) based on time, output current, and output frequency that protects the motor from overheating. The electronic thermal overload function is UL-recognized, so it does not require an external thermal relay for single motor operation.

This parameter selects the motor overload curve used according to the type of motor applied.

Table D.10 Overload Protection Settings

| Setting | Description | |
|---------|---|---|
| 0 | Disabled | Disabled the internal motor overload protection of the drive. |
| 1 | Standard fan-cooled motor (60 Hz default) | Selects protection characteristics for a standard self-cooled motor with limited cooling capabilities when running below the rated speed. The motor overload detection level (oL1) is automatically reduced when running below the motor rated speed. |
| 2 | Drive duty motor with a speed range of 1:10 | Selects protection characteristics for a motor with self-cooling capability within a speed range of 10:1. The motor overload detection level (oL1) is automatically reduced when running below 1/10 of the motor rated speed. |
| 3 | Vector motor with a speed range of 1:100 | Selects protection characteristics for a motor capable of cooling itself at any speed including zero speed (externally cooled motor). The motor overload detection level (oL1) is constant over the entire speed range. |
| 6 | Standard fan-cooled motor (50 Hz) | Selects protection characteristics for a standard self-cooled motor with limited cooling capabilities when running below the rated speed. The motor overload detection level (oL1) is automatically reduced when running below the motor rated speed. |

When connecting the drive to more than one motor for simultaneous operation, disable the electronic overload protection (L1-01 = 0) and wire each motor with its own motor thermal overload relay.

Enable motor overload protection (L1-01 ≠ 0) when connecting the drive to a single motor, unless another motor overload preventing device is installed. The drive electronic thermal overload function causes an oL1 fault, which shuts off the output of the drive and prevents additional overheating of the motor. The motor temperature is continually calculated while the drive is powered up.

■ L1-02: Motor Overload Protection Time

Setting Range: 0.1 to 5.0 min

Factory Default: 1.0 min

Parameter L1-02 determines how long the motor is allowed to operate before the oL1 fault occurs when the drive is running a hot motor at 60 Hz and at 150% of the full load amp rating (E2-01) of the motor. Adjusting the value of L1-02 can shift the set of oL1 curves up the y axis of the diagram below, but will not change the shape of the curves.

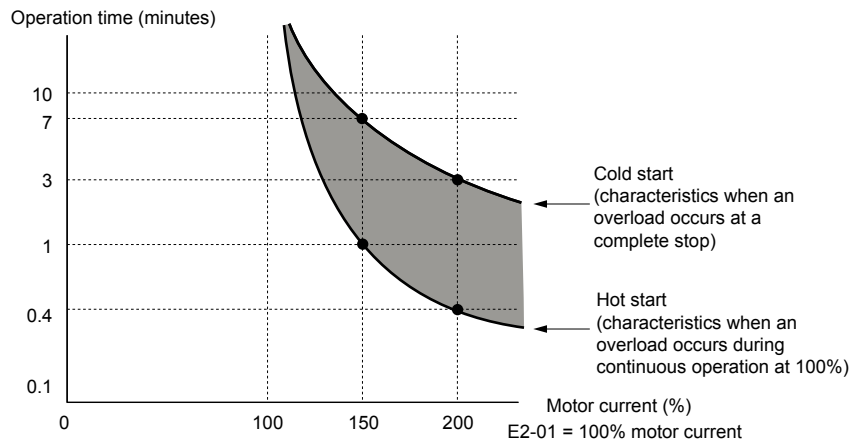


Figure D.8 Motor Overload Protection Time

◆ Precautionary Notes on External Heatsink (IP00/Open Type Enclosure)

When using an external heatsink, UL compliance requires covering exposed capacitors in the main circuit to prevent injury to surrounding personnel.

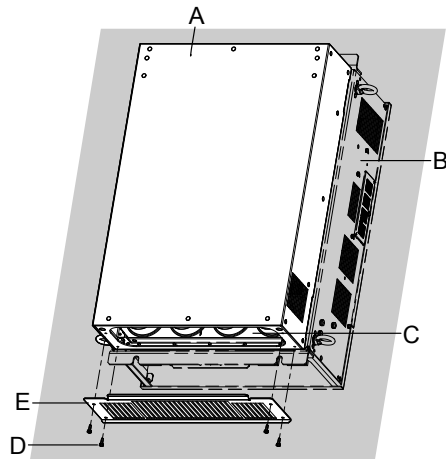
The portion of the external heatsink that projects out can be protected with the enclosure or with the appropriate capacitor cover after completing drive installation. Use [Table D.11](#) to match drive models with available capacitor covers. Order capacitor covers from a Yaskawa representative or directly from the Yaskawa sales department.

Table D.11 Capacitor Cover

| Drive Model | Code Number | Figure | |
|-------------|-----------------|-------------------|--------------------|
| 2A0110 | 100-061-273 | <i>Figure D.9</i> | |
| 2A0138 | 100-061-274 | | |
| 2A0169 | 100-061-275 | | |
| 2A0211 | | | |
| 2A0250 | 100-061-277 | | |
| 2A0312 | | | |
| 2A0360 | 100-061-278 | | |
| 2A0415 | | | |
| 4A0058 | 100-061-273 | | |
| 4A0072 | 100-061-274 | | |
| 4A0088 | 100-061-276 | | |
| 4A0103 | | | |
| 4A0139 | 100-061-275 | | |
| 4A0165 | | | |
| 4A0208 | 100-061-277 | | |
| 4A0250 | 100-061-278 | | |
| 4A0296 | | | |
| 4A0362 | 100-061-279 | | |
| 4A0414 | | | |
| 4A0515 | 100-061-280 | | |
| 4A0675 | | | |
| 4A0930 | 100-061-281 <1> | | <i>Figure D.10</i> |
| 4A1200 | | | |
| 5A0041 | 100-061-274 | <i>Figure D.9</i> | |
| 5A0052 | | | |
| 5A0062 | 100-061-275 | | |
| 5A0077 | | | |
| 5A0099 | 100-061-277 | | |
| 5A0125 | | | |
| 5A0145 | 100-061-278 | | |
| 5A0192 | | | |
| 5A0242 | | | |

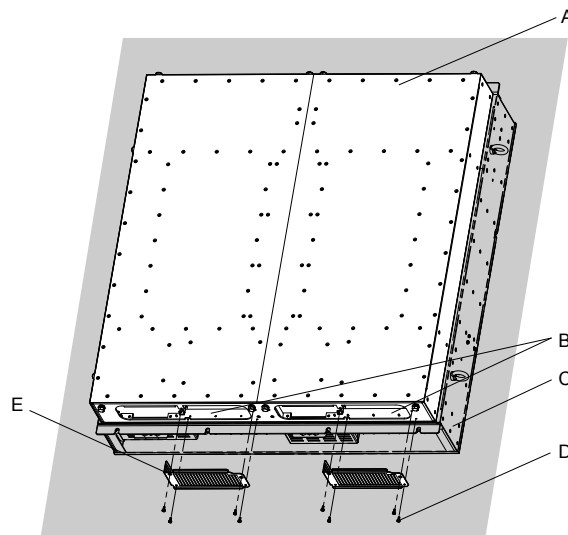
<1> Requires two sets.

Note: Model 4A1200 is UL compliant when the air entering the drive-installed panel or cabinet is 45 °C or cooler. For more information, contact your nearest Yaskawa representative or our sales office.



- A – Drive (outside panel)
- B – Drive (inside panel)
- C – Opening to capacitors
- D – Installation screws
- E – Capacitor cover

Figure D.9 Capacitor Cover



- A – Drive (outside panel)
- B – Opening to capacitors
- C – Drive (inside panel)
- D – Installation screws
- E – Capacitor cover

Figure D.10 Capacitor Cover (Models 4A0930, 4A1200)

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Appendix: E

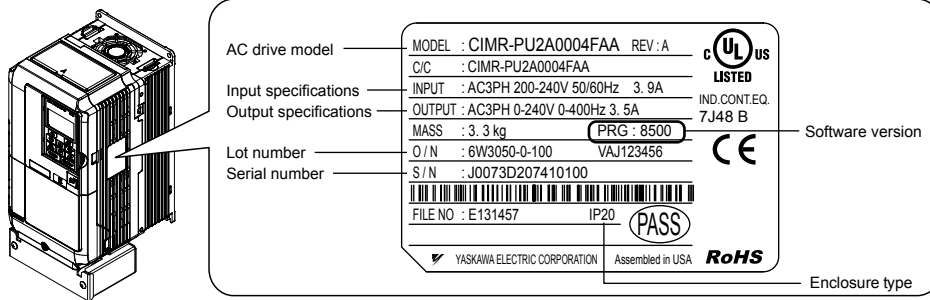
Quick Reference Sheet

This section provides tables to keep record of the drive specifications, motor specifications, and drive settings. Fill in the table data after commissioning the application and have them ready when contacting Yaskawa for technical assistance.

| | | |
|------------|--|------------|
| E.1 | DRIVE AND MOTOR SPECIFICATIONS..... | 570 |
| E.2 | BASIC PARAMETER SETTINGS..... | 571 |
| E.3 | USER SETTING TABLE..... | 573 |

E.1 Drive and Motor Specifications

◆ Drive Specifications



AC drive model — MODEL : CIMR-PU2A0004FAA REV:A
 C/C : CIMR-PU2A0004FAA
 Input specifications — INPUT : AC3PH 200-240V 50/60Hz 3.9A
 Output specifications — OUTPUT : AC3PH 0-240V 0-400Hz 3.5A
 MASS : 3.3 kg PRG : 8500
 Lot number — O/N : 6W3050-0-100 VAJ123456
 Serial number — S/N : J0073D207410100
 FILE NO : E131457 IP20
 YASKAWA ELECTRIC CORPORATION Assembled in USA RoHS

UL LISTED
 IND. CONT. EQ.
 7J48 B
 CE
 Software version
 Enclosure type

| Items | Description |
|------------------------|-------------|
| Model | CIMR-P |
| Serial Number | |
| Software Version (PRG) | |
| Options used | |
| Date of Usage | |

◆ Motor Specifications

■ Induction Motor

| Items | Description | Items | Description |
|-----------------------------|-------------|-------------------------------|-------------|
| Manufacturer | | Motor Rated Current (T1-04) | A |
| Model | | Motor Base Frequency (T1-05) | Hz |
| Motor Rated Power (T1-02) | HP | Number of Motor Poles (T1-06) | |
| Motor Rated Voltage (T1-03) | V | Motor Base Speed (T1-07) | r/min |

Note: These values must be entered as part of the Auto-Tuning process.

■ Motor Speed Encoder (if used)

| Items | Description | Items | Description |
|--------------|-------------|------------|-------------|
| Manufacturer | | Resolution | |
| Interface | | | |

E.2 Basic Parameter Settings

Use the following tables to keep records of important parameters. Have this data available when contacting Yaskawa technical support.

◆ Basic Setup

| Item | Setting Value | Memo |
|----------------------------|---------------|------|
| Frequency Reference Source | b1-01 = | |
| Run Command Source | b1-02 = | |

◆ V/f Pattern Setup

| Item | Setting Value | Memo |
|-----------------------------|---------------|------|
| V/f Pattern Selection | E1-03 = | |
| Max. Output Frequency | E1-04 = | |
| Max. Voltage | E1-05 = | |
| Base Frequency | E1-06 = | |
| Mid. Output Frequency | E1-07 = | |
| Mid. Output Frequency Volt. | E1-08 = | |
| Min. Output Frequency | E1-09 = | |
| Min. Output Frequency Volt. | E1-10 = | |

◆ Motor Setup

| Motor Type | Item | Setting Value | Memo |
|------------|--------------------------|---------------|------|
| Induction | Motor Rated Current | E2-01 = | |
| | Motor Rated Slip | E2-02 = | |
| | Motor No-Load Current | E2-03 = | |
| | No. of Motor Poles | E2-04 = | |
| | Line-to-Line Resistance | E2-05 = | |
| | Motor Leakage Inductance | E2-06 = | |

◆ Multi-Function Digital Inputs

| Terminal | Input Used | Setting Value and Function Name | Memo |
|----------|------------|---------------------------------|------|
| S1 | | H1-01 = | |
| S2 | | H1-02 = | |
| S3 | | H1-03 = | |
| S4 | | H1-04 = | |
| S5 | | H1-05 = | |
| S6 | | H1-06 = | |
| S7 | | H1-07 = | |
| S8 | | H1-08 = | |

E.2 Basic Parameter Settings

◆ Pulse Train Input/Analog Inputs

| Terminal | Input Used | Setting Value and Function Name | Memo |
|----------|------------|---------------------------------|------|
| RP | | H6-01 = | |
| A1 | | H3-02 = | |
| A2 | | H3-10 = | |
| A3 | | H3-06 = | |

◆ Multi-Function Digital Outputs


| Terminal | Output Used | Setting Value and Function Name | Memo |
|----------|-------------|---------------------------------|------|
| M1-M2 | | H2-01 = | |
| M3-M4 | | H2-02 = | |
| MD-ME-MF | | H2-03 = | |

◆ Monitor Outputs

| Terminal | Output Used | Setting Value and Function Name | Memo |
|----------|-------------|---------------------------------|------|
| FM | | H4-01 = | |
| AM | | H4-04 = | |



































E.3 User Setting Table

Use the Verify Menu to determine which parameters have been changed from their original default settings

 below the parameter number indicates that the parameter setting can be changed during run.

| No. | Name | User Setting | No. | Name | User Setting |
|--|--|--------------|--|--|--------------|
| A1-00  | Language Selection | | b3-26 | Direction Determining Level | |
| A1-01  | Access Level Selection | | b3-27 | Start Speed Search Select | |
| A1-03 | Initialize Parameters | | b4-01 | Timer Function On-Delay Time | |
| A1-04 | Password | | b4-02 | Timer Function Off-Delay Time | |
| A1-05 | Password Setting | | b5-01 | PID Function Setting | |
| A1-06 | Application Preset | | b5-02  | Proportional Gain Setting (P) | |
| A2-01 to A2-32 | User Parameters, 1 to 32 | | b5-03  | Integral Time Setting (I) | |
| A2-33 | User Parameter Automatic Selection | | b5-04  | Integral Limit Setting | |
| b1-01 | Frequency Reference Selection 1 | | b5-05  | Derivative Time (D) | |
| b1-02 | Run Command Selection 1 | | b5-06  | PID Output Limit | |
| b1-03 | Stopping Method Selection | | b5-07  | PID Offset Adjustment | |
| b1-04 | Reverse Operation Selection | | b5-08  | PID Primary Delay Time Constant | |
| b1-07 | LOCAL/REMOTE Run Selection | | b5-09 | PID Output Level Selection | |
| b1-08 | Run Command Selection while in Programming Mode | | b5-10  | PID Output Gain Setting | |
| b1-11 | Run Delay Time Setting | | b5-11 | PID Output Reverse Selection | |
| b1-14 | Phase Order Selection | | b5-12 | PID Feedback Loss Detection Selection | |
| b1-15 | Frequency Reference Selection 2 | | b5-13 | PID Feedback Loss Detection Level | |
| b1-16 | Run Command Selection 2 | | b5-14 | PID Feedback Loss Detection Time | |
| b1-17 | Run Command at Power Up | | b5-15 | PID Sleep Function Start Level | |
| b2-01 | DC Injection Braking Start Frequency | | b5-16 | PID Sleep Delay Time | |
| b2-02 | DC Injection Braking Current | | b5-17 | PID Accel/Decel Time | |
| b2-03 | DC Injection Braking Time at Start | | b5-18 | PID Setpoint Selection | |
| b2-04 | DC Injection Braking Time at Stop | | b5-19  </> | PID Setpoint Value | |
| b3-01 | Speed Search Selection at Start | | b5-20 | PID Setpoint Scaling | |
| b3-02 | Speed Search Deactivation Current | | b5-34  | PID Output Lower Limit | |
| b3-03 | Speed Search Deceleration Time | | b5-35  | PID Input Limit | |
| b3-04 | V/f Gain during Speed Search | | b5-36 | PID Feedback High Detection Level | |
| b3-05 | Speed Search Delay Time | | b5-37 | PID Feedback High Detection Time | |
| b3-06 | Output Current 1 during Speed Search | | b5-38 | PID Setpoint User Display | |
| b3-07 | Output Current 2 during Speed Search (Speed Estimation Type) | | b5-39 | PID Setpoint Display Digits | |
| b3-08 | Current Control Gain during Speed Search (Speed Estimation Type) | | b5-40 | Frequency Reference Monitor Content during PID | |
| b3-10 | Speed Search Detection Compensation Gain | | b5-41 | PI Output 2 Unit Selection | |
| b3-12 | Minimum Current Detection Level during Speed Search | | b5-42  | PI Output 2 Calculation Mode | |
| b3-14 | Bi-Directional Speed Search Selection | | | | |
| b3-17 | Speed Search Restart Current Level | | | | |
| b3-18 | Speed Search Restart Detection Time | | | | |
| b3-19 | Number of Speed Search Restarts | | | | |
| b3-24 | Speed Search Method Selection | | | | |
| b3-25 | Speed Search Wait Time | | | | |

E.3 User Setting Table

| No. | Name | User Setting | No. | Name | User Setting |
|---|---|--------------|---|---|--------------|
|  b5-43 | PI Output 2 Monitor Max Upper 4 Digits | | C3-03 | Slip Compensation Limit | |
|  b5-44 | PI Output 2 Monitor Max Lower 4 Digits | | C3-04 | Slip Compensation Selection during Regeneration | |
|  b5-45 | PI Output 2 Monitor Minimum | |  C4-01 | Torque Compensation Gain | |
| b5-46 | PID Units Selection | |  C4-02 | Torque Compensation Primary Delay Time | |
| b5-47 | Reverse Operation Selection 2 by PID Output | | C6-02 | Carrier Frequency Selection | |
|  b5-89 | Sleep Method Selection | | C6-03 | Carrier Frequency Upper Limit | |
| b5-90 | EZ Sleep Unit | | C6-04 | Carrier Frequency Lower Limit | |
|  b5-91 | EZ Minimum Speed | | C6-05 | Carrier Frequency Proportional Gain | |
|  b5-92 | EZ Sleep Level | |  d1-01 | Frequency Reference 1 | |
|  b5-93 | EZ Sleep Time | |  d1-02 | Frequency Reference 2 | |
|  b5-94 | EZ Wake-up Level | |  d1-03 | Frequency Reference 3 | |
| b5-95 | EZ Wake-up Mode | |  d1-04 | Frequency Reference 4 | |
|  b5-96 | EZ Wake-up Time | |  d1-05 | Frequency Reference 5 | |
| b6-01 | Dwell Reference at Start | |  d1-06 | Frequency Reference 6 | |
| b6-02 | Dwell Time at Start | |  d1-07 | Frequency Reference 7 | |
| b6-03 | Dwell Reference at Stop | |  d1-08 | Frequency Reference 8 | |
| b6-04 | Dwell Time at Stop | |  d1-09 | Frequency Reference 9 | |
| b8-01 | Energy Saving Control Selection | |  d1-10 | Frequency Reference 10 | |
| b8-04 | Energy Saving Coefficient Value | |  d1-11 | Frequency Reference 11 | |
| b8-05 | Power Detection Filter Time | |  d1-12 | Frequency Reference 12 | |
| b8-06 | Search Operation Voltage Limit | |  d1-13 | Frequency Reference 13 | |
|  C1-01 | Acceleration Time 1 | |  d1-14 | Frequency Reference 14 | |
|  C1-02 | Deceleration Time 1 | |  d1-15 | Frequency Reference 15 | |
|  C1-03 | Acceleration Time 2 | |  d1-16 | Frequency Reference 16 | |
|  C1-04 | Deceleration Time 2 | |  d1-17 | Jog Frequency Reference | |
|  C1-09 | Fast-Stop Time | | d2-01 | Frequency Reference Upper Limit | |
| C1-10 | Accel/Decel Time Setting Units | | d2-02 | Frequency Reference Lower Limit | |
| C1-11 | Accel/Decel Time Switching Frequency | | d2-03 | Master Speed Reference Lower Limit | |
| C2-01 | S-Curve Characteristic at Accel Start | | d3-01 | Jump Frequency 1 | |
| C2-02 | S-Curve Characteristic at Accel End | | d3-02 | Jump Frequency 2 | |
| C2-03 | S-Curve Characteristic at Decel Start | | d3-03 | Jump Frequency 3 | |
| C2-04 | S-Curve Characteristic at Decel End | | | | |
|  C3-01 | Slip Compensation Gain | | | | |
|  C3-02 | Slip Compensation Primary Delay Time | | | | |
















| No. | Name | User Setting | No. | Name | User Setting |
|--|---|--------------|-------|--|--------------|
| d3-04 | Jump Frequency Width | | F6-01 | Communications Error Operation Selection | |
| d4-01 | Frequency Reference Hold Function Selection | | F6-02 | External Fault from Comm. Option Detection Selection | |
| d4-03  | Frequency Reference Bias Step (Up/Down 2) | | F6-03 | External Fault from Comm. Option Operation Selection | |
| d4-04  | Frequency Reference Bias Accel/Decel (Up/Down 2) | | F6-04 | bUS Error Detection Time | |
| d4-05  | Frequency Reference Bias Operation Mode Selection (Up/Down 2) | | F6-07 | Multi-Step Speed Enable/Disable Selection when NefRef/ComRef is Selected | |
| d4-06 | Frequency Reference Bias (Up/Down 2) | | F6-08 | Reset Communication Parameters | |
| d4-07  | Analog Frequency Reference Fluctuation Limit (Up/Down 2) | | F6-10 | CC-Link Node Address | |
| d4-08  | Frequency Reference Bias Upper Limit (Up/Down 2) | | F6-11 | CC-Link Communications Speed | |
| d4-09  | Frequency Reference Bias Lower Limit (Up/Down 2) | | F6-14 | CC-Link bUS Error Auto Reset | |
| d4-10 | Up/Down Frequency Reference Limit Selection | | F6-20 | MECHATROLINK Station Address | |
| d6-01 | Field Weakening Level | | F6-21 | MECHATROLINK Frame Size | |
| d6-02 | Field Weakening Frequency Limit | | F6-22 | MECHATROLINK Link Speed | |
| E1-01 | Input Voltage Setting | | F6-23 | MECHATROLINK Monitor Selection (E) | |
| E1-03 | V/f Pattern Selection | | F6-24 | MECHATROLINK Monitor Selection (F) | |
| E1-04 | Maximum Output Frequency | | F6-25 | Operation Selection at Watchdog Timer Error (E5) | |
| E1-05 | Maximum Voltage | | F6-26 | MECHATROLINK bUS Errors Detected | |
| E1-06 | Base Frequency | | F6-30 | PROFIBUS-DP Node Address | |
| E1-07 | Middle Output Frequency | | F6-31 | PROFIBUS-DP Clear Mode Selection | |
| E1-08 | Middle Output Frequency Voltage | | F6-32 | PROFIBUS-DP Data Format Selection | |
| E1-09 | Minimum Output Frequency | | F6-35 | CANopen Node ID Selection | |
| E1-10 | Minimum Output Frequency Voltage | | F6-36 | CANopen Communication Speed | |
| E1-11 | Middle Output Frequency 2 | | F6-50 | DeviceNet MAC Address | |
| E1-12 | Middle Output Frequency Voltage 2 | | F6-51 | DeviceNet Communication Speed | |
| E1-13 | Base Voltage | | F6-52 | DeviceNet PCA Setting | |
| E2-01 | Motor Rated Current | | F6-53 | DeviceNet PPA Setting | |
| E2-02 | Motor Rated Slip | | F6-54 | DeviceNet Idle Mode Fault Detection | |
| E2-03 | Motor No-Load Current | | F6-55 | DeviceNet Baud Rate Monitor | |
| E2-04 | Number of Motor Poles | | F6-56 | DeviceNet Speed Scaling | |
| E2-05 | Motor Line-to-Line Resistance | | F6-57 | DeviceNet Current Scaling | |
| E2-06 | Motor Leakage Inductance | | F6-58 | DeviceNet Torque Scaling | |
| E2-10 | Motor Iron Loss for Torque Compensation | | F6-59 | DeviceNet Power Scaling | |
| E2-11 | Motor Rated Power | | F6-60 | DeviceNet Voltage Scaling | |
| F4-01 | Terminal V1 Monitor Selection | | F6-61 | DeviceNet Time Scaling | |
| F4-02  | Terminal V1 Monitor Gain | | F6-62 | DeviceNet Heartbeat Interval | |
| F4-03 | Terminal V2 Monitor Selection | | F6-63 | DeviceNet Network MAC ID | |
| F4-04  | Terminal V2 Monitor Gain | | H1-01 | Multi-Function Digital Input Terminal S1 Function Selection | |
| F4-05  | Terminal V1 Monitor Bias | | H1-02 | Multi-Function Digital Input Terminal S2 Function Selection | |
| F4-06  | Terminal V2 Monitor Bias | | H1-03 | Multi-Function Digital Input Terminal S3 Function Selection | |
| F4-07 | Terminal V1 Signal Level | | H1-04 | Multi-Function Digital Input Terminal S4 Function Selection | |
| F4-08 | Terminal V2 Signal Level | | H1-05 | Multi-Function Digital Input Terminal S5 Function Selection | |
| | | | H1-06 | Multi-Function Digital Input Terminal S6 Function Selection | |
| | | | H1-07 | Multi-Function Digital Input Terminal S7 Function Selection | |

E.3 User Setting Table

| No. | Name | User Setting | No. | Name | User Setting |
|--|---|--------------|--|--|--------------|
| H1-08 | Multi-Function Digital Input Terminal S8 Function Selection | | H5-06 | Drive Transmit Wait Time | |
| H2-01 | Multi-Function Contact Output (terminal M1-M2) | | H5-07 | RTS Control Selection | |
| H2-02 | Multi-Function Contact Output 2 (terminal M3-M4) | | H5-09 | CE Detection Time | |
| H2-03 | Multi-Function Contact Output (terminal MD-ME-MF) | | H5-10 | Unit Selection for MEMOBUS/Modbus Register 0025H | |
| H2-06 | Watt Hour Output Unit Selection | | H5-11 | Communications ENTER Function Selection | |
| H3-01 | Terminal A1 Signal Level Selection | | H5-12 | Run Command Method Selection | |
| H3-02 | Terminal A1 Function Selection | | H6-01 | Pulse Train Input Terminal RP Function Selection | |
| H3-03  | Terminal A1 Gain Setting | | H6-02  | Pulse Train Input Scaling | |
| H3-04  | Terminal A1 Bias Setting | | H6-03  | Pulse Train Input Gain | |
| H3-05 | Terminal A3 Signal Level Selection | | H6-04  | Pulse Train Input Bias | |
| H3-06 | Terminal A3 Function Selection | | H6-05  | Pulse Train Input Filter Time | |
| H3-07  | Terminal A3 Gain Setting | | H6-08 | Pulse Train Input Minimum Frequency | |
| H3-08  | Terminal A3 Bias Setting | | L1-01 | Motor Overload Protection Selection | |
| H3-09 | Terminal A2 Signal Level Selection | | L1-02 | Motor Overload Protection Time | |
| H3-10 | Terminal A2 Function Selection | | L1-03 | Motor Overheat Alarm Operation Selection (PTC input) | |
| H3-11  | Terminal A2 Gain Setting | | L1-04 | Motor Overheat Fault Operation Selection (PTC input) | |
| H3-12  | Terminal A2 Bias Setting | | L1-05 | Motor Temperature Input Filter Time (PTC input) | |
| H3-13 | Analog Input Filter Time Constant | | L1-13 | Continuous Electrothermal Operation Selection | |
| H3-14 | Analog Input Terminal Enable Selection | | L1-15 | Motor 1 Thermistor Selection (NTC) | |
| H3-16 | Terminal A1 Offset | | L1-16 | Motor 1 Overheat Temperature | |
| H3-17 | Terminal A2 Offset | | L1-20 | Operation at Motor Overheat (oH5) | |
| H3-18 | Terminal A3 Offset | | L2-01 | Momentary Power Loss Operation Selection | |
| H4-01 | Multi-Function Analog Output Terminal FM Monitor Selection | | L2-02 | Momentary Power Loss Ride-Thru Time | |
| H4-02  | Multi-Function Analog Output Terminal FM Gain | | L2-03 | Momentary Power Loss Minimum Baseblock Time | |
| H4-03  | Multi-Function Analog Output Terminal FM Bias | | L2-04 | Momentary Power Loss Voltage Recovery Ramp Time | |
| H4-04 | Multi-Function Analog Output Terminal AM Monitor Selection | | L2-05 | Undervoltage Detection Level (Uv1) | |
| H4-05  | Multi-Function Analog Output Terminal AM Gain | | L2-06 | KEB Deceleration Time | |
| H4-06  | Multi-Function Analog Output Terminal AM Bias | | L2-07 | KEB Acceleration Time | |
| H4-07 | Multi-Function Analog Output Terminal FM Signal Level Selection | | L2-08 | Frequency Gain at KEB Start | |
| H4-08 | Multi-Function Analog Output Terminal AM Signal Level Selection | | L2-10 | KEB Detection Time (Minimum KEB Time) | |
| H5-01 | Drive Node Address | | L2-11 | DC Bus Voltage Setpoint during KEB | |
| H5-02 | Communication Speed Selection | | L2-29 | KEB Method Selection | |
| H5-03 | Communication Parity Selection | | L3-01 | Stall Prevention Selection during Acceleration | |
| H5-04 | Stopping Method After Communication Error (CE) | | L3-02 | Stall Prevention Level during Acceleration | |
| H5-05 | Communication Fault Detection Selection | | L3-03 | Stall Prevention Limit during Acceleration | |
| | | | L3-04  | Stall Prevention Selection during Deceleration | |
| | | | L3-05 | Stall Prevention Selection during Run | |
| | | | L3-06 | Stall Prevention Level during Run | |
| | | | L3-11 | Overvoltage Suppression Function Selection | |
| | | | L3-17 | Target DC Bus Voltage for Overvoltage Suppression and Stall Prevention | |
| | | | L3-20 | DC Bus Voltage Adjustment Gain | |
| | | | L3-21 | Accel/Decel Rate Calculation Gain | |

| No. | Name | User Setting | No. | Name | User Setting |
|-------|---|--------------|-------|---|--------------|
| L3-23 | Automatic Reduction Selection for Stall Prevention during Run | | n1-01 | Hunting Prevention Selection | |
| L3-24 | Motor Acceleration Time for Inertia Calculations | | n1-02 | Hunting Prevention Gain Setting | |
| L3-25 | Load Inertia Ratio | | n1-03 | Hunting Prevention Time Constant | |
| L3-26 | Additional DC Bus Capacitors | | n1-05 | Hunting Prevention Gain while in Reverse | |
| L3-27 | Stall Prevention Detection Time | | n3-01 | High-Slip Braking Deceleration Frequency Width | |
| L4-01 | Speed Agreement Detection Level | | n3-02 | High-Slip Braking Current Limit | |
| L4-02 | Speed Agreement Detection Width | | n3-03 | High-Slip Braking Dwell Time at Stop | |
| L4-03 | Speed Agreement Detection Level (+/-) | | n3-04 | High-Slip Braking Overload Time | |
| L4-04 | Speed Agreement Detection Width (+/-) | | n3-13 | Overexcitation Deceleration Gain | |
| L4-05 | Frequency Reference Loss Detection Selection | | n3-14 | High Frequency Injection during Overexcitation Deceleration | |
| L4-06 | Frequency Reference at Reference Loss | | n3-21 | High-Slip Suppression Current Level | |
| L4-07 | Speed Agreement Detection Selection | | n3-23 | Overexcitation Operation Selection | |
| L5-01 | Number of Auto Restart Attempts | | o1-01 |  Drive Mode Unit Monitor Selection | |
| L5-02 | Auto Restart Fault Output Operation Selection | | o1-02 |  User Monitor Selection After Power Up | |
| L5-04 | Fault Reset Interval Time | | o1-03 | Digital Operator Display Selection | |
| L5-05 | Fault Reset Operation Selection | | o1-06 | User Monitor Selection Mode | |
| L6-01 | Torque Detection Selection 1 | | o1-07 | Second Line Monitor Selection | |
| L6-02 | Torque Detection Level 1 | | o1-08 | Third Line Monitor Selection | |
| L6-03 | Torque Detection Time 1 | | o1-09 | Frequency Reference Display Units | |
| L6-04 | Torque Detection Selection 2 | | o1-10 | User-Set Display Units Maximum Value | |
| L6-05 | Torque Detection Level 2 | | o1-11 | User-Set Display Units Decimal Display | |
| L6-06 | Torque Detection Time 2 | | o1-13 | Frequency Reference and Frequency Related Monitor Custom Units 1 | |
| L6-13 | Motor Underload Protection Selection | | o1-14 | Frequency Reference and Frequency Related Monitor Custom Units 2 | |
| L6-14 | Motor Underload Protection Level at Minimum Frequency | | o1-15 | Frequency Reference and Frequency Related Monitor Custom Units 3 | |
| L8-01 | Internal Dynamic Braking Resistor Protection Selection (ERF type) | | o2-01 | LO/RE Key Function Selection | |
| L8-02 | Overheat Alarm Level | | o2-02 | STOP Key Function Selection | |
| L8-03 | Overheat Pre-Alarm Operation Selection | | o2-03 | User Parameter Default Value | |
| L8-05 | Input Phase Loss Protection Selection | | o2-04 | Drive Model Selection | |
| L8-07 | Output Phase Loss Protection | | o2-05 | Frequency Reference Setting Method Selection | |
| L8-09 | Output Ground Fault Detection Selection | | o2-06 | Operation Selection when Digital Operator is Disconnected | |
| L8-10 | Heatsink Cooling Fan Operation Selection | | o2-07 | Motor Direction at Power Up when Using Operator | |
| L8-11 | Heatsink Cooling Fan Off Delay Time | | o2-20 |  Operator RUN Save at Power Loss | |
| L8-12 | Ambient Temperature Setting | | o3-01 | Copy Function Selection | |
| L8-15 | oL2 Characteristics Selection at Low Speeds | | o3-02 | Copy Allowed Selection | |
| L8-18 | Software Current Limit Selection | | o4-01 | Cumulative Operation Time Setting | |
| L8-19 | Frequency Reduction Rate during Overheat Pre-Alarm | | o4-02 | Cumulative Operation Time Selection | |
| L8-32 | Main Contactor and Cooling Fan Power Supply Failure Selection | | o4-03 | Cooling Fan Maintenance Operation Time Setting | |
| L8-35 | Installation Method Selection | | o4-05 | Capacitor Maintenance Setting | |
| L8-38 | Carrier Frequency Reduction Selection | | o4-07 | DC Bus Pre-charge Relay Maintenance Setting | |
| L8-40 | Carrier Frequency Reduction Off-Delay Time | | o4-09 | IGBT Maintenance Setting | |
| L8-41 | High Current Alarm Selection | | o4-11 | U2, U3 Initialize Selection | |
| L8-55 | Internal Braking Transistor Protection | | o4-12 | kWh Monitor Initialization | |
| L8-78 | Power Unit Output Phase Loss Protection | | o4-13 | Number of Run Commands Counter Initialization | |
| L8-93 | LSO Detection Time at Low Speed | | | | |
| L8-94 | LSO Detection Level at Low Speed | | | | |
| L8-95 | Average LSO Frequency at Low Speed | | | | |

E.3 User Setting Table

| No. | Name | User Setting | No. | Name | User Setting |
|---|---|--------------|---|---|--------------|
| o4-17 | Set/Reset Real-Time Clock | | S3-05 | Secondary PI Setpoint Value | |
| o4-20 | Time Display Format | |  S3-06 | Secondary PI Proportional Gain Setting | |
| S1-01 | Stillness Control Selection | |  S3-07 | Secondary PI Integral Time Setting | |
| S1-02 | Voltage Reduction Rate | |  S3-08 | Secondary PI Integral Limit Setting | |
| S1-03 | Voltage Restoration Level | |  S3-09 | Secondary PI Output Upper Limit | |
| S1-04 | Voltage Restoration Complete Level | |  S3-10 | Secondary PI Output Lower Limit | |
| S1-05 | Voltage Restoration Sensitivity Time Constant | |  S3-11 | Secondary PI Output Level Selection | |
| S1-06 | Voltage Restoration Time Constant at Impact | |  S3-12 | Secondary PI Disable Mode | |
| S1-07 | Output Phase Loss Level for Dynamic Noise Control | |  S3-13 | Secondary PI Low Feedback Detection Level | |
| S2-01 | Sequence Timer 1 Start Time | |  S3-14 | Secondary PI Low Feedback Detection Time | |
| S2-02 | Sequence Timer 1 Stop Time | |  S3-15 | Secondary PI High Feedback Level | |
| S2-03 | Sequence Timer 1 Day Selection | |  S3-16 | Secondary PI High Feedback Detection Time | |
| S2-04 | Sequence Timer 1 Selection | |  S3-17 | Secondary PI Feedback Detection Selection | |
| S2-05 | Sequence Timer 1 Reference Source | | S6-01 | Emergency Override Speed | |
| S2-06 | Sequence Timer 2 Start Time | | S6-02 | Emergency Override Reference Selection | |
| S2-07 | Sequence Timer 2 Stop Time | | S6-07 | Output Phase Loss Level for Dynamic Noise Control | |
| S2-08 | Sequence Timer 2 Day Selection | | T1-01 | Auto-Tuning Mode Selection | |
| S2-09 | Sequence Timer 2 Selection | | T1-02 | Motor Rated Power | |
| S2-10 | Sequence Timer 2 Reference Source | | T1-03 | Motor Rated Voltage | |
| S2-11 | Sequence Timer 3 Start Time | | T1-04 | Motor Rated Current | |
| S2-12 | Sequence Timer 3 Stop Time | | T1-05 | Motor Base Frequency | |
| S2-13 | Sequence Timer 3 Day Selection | | T1-06 | Number of Motor Poles | |
| S2-14 | Sequence Timer 3 Selection | | T1-07 | Motor Base Speed | |
| S2-15 | Sequence Timer 3 Reference Source | | T1-11 | Motor Iron Loss | |
| S2-16 | Sequence Timer 4 Start Time | | | | |
| S2-17 | Sequence Timer 4 Stop Time | | | | |
| S2-18 | Sequence Timer 4 Day Selection | | | | |
| S2-19 | Sequence Timer 4 Selection | | | | |
| S2-20 | Sequence Timer 4 Reference Source | | | | |
|  S3-01 | Secondary PI Enable Selection | | | | |
|  S3-02 | Secondary PI User Display | | | | |
|  S3-03 | Secondary PI Display Digits | | | | |
|  S3-04 | Secondary PI Unit Selection | | | | |

<1> Not available in models 4A0930 and 4A1200.

<2> Parameter setting cannot be changed while the drive is operating the motor in models 4A0930 and 4A1200.

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Industrial Fan and Pump Drive

Technical Manual

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