Doc no. LEC*-OMY0116-B NN28978903



Operation Manual

PRODUCT NAME

AC Servo Motor Driver (CC-Link Type)

MODEL/ Series

LECSC2-T Series



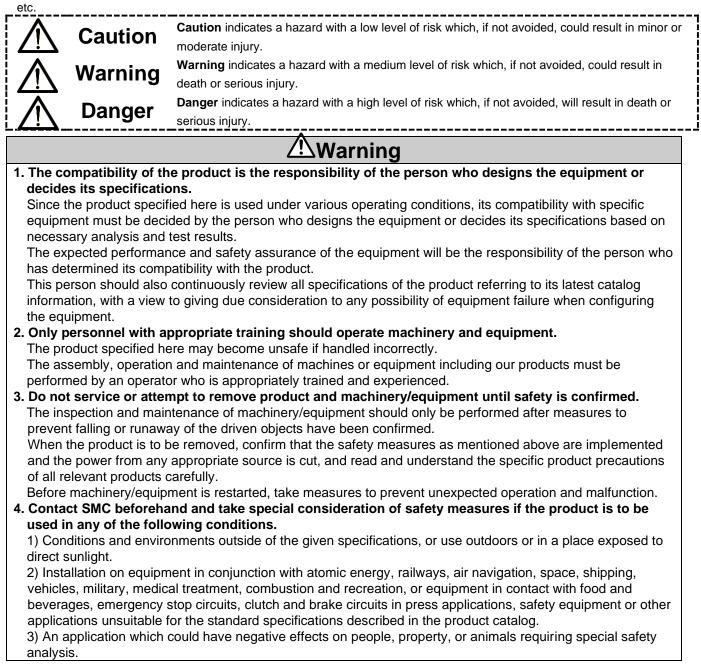
SMC Corporation



LECSC2-TD Series / Driver 1. Safety Instructions

These safety instructions are intended to prevent hazardous situations and/or equipment damage. These instructions indicate the level of potential hazard with the labels of "Caution," "Warning" or "Danger." They are all important notes for safety and must be followed in addition to International Standards (ISO/IEC) *1), and other safety regulations.

- *1) ISO 4414: Pneumatic fluid power -- General rules relating to systems
- ISO 4413: Hydraulic fluid power -- General rules relating to systems
 - IEC 60204-1: Safety of machinery -- Electrical equipment of machines (Part 1: General requirements)
 - ISO 10218: Manipulating industrial robots -- Safety

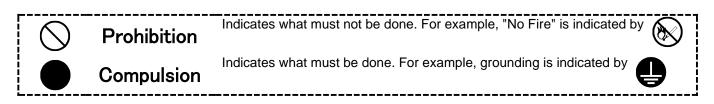




4) Use in an interlock circuit, which requires the provision of double interlock for possible failure by using a mechanical protective function, and periodical checks to confirm proper operation.

Note that the CAUTION level may lead to a serious consequence according to conditions. Please follow the instructions of both levels because they are important to personnel safety.

What must not be done and what must be done are indicated by the following diagrammatic symbols.



In this Instruction Manual, instructions at a lower level than the above, instructions for other functions, and so on are classified into "POINT".

After reading this installation guide, always keep it accessible to the operator.





LECSC2-T Series / Driver 1. Safety Instructions Caution

The product is provided for use in manufacturing industries.

The product herein described is basically provided for peaceful use in manufacturing industries. If considering using the product in other industries, consult SMC beforehand and exchange specifications or a contract if necessary.

If anything is unclear, contact your nearest sales branch.

Limited warranty and Disclaimer/Compliance Requirements

The product used is subject to the following "Limited warranty and Disclaimer" and "Compliance Requirements".

Read and accept them before using the product.

Limited warranty and Disclaimer

The warranty period of the product is 1 year in service or 1.5 years after the product is delivered, whichever is first.*3)

Also, the product may have specified durability, running distance or replacement parts. Please consult your nearest sales branch.

For any failure or damage reported within the warranty period which is clearly our responsibility, a replacement product or necessary parts will be provided.

This limited warranty applies only to our product independently, and not to any other damage incurred due to the failure of the product.

Prior to using SMC products, please read and understand the warranty terms and disclaimers noted in the specified catalog for the particular products.

*3) Vacuum pads are excluded from this 1 year warranty.

A vacuum pad is a consumable part, so it is warranted for a year after it is delivered. Also, even within the warranty period, the wear of a product due to the use of the vacuum pad or failure due to the deterioration of rubber material are not covered by the limited warranty.

Compliance Requirements

When the product is exported, strictly follow the laws required by the Ministry of Economy, Trade and Industry (Foreign Exchange and Foreign Trade Control Law).



1. To prevent electric shock, note the following

\land WARNING

- Before wiring or inspection, turn off the power and wait for 15 minutes or more until the charge lamp turns off. Then, confirm that the voltage between P(+) and N(-) is safe with a voltage tester and others. Otherwise, an electric shock may occur. In addition, always confirm from the front of the driver, whether the charge lamp is off or not.
- · Ground the driver and servo motor securely.
- Any person who is involved in wiring and inspection should be fully competent to do the work.
- Do not attempt to wire the driver and servo motor until they have been installed. Otherwise, you may get an electric shock.
- The cables should not be damaged, stressed, loaded, or pinched. Otherwise, you may get an electric shock.
- During power-on or operation, do not open the front cover of the driver. Otherwise, it may cause an electric shock.
- Do not operate the driver with the front cover removed. High-voltage terminals and charging area are exposed and you may get an electric shock.
- Except for wiring or periodic inspection, do not remove the front cover even of the driver if the power is off. The driver is charged and you may get an electric shock.
- To prevent an electric shock, always connect the protective earth (PE) terminal (marked) of the driver to the protective earth (PE) of the cabinet.
- To avoid an electric shock, insulate the connections of the power supply terminals.

2. To prevent fire, note the following

- Install the driver, servo motor, and regenerative resistor on incombustible material. Installing them directly or close to combustibles will lead to smoke or a fire.
- Always connect a magnetic contactor between the power supply and the main circuit power supply (L1/L2/L3) of the driver, in order to configure a circuit that shuts down the power supply on the side of the driver's power supply. If a magnetic contactor is not connected, continuous flow of a large current may cause smoke or a fire when the driver malfunctions.
- Not doing so may cause a fire when a regenerative transistor malfunctions or the like may overheat the regenerative resistor.
- Always connect a molded-case circuit breaker, or a fuse to each driver between the power supply and the main circuit power supply (L1/L2/L3) of the driver, in order to configure a circuit that shuts down the power supply on the side of the driver's power supply. If a molded-case circuit breaker or fuse is not connected, continuous flow of a large current may cause smoke or a fire when the driver malfunctions.
- When using the regenerative resistor, switch power off with the alarm signal.
- Provide adequate protection to prevent screws and other conductive matter, oil and other combustible matter from entering the driver and servo motor.



3. To prevent injury, note the follow

- Only the power/signal specified in the Instruction Manual should be applied to each terminal. Otherwise, it may cause an electric shock, fire, injury, etc.
- Connect cables to the correct terminals. Otherwise, a burst, damage, etc., may occur.
- Ensure that polarity (+/-) is correct. Otherwise, a burst, damage, etc., may occur.
- The driver heat sink, regenerative resistor, servo motor, etc., may be hot while the power is on and for some time after power-off. Take safety measures such as providing covers to avoid accidentally touching them by hands and parts such as cables.
- During operation, never touch the rotating parts of the servo motor. Doing so can cause injury.



4. Additional instructions

The following instructions should also be fully noted. Incorrect handling may cause a fault, injury, electric shock, etc.

(1) Transportation and installation

- Transport the products correctly according to their weights.
- Stacking in excess of the specified number of products is not allowed.
- Do not carry the servo motor by the cables, shaft or encoder.
- Do not hold the front cover to transport the driver. The driver may drop.
- Install the driver in a load-bearing place in accordance with the Instruction Manual.
- Do not get on or put heavy load on the equipment. Otherwise, it may cause injury.
- The driver and servo motor must be installed in the specified direction.
- Maintain specified clearances between the driver and the inner surfaces of a control cabinet or other equipment.
- Do not install or operate the driver and servo motor which have been damaged or have any parts missing.
- Provide adequate protection to prevent screws and other conductive matter, oil and other combustible matter from entering the driver and servo motor.
- Do not drop or strike driver or servo motor. Isolate from all impact loads.
- When you keep or use it, please fulfill the following environmental conditions.

Environment			Conditions			
			Driver		Servo motor	
	In	[°C]	0 to +55 (non-freezing)		0 to +40 (non-freezing)	
Ambient	operation	[°F]	32 to 131 (non-freezing)		32 to 104 (non-freezing)	
temperature	In storage	[°C]	-20 to +65 (non-freezing)		-15 to +70 (non-freezing)	
	In storage	[°F]	-4 to 149 (non-freezi	ng)	5 to 158 (non-freezing)	
Ambient	In operation		90%RH or less (non-co	ondensing)	80%RH or less (non-condensing	1)
humidity In storage		90%RH or less (non-condensing)				
Ambience		Indoors (no direct sunlight) Free from corrosive gas, flammable gas, oil mist, dust and dirt				
Altitude		Max. 1000m (3280 ft) above sea level				
					LECSC2-T5	
(Note)			5.9 or less		LECSC2-T7	
Vibration	[m/s ²]	X·Y·Z: 10 to 55Hz		LECSC2-T8	X • Y: 49	
					LECSC2-T9 series	

- Securely attach the servo motor to the machine. If attach insecurely, the servo motor may come off during
 operation.
- The servo motor with a reduction gear must be installed in the specified direction to prevent oil leakage.
- Take safety measures, e.g. provide covers, to prevent accidental access to the rotating parts of the servo motor during operation.
- Never hit the servo motor or shaft, especially when coupling the servo motor to the machine. The encoder may become faulty.
- Do not subject the servo motor shaft to more than the permissible load. Otherwise, the shaft may break.
- When the equipment has been stored for an extended period of time, contact your local sales office.
- To prevent a fire or injury in case of an earthquake or other natural disasters, securely install, mount, and wire the servo motor in accordance with the Instruction Manual.
- When fumigants that contain halogen materials, such as fluorine, chlorine, bromine, and iodine, are used for disinfecting and protecting wooden packaging from insects, they cause a malfunction when entering our products. Please take necessary precautions to ensure that remaining materials from fumigant do not enter our products, or treat packaging with methods other than fumigation, such as heat treatment. Additionally, disinfect and protect wood from insects before packing the products.



(2) Wiring ▲ CAUTION · Wire the equipment correctly and securely. Otherwise, the servo motor may operate unexpectedly. Do not install a power capacitor, surge absorber or radio noise filter (FR-BIF-(H) : Mitsubishi Electric Corporation) between the servo motor and driver. • To avoid a malfunction, connect the wires to the correct phase terminals (U/V/W) of the driver and servo motor. · Connect the servo motor power terminal (U, V, W) to the servo motor power input terminal (U, V, W) directly. Do not let a magnetic contactor, etc. intervene. Servo motor Driver Servo motor Driver U U U V Μ Μ W W Do not connect AC power directly to the servo motor. Otherwise, a fault may occur. • The surge absorbing diode installed on the DC output signal relay of the driver must be wired in the specified direction. Otherwise, the forced stop (EMG) and other protective circuits may not operate. Driver Driver 24 V DC 24 V DC DOCOM DOCOM (DOCOMD) (DOCOMD) Control output Control output signal signal For sink output interface For source output interface • When the cable is not tightened enough to the terminal block (connector), the cable or terminal block (connector) may generate heat because of the poor contact. Be sure to tighten the cable with specified torque. - Connecting a servo motor of the wrong axis to U, V, W, or CN2 of the driver may cause a malfunction. - Configure a circuit to turn off EM2 or EM1 when the main circuit power supply is turned off to prevent an unexpected restart of the driver. To prevent malfunction, avoid bundling power lines (input/output) and signal cables together or running them in parallel to each other. Separate the power lines from the signal cables. (3) Test run adjustment

- When executing a test run, follow the notice and procedures in this instruction manual. Otherwise, it may cause a malfunction, damage to the machine, or injury.
- Before operation, check and adjust the parameter settings. Improper settings may cause some machines to operate unexpectedly.
- Never make a drastic adjustment or change to the parameter values as doing so will make the operation unstable.
- Do not get close to moving parts during the servo-on status.



(4) Usage

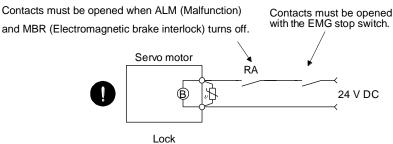
▲ CAUTION

- Provide an external emergency stop circuit to stop the operation and shut the power off immediately.
- For equipment in which the moving part of the machine may collide against the load side, install a limit switch or stopper to the end of the moving part. The machine may be damaged due to a collision.
- Do not disassemble, repair, or modify the product. Otherwise, it may cause an electric shock, fire, injury, etc. Disassembled, repaired, and/or modified products are not covered under warranty.
- Before resetting an alarm, make sure that the run signal of the driver is off in order to prevent a sudden restart. Otherwise, it may cause an accident.
- · Use a noise filter, etc., to minimize the influence of electromagnetic interference. Electromagnetic interference may affect the electronic equipment used near the driver.
- Do not burn or destroy the driver. Doing so may generate a toxic gas.
- Use the driver with the specified servo motor.
- · Wire options and peripheral equipment, etc. correctly in the specified combination. Otherwise, it may cause an electric shock, fire, injury, etc.
- The lock on the servo motor is designed to hold the motor shaft and should not be used for ordinary braking.
- For such reasons as incorrect wiring, service life, and mechanical structure (e.g. where a ball screw and the servo motor are coupled via a timing belt), the lock may not hold the motor shaft. To ensure safety, install a stopper on the machine side.
- If the dynamic brake is activated at power-off, alarm occurrence, etc., do not rotate the servo motor by an external force. Otherwise, it may cause a fire.

(5) Corrective actions



- Ensure safety by confirming the power off, etc. before performing corrective actions. Otherwise, it may cause an accident.
- If it is assumed that a power failure, machine stoppage, or product malfunction may result in a hazardous situation, use a servo motor with an lock or provide an external brake system for holding purpose to prevent such hazard.
- When an alarm occurs, eliminate its cause, ensure safety, and deactivate the alarm to restart operation.
- If the molded-case circuit breaker or fuse is activated, be sure to remove the cause and secure safety before switching the power on. If necessary, replace the driver and recheck the wiring. Otherwise, it may cause smoke, fire, or an electric shock.
- Provide an adequate protection to prevent unexpected restart after an instantaneous power failure.
- Configure a lock circuit so that it is activated also by an external EMG stop switch.



Refer to section 4.11.3 when wiring for the circuit configuration.

• After an earthquake or other natural disasters, ensure safety by checking the conditions of the installation, mounting, wiring, and equipment before switching the power on to prevent an electric shock, injury, or fire.



(6) Maintenance, inspection and parts replacement

- Make sure that the emergency stop circuit operates properly such that an operation can be stopped immediately and a power is shut off by the emergency stop switch.
- It is recommended that the driver be replaced every 10 years when it is used in general environment.

(7) General instruction

• To illustrate details, the equipment in the diagrams of this Instruction Manual may have been drawn without covers and safety guards. When the equipment is operated, the covers and safety guards must be installed as specified. Operation must be performed in accordance with this Instruction Manual.



About processing of waste

When you discard driver, a battery (primary battery), and other option articles, please follow the law of each country (area).

riangle for maximum safety

- These products have been manufactured as a general-purpose part for general industries, and have not been designed or manufactured to be incorporated in a device or system used in purposes related to human life.
- Before using the products for special purposes such as nuclear power, electric power, aerospace, medicine, passenger movement vehicles or under water relays, contact your local sales office.
- These products have been manufactured under strict quality control. However, when installing the product where major accidents or losses could occur if the product fails, install appropriate backup or failsafe functions in the system.



The number of write times to the EEP-ROM, which stores parameter settings, etc., is limited to 100,000. If the total number of the following operations exceeds 100,000, the driver and/or converter unit may fail when the EEP-ROM reaches the end of its useful life.

- · Write to the EEP-ROM due to parameter setting changes
- Home position setting in the absolute position detection system
- Write to the EEP-ROM due to device changes
- · Write to the EEP-ROM due to point table changes

Compliance with global standards

For the compliance with global standards, refer to app. 4.



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1. FUNCTIONS AND CONFIGURATION

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1. FUNCTIONS AND CONFIGURATION

1.1 Introduction

The LECSC2-T CC-Link compatible driver can support the CC-Link communication functions. Up to 42 axes of drivers can be controlled/monitored from the programmable PC or PLC...etc side.

As the servo, it has the function to perform positioning operation by merely setting the position data (target positions), servo motor speeds, acceleration and deceleration time constants, etc. to point tables as if setting them in parameters. The driver is the most appropriate to configure a program-free, simple positioning system or to simplify a system, for example.

There are 31 points of point tables to be used when 1 station is occupied and 255 points when 2 stations are occupied.

All servo motors are equipped with an absolute position encoder as standard. An absolute position detection system can be configured by merely adding a battery to the driver. Once the home position has been set, home position return is not required at power on, alarm occurrence, etc.

The LECSC2-T□ is made easier to use and higher in function by using it with the set up software(MR Configurator2TM).

When setup software (MR Configurator2[™]) is used, the selection of the model of LECSC2-T□ is needed. Please select 'MR-J3-T' through "Model" - "New" and "Project".

1.1.1 Features of CC-Link communication functions

(1) Fast communication

Fast communication can be made by cyclic transmission of not only bit data but also word data.

- (a) The highest communication speed is 10Mbps.
- (b) The broadcast polling system ensures as high as 3.9ms to 6.7ms even at the maximum link scan (10Mbps).
- (2) Variable communication speed/distance system

Selection of speed/distance allows use in a wide range of areas from a system requiring high speed to a system requiring long distance.

(3) System fault prevention (station separating function)

Because of connection in the bus system, any remote or local station that has become faulty due to poweroff or the like does not affect communications with normal remote and local stations. In addition, use of the two-piece terminal block allows the unit to be changed during data link.

(4) Factory Automation compatible

As the remote device stations of CC-Link, the drivers share a link system and can be controlled/monitored with programmable PC or PLC...etc user programs.

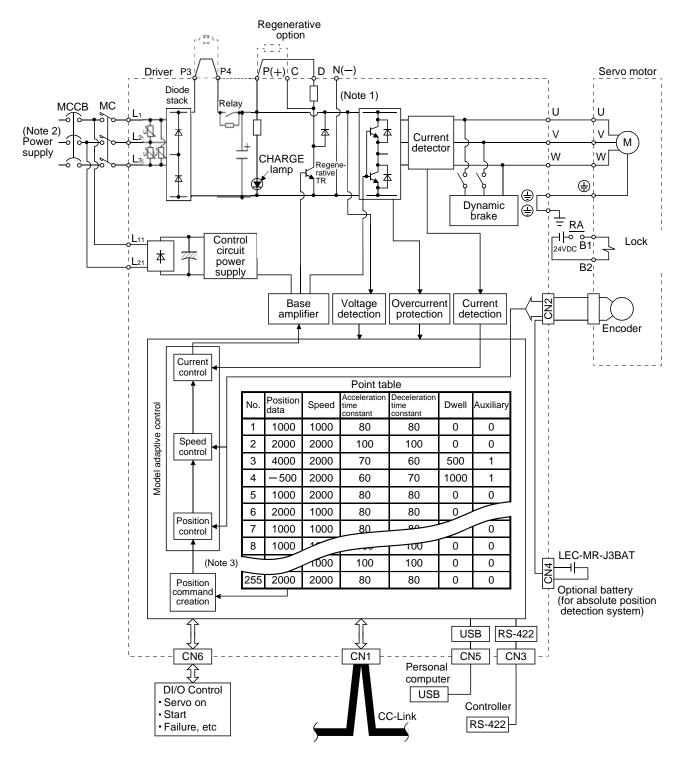
From the programmable PC or PLC...etc side, the running speed, acceleration/deceleration time constant and other settings of servo motors can be changed/checked and the servo motors started and stopped.



1.1.2 Function block diagram

The function block diagram of this servo is shown below.

(1) LECSC2-T



Note 1. The built-in regenerative resistor is not provided for the LECSC2-T5.

- 2. For 1-phase 200 to 230VAC, connect the power supply to L_1 , L_2 and leave L_3 open.
- Refer to section 1.2 for the power supply specification.
- 3. For the case when 2 stations are occupied. When 1 station is occupied, the point table ends at No.31.



1.1.3 System configuration

This section provides operations using this servo.

Use of CC-Link enables you to freely configure any system from a single-axis system to an up to 42-axis system.

Set the following values to the point table.

Name	Setting range	Unit		
Position data (Target positions)	-999999 to 999999	×0.001[mm] × 0.01[mm] × 0.1[mm] × 1[mm]		
Servo motor speed	0 to Allowed Speed for each actuator	[r/min]		
Acceleration time constant	0 to 20000	[ms]		
Deceleration time constant	0 to 20000	[ms]		
Dwell	0 to 20000	[ms]		
Auxiliary function	0 to 3 (Refer to section 4.2)			

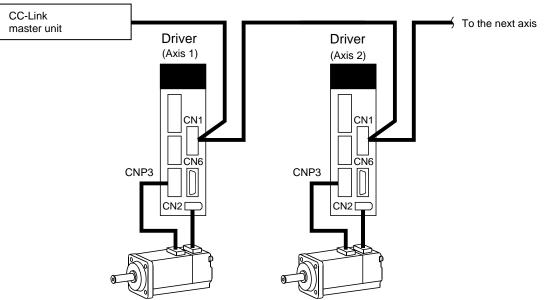
There are 31 points of point tables to be used when 1 station is occupied and 255 points when 2 stations are occupied.

(1) Operation using CC-Link communication functions

(a) Operation

All devices can be controlled by CC-Link communication. Also, each point table setting, point table selection, parameter value change, setting, monitor, servo motor operation and others can be performed.

(b) Configuration

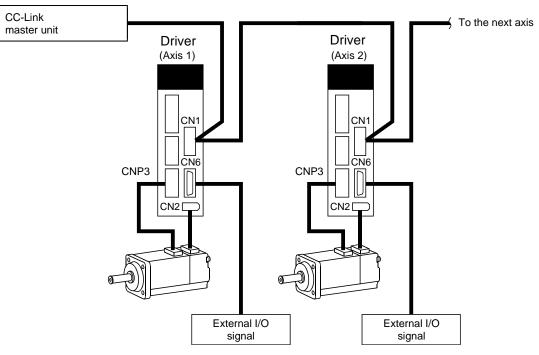




- (2) Operation using CC-Link communication functions and external input signals
 - (a) Operation

Using parameter No.PD06 to PD08 and parameter No.PD12, PD14, input devices can be assigned to the external input devices of CN1A and CN1B. The signals assigned to the external input signals cannot be used with the CC-Link communication functions. Output devices can be used with the CN6 connectors and CC-Link communication functions simultaneously.

(b) Configuration





1.2 Driver standard specifications

(1) 200V class

<u> </u>	Driver LECS	C2-□							
Item			- T5	Τ7	Т8	Т9			
		Voltage/frequency (Note 3)	3-р	hase or 1-phase 20	0 to 230VAC, 50/	50Hz			
		Permissible voltage	2 nhor		220\/AC: 170 to	252)/// 0			
		fluctuation (Note 3)	3-phase or 1-phase 200 to 230VAC: 170 to 253VAC						
Powe	r supply	Permissible frequency	Within ±5%						
		fluctuation							
		Power supply capacity		Refer to se					
		Inrush current		Refer to se					
		Voltage, frequency		1-phase 200 to 2	30VAC, 50/60Hz				
		Permissible voltage fluctuation		1-phase 170) to 253VAC				
Contr	ol circuit power	Permissible frequency							
suppl	y	fluctuation		Withir	n ±5%				
		Input		30	W				
		Inrush current		Refer to se	ection 125				
		Voltage		24VD0					
Inter	ace power supply								
		Power supply capacity	Sine-wave PWM control, current control system						
	rol System		Sine	e-wave PWM control	l, current control s	ystem			
Dyna	amic brake			Bui	lt-in				
			Overcurrent shut	t-off, regenerative ov	/ervoltage shut-of	f, overload shut-off			
Drote	ective functions		(electronic therm	al relay), servo moto	or overheat protec	tion, encoder error			
FIOL			protection, regene	rative brake error pr	otection, undervo	tage, instantaneous			
	1	1	power failure pro	tection, overspeed p	protection, excess	ive error protection			
		Operational specifications	Positioning by specifying the point table No. (255 points)						
	D	Position command input	Set in point table. 1-point feed length setting range: $\pm 1[\mu\text{m}]$ to $\pm 999.999[\text{mm}]$						
			Set in point table. Acceleration/deceleration time is set in point table.						
	Point table number	Speed command input	S-pattern acceleration/deceleration time constant is set in parameter						
	input		No.PC13.						
E		System		Signed absolute value command system, incremental value command system, signed absolute value command/incremental value command					
ste		Cycloni	specifying system						
Command system		Operational specifications		etting is used for pos	itioning.				
nan		Desition command input		used to set position					
JMC		Position command input	Feed length input s	setting range: ±1µm	to ±999.999m				
Ŭ	Position command		-	used to make selec					
	data input	Speed command input	Remote register is used to set speed command data (speed).						
	(when 2 stations		•	tion/deceleration tim	e constant is set i	n parameter			
	are occupied)		No.PC13.	alue command syste	m incromontal v	luo command			
		System	-	solute value comma					
			specifying system						
				r input, position data	input system				
		Point table	Positioning operati	on is performed onc	e in accordance v	ith the position and			
	Automatic operation		speed commands.						
ę	mode	Automatic continuous	Varied speed operation (2 to 255 speeds), automatic continuous						
тос		operation	positioning operation (2 to 255 points)						
ion				performed in accord					
ratic	Manual operation	Jog		tact input or through		nication function.			
E.	mode	Manual pulse generator		ade by manual pulse multiplication: $\times 1$		elected using			
Operation mode	moue		Command pulse multiplication: $\times 1$, $\times 10$ or $\times 100$ is selected using parameter.						
Opera	mode	······································	Point table number input, position data input system. Positioning operation						
Opera	Automatic operation	Point table		r input, position data	a input system. Po	sitioning operation			



	Driver LECSC	2-🗆	_	_				
			Т5	Τ7	Т8	Т9		
Voltage/	frequency		3-phase or 1-phase 200 to 230VAC, 50/60Hz					
		tuation	3-phase or 1-phase 200 to 230VAC: 170 to 253VAC					
Permiss	ible frequency f	luctuation						
Power supply capacity				Refer to se	ection 12.2			
Inrush c	urrent			Refer to se	ection 12.5			
		Voltage, frequency		1-phase 200 to 23	30VAC, 50/60Hz			
Permissible voltage fluctuation				1-phase 170	to 253VAC			
Control circuit power supply P		Permissible frequency fluctuation		Within	±5%			
		Input		30)	W			
Inrush current				Refer to se	ection 12.5			
	r oupply	Voltage		24VDC	£±10%			
ace powe	i supply	Power supply capacity		(Note 1)	150mA			
ol Systen	n		Sin	e-wave PWM control	, current control sy	vstem		
mic brake	9			Buil	t-in			
			Overcurrent shut	-off, regenerative ov	vervoltage shut-of	f, overload shut-off		
			(electronic therma	al relay), servo moto	or overheat protect	tion, encoder error		
ctive fund	tions		protection, regene	erative brake error pr	otection, undervol	tage, instantaneous		
						-		
		Operational specifications						
			Set in point table. 1-point feed length setting range: ±1[µm] to ±999.999[mm]					
Point table number input			Set in point table. Acceleration/deceleration time is set in point table.					
		t Speed command input	d command input S-pattern acceleration/deceleration time constant is set in parameter No.PC13.					
	System		Signed absolute value command system, incremental value command					
			system, signed absolute value command/incremental value command					
			specifying system					
		Operational specifications	Remote register s	etting is used for posi	itioning.			
		Position command input	Remote register is used to set position command data.					
			Feed length input setting range: ±1µm to ±999.999m					
Position	t Speed command input		Remote register is used to make selection from point table.					
input			Remote register is used to set speed command data (speed).					
•			S-pattern acceleration/deceleration time constant is set in parameter					
occupied	3)							
		Quality	0					
		System			nd/incremental val	ue command		
					input overem			
		Point table				ith the position and		
Automatic operation								
mode		Automatic continuous						
					us, automatic con	undous positioning		
				erformed in accordan	ce with the narom	atar-sat speed		
		Jog	U 1		•	•		
		Jog		command by contact input or through CC-Link communication function.				
Manual	operation mode		Manual feed is made by manual pulse generator. Command pulse multiplication: \times 1, \times 10 or \times 100 is selected using					
Manual	operation mode	Manual pulse generator			-	ected using		
	Permiss Permiss Power si Inrush ci ol circuit ace powe ol System mic brake ctive func Point tab Position input (when 2 occupied	Permissible frequency f Power supply capacity Inrush current ol circuit power supply ol System mic brake ctive functions Point table number inpu Position command data input (when 2 stations are occupied)	Permissible voltage fluctuation Permissible frequency fluctuation Power supply capacity Inrush current Voltage, frequency Permissible voltage fluctuation Permissible frequency fluctuation Input Inrush current Voltage Permissible frequency fluctuation Input Inrush current Voltage Power supply capacity Ol System mic brake Ctive functions Point table number input Position command data input (when 2 stations are occupied) Point table Automatic operation Automatic operation Point table Point	Voltage/frequency 3- Permissible voltage fluctuation 3-pha Permissible frequency fluctuation 3-pha Power supply capacity 1 Inrush current Voltage, frequency ol circuit power supply Permissible frequency Permissible frequency 1 Inrush current 1 Inrush current 1 Inrush current 1 ace power supply Overcurrent shut (electronic therma protections ctive functions Voltage Point table number input Seed command input Position command input Set in point table. Speed command in	Voltage/frequency 3-phase or 1-phase 20 Permissible voltage fluctuation 3-phase or 1-phase 200 Permissible frequency fluctuation Within Power supply capacity Refer to se Inrush current Refer to se Permissible voltage 1-phase 200 to 2: Permissible voltage 1-phase 170 ol circuit power supply Permissible frequency Permissible requency 1-phase 170 fluctuation 1-phase 170 Input 30 Inrush current Refer to se Ace power supply Power supply capacity Within Input 30 Inrush current Refer to se sce power supply Power supply capacity (Note 1) ol System Sine-wave PWM control mic brake Buil Overcurrent shut-off, regenerative or (electronic thermal relay), servo mote protection, regenerative brake error prower failure protection, overspeed protection, regenerative brake error prower failure protection/deceleration/deceleration/deceleratino/deceleratino/deceleration/deceleration/deceleration/decelerati	Voltage/frequency 3-phase or 1-phase 200 to 230VAC, 50/6 Permissible frequency fluctuation 3-phase or 1-phase 200 to 230VAC, 50/6 Power supply capacity Refer to section 12.2 Inrush current Refer to section 12.5 Voltage, frequency fluctuation Within ±5% Power supply capacity 1-phase 200 to 230VAC, 50/60Hz Permissible voltage 1-phase 200 to 230VAC, 50/60Hz Permissible requency 1.phase 170 to 253VAC Input 30W Inrush current Refer to section 12.5 Voltage 24VDC:10% Power supply Voltage Voltage 24VDC:10% Power supply capacity (Note 1) 150mA of System Sine-wave PWM control, current control system rict functions Section nice relation forme is set in So-pattern acceleration/deceleration time is set in So-pattern acceleration/deceleration time is set in S-pattern acceleration/deceleration t		

1. FUNCTIONS AND CONFIGURATION

	Driver LECSC2	2-0	TE	Τ7	Т8	то			
Item			T5 T7 T8 T9 Home position return is made starting with Z-phase pulse after passage of						
		Dog type	Home position retr proximity dog. Home position add Home position retr Automatic at-dog function.	tance may be set.					
		Count type	Home position ret proximity dog. Home position ad Home position ret	ing encoder pulses a ome position shift val set. return/automatic stro	ue may be set.				
		Data setting type	Home position return is made without dog. Home position may be set at any position by manual operation, etc. Home position address may be set.						
		Stopper type	Home position ret	urn is made by press dress may be set. Ho					
apor		Home position ignorance (Servo-on position as home position)	Position where se Home position add	rvo-on (RYn0) is swit dress may be set.	tched on is defined a	s home position.			
Operation mode	Automatic operation mode	Dog type rear end reference	Home position add Home position ret	urn is made with resp dress may be set. Ho urn direction may be home position return	ome position shift val set.	ue may be set.			
		Count type front end reference	Home position ret dog. Home position ad Home position ret	urn is made with resp dress may be set. Ho urn direction may be home position return	ome position shift val set.	ue may be set.			
		Dog cradle type		urn is made with resp se pulse. dress may be set. Ho urn direction may be home position return	ome position shift val set.	ue may be set.			
		Dog type last Z-phase reference	function. Home position return is made with respect to the front end of a proximely the last Z-phase pulse. Home position address may be set. Home position return direction may be set. Automatic at-dog home position return return/automatic stroke return function.						



1. FUNCTIONS AND CONFIGURATION

/	Drive	er LECS	C2-🗆		TC	77	то	то	
Item					T5	Τ7	Т8	Т9	
Operation mode	Automatic operation mode Dog type front energies reference Dogless Z-phase reference			nt end	Home position return is made to the dog front end with respect to the front end of a proximity dog. Home position address may be set. Home position shift value may be set. Home position return direction may be set. Automatic at-dog home position return return/automatic stroke return function.				
Operatio				erence	Home position return is made with respect to the first Z-phase to the Z- phase. Home position address may be set. Home position shift value may be set. Home position return direction may be set.				
	Automatic positioning to home position				High-speed automat	tic return to a defined	I home position.		
Othe	r functions				Absolute position detection, backlash function Overtravel prevention using external limit switch Software stroke limit				
Struc	Structure		Self-cooled, open (IP00)						
0	Permissible voltage fluctuation		3-phase or 1-phase 200 to 230VAC: 170 to 253VAC						
		Permissible frequency fluctuation Power supply capacity		Within ±5%					
				Refer to section 12.2					
			Inrush current		Refer to section 12.5				
				[°C]		(Note 2) 0 to +55 ((non-freezing)		
	Ambient	In operati	on	[°F]					
	temperature			[°C]	-20 to +65 (non-freezing)				
ant		In storage	9	[°F]	-4 to +149 (non-freezing)				
ЭШС	Ambient	In operati	on						
Environment	humidity	In storage	e		90%RH or less (non-condensing)				
Ш	Ambient				Indoors (no direct sunlight) Free from corrosive gas, flammable gas, oil mist, dust and dirt				
	Altitude				Max. 1000m above sea level				
	Vibration				5	5.9 [m/s ²] or less, (X·			
Mass	s			[kg]	0.8	0.8	1.0	1.4	

Note 1. 150mA is the value applicable when all I/O signals are used. The current capacity can be decreased by reducing the number of I/O points.

2. When closely mounting the Driver, operate them at the ambient temperatures of 0 to 45°C (32 to 113°F) or at 75% or smaller effective load ratio.

3. The driver will be damaged if 3-phase 400V AC is applied.



1.3 Function list

The following table lists the functions of this servo. For details of the functions, refer to the reference field.

Function	Description	Reference
Positioning by automatic operation	Select the required ones from among 31 preset point tables and perform operation in accordance with the set values. Use the external input signal or communication function to choose the point tables.	Section 5.4
Varied speed operation	Servo motor speed can be varied continuously until the preset moving distance is reached. (Max. set speeds: 255 speeds)	Section 5.4.2 (4)(b)
Automatic continuous positioning operation	By merely choosing one point table and starting operation, positioning can be executed continuously in accordance with several point tables.	Section 5.4.2 (4)
Home position return	Dog type, count type, data setting type, stopper type, home position ignorance, dog type rear end reference, count type front end reference, dog cradle type	Section 5.6
High-resolution encoder	High-resolution encoder of 262144 pulses/rev is used as a servo motor encoder.	
Absolute position detection system	By merely setting the home position once, home position return need not be done at each power on.	Section 5.7
Gain changing function	You can switch between gains during rotation and gains during stop or use an input device to change gains during operation.	Section 9.6
Advanced vibration suppression control	This function suppresses vibration at the arm end or residual vibration.	Section 9.4
Adaptive filter I	Driver detects mechanical resonance and sets filter characteristics automatically to suppress mechanical vibration.	Section 9.2
Low-pass filter	Suppresses high-frequency resonance which occurs as servo system response is increased.	Section 9.5
Machine analyzer function	Analyzes the frequency characteristic of the mechanical system by simply connecting a set up software(MR Configurator2 TM) installed personal computer and driver. Set up software(MR Configurator2 TM) is necessary for this function.	
Machine simulation	Can simulate machine motions on a personal computer screen on the basis of the machine analyzer results. Set up software(MR Configurator2 [™]) is necessary for this function.	
Gain search function	Personal computer changes gains automatically and searches for overshoot-free gains in a short time. Set up software(MR Configurator2 [™]) is necessary for this function.	
Slight vibration suppression control	Suppresses vibration of ± 1 pulse produced at a servo motor stop.	Parameters No. PB24
Electronic gear	The electronic gear is used to make adjustment so that the driver setting matches the machine moving distance. Also, changing the electronic gear value allows the machine to be moved at any multiplication ratio to the moving distance using the driver.	Parameter No. PA06, PA07
Auto tuning	Automatically adjusts the gain to optimum value if load applied to the servo motor shaft varies.	Section 8.2
S-pattern acceleration/deceleration time constant	Acceleration/deceleration can be made smoothly.	Parameters No. PC13
Regenerative option	Used when the built-in regenerative resistor of the driver does not have sufficient regenerative capability for the regenerative power generated.	Section 13.2
Brake unit	Used when the regenerative option cannot provide enough regenerative power. Can be used with the driver of 5kW or more.	Section 13.3
Regeneration converter	Used when the regenerative option cannot provide enough regenerative power. Can be used with the driver of 5kW or more.	Section 13.4
Alarm history clear	Alarm history is cleared.	Parameter No. PC18



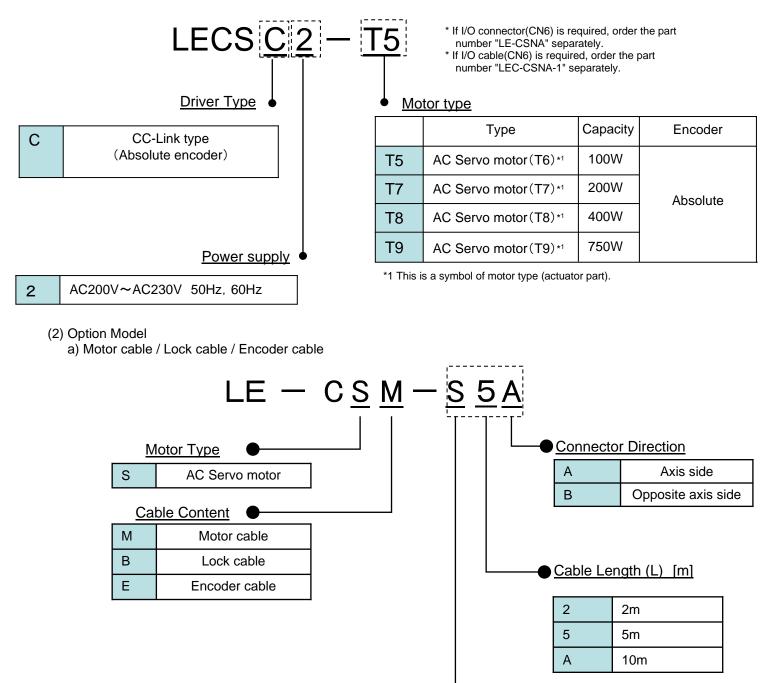
1. FUNCTIONS AND CONFIGURATION

Function	Description	Reference
I/O signal selection (Device setting)	Any input device such as servo-on (SON) can be assigned to any pin of CN6 connector.	Parameter No. PD06 to PD08 PD12 • PD14
Torque limit	Servo motor-torque is limited.	Section 4.6.3 Section 6.1.11
Output signal (DO) forced output	Output signal can be forced on/off independently of the servo status. Use this function for output signal wiring check, etc.	Section 7.7.4
Test operation mode	JOG operation * positioning operation * DO forced output * single - step feed. Set up software(MR Configurator2 [™]) is necessary for this function.	Section 7.7
Limit switch	The servo motor travel region can be limited using the forward rotation stroke end (LSP)/reverse rotation stroke end (LSN).	
Software limit	The travel region is limited using parameters in terms of address. The function similar to that of a limit switch is limited by parameter.	Section 6.3.6



1.4 Model code definition

(1) Model

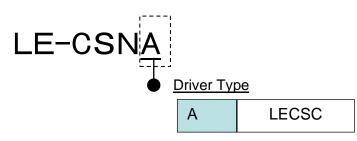


Cable Type

S	Standard cable
R	Robot cable



b) I/O Connector



- *LE-CSNA is 10126-3000PE(Connector)/10326-52F0-008 (Shell kit) of Sumitomo 3M Limited or equivalent goods. Applicable wire size: AWG24~30
- c) Regenerative options



Regenerative option Type

032	Permissible regenerative power 30W
12	Permissible regenerative power 100W

*MR-RB of Mitsubishi Electric Corporation.

d) Setup software (MR Configurator2[™]).

ag	NIL	Japanese version
	E	English version
	С	Chinese version

* SW1DNC-MRC2- of Mitsubishi Electric Corporation. Refer to the website of Mitsubishi Electric Corporation for the information of the operating environment and upgrading. Prepare USB cable should be ordered separately.

e) USB cable(3m)

LEC-MR-J3USB

* MR-J3USBCBL3M of Mitsubishi Electric Corporation.

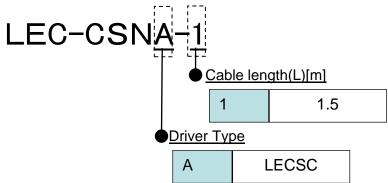
f) Battery



* MR-J3BAT of Mitsubishi Electric Corporation.
 Battery for replacement.
 Absolute position data is maintained by installing the battery to the driver.



g) I/O Connector



*LEC-CSNA-1 is 10126-3000PE(Connector)/10326-52F0-008(Shell kit) of Sumitomo 3M Limited or equivalent goods.

*Conductor size:AWG24

Wiring

LEC-CSNA-1: Pin no. 1 to 26

	nector	Pair no.	Insulation	Dot mark	Dot		nector	Pair no.	Insulation	Dot mark	Dot
pir	n no.	of wire	color	Dorman	color	pir	n no.	of wire	color	Dorman	color
	1	1	Orango		Red		19	10	Pink		Red
	2		Orange		Black		20	10	FILK		Black
	3	2	Light		Red		21	11	0		Red
	4	2	gray		Black		22		Orange		Black
	5	0	14/1-14-2		Red		23	10	Light		Red
	6	3	White		Black		24	12	gray		Black
	7	4	Vallau		Red		25	13	Milita		Red
	8	4 Yellow	reliow		Black		26	15	White		Black
	9	E	5 Pink		Red						
	10	5			Black						
	11	6	0.00000		Red						
	12	0	Orange		Black						
	13	7	Light		Red						
	14	'	gray		Black						
	15	- 8 1	White		Red						
	16		writte		Black						
	17	9	Yellow		Red						
	18	9	Tellow		Black						

1.5 Combination with servo motor

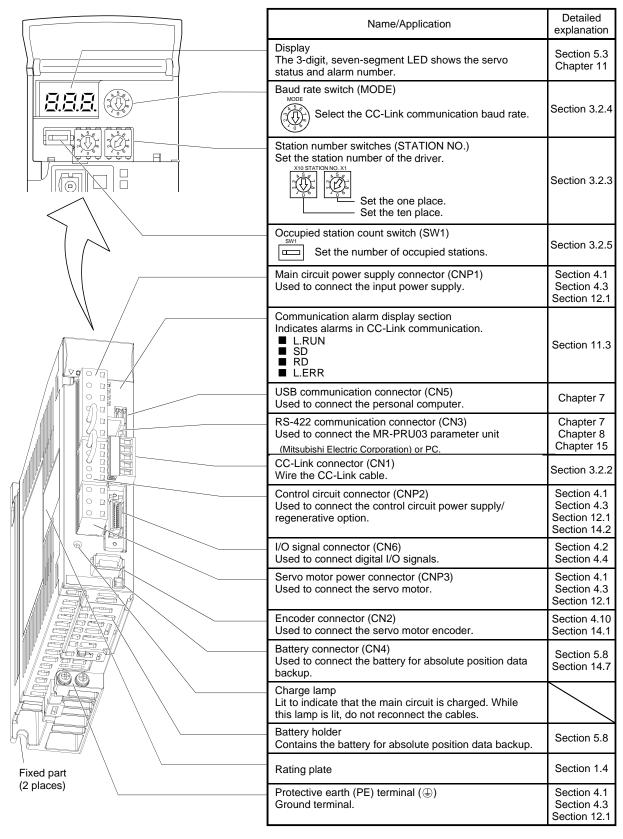
The following table lists combinations of drivers and servo motors. The same combinations apply to the servo motors with a lock and the servo motors with a reduction gear.

Driver	Servo motor
	LE-D-D
LECSC2-T5	Т6
LECSC2-T7	T7
LECSC2-T8	Т8
LECSC2-T9	Т9



1.6 Structure

- 1.6.1 Parts identification
 - (1) LECSC2-T□





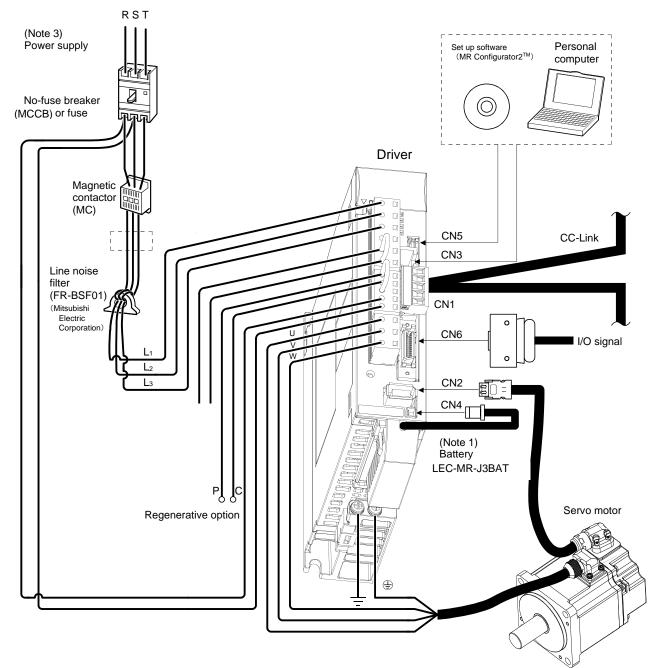
1.7 Configuration including auxiliary equipment

POINT
 Equipment other than the driver and servo motor are optional or recommended products.

(1) LECSC2-T

(a) For 3-phase or 1-phase 200V to 230VAC

Caution: The driver will be damaged if 3-phase 400V AC is applied.



Note 1. The battery is used for the absolute position detection system in the position control mode.

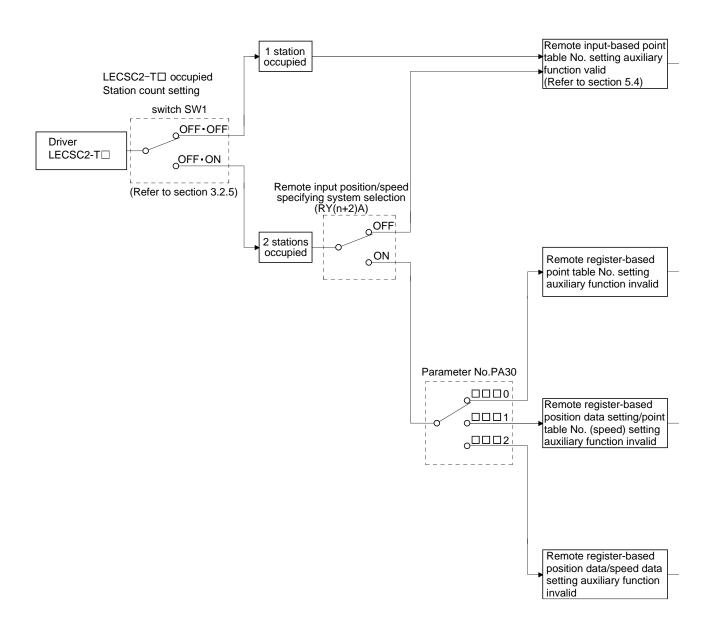
3. For 1-phase 200V to 230VAC, connect the power supply to L₁ · L₂ and leave L₃ open. Refer to section 1.2 for the power supply specification.



1.8 Selection of operation method

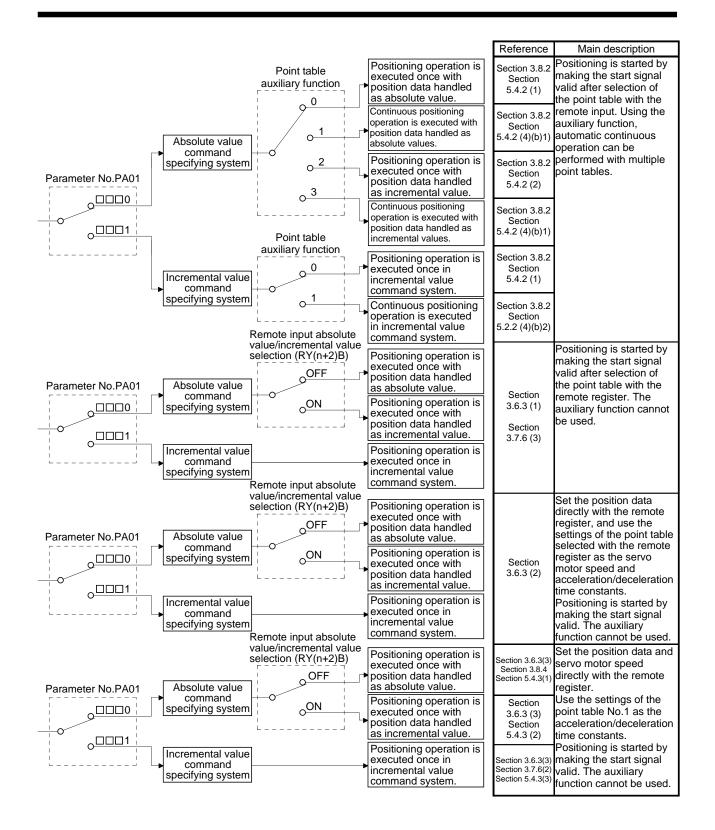
Using the CC-Link communication functions, this servo enables a wide variety of operation methods. The operation method changes depending on the input device, parameter and point table setting.

The flow of the operation method that changes depending on the device and parameter setting status is shown in the chart for your reference.





1. FUNCTIONS AND CONFIGURATION





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2.2 Keep out foreign materials	
2.3 Cable stress	
2.4 Inspection items	
2.5 Parts having service lives	
	-

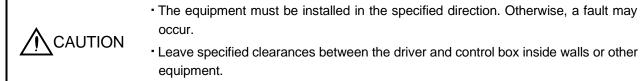


2. INSTALLATION	
	 To prevent electric shock, ground each equipment securely.
CAUTION	 Stacking in excess of the specified number of product packages is not allowed. Do not hold the front cover, cables, or connectors when carrying the driver. Otherwise, it may drop. Install the equipment on incombustible material. Installing it directly or close to combustibles will lead to a fire. Install the driver and the servo motor in a load-bearing place in accordance with the Instruction Manual. Do not get on or put heavy load on the equipment. Otherwise, it may cause injury. Use the equipment within the specified environment. For the environment, refer to section 1.2. Provide an adequate protection to prevent screws and other conductive matter, oil and other combustible matter from entering the driver. Do not drop or apply heavy impact on the drivers and the servo motors. Otherwise, injury, malfunction, etc. may occur. Do not install or operate the driver which have been damaged or have any parts missing. When the equipment has been stored for an extended period of time, contact your local sales office. When handling the driver, be careful about the edged parts such as corners of the driver. The driver must be installed in the metal cabinet. When funginst that contain halogen materials such as fluorine, chlorine, bromine, and iodine are used for disinfecting and protecting wooden packaging from insects, they cause malfunction when entering our products. Please take necessary precautions to ensure that remaining materials from funigation (heat method). Additionally, disinfect and protect wood from insects before packing products.



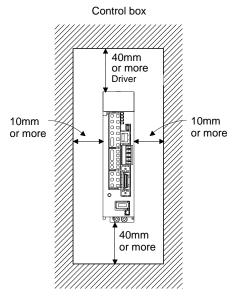
2. INSTALLATION

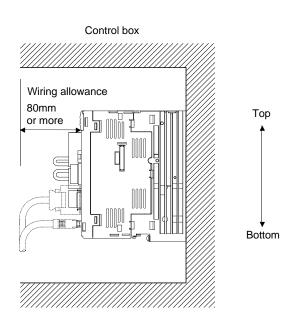
2.1 Installation direction and clearances



(1) LECSC2-T

(a) Installation of one driver







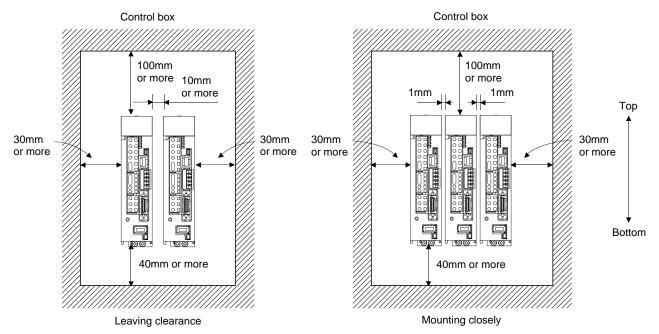
(b) Installation of two or more drivers

POINT	
 Close mou 	nting is available for the driver of under 3.5kW for 200V class.

Leave a large clearance between the top of the driver and the internal surface of the control box, and install a cooling fan to prevent the internal temperature of the control box from exceeding the environmental conditions.

When installing the drivers closely, leave a clearance of 1mm between the adjacent drivers in consideration of mounting tolerances.

In this case, bring the ambient temperature within 0 to 45°C (32 to 113°F), or use it at 75% or a smaller effective load ratio.





(2) Others

When using heat generating equipment such as the regenerative option, install them with full consideration of heat generation so that the driver is not affected.

Install the driver on a perpendicular wall in the correct vertical direction.

- 2.2 Keep out foreign materials
- (1) When installing the unit in a control box, prevent drill chips and wire fragments from entering the driver.
- (2) Prevent oil, water, metallic dust, etc. from entering the driver through openings in the control box or a cooling fan installed on the ceiling.
- (3) When installing the control box in a place where there are much toxic gas, dirt and dust, conduct an air purge (force clean air into the control box from outside to make the internal pressure higher than the external pressure) to prevent such materials from entering the control box.
- 2.3 Cable stress
- (1) The way of clamping the cable must be fully examined so that flexing stress and cable's own weight stress are not applied to the cable connection.
- (2) For use in any application where the servo motor moves, fix the cables (encoder, power supply, brake) with having some slack from the connector connection part of the servo motor to avoid putting stress on the connector connection part. Use the optional encoder cable within the flexing life range. Use the power supply and brake wiring cables within the flexing life of the cables.
- (3) Avoid any probability that the cable sheath might be cut by sharp chips, rubbed by a machine corner or stamped by workers or vehicles.
- (4) For installation on a machine where the servo motor will move, the flexing radius should be made as large as possible. Refer to section 9.4 for the flexing life.
- (5) The minimum bending radius : Min. 45mm.



2.4 Inspection items

 Before starting maintenance and/or inspection, turn off the power and wait for 15 minutes or more until the charge lamp turns off. Then, confirm that the voltage between P(+) and N(-) is safe with a voltage tester and others. Otherwise, an electric shock may occur. In addition, always confirm from the front of the driver whether the charge lamp is off or not.
 Any person who is involved in inspection should be fully competent to do the work. Otherwise, you may get an electric shock.

POINT

- Do not test the driver with a megger (measure insulation resistance), or it may become faulty.
- Do not disassemble and/or repair the equipment on customer side.

It is recommended to make the following checks periodically.

- (1) Check for loose terminal block screws. Retighten any loose screws.
- (2) Check the cables and the like for scratches and cracks. Perform periodic inspection according to operating conditions.

2.5 Parts having service lives

The following parts must be changed periodically as listed below. If any part is found faulty, it must be changed immediately even when it has not yet reached the end of its life, which depends on the operating method and environmental conditions.

	Part name	Life guideline
	Smoothing capacitor	10 years
Driver	Relay	Number of power-on and number of emergency stop times : 100,000 times
	Cooling fan	10,000 to 30,000hours (2 to 3 years)
	Absolute position battery	Refer to section 5.8

(1) Smoothing capacitor

Affected by ripple currents, etc. and deteriorates in characteristic. The life of the capacitor greatly depends on ambient temperature and operating conditions. The capacitor will reach the end of its life in 10 years of continuous operation in normal air-conditioned environment.

(2) Relays

Their contacts will wear due to switching currents and contact faults occur. Relays reach the end of their life when the cumulative number of power-on and emergency stop times is 100,000, which depends on the power supply capacity.

(3) Driver cooling fan

The cooling fan bearings reach the end of their life in 10,000 to 30,000 hours. Normally, therefore, the cooling fan must be changed in a few years of continuous operation as a guideline. It must also be changed if unusual noise or vibration is found during inspection.



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3. CC-LINK COMMUNICATION FUNCTIONS

3.1	Communication	specifications
0.1	Communication	opoonnounorie

e	lincations	
	POINT	
	 This servo 	is equivalent to a remote device station.

For details of the programmable PC or PLC...etc side specifications, refer to the CC-Link system master unit manual.

		Item			Specifications		
Power supply			5VDC supplied from driver				
	Applicable CC-Link version			Ver.1.10			
	Commun	ication speed		10M/5	M/2.5M/625k/15	6kbps	
	Commun	ication system	Broadcast polling system				
	Synchror	nization system		Frame synchronization system MRZI			
	Encoding	g system					
Ч	Transmis	sion path format	Bus format (conforming to EIA RS485) CRC (X ¹⁶ +X ¹² +X ⁵ +1)				
CC-Link	Error cor	trol system					
ŏ	Connecti	on cable	CC-Link Ver.1.10-compliant cable (Shielded 3-core twisted pair cable Conforming to HDLC		pair cable)		
	Transmis	sion format					
Remote station number		1 to 64					
	(Note)	Communication speed	156Kbps	625Kbps	2.5Mbps	5Mbps	10Mbps
	Cable	Maximum overall cable length	1200m	900m	400m	160m	100m
	length	Inter-station cable length	0.2m or more				
			Max. 42 (when	1 station is occu	upied by 1 driver)), (max. 32 whe	n 2 stations are
Number of drivers connected		occupied by 1 driver), when there are only remote device stations. Can be					
		used with other	r equipment.				

Note. If the system comprises of both CC-Link Ver.1.00- and Ver.1.10-compliant cables, Ver.1.00 specifications are applied to the overall cable length and the cable length between stations. For more information, refer to the CC-Link system master/local unit user's manual.



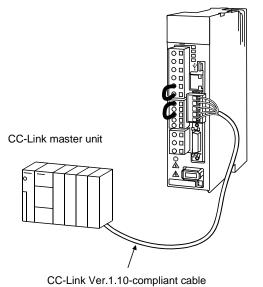
3.2 System configuration

- 3.2.1 Configuration example
- (1) Programmable PC or PLC...etc side

Fit "Type QJ61BT11N", "Type A1SJ61BT11" or "Type A1SJ61QBT11" "Control & Communication Link system master/local module" to the main or extension base unit which is loaded with the programmable PC or PLC...etc CPU used as the master station.

(2) Wiring

Connect the programmable CC-Link unit master station and the driver by a twisted pair cable (3-wire type).

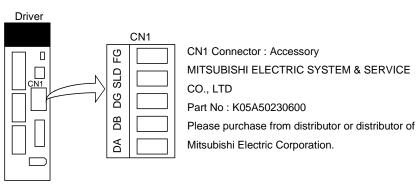




3.2.2 Wiring method

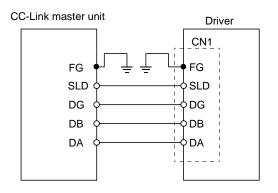
(1) Communication connector

The pin layout of the communication connector CN10 on the driver unit is shown below.



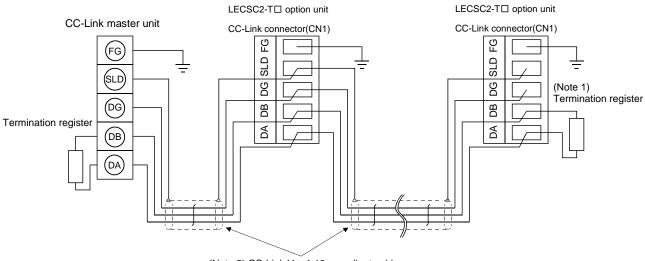
(2) Connection example

The driver and CC-Link master unit are wired as shown below. Refer to section 13.4 (3) for the CC-Link Ver.1.10-compliant cable used for connection.



(3) Example of connecting multiple servo units

As the remote I/O stations of CC-Link, drivers share the link system and can be controlled/monitored using programmable PC or PLC...etc user programs.

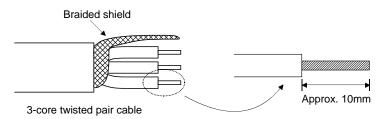


(Note 2) CC-Link Ver.1.10-compliant cable

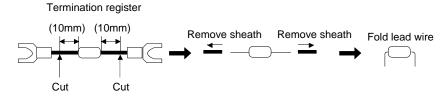
Note 1. Use the termination resistor supplied with the programmable PC or PLC...etc. The resistance of the termination resistor depends on the cable used. 2. Refer to (4) in this section.



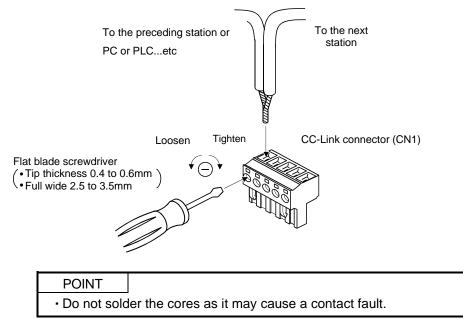
- (4) How to wire the CC-Link connector (CN1)
 - (a) Strip the sheath of the cable and separate the internal wires and braided shield.
 - (b) Strip the sheaths of the braided shield and internal wires and twist the cores.



- (c) Match and twist the wires and braided shield of the cable connected to the preceding axis or programmable PC or PLC...etc driver and the corresponding wires and braided shield of the cable connected to the subsequent axis.
- (d) For the last axis, work the termination resistor supplied to the CC-Link master unit as shown below.



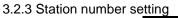
(e) Insert the core of the cable into the opening and tighten it with a flat-blade screwdriver so that it will not come off. (Tightening torque: 0.5 to 0.6N • m) When inserting the wire into the opening, make sure that the terminal screw is fully loose.



Use of a flat-blade torque screwdriver is recommended to manage the screw tightening torque. The following table indicates the recommended products of the torque screwdriver for tightening torque management and the flat-blade bit for torque screwdriver. When managing torque with a Phillips bit, please consult us.

Product	Model	Manufacturer/Representative
Torque screwdriver	N6L TDK	Nakamura Seisakusho
Bit for torque screwdriver	B-30, flat-blade, H3.5 X 73L	Shiro Sangyo





POINT
Be sure to set the station numbers within the range of 1 to 64. Do not set the other values.

(1) How to number the stations

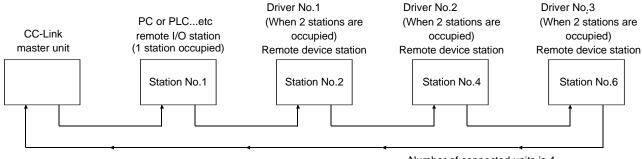
Set the servo station numbers before powering on the drivers. Note the following points when setting the station numbers.

- (a) Station numbers may be set within the range 1 to 64.
- (b) One driver occupies 1 or 2 stations. (One station of programmable PC or PLC...etc remote device station)
- (c) Max. number of connected units: 42

Note that the following conditions must be satisfied.

- $\{(1\times a) + (2\times b) + (3\times c) + (4\times d)\} \le 64$
- a: Number of 1-station occupying units
- b: Number of 2-station occupying units
- c: Number of 3-station occupying units (not available for LECSC2-T \Box)
- d: Number of 4-station occupying units (not available for LECSC2-T□)
- $\{(16 \times A) + (54 \times B) + (88 \times C)\} \le 2304$
- A: Number of remote I/O stations \leq 64
- B: Number of remote device stations \leq 42
- C: Number of local stations ≤ 26

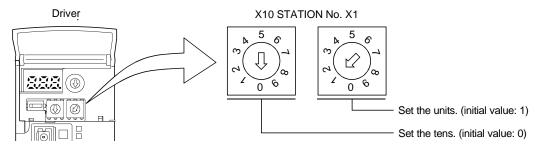
(d) When the number of units connected is 4, station numbers can be set as shown below.



Number of connected units is 4.

(2) Station number setting method

Set the station number with the station number switches (STATION NO.) on the driver front. The station number that may be set is any of 1 to 64 in decimal. In the initial status, the station number is set to station 1.

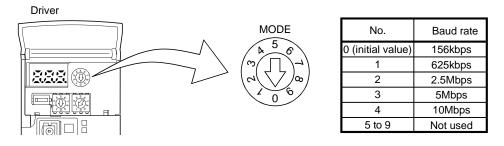




3.2.4 Communication baud rate setting

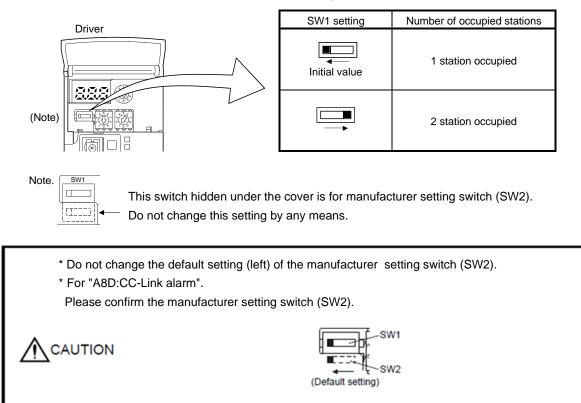
Set the transfer baud rate of CC-Link with the transfer baud rate switch (MODE) on the driver front. The initial value is set to 156kbps.

The overall distance of the system changes with the transfer speed setting. For details, refer to the CC-Link system master/local unit user's manual.



3.2.5 Occupied station count setting

Set the number of occupied stations with the occupied station count switch (SW1) on the driver front. The usable I/O device and the number of connectable units change with the set number of occupied stations. Refer to section 3.2.3. In the initial status, the number of stations occupied is set to 1.



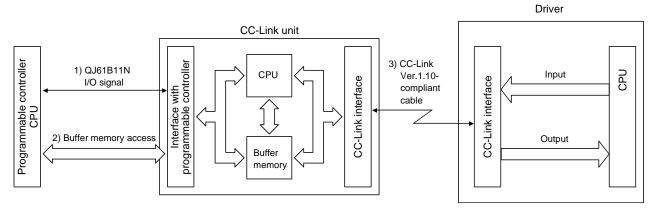


3.3 Functions

3.3.1 Function block diagram

This section explains the transfer of I/O data to/from the driver in CC-Link, using function blocks.

- (1) Between the master station and driver in the CC-Link system, link refresh is normally performed at intervals of 3.5 to 18ms (512 points). The link scan time of link refresh changes with the communication speed. For details, refer to the CC-Link system master/local unit user's manual.
- (2) The I/O refresh and master station sequence program are executed asynchronously. Some programmable PC or PLC...etc allow link scans to be synchronized with programmable driver scans.
- (3) The FROM instruction from the buffer memory of the CC-Link system master/local unit is used to read data from the driver, and the TO instruction is used to write data. Some programmable PC or PLC...etc allow automatic refresh to be set to omit the FROM and TO instructions.



3.3.2 Functions

The following table lists the functions that may be performed from the programmable PC or PLC...etc in the CC-Link system in the CC-Link operation mode or test operation mode.

ltom	Operation mode		
Item	CC-Link operation mode	Test operation mode	
Monitor	0	0	
Operation	0		
Parameter write	0	0	
Parameter read	0	0	
Point table data write	0	0	
Point table data read	0	0	



3.4 Driver setting

(1) Driver side operation modes

This driver has the following operation modes.

Operation mode	Description
Test operation mode	Personal computer in which set up software(MR Configurator2 [™]) is installed is used to run the servo motor.
CC-Link operation mode	CC-Link communication functions are used to operate the servo with the programmable PC or PLCetc programs.

(2) Operation mode changing

(a) Operation mode changing conditions Change the operation mode after making sure that.

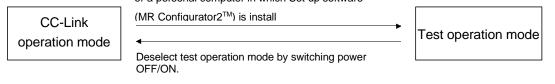
- 1) The servo motor is at a stop.
- 2) The forward rotation start (RYn1) or reverse rotation start (RYn2) is OFF.

(b) Operation mode changing method

When changing from test operation to CC-Link operation, deselect test operation by switching power OFF/ON.

Test operation mode is selected using a parameter unit

or a personal computer in which Set up software





3.5 I/O signals (I/O devices) transferred to/from the programmable PC or PLC...etc CPU

3.5.1 I/O signals (I/O devices)

The input signals (input devices) may be used as either the CC-Link or CN6 external input signals. Make selection in parameter No.PD06 to PD11, PD12 and PD14. The output signals (output devices) can be used as both the CC-Link • CN6 external output signals.

POINT	

 In the factory-shipped status, the forward rotation stroke end (LSP), reverse rotation stroke end (LSN) and proximity dog (DOG) are valid as the CN6 external input signals.

(1) When 1 station is occupied

RYn/RXn: 32 points each, RWrn/RWwn: 4 points each

Programmable PC or PLCetc \rightarrow Driver (RYn)					
(Note) Device No.	Signal name	Signal abbreviation	CN6 connector pin No.		
RYn0	Servo-on	SON			
RYn1	Forward rotation start	ST1			
RYn2	Reverse rotation start	ST2			
RYn3	Proximity dog	DOG	2		
RYn4	Forward rotation stroke end	LSP	3		
RYn5	Reverse rotation stroke end	LSN	4		
RYn6	Automatic/manual selection	MDO			
RYn7	Temporary stop/Restart	TSTP	/		
RYn8	Monitor output execution demand	MOR	/		
RYn9	Instruction code execution demand	COR			
RYnA	Point table No. selection 1	DI0	/		
RYnB	Point table No. selection 2	DI1	/		
RYnC	Point table No. selection 3	DI2			
RYnD	Point table No. selection 4	DI3	/		
RYnE	Point table No. selection 5	DI4	/		
RYnF	Clear	CR	/		
RY(n+1)0					
to	Reserved				
RY(n+1)9					
RY(n+1)A	Reset	RES			
RY(n+1)B					
to	Reserved				
RY(n+1)F					

	Driver \rightarrow Programmable PC or PLCetc (RXn)					
(Note) Device No.	Signal name	Signal abbreviation	CN6 connector pin No.			
RXn0	Ready	RD	14			
RXn1	In position	INP				
RXn2	Rough match	CPO				
RXn3	Home position return completion	ZP	16			
RXn4	Limiting torque	TLC				
RXn5	Reserved	/				
RXn6	Electromagnetic brake interlock	MBR				
RXn7	Temporary stop	PUS				
RXn8	Monitoring	MOF	/			
RXn9	Instruction code execution completion	COF				
RXnA	Warning	WNG				
RXnB	Battery warning	BWNG				
RXnC	Movement completion	MEND				
RXnD	Dynamic brake interlock	DB				
RXnE	Position range output	POT				
RXnF	Reserved	/				
RX(n+1)1 to RX(n+1)9	Reserved					
RX(n+1)A	Trouble	ALM	15			
RX(n+1)B	Remote station communication ready	CRD				
RX(n+1)C			\setminus \neg			
to	Reserved					
RX(n+1)F			\backslash			

I	Programmable PC or PLCetc \rightarrow Driver (RWwn)				
Address No.	Signal name				
RWwn	Monitor 1				
RWwn+1	Monitor 2				
RWwn+2	Instruction code				
RWwn+3	Writing data				

Driver \rightarrow Programmable PC or PLCetc (RWrn)			
Address No.	Signal name		
RWrn	Monitor 1 data		
RWrn+1	Monitor 2 data		
RWrn+2	Respond code		
RWrn+3	Reading data		

Note. "n" depends on the station number setting.



(2) When 2 stations are occupied

RXn/RYn: 64 points each, RWrn/RWwn: 8 points each

	Programmable PC or PLCetc \rightarrow I	0	CN6		Driver \rightarrow Programmable PC or PLC		CN6
(Note 1) Device No.	Signal name	Signal abbreviation	connector pin No.	(Note 1) Device No.	Signal name	Signal abbreviation	connecto pin No.
RYn0	Servo-on	SON		RXn0	Ready	RD	14
RYn1	Forward rotation start	ST1		RXn1	In position	INP	
RYn2	Reverse rotation start	ST2	\backslash	RXn2	Rough match	CPO	
RYn3	Proximity dog	DOG	2	RXn3	Home position return completion	ZP	16
RYn4	Forward rotation stroke end	LSP	3	RXn4	Limiting torque	TLC	
RYn5	Reverse rotation stroke end	LSN	4	RXn5	Reserved		
RYn6	Automatic/manual selection	MDO		RXn6	Electromagnetic brake interlock	MBR	
RYn7	Temporary stop/Restart	TSTP		RXn7	Temporary stop	PUS	
RYn8	Monitor output execution demand	MOR	/	RXn8	Monitoring	MOF	/
RYn9	Instruction code execution demand	COR		RXn9	Instruction code execution completion	COF	
RYnA	Point table No. selection 1	DI0	/	RXnA	Warning	WNG	
RYnB	Point table No. selection 2	DI1		RXnB	Battery warning	BWNG	
RYnC	Point table No. selection 3	DI2		RXnC	Movement completion	MEND	
RYnD	Point table No. selection 4	DI3		RXnD	Dynamic brake interlock	DB	
RYnE	Point table No. selection 5	DI4	/	RXnE	Position range output	POT	
RYnF	Clear	CR		RXnF			
RY(n+1)0				to	Reserved		
to	Reserved			RX(n+1)F			
RY(n+1)F	Position instruction execution			RX(n+2)0	Position instruction execution completion		
RY(n+2)0	demand (Note) Speed instruction execution			RX(n+2)1	Speed instruction execution completion	$\overline{}$	
RY(n+2)1	demand (Note)			RX(n+2)2	Point table No. output 1	PT0	
RY(n+2)2	Reserved	\sim		RX(n+2)3	Point table No. output 2	PT1	\backslash
RY(n+2)3		DI5	\backslash	RX(n+2)4	Point table No. output 3	PT2	\backslash
RY(n+2)4		DI6	\backslash	RX(n+2)5	Point table No. output 4	PT3	\backslash
RY(n+2)5		DI7		RX(n+2)6	Point table No. output 5	PT4	\backslash
RY(n+2)6	Internal torque limit selection	TL1	\backslash	RX(n+2)7	Point table No. output 6	PT5	\backslash
RY(n+2)7	Proportion control	PC	\backslash	RX(n+2)8	Point table No. output 7	PT6	/
RY(n+2)8	Gain changing	CDP		RX(n+2)9	Point table No. output 8	PT7	/
RY(n+2)9	Reserved		\backslash	RX(n+2)A	•		
RY(n+2)A	Position/speed specifying system			to	Reserved		
KT(II T 2)A	selection			RX(n+2)F			
RY(n+2)B	Absolute value/incremental value	\sim		RX(n+3)0		\sim	
IXT(II T 2)D	selection			to	Reserved		
RY(n+2)C		\searrow	\searrow	RX(n+3)9			
to	Reserved			RX(n+3)A	Trouble	ALM	15
RY(n+2)F				RX(n+3)B	Remote station communication	CRD	\sim
RY(n+3)0 to	Reserved			RX(n+3)B RX(n+3)C	ready		
RY(n+3)9				to	Reserved		
RY(n+3)	Reset	RES		RX(n+3)F			
RY(n+3)B				100(1110)	1		<u> </u>
`` '	Reserved						
to	IVE261A60						

Note. "n" depends on the station number setting.



F	Programmable PC or PLCetc \rightarrow Driver (RWwn)	Driver \rightarrow Programmable PC or PLCetc (RWrn)		
(Note 1) Address No.	Signal name		Signal name	
RWwn	(Note 2) Monitor 1	RWrn	Monitor 1 data lower 16 bit	
RWwn+1	(Note 2) Monitor 2	RWwn+1	Monitor 1 data upper 16 bit	
RWwn+2	Instruction code	RWwn+2	Respond code	
RWwn+3	Writing data	RWwn+3	Reading data	
RWwn+4	(Note 3) Position command data lower 16 bit/Point table No.	RWwn+4		
RWwn+5	Position command data upper 16 bit	RWwn+5	Monitor 2 data lower 16 bit	
RWwn+6	(Note 4) Speed command data/Point table No.	RWwn+6	Monitor 2 data upper 16 bit	
RWwn+7	Reserved	RWwn+7	Reserved	

Note 1. "n" depends on the station number setting.

2. Specify the code of the lower 16 bit as the monitor code of 32-bit data.

3. When the parameter No.PC30 setting is "DDD", specify the point table No. in RWwn+4. When the parameter No.PC30 setting is "DDD1" or "DDD2", specify the position data in RWwn+4/RWwn+5 and turn ON Position instruction execution demand (RY(n+2)0).

4. When the parameter No.PC30 setting is "□□□1", specify the point table No. in RWwn+6. When the parameter No.PC30 setting is "□□□2", specify the speed data in RWwn+6, and turn ON Speed instruction execution demand (RY(n+2)1). When setting the parameter No.PC30 to "□□□2", always set the acceleration/deceleration time constant in the point table No.1. When the parameter No.PC30 setting is "□□□0", the RWwn+6 value is not used.



3.5.2 Detailed explanation of I/O signals

(1) Input signals (Input devices)

The note signs in the remarks column indicates the following descriptions.

- *1: Can be used as external input signals of CN6 connector by setting parameters No.PD06 to PD08 and parameter No.PD12 PD14.
- *2: Can be automatic turned ON internally by setting parameters No.PD01 PD04.

The device whose Device No. field has an oblique line cannot be used in CC-Link.

Circal name		Devid	e No.	
Signal name (Device name)	Description	1 station	2 stations	Remarks
(Device name)		occupied	occupied	
Servo-on	Turning RYn0 (SON) ON powers on the base circuit, making	RYn0	RYn0	*1
(SON)	operation ready to start. (Servo on status)			*2
	Turning it OFF powers off the base circuit, coasting the servo			
	motor. (Servo off status)			
Forward rotation start	1. In absolute value command system	RYn1	RYn1	*1
(ST1)	Turning RYn1 (ST1) ON for automatic operation executes			
	positioning once on the basis of the position data set to the			
	point table.			
	Turning RYn1 (ST1) ON for a home position return			
	immediately starts a home position return.			
	Keeping RYn1 (ST1) ON for JOG operation performs			
	rotation in the forward rotation direction.			
	Forward rotation indicates the address increasing direction.			
	2. In incremental value command system			
	Turning RYn1 (ST1) ON for automatic operation executes			
	positioning once in the forward rotation direction on the basis			
	of the position data set to the point table.			
	Turning RYn1 (ST1) ON for a home position return			
	immediately starts a home position return.			
	Keeping RYn1 (ST1) ON for JOG operation performs			
	rotation in the forward rotation direction.			
	Forward rotation indicates the address increasing direction.			
Reverse rotation start	Use this device in the incremental value command system.	RYn2	RYn2	*1
(ST2)	Turning RYn2 (ST2) ON for automatic operation executes			
	positioning once in the reverse rotation direction on the basis			
	of the position data set to the point table.			
	Keeping RYn2 (ST2) ON for JOG operation performs rotation			
	in the reverse rotation direction.			
	Reverse rotation indicates the address decreasing direction.			
	Reverse rotation start (RYn2) (ST2) is also used as the start			
	signal of the high-speed automatic positioning function to the			
	home position.			



						Devie	ce No.	
Signal name	Description						2 stations occupied	Remarks
Proximity dog (DOG)	In the shipment status, the proximity dog external input signal (CN6-2) is valid. For use in CC-Link, make it usable in parameter No.PD14. When RYn3 (DOG) is turned OFF, the proximity dog is detected. The polarity of dog detection can be changed using parameter No.PD16.				RYn3	RYn3	*1	
	Parameter N) detection polari FF N	ty			
Forward rotation stroke end (LSP)			s, the forward r ignal (CN6-3) a			RYn4	RYn4	*1 *2
Reverse rotation stroke end (LSN)	 rotation stroke end is valid as the external input signal (CN6-4). Before operation, short between CN6-3 and DOCOM, and between CN6-4 and DOCOM. Opening them causes a sudden stop, resulting in servo lock. For use in CC-Link, make it usable in parameter No.PD12. When starting operation, turn RYn4 (LSP) /RYn5 (LSN) to ON. Turning it to OFF causes a sudden stop, resulting in servo lock. A stopping method can be changed in parameter No.PD20. When not using the forward/reverse rotation stroke end, set "Automatic ON" in parameter No.PD01. 				N6-4). d udden 2. o ON. o	RYn5	RYn5	
	(Note) In	put signal	Oper	ation				
	RYn4	RYn5	CCW direction	CW direction				
	1	1	0	0				
	0	1	\sim	0				
	1	0	$\overline{)}$	$\overline{}$				
	0	0		\sim				
	Note. 0: OFF	_						
Automatic/manual selection (MD0)	Turning RYn6 mode, and tur If RYn6 (MD0)	(MD0) ON se ning it OFF se is turned OF	elects the autor elects the manu F during autor eceleration time	ual operation m natic operation,		RYn6	RYn6	*1
Temporary stop/Restart (TSTP)	temporary stor time constant Turning RYn7 Forward rotati (RYn2) (ST2) stop. When the auto operation moor remaining dist	b. (The deceled during operat ON again ma on start (RYn is ignored if it omatic operati le during a ter ance is erase oposition retu	akes a restart. 1) (ST1) or Rev is turned ON o ion mode is cha mporary stop, t d. irn or during JC	the deceleration s verse rotation s luring a tempor anged to the ma he movement	on tart ary	RYn7	RYn7	*1



		Devid	e No.	
Signal name	Description	1 station occupied	2 stations occupied	Remarks
Monitor output execution demand (MOR)	When RYn8 (MOR) is turned ON, the following data and signals are set. At the same time, RXn8 turns ON. While RYn8 (MOR) is ON, the monitor values are kept updated. 1) When 1 station is occupied Remote register RWrn: Data demanded by Monitor 1 (RWwn) Remote register RWrn+1: Data demanded by Monitor 2 (RWwn+1) Remote register RWrn+2: Respond code indicating normal or error 2) When 2 stations are occupied Remote register RWrn: Lower 16 bits of data demanded by Monitor 1 (RWwn) Remote register RWrn+1: Upper 16 bits of data demanded by Monitor 1 (RWwn) Remote register RWrn+5: Lower 16 bits of data demanded by Monitor 2 (RWwn+2) Remote register RWrn+6: Upper 16 bits of data demanded by Monitor 2 (RWwn+2)	RYn8	RYn8	
Instruction code execution	Remote register RWrn+2: Respond code indicating normal or error Turning RYn9 (COR) ON executes the processing	RYn9	RYn9	
demand (COR)	corresponding to the instruction code stored in remote register RWwn+2. After completion of instruction code execution, the respond code indicating normal or error is set to RWrn+2. At the same time, RXn9 (COR) turns ON. Refer to section 3.5.4 for details.			
Point table No. selection 1 (DI0)	The point table No. and the home position return are selected by RYnA to $RY(n+2)5$ (DI0 to DI7).	RYnA	RYnA	*1 *2
Point table No. selection 2 (DI1)	(Note 1) Remote input	RYnB	RYnB	
Point table No. selection 3 (DI2)	table No. RY (n+2)5 RY (n+2)4 RY (n+2)3 RYnE RYnD RYnC RYnB RYnA (Note 2) 0 0 0 0 0 0 0 0	RYnC	RYnC	
Point table No. selection 4 (DI3)	1 0 0 0 0 0 0 1 2 0 0 0 0 0 1 0	RYnD	RYnD	
Point table No. selection 5 (DI4)	3 0 0 0 0 0 1 1 4 0 0 0 0 0 1 0 0	RYnE	RYnE	
Point table No. selection 6 (DI5)			RY(n+2)3	
Point table No. selection 7 (DI6)	254 1 1 1 1 1 1 0 255 1 1 1 1 1 1 1 1		RY(n+2)4	
Point table No. selection 8 (DI7)	Note 1. 0: OFF 1: ON 2. Home position return is a setting		RY(n+2)5	
Clear (CR)	When the parameter No.PD22 setting is "□□□1", the position control counter droop pulses is cleared at the leading edge of RYnF (CR). The pulse width should be 10ms or more. When the parameter No.PD22 setting is "□□□2", the pulses are always cleared while RYnF (CR) is on.	RYnF	RYnF	*1



		Devic	e No.	
Signal name	Description			Domorko
Signal name	Description	1 station	2 stations	Remarks
		occupied	occupied	
Position instruction demand	When $RY(n+2)0$ is turned ON, the point table No. or position	\square	RY(n+2)0	\backslash
	command data set to remote register RWwn+4/RWwn+5 is			
	set.			
	When it is set to the driver, the respond code indicating normal			
	or error is set to RWrn+2. At the same time, $RX(n+2)0$ turns			
	ON.			
	Refer to section 3.6.3 for details.			
Speed instruction demand	When $RY(n+2)1$ is turned ON, the point table No. or speed	Ν	RY(n+2)1	N
	command data set to remote register RWwn+6 is set.		· · /	
	When it is set to the driver, the respond code indicating normal			
	or error is set to RWrn+2. At the same time, $RX(n+2)1$ turns			
	ON.			
	Refer to section 3.6.3 for details.			
Internal torque limit selection	Turning RY($n+2$)6 (TL1) OFF makes the torque limit value of	\sim	RY(n+2)6	*1
			KT(II+2)0	I
(TL1)	parameter No.PA11 (forward rotation torque limit) • parameter			
	No.PA12 (reverse rotation torque limit) valid, and turning it ON			
	makes that of parameter No.PC35 (internal torque limit). (Refer			
	to section 4.6.3)			
Proportion control	When $RY(n+2)7$ (PC) is turned ON, the speed amplifier is	Ν	RY(n+2)7	*1
(PC)	switched from the proportional integral type to the proportional	1		*2
	type.			
	If the servo motor at a stop is rotated even one pulse by an			
	external factor, it develops torque in an attempt to compensate			
	for a position shift. When the shaft is locked mechanically after			
	Movement completion (RXnC) (MEND) is turned ON, for			
	example, turning Proportion control $(RY(n+2)7)$ (PC) ON as			
	soon as Movement completion (RXnC) (MEND) turns ON			
	allows control of unnecessary torque developed in an attempt			
	to compensate for a position shift.			
	When the shaft is to be locked for an extended period of time,			
	turn Internal torque limit selection ($RY(n+2)6$) (TL1) ON			
	simultaneously with Proportion control $(RY(n+2)7)$ (PC) to			
	make the torque not more than the rated torque using Internal	\		
	torque limit (parameter No.PC35).	\		
Gain changing	When $RY(n+2)8$ (CDP) is turned ON, the load inertia moment	\land	RY(n+2)8	*1
(CDP)	ratio and the corresponding gain values change to the values			
	of parameter No.PB29 to PB32. To change the gain using			
	RY(n+2)8 (CDP), make the auto tuning invalid.			
Position/speed specifying	Select how to give a position command/speed command.	Ν	RY(n+2)A	Ν
system selection	(Refer to section 3.6.3.)	$\left \right\rangle$	()	$ \rangle$
,	OFF: Remote input-based position/speed specifying system			
	Specifying the point table No. with Point table No.			
	selection (RYnA to RYnE) gives a position			
	command/speed command.			
	ON : Remote register-based position/speed specifying system			
	Setting the instruction code to the remote register			
	(RWwn+4 to RWwn+6) gives a position			
	command/speed command.			
	Set the parameter No.PC30 (direct specification	\		\
	selection) to " \Box \Box \Box 2".	۱ <u> </u>		۱ <u>۱</u>



		Devic	e No.	
Signal name	Description	1 station	2 stations	Remarks
		occupied	occupied	
Absolute value/incremental	RY(n+2)B is made valid when the remote register-based	\setminus	RY(n+2)B	\setminus
value selection	position/speed specifying system is selected with	$\langle \rangle$		\setminus
	Position/speed specifying system selection $(RY(n+2)A)$ and			\setminus
	the absolute value command system is selected in parameter			\setminus
	No.PD10. Turn RY($n+2$)B OFF or ON to select whether the			\setminus
	set position data is in the absolute value command system or			\setminus
	incremental value command system.			\setminus
	OFF: Position data is handled as an absolute value.			\setminus
	ON : Position data is handled as an incremental value.			\
Reset	Keeping RY($n+1$)A or RY($n+3$)A (RES) ON for 50ms or	RY(n+1)A	RY(n+3)A	*1
(RES)	longer allows an alarm to be deactivated.			
	Some alarms cannot be deactivated by Reset RY(n+1)A or			
	RY(n+3)A (RES). (Refer to section 10.4.1.)			
	If $RY(n+1)A$ or $RY(n+3)A$ (RES) is turned ON with no alarm			
	occurring, the base circuit will not be shut off. When " $\Box \Box 1 \Box$ "			
	is set in parameter No.PD20 (function selection D-1), the base			
	circuit is shut off.			
	This device is not designed to make a stop. Do not turn it ON			
	during operation.			
Forced stop	This device is exclusively used as a CN6 external input signal.	\backslash	\backslash	*2
(EMG)	It cannot be used for CC-Link.			
	Turn EMG off to bring the motor to an forced stop state, in			
	which the base circuit is shut off and the dynamic brake is			
	operated.			
	Turn EMG on in the forced stop state to reset that state.			



(2) Output signals (Output device)

POINT

• The output devices can be used for both the remote output and the external output signals of CN6 connector.

The signal whose Device No. field has an oblique line cannot be used in CC-Link.

		Device No.		
Signal name	Description	1 station occupied	2 stations occupied	
Ready (RD)	In the factory-shipped status, a ready is assigned to the CN6-14 pin as an external output signal. RXn0 (RD) turns ON when the driver is ready to operate after servo-on.	RXn0	RXn0	
In position (INP)	 RXn1 (INP) turns ON when the droop pulse value is within the preset in-position range. The in-position range can be changed using parameter No.PA10. Increasing the in-position range may result in a continuous conduction status during low-speed rotation. RXn1 (INP) turns ON at servo-on. 	RXn1	RXn1	
Rough match (CP0)	RXn2 (CP0) turns ON when the command remaining distance becomes less than the rough match output range set in the parameter. RXn2 (CP0) turns ON at servo-on.	RXn2	RXn2	
Home position return completion (ZP)	 In the factory-shipped status, the home position return completion is assigned to the CN6-16 pin as an external output signal. RXn3 (ZP) turns ON when a home position return is completed. RXn3 (ZP) turns ON at completion of a home position return. In an absolute position detection system, RXn3 (ZP) turns ON when operation is ready to start, but turns OFF in any of the following cases. 1) Servo-on (RYn0) (SON) is turned OFF. 2) Forced stop (EMG) is turned OFF. 3) Reset (RY(n+1)A or RY(n+3)A) (RES) is turned ON. 4) Alarm occurs. 5) Forward rotation stroke end (RYn4) (LSP) or Reverse rotation stroke end (RYn5) (LSN) is turned OFF. 6) Home position return has not been made after product purchase. 7) Home position return has not been made after electronic gear change. 9) Home position return has not been made after the absolute position detection system was changed from invalid to valid. 10) Parameter No.PA14 (Rotation direction selection) has been changed. 11) Software limit is valid. 12) While a home position return is being made. When any of 1) to 12) has not occurred and a home position return is already completed at least once, Home position return completion (RXn3) (ZP) turns to the same output status as Ready (RXn0) (RD). 	RXn3	RXn3	
Limiting torque (TLC)	RXn4 (TLC) turns ON when the torque is reached at the time of torque generation.	RXn4	RXn4	
Electromagnetic brake interlock (MBR)	RXn6 (MBR) turns OFF at servo-off or alarm occurrence. At alarm occurrence, it turns OFF independently of the base circuit status.	RXn6	RXn6	
Temporary stop (PUS)	RXn7 (PUS) turns ON when deceleration is started to make a stop by Temporary stop/Restart (RYn7) (TSTP). When Temporary stop/Restart (RYn7) (TSTP) is made valid again to resume operation, RXn7 (PUS) turns OFF.	RXn7	RXn7	
Monitoring (MOF)	Refer to Monitor output execution demand (RYn8) (MOR).	RXn8	RXn8	



											Devic	e No.
Signal name				De	scriptio	n				1 stati occupi		2 stations occupied
Instruction code execution completion (COF)	Refer to In	Refer to Instruction code execution demand (RYn9) (COR).						RXn	9	RXn9		
Warning (WNG)		RXnA (WNG) turns ON when a warning occurs.When no warning has occurred, RXnA (WNG) turns OFF within about 1s after power-on.							-	RXn/	Ą	RXnA
Battery warning (BWNG)	Battery wa	RXnB (BWNG) turns ON when Open battery cable warning (A92) or Battery warning (A9F) occurs. When no battery warning has occurred, RXnB (BWNG) turns OFF within about 1s after power-on.							RXnI	В	RXnB	
Movement completion (MEND)	RXnC (ME the comma RXnC (ME	ND) tu and rem	rns ON aining o	when I distance	n positi e is "0".				ON and	RXn0	C	RXnC
Dynamic brake interlock (DB)	RXnD (DI operated. kW or mo driver of 7	3) turn When ι re, this	s off s using th device	imultan e exteri is requ	eously nal dyna iired. (F	amic bra Refer to	ake on sectior	the driv n 13.6.)	ver of 11	RXnI	D	RXnD
Position range (POT)	RXnE (PC range set i It is OFF w base circu	n the pa /hen a h	aramete	er.						RXnl	E	RXnE
Position instruction execution completion	Refer to S	peed in:	structio	ו execu	tion der	nand (R	Y(n+2)	0).			/	RX(n+2)0
Speed instruction execution completion	is required 11kW or m	Refer to Position instruction execution demand (RY(n+2)1). This device is required when using the external dynamic brake with a driver of 11kW or more. (Refer to section 13.6.) This is not required with drivers of 7kW or less.									RX(n+2)1	
Point table No. output 1 (PT0)	As soon as table No. is			•	n (RXn0	C) (MEN	ID) turn	s ON, tł	ne point			RX(n+2)2
Point table No. output 2 (PT1)	Point table No.	RX	RX	(N RX	lote) Re RX	mote ou RX	tput RX	RX	RX			RX(n+2)3
Point table No. output 3 (PT2)	1	(n+2)9 0	(n+2)8 0	(n+2)7 0	(n+2)6 0	(n+2)5 0	(n+2)4 0	(n+2)3 0	(n+2)2 1		•	RX(n+2)4
Point table No. output 4 (PT3)	2	0	0	0	0	0	0	1	0			RX(n+2)5
Point table No. output 5 (PT4)	4	0	0	0	0	0	1	0	0		-	RX(n+2)6
Point table No. output 6 (PT5)	- 254	1	<u> </u>	- 1	1	- 1	- 1	- 1	•			RX(n+2)7
Point table No. output 7 (PT6)	255 Note. 0: O	1 FF 1: C	1 DN	1	1	1	1	1	1			RX(n+2)8
Point table No. output 8 (PT7)	 RX(n+2)2 to RX(n+2)9 (PT0 to PT7) turn OFF in any of the following statuses. Power on Servo off During home position return Home position return completion In any of the following statuses, RX(n+2)2 to RX(n+2)9 (PT0 to PT7) maintain their pre-change status (ON/OFF). When operation mode is changed When Automatic/manual selection (RYn6) (MD0) is turned from OFF to ON or from ON to OFF to change the operation mode. During manual operation During execution of automatic positioning to home position 									RX(n+2)9		



		Devid	Device No.		
Signal name	Description	1 station	2 stations		
		occupied	occupied		
Trouble	A trouble is assigned to the CN6-15 pin as an external output signal.	RX(n+1)A	RX(n+3)A		
(ALM)	RX(n+1)A or RX(n+3)A (ALM) turns ON when the protective circuit is				
	activated to shut off the base circuit.				
	When no alarm has occurred, RX(n+1)A or RX(n+3)A (ALM) turns				
	OFF within about 1.5s after power is switched ON.				
Remote station	This signal turns ON at power-on and turns off at a trouble occurrence	RX(n+1)B	RX(n+3)B		
communication ready	or in the reset (RY(n+1)A or RY(n+3)A) (RES) ON status.				
(CRD)					

(3) Remote registers

The signal whose Remote Register field has an oblique line cannot be used.

(a) Input (Programmable PC or PLC...etc \rightarrow Driver)

Remote register				
1 station	2 stations	Signal name	Description	Setting range
occupied	occupied			
RWwn	RWwn	Monitor 1	 Demands the status indication data of the driver. 1) When 1 station is occupied Setting the monitor code of the status indication item to be monitored to RWwn and turning RYn8 to ON sets data to RWrn. RXn8 turns on at the same time. 2) When 2 stations are occupied Setting the monitor code of the status indication item to be monitored to RWwn and turning RYn8 to ON sets data to RWrn. RXn8 turns on at the same time. When demanding 32-bit data, specifying the lower 16-bit code No. and turning RYn8 to ON sets the lower 16-bit data to RWwn and the upper 16-bit data to RWrn. Data is stored in the RXn8. RXn8 turns on at the same time. Refer to section 3.5.3 for the item of the monitor code of the status indication. 	Refer to section 3.5.3.
RWwn+1	RWwn+1	Monitor 2	 Demands the status indication. Demands the status indication data of the driver. 1) When 1 station is occupied Setting the monitor code of the status indication item to be monitored to RWwn+1 and turning RYn8 to ON sets data to RWrn+1. RXn8 turns on at the same time. 2) When 2 stations are occupied Setting the monitor code of the status indication item to be monitored to RWwn+1 and turning RYn8 to ON sets data to RWrn+5. RXn8 turns on at the same time. When demanding 32-bit data, specifying the lower 16-bit code No. and turning RYn8 to ON sets the lower 16-bit data to RWwn+5 and the upper 16-bit data to RWrn+6. Data is stored in the RXn8. RXn8 turns on at the same time. Refer to section 3.5.3 for the item of the monitor code of the status indication. 	Refer to section 3.5.3.



Remote	register			
1 station occupied	2 stations occupied	Signal name	Description	Setting range
RWwn+2	RWwn+2	Instruction code	Sets the instruction code used to perform parameter or point table data read and write, alarm reference or the like. Setting the instruction code No. to RWwn+2 and turning RYn9 to ON executes the instruction. RXn9 turns to ON on completion of instruction execution. Refer to section 3.5.4 (1) for instruction code No. definitions.	Refer to section 3.5.4 (1).
RWwn+3	RWwn+3	Writing data	Sets the written data used to perform parameter or point table data write, alarm history clear or the like. Setting the written data to RWwn+3 and turning RYn9 to ON writes the data to the driver. RXn9 turns to ON on completion of write. Refer to section 3.5.4 (2) for written data definitions.	Refer to section 3.5.4 (2).
	RWwn+4	Point table No./Position command data lower 16 bit	Set the point table No. to be executed in the automatic operation mode when 2 stations are occupied. When the point table No. is set to RWwn+4 and RY(n+2)0 is turned ON, the point table No. is set to the driver. On completion of setting, RX(n+2)0 turns ON. When the point table is not used, set the position command data. When the lower 16 bits are set to RWwn+4 and the upper 16 bits to RWwn+5, and RY(n+2)0 is turned ON, the position command data in the upper and lower 16 bits are	Point table No.: 0 to 255 Absolute value command: Position command data: -999999 to 999999 Incremental value command: Position command data: 0 to 999999
	RWwn+5	Position command data upper 16 bit	written. On complete of write, RX(n+2)0 turns ON. Use parameter No.PC30 to select whether point table No. setting or position command data setting will be made. Refer to section 3.6.3 for details of Point table No./Position command data.	
	RWwn+6	Point table No./Speed command data	When the point table is not used, set the point table No. to be executed or the speed command data (servo motor speed [r/min]). When the point table No. is set to RWwn+6 and RY(n+2)1 is turned ON, the point table No. or speed command data is set to the driver. On completion of setting, RX(n+2)1 turns ON. Use parameter No.PC30 to select whether point table No. setting or speed command data setting will be made. Refer to section 3.6.3 for details of Point table No./Speed command data. When setting the servo motor speed in this remote register, always set the acceleration/deceleration time constant in the point table No.1.	Point table No.: 0 to 255 Speed command data: 0 to Allowed Speed for each actuator



(b) Output (Driver \rightarrow Programmable PC or PLC...etc)

Note that the data set to RWrn and RWrn+1 depends on whether 1 station or 2 stations are occupied. If you set inappropriate code No. or data to the remote register input, the error code is set to respond code (RWrn+2). Refer to section 3.5.5 for the error code.

When 1 station is occupied

Remote register	Signal name	Description
RWrn	Monitor 1 data	The data of the monitor code set to RWwn is set.
RWrn+1	Monitor 2 data	The data of the monitor code set to RWwn+1 is set.
	Deepend and	"0000" is set when the codes set to RWwn to RWwn+3 are executed
RWrn+2	Respond code	normally.
RWrn+3	Reading data	Data corresponding to the read code set to RWwn+2 is set.

When 2 stations are occupied

Remote register	Signal name	Description
RWrn	Monitor 1 data lower 16bit	The lower 16 bits of the data of the monitor code set to RWwn are set.
RWrn+1	Monitor 1 data upper 16bit	The upper 16 bits of the data of the monitor code set to RWwn are set. A sign is set if there are no data in the upper 16 bits.
RWrn+2	Respond code	"0000" is set when the codes set to RWwn to RWwn+6 are executed normally.
RWrn+3	Reading data	Data corresponding to the read code set to RWwn+2 is set.
RWrn+4		
RWrn+5	Monitor 2 data lower 16bit	The lower 16 bits of the data of the monitor code set to RWwn+1 are set.
RWrn+6	Monitor 2 data upper 16bit	The upper 16 bits of the data of the monitor code set to RWwn+1 are set. A sign is set if there are no data in the upper 16 bits.
RWrn+7		

3.5.3 Monitor1(RWwn) • Monitor 2(RWwn+1)

To demand 32-bit data when 2 stations are occupied, specify the lower 16-bit code No. Use any of the instruction codes 0101 to 011C to read the decimal point position (multiplying factor) of the status indication. Setting any code No. that is not given in this section will set the error code ($\Box\Box$ 1 \Box) to respond code (RWrn+2). At this time, "0000" is set to monitor1 data (RWrn, RWrn+1), monitor2 data (RWrn+5 and RWrn+6).

Monitor Code No.			Monitored item	Monitor1 data (RWrn, RWrn+1) Monitor2 data (RWrn+5 and RWrn+6) Answer data (Driver → Programmable PC or PLCetc)	
1 station	2 stations			Data length	Unit
occupied	occupied				
0000h	0000h				
0001h	0001h	Current position lower 16bit	The actual current position where the machine home position is assumed as zero.	16bit	
0002h		Current position upper 16bit		16bit	
0003h	0003h	Command position lower 16bit	The command position.	16bit	×10 ^{STM} [µm]
0004h		Command position upper 16bit		16bit	(*1)
0005h	0005h	Command remaining distance lower 16bit	The residual distance up to the position data in the point table or the present command	16bit	
0006h		Command remaining distance upper 16bit	position.	16bit	
0007h	0007h				
0008h	0008h	Point table No.	The point table No. being performed.	16bit	[No.]
0009h					
000Ah	000Ah	Feedback pulse value lower 16bit	Feedback pulses from the motor encoder.	16bit	[pulse]
000Bh		Feedback pulse value upper 16bit		16bit	[pulse]
000Ch					
000Dh					
000Eh	000Eh	Droop pulse value lower 16bit	The number of droop pulses in the deviation counter. Reverse rotation is indicated by a	16bit	[pulse]
000Fh		Droop pulse value upper 16bit	minus (-) sign. The number of pulses is in the encoder pulse unit.	16bit	[pulse]
0010h	0010h				
0011h	0011h	Regenerative load factor	The ratio of regenerative power to permissible regenerative power in %.	16bit	[%]
0012h	0012h	Effective load factor	The continuous effective load current. The effective value is relative to the rated current of 100%.	16bit	[%]
0013h	0013h	Peak load factor	The maximum torque. The highest value in the past 15 seconds is relative to the rated torque of 100%.	16bit	[%]



Monitor Code No.			Monitored item	Monitor1 data (RWrn, RWrn+1) Monitor2 data (RWrn+5 and RWrn+6 Answer data (Driver → Programmable PC or PLCetc)	
1 station occupied	2 stations occupied			Data length	Unit
0014h		Instantaneously occurring torque	Torque that occurred instantaneously. The value of the torque that occurred is in real time relative to the rated torque of 100%.	16bit	[%]
0015h	0015h	ABS counter	The move distance from the home position (0) in the absolute position detection system in terms of the absolute position detector's multi-revolution counter value.	16bit	[rev]
0016h	0016h	Motor speed lower 16bit	The motor speed.	16bit	imes0.1[rev/min]
0017h		Motor speed upper 16bit		16bit	×0.1[rev/min]
0018h	0018h	Bus voltage	The voltage of the main circuit converter (across (P) - (N) and (P+) - (N-)).	16bit	[V]
0019h	0019h	ABS position lower	It becomes amount of movement from the origin in the absolute position system.	16bit	[pulse]
001Ah		ABS position middle 16bit	The number of pulses is in the encoder pulse unit.	16bit	[pulse]
001Bh	001Bh	ABS position upper 16bit	1	16bit	[pulse]
001Ch	001Ch	Within one-revolution position lower 16bit	Position within one-revolution is displayed in	16bit	[pulse]
001Dh		Within one-revolution position upper 16bit	encoder pulses. The value returns to 0 when it exceeds the maximum number of pulses.	16bit	[pulse]

(*1) Feed length multiplication selection (parameter No.PA05) Set the unit multiplication factor (STM) of position data.

Parameter No.PA05 setting	Feed unit [µm]	Position data input range [mm] (incremental value command system)	Position data input range [mm] (absolute value command system)
	1	0 to 999.999	-999.999 to +999.999
	10	0 to 9999.99	-9999.99 to +9999.99
	100	0 to 99999.9	-99999.9 to +99999.9
	1000	0 to 999999	-999999 to +999999

3.5.4 Instruction codes (RWwn+2)

Refer to section 3.6.2 for the instruction code timing charts.

(1) Read instruction code No. (0000h to 0AFFh)

The word data requested to be read with the Read instruction code No. (0000h to 0AFFh) is read by Read code (RWrn+3).

Set the Read instruction code No. (0000h to 0AFFh) corresponding to the item to instruction codes (RWwn+2). The codes and answer data are all 4-digit hexadecimal numbers.

Setting any Read instruction code No. (0000h to 0AFFh) that is not given in this section will set the error code ($\Box\Box\Box\Box$) to respond code (RWrn+2). At this time, "0000" is set to Reading data (RWrn+3).

Read instruction code No.	Item/Function	Reading data (RWrn+3) contents (Driver \rightarrow Programmable PC or PLCetc)
0000h	Operation mode	0000: CC-Link operation mode
	Reads the current operation mode.	0001: Test operation mode
0002h	Travel multiplying factor Reads the multiplying factor of the position data in the point table set in parameter No. PA05.	
0010h	Current alarm (warning) reading Reads the alarm No. or warning No. occurring currently.	0 0 Occurring alarm No./warning No.
0020h	Alarm number in alarm history (most recent alarm)	0 0
0021h	Alarm number in alarm history (first recent alarm)	Alarm No. that occurred in past
0022h	Alarm number in alarm history (second recent alarm)	
0023h	Alarm number in alarm history	
	(third recent alarm)	
0024h	Alarm number in alarm history	
	(fourth recent alarm)	
0025h	Alarm number in alarm history (fifth recent alarm)	
0030h	Alarm occurrence time in alarm history (most recent alarm)	
0031h	Alarm occurrence time in alarm history	
	(first recent alarm)	Occurrence time of alarm that occurred in past
0032h	Alarm occurrence time in alarm history	
	(second recent alarm)	
0033h	Alarm occurrence time in alarm history	
	(third recent alarm)	
0034h	Alarm occurrence time in alarm history	
	(fourth recent alarm)	
0035h	Alarm occurrence time in alarm history	
	(fifth recent alarm)	

Read instruction code No.	Item/Function	Reading data (RWrn+3) contents (Driver \rightarrow Programmable PC or PLCetc)
0040h	Input device status 0 Reads the statuses (OFF/ON) of the input devices.	bit 0 to bit F indicate the OFF/ON statuses of the corresponding input devices. Refer to section 3.5.1 for the meanings of the abbreviations. bitF bit0 When 2 stations are occupied, DI0, DI1 and DI2 do not function and therefore they are always "0". bit0: SON bit4: LSP bit8: MOR bitC: DI2 bit1: ST1 bit5: LSN bit9: COR bitD: DI3 bit2: ST2 bit6: MDO bitA: DI0 bitE: DI4 bit3: DOG bit7: TSTP bitB: DI1 bitF:
0041h	Input device status 1 Reads the statuses (OFF/ON) of the input devices.	bit0 to bit F indicate the OFF/ON statuses of the corresponding input devices. Refer to section 3.5.1 for the meanings of the abbreviations. bitF bit0 bit0: PSR bit4: DI6 bit8: CDP bitC: bit1: SPR bit5: DI7 bit9: bitD: bit2: bit6: TL1 bitA: CSL bitE: bit3: DI5 bit7: PC bitB: INC bitF:
0042h	Input device status 2 Reads the statuses (OFF/ON) of the input devices.	bit 0 to bit F indicate the OFF/ON statuses of the corresponding input devices. Refer to section 3.5.1 for the meanings of the abbreviations. bitF bit0 bit0: bit4: bit8: bitC: bit1: bit5: bit9: bitD: bit2: bit6: bitA: RES bitE: bit3: bit7: bitB: bitF:
0050h	Output device status 0 Reads the statuses (OFF/ON) of the Output devices.	bit 0 to bit F indicate the OFF/ON statuses of the corresponding output devices. Refer to section 3.5.1 for the meanings of the abbreviations. bitF bit0 bit0: RD bit4: TLC bit8: MOF bitC: MEND bit1: INP bit5: bit9: COF bitD: bit2: CPO bit6: MBR bitA: WNG bitE: POT bit3: ZP bit7: PUS bitB: BWNG bitF:
0051h	Output device status 1 Reads the statuses (OFF/ON) of the Output devices.	bit 0 to bit F indicate the OFF/ON statuses of the corresponding output devices. Refer to section 3.5.1 for the meanings of the abbreviations. bitF bit0 bit0: PSF bit4: PT2 bit8: PT6 bitC: bit1: SPF bit5: PT3 bit9: PT7 bitD: bit2: PT0 bit6: PT4 bitA: bitE: bit3: PT1 bit7: PT5 bitB: bitF:



Read instruction code No.	Item/Function	Reading data (RWrn+3) contents (Driver \rightarrow Programmable PC or PLCetc)
0052h	Output device status 2 Reads the statuses (OFF/ON) of the Output devices.	bit 0 to bit F indicate the OFF/ON statuses of the corresponding output devices. Refer to section 3.5.1 for the meanings of the abbreviations. bitF bit0 bit0: bit4: bit8: bitC: bit1: bit5: bit9: bitD: bit2: bit6: bit4: ALM bitE: bit3: bit7: bitB: CRD bitF:
0081h	Energization time Reads the energization time from shipment.	Returns the energization time [h].
0082h	Power ON frequency Reads the number of power-on times from shipment.	Returns the number of power-on times.
00A0h	Ratio of load inertia moment Reads the estimated ratio of load inertia moment to servo motor shaft inertia moment.	Return unit [times].
00B0h	Home position within-1-revolution position lower 16bit (CYC0) Reads the lower 16 bits of the cycle counter value of the absolute home position.	Return unit [pulses].
00B1h	Home position within-1-revolution position upper 16bit Reads the upper 16 bits of the cycle counter value of the absolute home position.	Return unit [pulses].
00B2h	Home position Multi-revolution data (ABS0) Multi-revolution counter value of absolute home position reading.	Return unit [rev].
00C0h	Error parameter No./Point data No. reading Reads the parameter No./point table No. in error.	Parameter No. or point table No. Parameter group 0: Basic setting parameters (No.PA) 1: Gain/filter parameters (No.PB) 2: Extension setting parameters (No.PC) 3: I/O setting parameters (No.PD) Type 1: Parameter No. 2: Point table No.



Read instruction code No.	Item/Function	Reading data (RWrn+3) contents (Driver \rightarrow Programmable PC or PLCetc)
0100h to 011Dh	Monitor multiplying factor Reads the multiplying factor of the data to be read with the monitor code. The instruction codes 0100 to 011D correspond to the monitor codes 0000 to 001D. 0000 applies to the instruction code that does not correspond to the monitor code.	Monitor multiplying factor 0003: ×1000 0002: ×100 0001: ×10 0000: ×1
0200h	Parameter group reading Reads the parameter group to be read with code No.8200h to be written.	0 0 0 Parameter group 0: Basic setting parameters (No.PA □) 1: Gain/filter parameters (No.PB □) 0: 2: Extension setting parameters (No.PC □) 3: I/O setting parameters (No.PD □)
0201h (1) to 02FFh (255)	Parameter data reading Reads the set value of each No. of the parameter group read with code No.0200h. The decimal value converted from the 2 lower digits of the code No. corresponds to the parameter No. If the instruction code is set outside the range set in parameter No.PA19, an error code is returned and the data cannot be read.	The value set in the parameter No. corresponding to the requested group name is stored.
0301h (1) to 03FFh (255)	Data form of parameter Reads the data format of each No. of the parameter group read with code No.0200h. The decimal value converted from the 2 lower digits of the code No. corresponds to the parameter No. If the instruction code is set outside the range set in parameter No.PA19, an error code is returned and the data cannot be read.	The value set in the parameter No. corresponding to the requested group name is stored. 0
0401h (1) to 04FFh (255) 0501h (1) to 05FFh (255)	Position data of point table No.1 to 255 Reads the point table data of point table No.1 to 255. 0400 to 04FF: Position data in lower 16 bits of point table No.1 to 255 0500 to 05FF: Position data in upper 16 bits of point table No.1 to 255 Example Instruction code 0413: Lower 16 bits of point table No.19 Instruction code 0513: Upper 16 bits of point table No.19	The position data (upper 16 bits or lower 16 bits) set in the requested point table No. is returned.

i		
Read instruction code No.	Item/Function	Reading data (RWrn+3) contents (Driver \rightarrow Programmable PC or PLCetc)
0601h (1) to 06FFh (255)	Servo motor speed of point table No.1 to 255 The decimal value converted from the 2 lower digits of the code No. corresponds to the point table No.	The servo motor speed set to the requested point table No. is returned.
0701h (1) to 07FFh (255)	Acceleration time constant of point table No.1 to 255 The decimal value converted from the 2 lower digits of the code No. corresponds to the point table No.	The acceleration time constant set to the requested point table No. is returned.
0801h (1) to 08FFh (255)	Deceleration time constant of point table No.1 to 255 The decimal value converted from the 2 lower digits of the code No. corresponds to the point table No.	The deceleration time constant set to the requested point table No. is returned.
0901h (1) to 09FFh (255)	Dwell of point table No.1 to 255 The decimal value converted from the 2 lower digits of the code No. corresponds to the point table No.	The dwell set to the requested point table No. is returned.
0A01h (1) to 0AFFh (255)	Auxiliary function of point table No.1 to 255 The decimal value converted from the 2 lower digits of the code No. corresponds to the point table No.	The Auxiliary function set to the requested point table No. is returned.

(2) Write instruction code No. (8010h to 91FFh)

Set the data, which was requested to be written with the Write instruction code No. (8010h to 91FFh). Set the Write instruction code No. (8010h to 91FFh) corresponding to the item to Instruction code (RWwn+2) and the written data to Writing data (RWwn+3). The Write instruction code No. (8010h to 91FFh) and answer data are all 4-digit hexadecimal numbers.

When the Write instruction code No. (8010h to 91FFh) which has not been described in this section is set, the error code ($\Box\Box$ 1 \Box) is stored in respond code (RWrn+2).

Write instruction code No.	Item	Writing data (RWwn+3) contents (Programmable PC or PLCetc \rightarrow Driver)
8010h	Alarm reset command Deactivates the alarm that occurred.	1EA5
8101h	Feedback pulse value display data is clear Resets the display data of the status indication "feedback pulse value" to 0.	1EA5
8200h	Parameter group write command Writes the group of parameters that are written to with codes No.8201h to 82FFh and 8301h to 83FFh. Writes the group of parameters that are read with codes No.0201h to 02FFh and 0301h to 03FFh.	0 0 0 Parameter group 0: Basic setting parameters (No.PA □) 1: Gain/filter parameters (No.PB □) 2: Extension setting parameters (No.PC □) 3: I/O setting parameters (No.PD □)

Write					
instruction	Item	Writing data (RWwn+3) contents (Programmable PC or PLCetc \rightarrow Driver)			
code No.					
8201h	Data RAM instruction of parameter	Convert the decimal values into hexadecimal before setting.			
(1)	Writes the set value of each No. of the parameter group written by code No.8200h to				
to	RAM. These values are cleared when power				
82FFh	is switched off.				
(255)	The decimal value converted from the 2 lower				
	digits of the code No. corresponds to the				
	parameter No.				
	An error code is returned if an instruction				
	code outside the range set in parameter No. PA19 or a value outside the setting range of				
	the corresponding parameter is written.				
8301h	Data EEP-ROM instruction of parameter	Convert the decimal values into hexadecimal before setting.			
(1)	Writes the set value of each No. of the				
to	parameter group written with code No.8200h				
83FFh	to EEP-ROM. Written to EEP-ROM, these				
(255)	values are held if power is switched off.				
	The decimal value converted from the 2 lower				
	digits of the code No. corresponds to the parameter No.				
	An error code is returned if an instruction				
	code outside the range set in parameter No.				
	PA19 or a value outside the setting range of				
	the corresponding parameter is written.				
8401h	Position data RAM command of point table	Convert the values into hexadecimal before setting.			
(1)	Writes the position data of point table No. 1 to				
to	255 to RAM. These values are cleared when power is switched off.				
84FFh					
(255)	Point				
8501h		ver bits makes position data. When changing the			
(1)		of both lower and upper bits in order of lower 16-			
to	bit data and upper 16-bit of				
85FFh					
(255)		data in lower 16 bits of point table No.1 to 255			
	8500h to 85FFh: Position	data in upper 16 bits of point table No.1 to 255			
	Example				
	Instruction code 8413h: L	ower 16 bits of point table No.19			
	Instruction code 8513h: U	pper 16 bits of point table No.19			
8601h	Motor speed of point table	Convert the values into hexadecimal before setting.			
(1)	Writes the motor speeds of point table No.1 to	content the transfer monadecimal before setting.			
to	255 to RAM. These values are cleared when				
86FFh	power is switched off.				
(255)	The decimal value converted from the 2 lower				
	digits of the code No. corresponds to the point table No.				
8701h	Acceleration time constant data RAM	Convert the values into hexadecimal before setting.			
(1)	command of point table	Convert the values into nexadecimal before setting.			
to	Writes the acceleration time constants of point				
87FFh	table No.1 to 255 to RAM. These values are				
(255)	cleared when power is switched off.				
, í	The decimal value converted from the 2 lower				
	digits of the code No. corresponds to the point table No.				



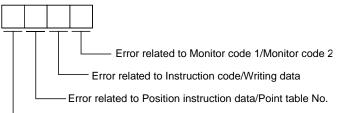
Write						
instruction	Item	Writing data (RWwn+3) contents				
code No.		(Programmable PC or PLCetc \rightarrow Driver)				
8801h	Deceleration time constant data RAM	Convert the values into hexadecimal before setting.				
(1)	command of point table					
to	Writes the deceleration time constants of					
88FFh	point table No.1 to 255 to RAM. These values are cleared when power is switched off.					
(255)	The decimal value converted from the 2 lower					
	digits of the code No. corresponds to the point					
	table No.					
8901h	Dwell data RAM command of point table	Convert the values into hexadecimal before setting.				
(1)	Writes the dwell data of point table No.0 to 255 to RAM. These values are cleared when					
to	power is switched off.					
89FFh	The decimal value converted from the 2 lower					
(255)	digits of the code No. corresponds to the point					
	table No.					
8A01h	Auxiliary function data RAM command of point table	Convert the values into hexadecimal before setting.				
(1)	Writes the auxiliary function data of point table					
to 8AFFh	No.0 to 31 to RAM. These values are cleared					
(255)	when power is switched off.					
(200)	The decimal value converted from the 2 lower					
	digits of the code No. corresponds to the point					
8B01h	table No. Position data EEP-ROM command of point	Convert the values into hexadecimal before setting.				
(1)	table	convolt the values into novadosimal before setting.				
to	Writes the position data of point table No.1 to					
8BFFh	255 to EEP-ROM. Written to EEP-ROM,					
(255)	these values are held if power is switched off.					
00046	Point					
8C01h (1)		ver bits makes position data. When changing the				
to		of both lower and upper bits in order of lower 16-				
8CFFh	bit data and upper 16-bit of					
(255)						
	8B01h to 8BFFh: Position	data in lower 16 bits of point table No.1 to 255				
	8C01h to 8CFFh: Position data in upper 16 bits of point table No.1 to 255					
	Example					
	Instruction code 8B13h: Lower 16 bits of point table No.19					
	Instruction code 8C13h: L	Jpper 16 bits of point table No.19				
		·· ·				
8D01h	Servo motor speed data EEP-ROM command	Convert the values into hexadecimal before setting.				
(1)	of point table					
to	Writes the servo motor speeds of point table					
8DFFh	No.1 to 255 to EEP-ROM. Written to EEP-					
(255)	ROM, these values are held if power is switched off.					
	The decimal value converted from the 2 lower					
	digits of the code No. corresponds to the point					
	table No.					

Write instruction code No.	Item	Writing data (RWwn+3) contents (Programmable PC or PLCetc \rightarrow Driver)
8E01h (1) to 8EFFh (255)	Acceleration time constant data EEP-ROM command of point table Writes the acceleration time constants of point table No.1 to 255 to EEP-ROM. Written to EEP-ROM, these values are held if power is switched off. The decimal value converted from the 2 lower digits of the code No. corresponds to the point table No.	Convert the values into hexadecimal before setting.
8F01h (1) to 8FFFh (255)	Deceleration time constant data EEP-ROM command of point table Writes the deceleration time constants of point table No.1 to 255 to EEP-ROM. Written to EEP-ROM, these values are held if power is switched off. The decimal value converted from the 2 lower digits of the code No. corresponds to the point table No.	Convert the values into hexadecimal before setting.
9001h (1) to 90FFh (255)	Dwell data EEP-ROM command of point table Writes the dwell data of point table No.1 to 255 to EEP-ROM. Written to EEP-ROM, these values are held if power is switched off. The decimal value converted from the 2 lower digits of the code No. corresponds to the point table No.	Convert the values into hexadecimal before setting.
9101h (1) to 91FFh (255)	Auxiliary function data EEP-ROM command of point table Writes the auxiliary function data of point table No.1 to 255 to EEP-ROM. Written to EEP- ROM, these values are held if power is switched off. The decimal value converted from the 2 lower digits of the code No. corresponds to the point table No.	Convert the values into hexadecimal before setting.



3.5.5 Respond codes (RWrn+2)

If any of the monitor codes, instruction codes, position command data/point table Nos., speed command data/point table Nos. set to the remote register is outside the setting range, the corresponding error code is set to respond code (RWwn+2). "0000" is set if they are normal.



---Error related to Speed instruction data/Point table No.

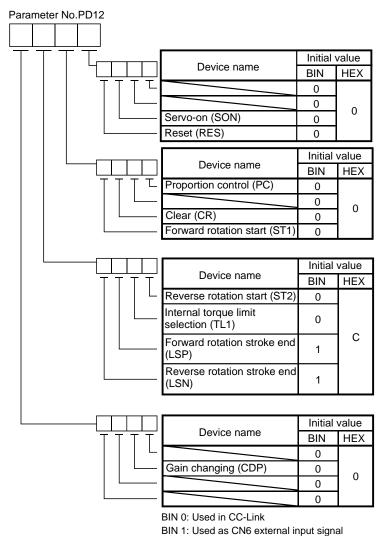
Code No.	Error	Details				
0	Normal answer	Instruction was completed normally.				
1	Code error	The monitor code not in the specifications was set.Read/write of the point table of No.255 or later was set.				
2	Parameter - point table selection error	 The parameter No. disabled for reference was set. 				
3	Write range error	 An attempt was made to write the parameter or point table data outside the setting range. 				



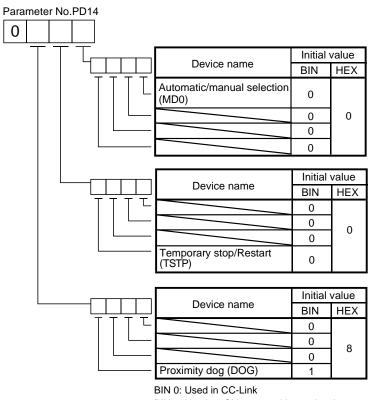
3.5.6 Setting the CN6 external input signals

Using parameter No.PD06 to PD08, PD12 and PD14, you can assign the input devices as the CN6 external input signals. The signals assigned as the CN6 external input devices cannot be used in CC-Link. Refer to section 4.5.1 for the pins to which signals can be assigned.

In the initial status, the forward rotation stroke end, reverse rotation stroke end and proximity dog are preset to be usable as the CN6 external input signals.



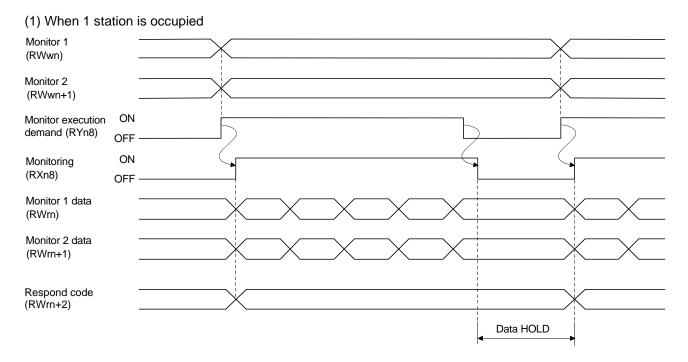




BIN 1: Used as CN6 external input signal



3.6 Data communication timing charts3.6.1 Monitor1 (RWwn) • Monitor2 (RWwn+1)



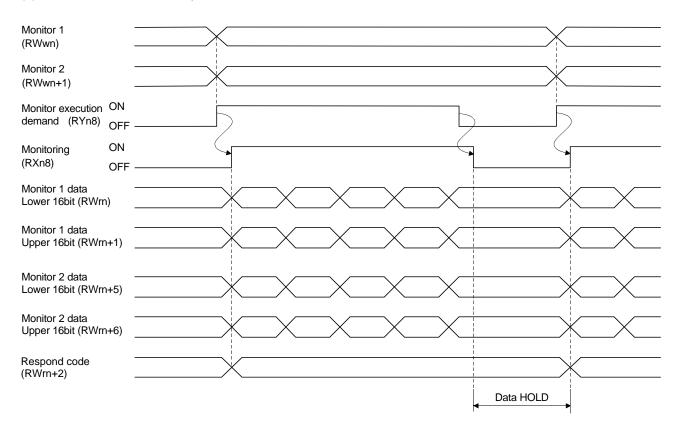
Set the monitor codes No. (0000 to 001D) (refer to section 3.5.3) to Monitor 1 (RWwn) and Monitor 2 (RWwn+1) and turn Monitor output execution demand (RYn8) to ON. Turning Monitor execution demand (RYn8) to ON sets the next data. Data are all hexadecimal numbers. At this time, Monitoring (RXn8) turns to ON at the same time.

Monitor data 1 (RWrn): Data demanded by Monitor 1 (RWwn) Monitor data 2 (RWrn+1): Data demanded by Monitor 2 (RWwn+1)

For 32-bit data, set the lower 16 bits of the monitor code to Monitor 1 (RWwn) and the upper 16 bits to Monitor 2 (RWwn+1) and read them simultaneously.

The monitor data set to the remote register are always updated while Monitor execution demand (RYn8) is ON. When Monitoring (RXn8) turns to OFF, the data set to Monitor1 data (RWrn), Monitor2 data (RWrn+1) are held. If the monitor code No. (0000 to 001D) not in the specifications is set to either Monitor 1 (RWwn) or Monitor 2 (RWwn+1), the corresponding error code ($\Box\Box\Box$) is set to respond code (RW_m+2).





(2) When 2 stations are occupied

Set the monitor codes (0000 to 001D) (refer to section 3.5.3) to Monitor 1 (RWwn) and Monitor 2 (RWwn+1) and turn Monitor output execution demand (RYn8) to ON. Turning Monitor execution demand (RYn8) to ON sets the next data. 32-bit data are all divided into the upper 16 bits and lower 16 bits, and set to the remote register. Data are all hexadecimal numbers. At this time, Monitoring (RXn8) turns to ON at the same time.

Monitor data 1 lower 16 bit (RWrn): Lower 16 bits of data demanded by Monitor 1 (RWwn) Monitor data 1 upper 16 bit (RWrn+1): Upper 16 bits of data demanded by Monitor 1 (RWwn) Monitor data 2 lower 16 bit (RWrn+5): Lower 16 bits of data demanded by Monitor 2 (RWwn+1) Monitor data 2 upper 16 bit (RWrn+6): Upper 16 bits of data demanded by Monitor 2 (RWwn+1)

A sign is set if data does not exist in RWrn+1 • RWrn+6. A "+" sign is indicated by "0000", and "-" by "FFFF". The monitor data set to the remote register are always updated while Monitoring (RXn8) is ON.

When Monitoring (RXn8) turns to OFF, the data set to Monitor data RWrn, RWrn+1, RWrn+5, RWrn+6 are held.

If the monitor code No. (0000 to 001D) not in the specifications is set to either Monitor 1 (RWwn) or Monitor 2 (RWwn+1), the corresponding error code ($\Box\Box\Box$ 1) is set to respond code (RW_m+2).



3.6.2 Instruction codes (RWwn+2)

(1) Read instruction code No. (0000h to 0A1Fh)

Instruction code (RWwn+2)	
Instruction code execution demand (RYn9)	
Instruction code execution completion (RXn9)	
Reading data (RWrn+3)	
Respond code (RWrn+2)	
	Data read period →

Set the Read instruction code No. (0000h ~ 0A1Fh) (refer to section 3.5.4 (1)) to Instruction code (RWwn+2) and turn Instruction code execution demand (RYn9) to ON. Turning Instruction code execution demand (RYn9) to ON sets the data corresponding to the preset Read instruction code No. (0000h ~ 0A1Fh) to Reading data (RWrn+3). Data are all hexadecimal numbers. At this time, Instruction code execution completion (RXn9) turns to ON at the same time.

Read the read data set to Reading data (RWrn+3) while Instruction code execution completion (RXn9) is ON. The data set to Reading data (RWrn+3) is held until the next Read instruction code No. (0000h \sim 0A1Fh) is set and Instruction code execution demand (RYn9) is turned to ON.

If the Read instruction code No. $(0000h \sim 0A1Fh)$ not in the specifications is set to Instruction code (RWwn+2), the corresponding error code ($\Box\Box\Box\Box$) is set to respond code. If any unusable parameter, point table is read, the corresponding error code ($\Box\Box\Box\Box$) is set.

Turn Instruction code execution demand (RYn9) to OFF after completion of data read.



(2) Write instruction code No. (8000h to 911Fh)

Instruction code (RWwn+2)	
Writing data (RWwn+3)	
Instruction code execution demand (RYn9)	
Instruction code processing	Write in execution
Instruction code execution completion (RXn9)	
Respond code (RWrn+2)	

Set the Write instruction code No. (8000h to 911Fh) (refer to section 3.5.4 (2)) to Instruction code (RWwn+2) and the data to be written (data to be executed) to Writing data (RWwn+3) in hexadecimal, and turn Instruction code execution demand (RYn9) to ON.

Turning instruction code execution completion to ON sets the data set in Wiring data (RWwn+3) to the item corresponding to the Write instruction code No. (8000h to 911Fh). When write is executed, Instruction code execution completion (RXn9) turns to ON.

If the Write instruction code No. (8000h to 911Fh) not in the specifications is set to Instruction code (RWwn+2), the corresponding error code ($\Box\Box\Box$) is set to respond code.

Turn Instruction code execution demand (RYn9) to OFF after Instruction code execution completion (RXn9) has turned to ON.



3.6.3 Remote register-based position/speed setting

The functions in this section are usable when Position/speed specifying system selection (RY(n+2)A) is ON (remote register-based position/speed specifying system is selected) with 2 stations occupied.

The position command/speed command necessary for positioning can be selected by parameter No.PC30 setting as indicated below.

ParameterNo.PC	30			
L	Set valure	Position command	Speed command	Acceleration time constant / Deceleration time constant
	0	Specify the point table	No.	
	1	Set the position data.	Specify the point table No.	
	2		Set the servo motor speed	Use the value set in point table No.1.

(1) When setting the point table No.

Specify the point table No. stored in the driver and execute positioning.

Preset "DDD" (initial value) in parameter No.PC30 to enable point table No.-setting operation.

Point table No.	-	
(RWwn+4)	-	X
Position instruction demand (RY(n+2)0)	ON OFF -	
Point table No. designation Position instruction execution completion (RX(n+2)0)	ON OFF-	(Note) Data reserved
Respond code (RWrn+2)	-	
Forward/reverse	ON	<mark>∢ 6ms</mark> ▶
rotation start (RYn1• RYn2)	OFF -	

Note. This data is stored into RAM of the driver. Hence, the data is cleared when power is switched off.

Set the point table No. to point table No. (RWwn+4) and turn Position instruction demand (RY(n+2)0) to ON. Turning RY(n+2)0 to ON stores the position block No. into RAM of the driver.

When the data is stored, Position instruction execution completion (RX(n+2)0) turns to ON.

If data outside the setting range is set to Position block No. (RWwn+4), the error code (refer to section 3.5.5) is set to respond code.

Turn Forward rotation start (RYn1)/Reverse rotation start (RYn2) to ON after Position instruction execution completion (RX(n+2)0) has turned to ON.



(2) When setting the position command data/point table No. (speed command)

Specify the position address with the remote register, and specify the speed command data by specifying the point table No. to use the preset servo motor speed, acceleration time constant and deceleration time constant the speed command data, and execute positioning.

Preset "DDD1" in parameter No.PC30 to enable position command data-set and point table No. (speed instruction)-setting operation.

Position instruction Lower 16bit (RWwn		
Position instruction Upper 16bit (RWwn		
Point table No. (RWwn+6)		
Position instruction demand (RY(n+2)0)	ON OFF	
Speed instruction demand (RY(n+2)1)	ON OFF	
Position data setting Point table No. designation)	(Note) Data reserved
Position instruction execution completio (RX(n+2)0)	ON n OFF	
Speed instruction execution completio (RX(n+2)1)	ON n OFF	
Respond code (RWrn+2)		
Forward rotation Reverse rotation start (RYn1 · RYn2)	ON OFF	<mark>€ms</mark>

Note. This data is stored into RAM of the driver. Hence, the data is cleared when power is switched off.

Set the lower 16 bits of the position instruction data to Position instruction data lower 16 bit (RWwn+4), the upper 16 bits of the position instruction data to Position instruction data upper 16 bit (RWwn+5), and point table for speed command No. to point table No. (RWwn+6), and turn Position instruction demand (RY(n+2)0) and Speed instruction demand (RY(n+2)1) to ON.

Turning RY(n+2)0 and RY(n+2)1 to ON stores the position command data and point table No. into RAM of the driver.

When the data are stored, Position instruction execution completion (RX(n+2)0) and Speed instruction execution completion (RX(n+2)1) turn to ON.

If data outside the setting range is set to any of Position instruction data lower 16 bit (RWwn+4), Position instruction data upper 16 bit (RWwn+5) and point table No. (RWwn+6), the error code (refer to section 3.5.5) is set to respond code.

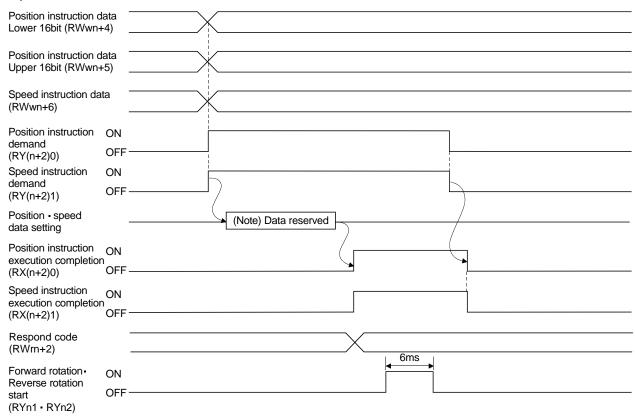
Turn Forward rotation start (RYn1) • Reverse rotation start (RYn2) to ON after Position instruction execution completion (RX(n+2)0) and Speed instruction execution completion (RX(n+2)1) have turned to ON.



(3) When setting the position command data and speed command data

Specify the position address and servo motor speed with the remote register, and execute positioning. At this time, use the acceleration time constant and deceleration time constant set in point table No.1.

Preset "DDD2" in parameter No.PC30 to enable position command data- and speed command data-set operation.



Note. This data is stored into RAM of the driver. Hence, the data is cleared when power is switched off.

Set the lower 16 bits of the position instruction data to Position instruction data lower 16 bit (RWwn+4), the upper 16 bits of the position instruction data to Position instruction data upper 16 bit (RWwn+5), and speed instruction data to Speed instruction data (RWwn+6), and turn Position instruction demand (RY(n+2)0) and Speed instruction demand (RY(n+2)1) to ON.

Turning RY(n+2)0 and RY(n+2)1 to ON stores the position command data and speed command data into RAM of the driver.

When the data are stored, Position instruction execution completion (RX(n+2)0) and Speed instruction execution completion (RX(n+2)1) turn to ON.

If data outside the setting range is set to any of Position instruction data lower 16 bit (RWwn+4), Position instruction data upper 16 bit (RWwn+5) and Speed command data (RWwn+6), the error code (refer to section 3.5.5) is set to respond code.

Turn Forward rotation start (RYn1) • Reverse rotation start (RYn2) to ON after Position instruction execution completion (RX(n+2)0) and Speed instruction execution completion (RX(n+2)1) have turned to ON.



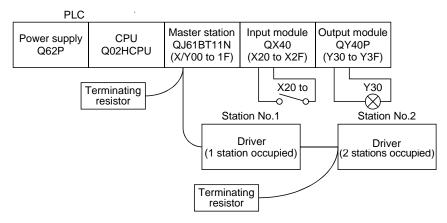
3.7 Function-by-function programming examples

This section explains specific programming examples for servo operation, monitor, parameter read and write, and others on the basis of the equipment makeup shown in section 3.7.1.

3.7.1 System configuration example

As shown below, the CC-Link system master • local unit is loaded to run two drivers (1 station occupied / 2 stations occupied).

(1) System configuration



(2) Master station network parameter setting

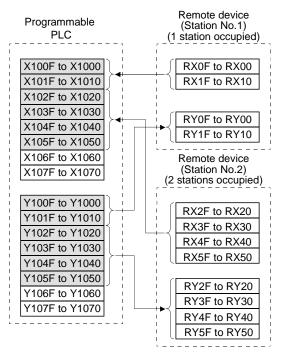
In the programming examples, network parameters are set as below.

ltem		Setting condition	Item	Setting condition	
Start I/O No.		0000	0000 Remote register (RWr)		
	Data link disorder	Clear	lear Refresh device		
	station settings	(No check on	Remote register (RWw)	W100	
Operational setting	station settings	"Hold input data") Refresh device		VV 100	
	Case of CPU	Defreeh	Special relay (SB)	SB0	
	STOP setting Refresh		Refresh device	3B0	
Туре		Master station	Special relay (SW)	SW0	
Mode		Remote net	Remote net Refresh device		
		(Ver.1 mode)	Retry count	3	
All connect count		2	Automatic reconnection station count	1	
Remote input (RX)		X1000	CPU down select	Stop	
Refresh device		X1000	Scan mode setting	Asynchronous	
Remote output (RY)		¥4000			
Refresh device		Y1000			

(3) Relationship of remote I/O (RX, RY)

The following shows a relationship between the devices of the programmable PLC CPU and the remote I/Os (RX, RY) of the remote device stations.

Shaded area shows the devices actually used.

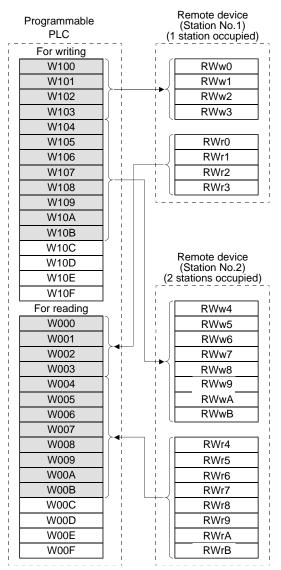




(4) Relationship of remote register (RWw, RWr)

The following shows a relationship between the devices of the programmable driver CPU and the remote registers (RWw, RWr) of the remote device stations.

Shaded area shows the devices actually used.



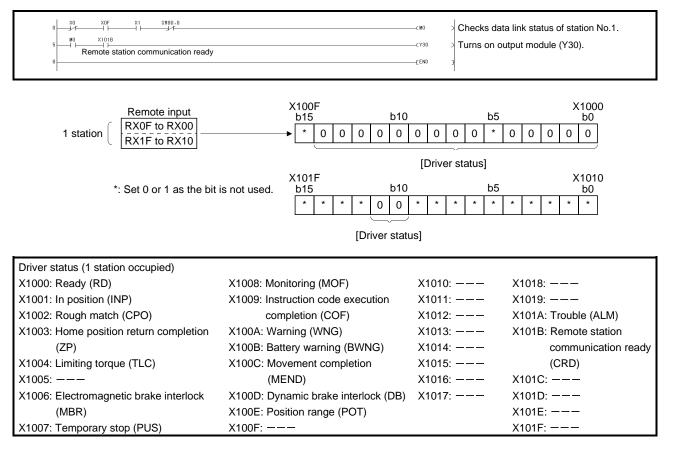


3.7.2 Reading the driver status

When the driver on station number 1 becomes ready for the remote station communication, Y30 of the output module turns on.

The program is for turning on Y30 when CC-Link communication is normal.

Specific programming examples are explained based on the equipment configuration shown in Section 3.7.1.



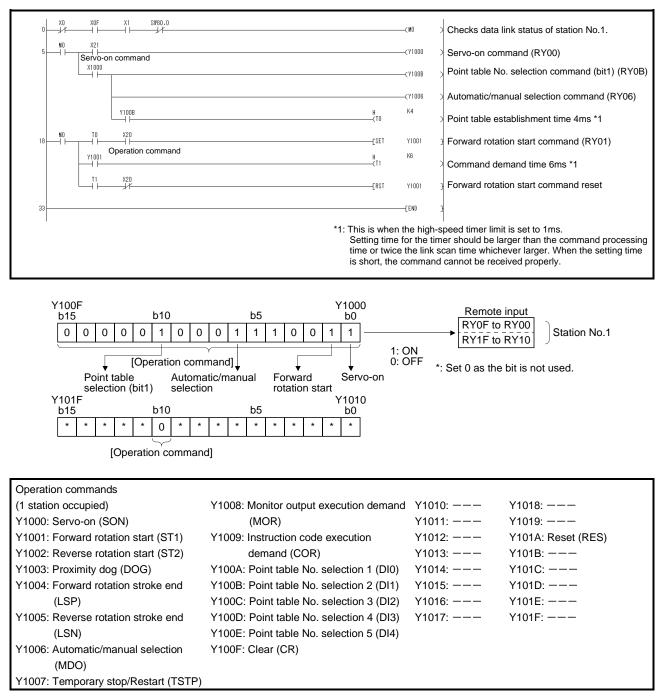


3.7.3 Writing the operation commands

Perform positioning operation of point table No.2 for the driver of station 2.

Start the operation by turning on X20.

Specific programming examples are explained based on the equipment configuration shown in Section 3.7.1.





3.7.4 Reading the data

Read various data of the driver.

Specific programming examples are explained based on the equipment configuration shown in Section 3.7.1.

(1) Reading the monitor value

Read the (feedback pulse value) of the driver of station 2 to D1.

Data No.	Description		
H000A	Cumulative feedback pulse data (hexadecimal)		

Read the cumulative feedback pulse monitor by turning on X20.

0 → X0 X0F 0 → X → 1 → 1 → 1 → 1 → 1 → 1 → 1 → 1 → 1	×1	SW80.1	 [MOV	HOA	(MO) 1/104 :	Checks data link status of station No.2. Sets monitor code (H000A) of feedback pulse in RWw4.
14	X1028		Edmon	¥4		Turns on Monitor output execution demand (RY28). Reads feedback pulse (RWr4, RWr5) to D10 and D11 when monitoring (RX28) turns on.



(2) Reading the parameter

Read parameter No.PA04 "Function selection A-1" of the driver of station 2 to D1.

Data No.	Description
H8200	Parameter group selection
H2024	Parameter No.PA04 setting (hexadecimal)

Read the parameter No.PA04 by turning on X20. The respond code at instruction code execution is set to D2.

0	X0 →/*	XOF	×1	\$\\\0.1 		(M0	Checks data link status of station No.2.
5	M0 	X20 Read corr	mand		[PLS	M302]
9	₩302 —				[SET	M303	3
11	₩303	Y1029	X1029	ГМОЛ	H8200	¥106	Writes parameter group No. write (H8200) to
				Ewov	HO	₩107	RWw6 and parameter group PA (H0000) to
					ESET	Y1029	Turns on instruction code execution demand (RY29).
					[RST	M303	3
					[SET	M304	
21	M304	Y1029	X1029		[RST	¥1029	Turns off instruction code execution demand (RY29) when instruction code execution completion (RX29) turns on.
		¥1029	X1029	ENON	H204	¥106	Writes parameter No.PA04 read (H0204) to RWw6.
					[SET	Y1029] Turns on instruction code execution demand (RY29).
					[RST	₩304	3
					[SET	M305	3
34	M305	Y1029	X1029	-Ewon	₩7	D1	Reads function selection A-1 (RWr7) and respond code (RWr6) to D1 and D2 when
					W6	D2	respond code (RWr6) to D1 and D2 when instruction code execution demand (RX29) turns on.
					[RST	Y1029	Turns off instruction code execution demand (RY29).
					[RST	N305	3
43						END	3



(3) Reading the alarm definition

Read the alarm definition of the driver of station 2 to D1.

Data No.	Description				
H0010	Occurring alarm/warning No. (hexadecimal)				

Read current alarms by turning on X20.

The respond code at instruction code execution is set to D2.

0	X0	XOF	X1	SN80 - 1 		(MO	Checks data link status of station No.2.
5	₩0 	X20 Read cor	nmand		Ebr	M 302	3
9	₩302 ——	iteau coi	IIIIailu		ESET	M303	3
11	₩303 ——	¥1029 ↓/	X1029	Емол	H10	¥106	Writes current alarm read (H0010) to RWw6.
					ESET	Y1029	Turns on instruction code execution demand (RY29).
					ERST	M303	3
			l		ESET	M304	3
19	₩304	¥1029	X1029	Емол	97	D1	Reads current alarm (RWr7) and respond code (RWr6) to D1 and D2 when instruction code
				EWOA	¥6	D2	execution demand (RX29) turns on.
					ERST	Y1029	Turns off instruction code execution demand (RY29).
			l		ERST	M304	3
28						[END	1



3.7.5 Writing the data

This section explains the programs for writing various data to the driver. Specific programming examples are explained based on the equipment configuration shown in Section 3.7.1.

(1) Writing the servo motor speed data of point table

Change the servo motor speed data in the point table No.1 of the driver of station 2 to "100".

The following shows a program example for writing data to the driver when two stations are occupied. Writing is disabled for the driver when one station is occupied.

Code No.	Description
H8D01	Write of servo motor speed data of point table No.1 (hexadecimal)

Set data	Description
K100	Servo motor speed data of point table No.1
1100	(decimal)

Write the data to the servo motor speed data of point table No.1 by turning on X20. The respond code at instruction code execution is set to D2.

0	X0	X0F ──┤	X1 —↓	\$₩80.1			—(MO	Checks data link status of station No.2.
5—	M0 	X20 Write	X1021	ition		-[PLS	M302	3
10	M302	command	. t			-[SET	M303	3
12	M303	¥1029 →↓/	X1029		[MOV	H8D01	₩106	Writes speed data (H8D01) of point table No.1 (to RWw6, and speed data (K100) to RWw7.
					Ewon	K100	¥107	$\int to RWw6, and speed data (K100) to RWw7.$
						[SEI	Y1029	¹ Turns on instruction code execution demand (RY29).
						-ERST	M303	3
						-ESE1	M304	3
22	₩304 —	¥1029 ──┤	X1029		——————————————————————————————————————	¥6	D2	Reads respond code (RWr6) to D2 when instruction code execution completion (RX29) turns on.
						-ERST	Y1029	Turns off instruction code execution demand (RY29).
			l			-ERST	M304	
29							-END	3



(2) Writing the parameter

The following shows a program example when two stations are occupied. Change parameter No.PC12 (JOG speed) of the driver of station 2 to "100". The parameter group PC is specified as follows.

Code No.	Description			
8200h	Parameter group selection			
Set data	Description			
H0002	Set data (hexadecimal)			

The parameter No.12 is changed to "100" as follows.

Code No.	Description
H820C	Parameter No.PC12 write (hexadecimal)

Set data	Description
K100	Set data (decimal)

Write the data to the parameter No.PC12 by turning on X20. The respond code at instruction code execution is set to D2.

	XOF	X1	\$¥80.1 			-(MO)	Checks data link status of station No.2.
5 MO	X20	nmand			[PLS	M302	ŀ
9 M302					-ESET	M303	}
11 M303	¥1029 ↓∕ř	X1029 —↓/*		ENOA	H8200	¥106	Writes parameter group No. write (H8200) to RWw6 and parameter group PC (H0002) to
				[MOA	H2	¥107	RWw7.
					-[SET	Y1029	Turns on instruction code execution demand (RY29).
					-ERST	M303	
					-ESET	M304	Turns off instruction code execution demand (RY29) when instruction code execution completion (RX29) turns on.
21 M304	¥1029	X1029			-ERST	Y1029	}
	¥1029	X1029		ENOA	H820C	₩106	Writes parameter No.PC12 write (H820C) to RWw6 and data (K100) to RWw7.
				Ewoa	K100	¥107	RWw6 and data (K100) to RWw7.
					Esei	Y1029	Turns on instruction code execution demand (RY29).
					-ERST	M304	}
					-ESET	M305	
36 M305	Y1029	X1029		Enoa	¥6	D2	Reads RWw6 to D2 when instruction code execution completion (RX29) turns on.
					-Erst	Y1029	Turns off instruction code execution demand (RY29).
					-ERST	M305	
43						-[END]	



(3) Driver alarm resetting program examples

(a) Deactivate the alarm of the driver of station 2 by issuing a command from the programmable PLC.

Reset the driver on the occurrence of a servo alarm by turning on X20.

	X1 SW80.1	(MO	Checks data link status of station No.2.
	X20 H Reset	CY105A	Turns on reset command (RY5A). Turns off reset command (RY5A) when trouble flag (RX5A) turns off.
9 flag	command	END	

(b) Deactivate the alarm of the driver of station 2 using the instruction code.

Code No.	Description
H8010	Alarm reset command (hexadecimal)

Set data	Description
H1EA5	Execution data (hexadecimal)

Reset the driver by turning on X20.

The respond code at instruction code execution is set to D2.

0 X0 X0F X1 SV80.1			-(MO)	Checks data link status of station No.2.
5		-[PLS	M302	
9 M302 9 H H		-[SET	M303	
	NOV	H8010	¥106	Writes alarm reset command (H8010) to RWw6 and execution data (H1EA5) to RWw7.
	NOV	H1EA5	¥107	RWw6 and execution data (H1EA5) to RWw7.
		-[SEI	Y1029	Turns on instruction code execution demand (RY29).
		-ERST	M303	
		-[SET	N304	
21 H304 Y1029 X1029 21 H H H H H	NOV	W6	D2	Reads respond code (RWr6) to D2 when instruction code execution completion (RX29) turns on.
		-ERST	Y1029	Turns off instruction code execution demand (RY29).
		-ERST	M304	+
28			-[END]	



3.7.6 Operation

This section explains the operation programs of the driver. Specific programming examples are explained based on the equipment configuration shown in Section 3.7.1.

(1) JOG operation

Perform JOG operation of the driver of station 1 and read the "current position" data.

Code No.	Description
H0001	Lower 16-bit data of current position (hexadecimal)
H0002	Upper 16-bit data of current position (hexadecimal)

Start the forward rotation JOG operation by turning on X22. Start the reverse rotation JOG operation by turning on X23.

			(MO	Checks data link status of station No.1.
			(Y1000	> Servo-on command (RY00).
communication X1000 Y1006 X22 X23 Y1002			(Y1001	> Forward rotation start (RY01).
Ready Automatic/ manual selection Ready Automatic/ Second 222 X22 X22 X23 Y1001 X22 Y1001 X23 Y1001 X23 Y1001			(Y1002	Reverse rotation start (RY02).
20 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0	Ewon	H1	¥100	Sets monitor code (H0001) of current position (lower 16 bits) to RWw0.
	Ewon	H2	W101	Sets monitor code (H0002) of current position (upper 16 bits) to RWw1.
			(Y1008	> Turns on monitor command (RY08).
	EDMOA	¥0	D10	Reads current position (RWr0, RWr1) to D10 and D11 when monitoring (RX08) turns on.
30			END	3



(2) Remote register-based position data/speed data setting

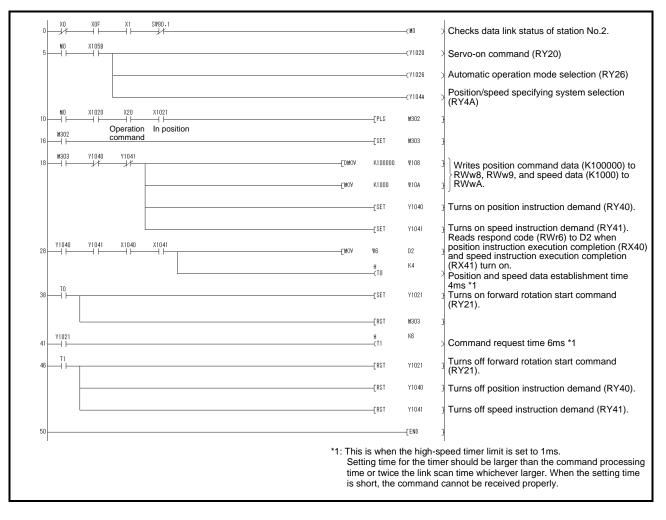
The following program example is only applicable when two stations are occupied.

Operate the driver of station 2 after specifying the position data as "100000" and the speed data as "1000" in the direct specification mode.

Preset "DDD2" in parameter No.PC30.

Set data	Description
K100000	Position command data (decimal)
K1000	Speed command data (decimal)

Execute positioning operation with position and speed settings specified in the remote register by turning on X20.





(3) Remote register-based point table No. setting (incremental value command system)

The following program example is only applicable when two stations are occupied.

Operate the driver of station 2 with incremental values after specifying the point table No.5 in the direct specification mode.

Preset "DDD" in parameter No.PA01 and "DDD" in parameter No.PA30.

Set data	Description
K5	Point table No. (decimal)

Execute positioning operation to the point table No.5 by turning on X20.

	XOF	×1	SW80.1				—(MO)	Checks data link status of station No.2.
5 MO	×1058						—(Y1020)	Servo-on command (RY20)
							—(Y1026	Automatic operation mode selection (RY26)
							—(Y104A)	Position/speed specifying system selection (RY4A)
							—(Y104B)	Incremental value selection (RY4B)
		X20	X1021	 		-ELS	M302]
17 M302	2 0	command	in position			-EREL	M303	3
19 - M303	8 Y1040			 	-Emon	K5	¥108	³ Writes point table No.5 (K5) to RWw8.
						[SET	Y1040	Turns on position instruction demand (RY40).
24 Y104	0 X1040			 	-ENOA	¥6	D2	Reads respond code (RWr6) to D2 when position instruction execution completion (RX40) turns on.
						н —(то	K4	Point table establishment time 4ms *1
32 TO						[SET	Y1021	Turns on forward rotation start command (RY21).
						-ERST	M303	3
35	1					н —(T1	K6	Command request time 6ms *1
40 T1						-ERST	Y1021	Turns off forward rotation start command (RY21).
						-ERST	Y1040	Turns off position instruction demand (RY40).
43							-END	в
Ι				**	Settin time	ng time f or twice	for the time the link so	beed timer limit is set to 1ms. er should be larger than the command processing an time whichever larger. When the setting time cannot be received properly.

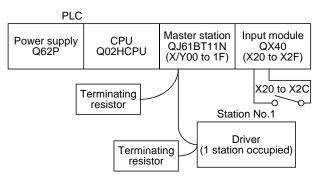


3.8 Continuous operation program example

This section shows a program example which includes a series of communication operations from a servo start. The program will be described on the basis of the equipment makeup shown in section 3.8.1, 3.8.3.

3.8.1 System configuration example when 1 station is occupied

As shown below, the CC-Link system master - local unit is loaded to run one driver (1 station occupied).



Input signal assignment

Input signal	Signal name	General operation when the input is on
X20	Reset command	Resets the driver on an occurrence of a servo alarm.
X21	Servo-on command	Turns on the servo motor. (Servo-on status)
X22	Forward rotation JOG command	Executes a forward JOG operation in the manual operation mode.
X23	Reverse rotation JOG command	Executes a reverse JOG operation in the manual operation mode.
X24	Automatic/manual selection	OFF: Manual operation mode ON: Automatic operation mode
X25	Home position return command	Executes a dog type home position return when home position return is incomplete in the automatic operation mode.
X26	Proximity dog command	OFF: Proximity dog is on. (Note) ON: Proximity dog is off.
X27	Positioning start command	Executes a positioning operation to the point table number specified by X28 to X2C when home position return is incomplete in the automatic operation mode.
X28	No. selection 1	Specifies the position for the point table No. selection 1
X29	No. selection 2	Specifies the position for the point table No. selection 2
X2A	No. selection 3	Specifies the position for the point table No. selection 3
X2B	No. selection 4	Specifies the position for the point table No. selection 4
X2C	No. selection 5	Specifies the position for the point table No. selection 5

Note. This is when the parameter No.PD16 is set to "DD0 (initial value)" (detects the dog at off).



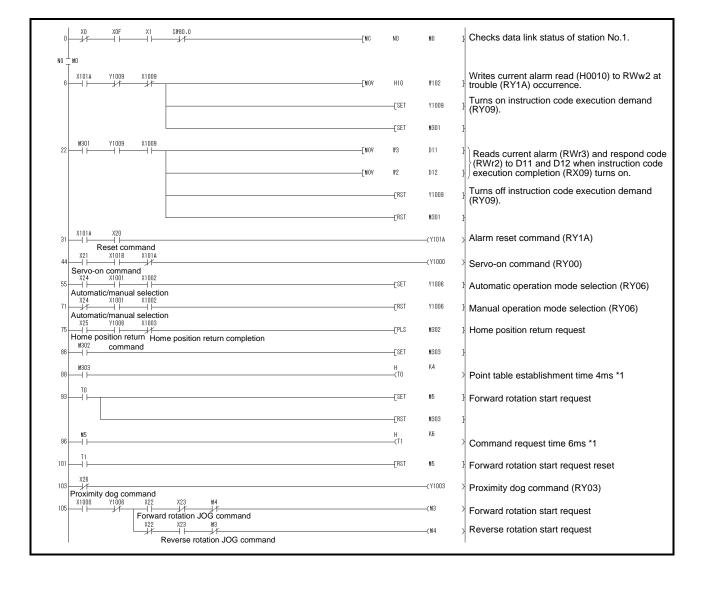
3.8.2 Program example when 1 station is occupied

POINT
To execute a dog type home position return with the CC-Link communication functions, set "□0□□" in parameter No.PD14 and use Proximity dog (DOG) with the remote input (RY03) in this example.

Operate the driver of station 1 in the positioning mode and read the "current position" data. Specific programming examples are explained based on the equipment configuration shown in Section 3.8.1.

Operation: Alarm reset, dog type home position return, JOG operation, automatic operation under point table command

Code No.	Description
H0001	Lower 16-bit data of current position (hexadecimal)
H0002	Upper 16-bit data of current position (hexadecimal)



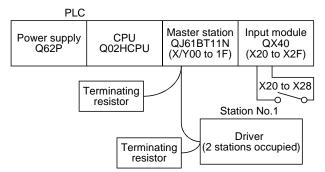


Positioning start command			1
	[PLS	N304	Positioning start command
In Rough Home position #304 position match return completion			_
	[SET	M305	B
N305	H (T3	K4	Point table establishment time 4ms *1
	(13		
	[SET	NG	Forward rotation start request
	-		
	[RST	M305	B
148 M6	H (T2	K6	Command request time 6ms *1
	[RST	MG	Forward rotation start request reset
X28 M303			
No.selection 1		(Y100A	Point table No. selection 1 (RY0A)
		(Y100B	Point table No. selection 2 (RY0B)
No.selection 2			
		(Y100C)	Point table No. selection 3 (RY0C)
		(Y100D	Paint table Na calestian 4 (DV(0D)
No.selection 4		,	Point table No. selection 4 (RY0D)
179 X2C M303		(Y100E	Point table No. selection 5 (RY0E)
No.selection 5			
182		(Y1001)	Forward rotation start (RY01)
MG			
M4			Devices and the start (D)(00)
		(Y1002	Reverse rotation start (RY02)
X101B 200	H1	¥100	Sets monitor code (H001) of current position
			(lower 16 bits) in RWw0.
[MOV	H2	¥101	Sets monitor code (H002) of current position (upper 16 bits) in RWw1.
		401000	Turns on monitor output execution demand
		(Y1008)	(RY08).
	WO	D120	Reads current position (Rwr0, RWr1) to D120
			and D121 when monitoring (RX08) turns on.
218	[MCR	NO	Н
210		FEND	
219		[END	н Н
1 *1. Thia	is when	the high o	beed timer limit is set to 1ms.
Set	ting time	for the time	er should be larger than the command processing
tim	e or twice	the link so	can time whichever larger. When the setting time
is s	hort, the	command	cannot be received properly.



3.8.3 System configuration example when 2 stations are occupied

As shown below, the CC-Link system master - local unit is loaded to run one drivers (2 station occupied).



Input signal assignment

Input signal	Signal name	General operation when the input is on		
X20	Reset command	Resets the driver on an occurrence of a servo alarm.		
X21	Servo-on command	Turns on the servo motor. (Servo-on status)		
X22	Forward rotation JOG command	Executes a forward JOG operation in the manual operation mode.		
X23	Reverse rotation JOG command	Executes a reverse JOG operation in the manual operation mode.		
X24	Automatic/manual selection	OFF: Manual operation mode ON: Automatic operation mode		
X25	Home position return command	Executes a dog type home position return when home position return is incomplete in the automatic operation mode.		
X26	Proximity dog command	OFF: Proximity dog is on. (Note) ON: Proximity dog is off.		
X27	Positioning start command	Executes a positioning operation with position and speed settings specified in the remote register when home position return is completed in the automatic operation mode.		
X28	Position/speed setting system changing command	Changes to position/speed specification by the remote register.		

Note. This is when the parameter No.PD16 is set to "DD0 (initial value)" (detects the dog at off).



3.8.4 Program example when 2 stations are occupied

POINT

• To execute a dog type home position return with the CC-Link communication functions, set "D0DD" in parameter No.PD14 and use Proximity dog (DOG) with the remote input (RY03) in this example.

Operate the driver of station 1 in the positioning mode and read the "motor speed" data.

Preset the parameter No.PC30 to " \Box \Box \Box 2".

Specific programming examples are explained based on the equipment configuration shown in Section 3.8.3.

Operation: Alarm reset, dog type home position return, JOG operation, automatic operation under point table command

Code No.	Description
H0016	32-bit data of motor speed (hexadecimal)

Code No.	Description
K50000	Position command data (decimal)
K100	Speed command data (decimal)

	—Еис	NO	MO	Checks data link status of station No.1.
N0 H0 X1034 Y1009 X1009 6 1 1 7 7 7 7 7	[NOA	H10	¥102	Writes current alarm read (H0010) to RWw2 at trouble (RX3A) occurrence.
		-ESET	Y1009	Turns on instruction code execution demand (RY09).
		[SET	M301	+
22 H301 Y1009 X1009	[HOV	₩3	D11	Reads current alarm (RWr3) and respond code
	[HOV	₩2	D12	(RWr2) to D11 and D12 when instruction code execution completion (RX09) turns on.
		-ERST	Y1009	Turns off instruction code execution demand (RY09).
		[RST	M301	
31 X103A X20 Reset command			(Y103A)	Alarm reset command (RY3A)
			-(Y1000)	Servo-on command (RY00)
Servo-on command x24 x1001 x1002 55 1 1 1		ESET	¥1006	Automatic operation mode selection (RY06)
Automatic/manual selection x24 x1001 x1002 71 x24 x1001 x1002			Y1006 ·	Manual operation mode selection (RY06)
Automatic/manual selection		[PLS	M302	
Home position return Home position return completion		-		Home position return request
		—[Set	M303	
88		(T0		Point table establishment time 4ms *1
		[SET	M5	Forward rotation start request
		[RST	M303	-
96 M5		H (T1	К6	Command request time 6ms *1
		[RST	M5	Forward rotation start request reset
103 X26			-(Y1003)	Proximity dog command (RY03)
Próximity dog command X1000 Y1006 X22 X23 N4 105			(M3	Forward rotation start request
Forward rotation JOG command				
Reverse rotation JOG command			—(M4)	Reverse rotation start request



23-		1/speed so 11006	etting syste	em chang	ing command			(Y102A	 Position/speed specifying system selection (RY2A)
33	×27		x1001 In	Rough	Home position		[PLS	M304	3
40	M304		position	match	return completion		ESET	M305	3
42	₩305 ——	¥1020 →↓ ř	¥1021			[DMOV	K50000	¥104	Writes position command data (K50000) to RWw4, RWw5, and speed data (K100) to
						[MOV	K100	₩106	$\mathbb{R}^{\mathcal{W}}$
							[SET	Y1020] Turns on position instruction demand (RY2
			l				[SET	Y1021	Turns on speed instruction demand (RY21) Reads respond code (RWr2) to D2 when
52	¥1020	¥1021 →	X1020	×1021		Ewon	₩2	D2	position instruction execution completion (F and speed instruction execution completion
				l			н (ТЗ	K4	 (RX21) turn on. Position and speed data establishment time 4ms *1
62	T3 ──↓						[SET	MG	Positioning start command
							ERST	M305	3
85 -	M6 						H (T2	K6	Command request time 6ms *1
70							ERST	MB	Positioning start command reset
							[RST	Y1020	Turns off position instruction demand (RY2
							CRST	Y1021	Turns off speed instruction demand (RY21)
74	M3 							(Y1001	> Forward rotation start (RY01)
84	M4 ──┤							(Y1002	> Reverse rotation start (RY02)
92	X103B					[NOV	H16	₩100	Sets monitor code (H0016) of motor speed RWw0.
								(Y1008	Turns on monitor output execution demand (RY08).
		X1008				Ednoa	WO	D120	Reads motor speed (RWr0, RWr1) to D120 D121 when monitoring (RX08) turns on.
80							[MCR	NO	J
09								(END	J
						Sett	ing time	for the tin	s speed timer limit is set to 1ms. ner should be larger than the command proces scan time whichever larger. When the setting t



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4. SIGNALS AND WIRING

	 Any person who is involved in wiring should be fully competent to do the work. 					
	 Before wiring, turn off the power and wait for 15 minutes or more until the charge lamp turns off. Then, confirm that the voltage between P(+) and N(-) is safe with a voltage tester and others. Otherwise, an electric shock may occur. In addition, always confirm from the front of the driver whether the charge lamp is off or not. Ground the driver and the servo motor securely. 					
	 Do not attempt to wire the driver and servo motor until they have been installed. Otherwise, you may get an electric shock. 					
	 The cables should not be damaged, stressed excessively, loaded heavily, or pinched. Otherwise, you may get an electric shock. 					
	 To avoid an electric shock, insulate the connections of the power supply terminals. 					
	 Wire the equipment correctly and securely. Otherwise, the servo motor may operate unexpectedly, resulting in injury. 					
	 Connect cables to correct terminals to prevent a burst, fault, etc. 					
	• Ensure that polarity $(+, -)$ is correct. Otherwise, a burst, damage, etc. may occur.					
	 The surge absorbing diode installed to the DC relay designed for control output 					
	should be fitted in the specified direction. Otherwise, the signal is not output due to					
	a fault, disabling the forced stop (EMG) and other protective circuits.					
	Driver Driver					
	DOCOM 24 V DC (DOCOMD) H Control output RA For sink output interface For source output interface					
	 Use a noise filter, etc. to minimize the influence of electromagnetic interference, which may be given to electronic equipment used near the driver. 					
	 Do not install a power capacitor, surge suppressor or radio noise filter (FR-BIF- (H) :Mitsubishi Electric Corporation) with the power line of the servo motor. 					
	 When using the regenerative resistor, switch power off with the alarm signal. Otherwise, a transistor fault or the like may overheat the regenerative resistor, causing a fire. 					
	 Do not modify the equipment. 					
	 Connect the servo amplifier power output (U/V/W) to the servo motor power input (U/V/W) directly. Do not let a magnetic contactor, etc. intervene. Otherwise, it may cause a malfunction. 					
	Driver Servo motor					



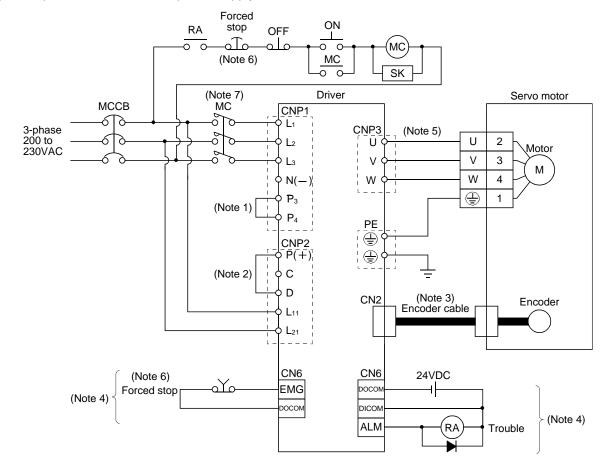
4. SIGNALS AND WIRING

4.1 Input power supply circuit					
	 Always connect a magnetic contactor (MC) between the main circuit power supply and L₁, L₂, and L₃ of the driver, and configure the wiring to be able to shut down the power supply on the side of the driver's power supply. If a magnetic contactor (MC) is not connected, continuous flow of a large current may cause a fire when the driver malfunctions. 				
	 Use the trouble (ALM) to switch power off. Otherwise, a regenerative transistor fault or the like may overheat the regenerative resistor, causing a fire. 				
	 The N- terminal is not a neutral point of the power supply. Incorrect wiring will cause a burst, damage, etc. 				
	 Check the servo amplifier model, and then input proper voltage to the servo amplifier power supply. If input voltage exceeds the upper limit of the specification, the servo amplifier will break down. 				

Wire the power supply and main circuit as shown below so that the servo-on (RYn0) turns off as soon as alarm occurrence is detected and power is shut off.

A no-fuse breaker (MCCB) must be used with the input cables of the power supply.





(1) For 3-phase 200 to 230VAC power supply to LECSC2-T

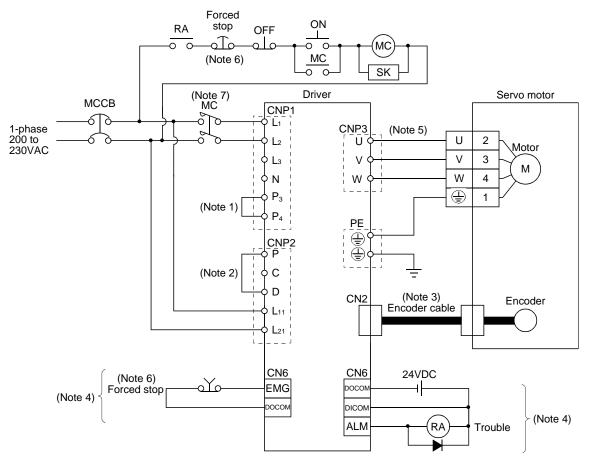
Note 1. Always connect P3 and P4. (Factory-wired.)

- 2. Always connect P and D. (Factory-wired.) When using the regenerative option, refer to section 13.2.
- 3. For encoder cable, use of the option cable is recommended. Refer to section 13.1 for selection of the cable.
- 4. For the sink I/O interface. For the source I/O interface, refer to section 4.8.3.
- 5. Refer to section 4.10.
- 6. Configure a circuit to turn off forced stop (EMG) when the main circuit power is turned off to prevent an unexpected restart of the servo amplifier.
- 7. Use a magnetic contactor with an operation delay time (interval between current being applied to the coil until closure of contacts) of 80 ms or less.

Depending on the main circuit voltage and operation pattern, bus voltage decreases, and that may cause the forced stop deceleration to shift to the dynamic brake deceleration. When dynamic brake deceleration is not required, slow the time to turn off the magnetic contactor.







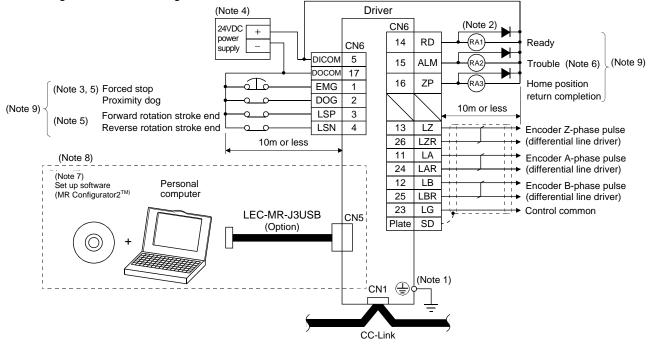
Note 1. Always connect P3 and P4. (Factory-wired.)

- 2. Always connect P and D. (Factory-wired.) When using the regenerative option, refer to section 13.2.
- 3. For encoder cable, use of the option cable is recommended. Refer to section 13.1 for selection of the cable.
- 4. For the sink I/O interface. For the source I/O interface, refer to section 4.8.3.
- 5. Refer to section 4.10.
- 6. Configure a circuit to turn off forced stop (EMG) when the main circuit power is turned off to prevent an unexpected restart of the servo amplifier.
- 7. Use a magnetic contactor with an operation delay time (interval between current being applied to the coil until closure of contacts) of 80 ms or less.

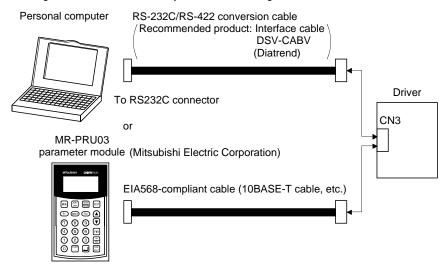
Depending on the main circuit voltage and operation pattern, bus voltage decreases, and that may cause the forced stop deceleration to shift to the dynamic brake deceleration. When dynamic brake deceleration is not required, slow the time to turn off the magnetic contactor.



4.2 I/O signal connection diagram



- Note 1. To prevent an electric shock, always connect the protective earth (PE) terminal (terminal marked) of the driver to the protective earth (PE) of the control box.
 - 2. Connect the diode in the correct direction. If it is connected reversely, the driver will be faulty and will not output signals, disabling the emergency stop (EMG) and other protective circuits.
 - 3. The forced stop switch (normally closed contact) must be installed.
 - 4. Supply 24VDC±10% 150mA current for interfaces from the outside. 150mA is the value applicable when all I/O signals are used. The current capacity can be decreased by reducing the number of I/O points. Refer to section 4.8.2 (1) that gives the current value necessary for the interface.
 - 5. When starting operation, always turn on forced stop (EMG) and Forward/Reverse rotation stroke end (LSP/LSN). (Normally closed contacts)
 - 6. Trouble (ALM) turns on in normal alarm-free condition.
 - 7. Use LEC-MC2E.
 - Personal computers or parameter modules can also be connected via the CN3 connector, enabling RS-422 communication. Note that using the USB communication function (CN5 connector) prevents the RS-422 communication function (CN3 connector) from being used, and vice versa. They cannot be used together.



9. For the sink I/O interface. For the source I/O interface, refer to section 4.8.3.



4.3 Explanation of power supply system

4.3.1 Signal explanations

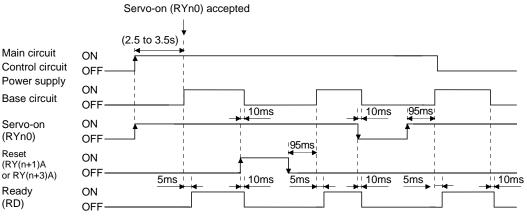
POINT	
 For the lay 	out of connector and terminal block, refer to outline drawings in
chapter 12.	

Abbreviation	Connection target (application)		Description
		Supply the following power to L_1 , L_2 , L_3 connect the power supply to L_1 , L_2 , and keeping	3. For the 1-phase 200 to 230VAC power supply, eep L ₃ open.
L2	Main circuit power supply	Driver Power supply	LECSC2-T5 / LECSC2-T7 LECSC2-T8 / LECSC2-T9
L3		3-phase 200 to 230VAC, 50/60Hz 1-phase 200 to 230VAC, 50/60Hz	$\frac{L_1 \cdot L_2 \cdot L_3}{L_1 \cdot L_2}$
P C D	Regenerative option	• •	e resistor, connect P(+) and D. (Factory-wired) onnect P(+) and D, and connect regenerative option
	Control circuit power supply	Supply the following power to L ₁₁ · L ₂₁ . Driver Power supply 1-phase 200 to 230VAC, 50/60Hz	LECSC2-T5 / LECSC2-T7 LECSC2-T8 / LECSC2-T9 L11 · L21
U V W	Servo motor power	Connect to the servo motor power supply close the motor power line. Otherwise, a r	terminals (U, V, W). During power-on, do not open or nalfunction or faulty may occur.
Ν	Regenerative converter Brake unit	Do not connect to driver.	
	Protective earth (PE)	Connect to the earth terminal of the serve control box to perform grounding.	o motor and to the protective earth (PE) of the



4.3.2 Power-on sequence

- (1) Power-on procedure
 - 1) Always wire the power supply as shown in above section 4.1 using the magnetic contactor with the main circuit power supply (three-phase: L1, L2, L3, single-phase: L1, L2). Configure up an external sequence to switch off the magnetic contactor as soon as an alarm occurs.
 - 2) Switch on the control circuit power supply L11, L21 simultaneously with the main circuit power supply or before switching on the main circuit power supply. If the main circuit power supply is not on, the display shows the corresponding warning. However, by switching on the main circuit power supply, the warning disappears and the driver will operate properly.
 - 3) The driver can accept the servo-on (RYn0) about 2.5 to 3.5s after the main circuit power supply is switched on. Therefore, when servo-on (RYn0) is switched on simultaneously with the main circuit power supply, the base circuit will switch on in about 2.5 to 3.5s, and the ready (RD) will switch on in further about 5ms, making the driver ready to operate. (Refer to paragraph (2) in this section.)
 - 4) When the reset (RY(n+1)A or RY(n+3)A) is switched on, the base circuit is shut off and the servo motor shaft coasts.
- (2) Timing chart



Power-on timing chart



(3) Forced stop

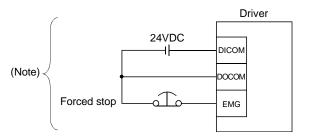
• Provide an external forced stop circuit to ensure that operation can be stopped and CAUTION power switched off immediately.

Make up a circuit that shuts off main circuit power as soon as EMG is turned off at a forced stop. When EMG is turned off, the dynamic brake is operated to bring the servo motor to a sudden stop. At this time, the display shows the servo forced stop warning (AE6).

During ordinary operation, do not use the external forced stop (EMG) to alternate stop and run.

The driver life may be shortened.

Also, if the forward rotation start (RYn1) and reverse rotation start (RYn2) are on or a pulse train is input during a forced stop, the servo motor will rotate as soon as the warning is reset. During a forced stop, always shut off the run command. Note also that during a forced stop, RYn1 and RYn2 must be off.



Note. For the sink I/O interface. For the source I/O interface, refer to section 4.8.3.



4.3.3 CNP1, CNP2, CNP3 wiring method

POINT

 Refer to table 13.1 in section 13.9 for the wire sizes used for wiring.

Use the supplied driver power supply connectors for wiring of CNP1, CNP2 and CNP3.

(1) LECSC2-T

(a) Driver power supply connectors

Driver power supply connectors

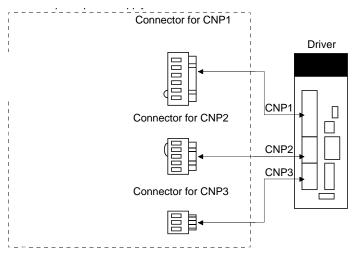


Table 3.1 Connector and applicable wire

Connector Receptacle assembly	Receptacle	Applicable wire		Stripped	Manufacturer	Remarks
	assembly	Size	Insulator OD	length [mm]	Manufacturer	Remarks
CNP1	K05A01490216				MITSUBISHI	Open tool comes with.
CNP2	K05A01490209	AWG 18 to 14	39 mm or shorter	9	ELECTRIC SYSTEM & SERVICE CO., LTD	-
CNP3	K05A01490210				(Note)	-

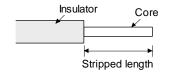
Note. Please purchase from distributor or distributor of Mitsubishi Electric Corporation.



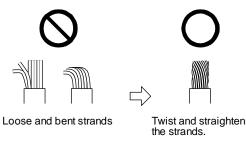
(2) Cable connection procedure

(a) Fabrication on cable insulator

Refer to table 3.1 for stripped length of cable insulator. The appropriate stripped length of cables depends on their type, etc. Set the length considering their status.



Twist strands lightly and straighten them as follows.



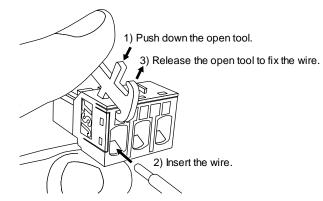
You can also use a ferrule to connect with the connectors. The following shows references to select ferrules according to wire sizes.

Driver	Wire size	Ferrule model (F	Crimping tool	
Diivei	WITE SIZE	For one	For two	(Phoenix Contact)
LECSS2-T5 to	AWG 16	AI1.5-10BK	AI-TWIN2×1.5-10BK	CRIMPFOX-ZA3
LECSS2-T9 AWG 14		AI2.5-10BU		CRIMPFOX-ZA3

(b) Inserting wire

Insert the open tool as follows and push down it to open the spring. While the open tool is pushed down, insert the stripped wire into the wire insertion hole. Check the insertion depth so that the cable insulator does not get caught by the spring.

Release the open tool to fix the wire. Pull the wire lightly to confirm that the wire is surely connected.

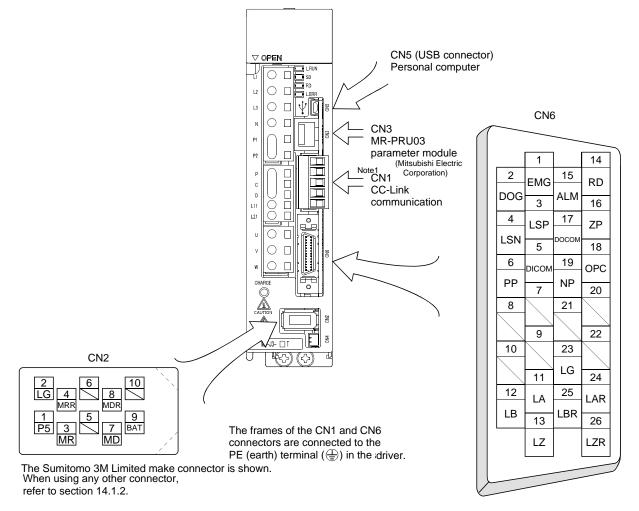




4.4 Connectors and signal arrangements

POINT	
The pin cor	figurations of the connectors are as viewed from the cable
connector v	viring section.

The driver front view shown is that of the LECSC2-T5. Refer to chapter 11 Outline Drawings for the appearances and connector layouts.



Note1.

CN1 Connector : Accessory MITSUBISHI ELECTRIC SYSTEM & SERVICE CO., LTD Part No : K05A50230600

Please purchase from distributor or distributor of Mitsubishi Electric Corporation.



4.5 Signal (device) explanation

4.5.1 I/O devices

The CN6 connector provides three pins for inputs and three other pins for outputs. Devices assigned to these pins are changeable. To make this change, configure parameter settings of Nos. PD06 to PD11, PD12, and PD14. Refer to section 4.8.2 for the I/O interfaces (symbols in the I/O Division field in the table) of the corresponding connector pins.

Pin type	CN6 connector pin No.	I/O division	Device in initial status	Parameter of change target device
Input-only pins	1	DI-1	Forced stop (EMG)	
	2		Proximity dog (DOG)	No.PD06
	3		Forward rotation stroke end (LSP)	No.PD07
	4		Reverse rotation stroke end (LSN)	No.PD08
Output-only pins	14	DO-1	Ready (RD)	No.PD09
	15		Trouble (ALM)	No.PD10
	16		Home position return completion (ZP)	No.PD11



(1) Input device

POINT

• Input devices assigned to the CN6 connector pins cannot be used with the remote input of the CC-Link communication function.

Device	Symbol	Connector pin No.	Functions/Applications
Forced stop	EMG	CN6-1	Forced stop (EMG) is fixed at CN6-1. Assigning this device to any other pin is not allowed. For device details, refer to section 3.5.1 (1).
Servo-on	SON	/	For device details, refer to section 3.5.1 (1).
Forward rotation start	ST1	/	
Reverse rotation start	ST2	/	
Proximity dog	DOG	CN6-2 (Note)	
Forward rotation stroke end	LSP	CN6-3 (Note)	
Reverse rotation stroke end	LSN	CN6-4 (Note)	
Automatic/manual selection	MD0		
Temporary stop/Restart	TSTP	/	
Internal torque limit selection	TL1		
Proportion control	PC	/	
Gain changing	CDP		
Reset	RES		
Clear	CR		Turn CR on to clear the position control counter droop pulses on its leading edge. The pulse width should be 10ms or more. When the parameter No.PD22 setting is " $\Box \Box \Box$ 1", the pulses are always cleared while CR is on.

Note. These are pin Nos. assigned at default.



(2) Output device

POINT

• Output devices assigned to the CN6 connector pins can be used with the remote output of the CC-Link communication function.

Device	Symbol	Connector pin No.	Functions/Applications
Ready	RD	CN6-14 (Note)	For device details, refer to section 3.5.1 (2).
Trouble	ALM	CN6-15 (Note)	ALM turns off when power is switched off or the protective circuit is activated to shut off the base circuit. Without alarm occurring, ALM turns on within 1.5s after power-on. The significance of this device is opposite of that of remote output (RX (n+1)A or RX (n+3)A).
Home position return completion	ZP	CN6-16 (Note)	For device details, refer to section 3.5.1 (2).
In position	INP	\sim	
Rough match	CPO		
Limiting torque	TLC	\sim	
Electromagnetic brake interlock	MBR		
Temporary stop	PUS		
Warning	WNG		
Battery warning	BWNG		
Movement completion	MEND		
dynamic brake interlock	DB		
Position range	POT		
Point table No. output 1	PT0		
Point table No. output 2	PT1		
Point table No. output 3	PT2		
Point table No. output 4	PT3		
Point table No. output 5	PT4		
Point table No. output 6	PT5		
Point table No. output 7	PT6		
Point table No. output 8	PT7		
Speed command reached	SA		SA turns on when servo-on (SON) is on and the commanded speed is at the target speed. SA always turns on when servo-on (SON) is on and the commanded speed is 0r/min. SA turns off when servo-on (SON) is off or the commanded speed is in acceleration/deceleration.



Device	Symbol	Connector pin No.	Functions/Applications
Zero speed	ZSP		ZSP turns on when the servo motor speed is zero speed (50r/min) or less. Zero speed can be changed using parameter No.PC17. Example Zero speed is 50r/min Forward 70r/min 0N level 70r/min direction 0r/min 0N level 50r/min direction 0r/min 0FF level 100 0r/min direction 0FF level 100 0r/min 0FF level 100 0r/min direction 0FF level 100 0r/min 0FF level 100 0r/min 0FF level 100 0FF 0FF 0FF 0FF 0FF 0FF 0FF 0FF 0FF
Variable gain selection	CDPS		CDPS is on during gain changing.

Note. These are pin Nos. assigned at default.

4.5.2 Output signals

Refer to section 4.8.2 for the output interfaces (symbols in the I/O Division field in the table) of the corresponding connector pins.

Signal	Symbol	Connector pin No.	Functions/Applications	I/O division
Encoder A-phase pulse (differential line driver)	LA LAR	CN6-11 CN6-24	- · · · · · · · · · · · · · · · · · · ·	
Encoder B-phase pulse (differential line driver)	LB LBR			
Encoder Z-phase pulse (differential line driver)	LZ LZR	CN6-13 CN6-26	Outputs the zero-point signal of the encoder in the differential line driver system. One pulse is output per servo motor revolution. This signal turns on when the zero-point position is reached. (Negative logic) The minimum pulse width is about 400µs. For home position return using this pulse, set the creep speed to 100r/min. or less.	DO-2



4.5.3 Power supply

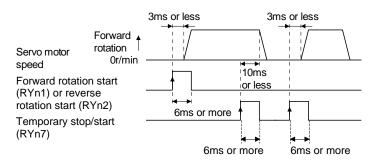
Signal	Symbol	Connector pin No.	Functions/Applications	I/O division
Digital I/F power supply input	DICOM	CN6-5	Used to input 24VDC (24VDC±10% 150mA) for I/O interface. The power supply capacity changes depending on the number of I/O interface points to be used. Connect the plus of 24VDC terminal external power supply for the sink interface.	
Digital I/F common	connected internally. Separated from LG.		Connect the plus of 24VDC terminal external power supply for the	
Control common	LG	CN6-23	Common terminal for the differential line driver of the encoder pulses (LA · LAR · LB · LBR · LZ · LZR).	
Shield	SD	Plate	Connect the external conductor of the shield cable.	

4.6 Detailed description of signals (devices)

- 4.6.1 Forward rotation start reverse rotation start temporary stop/restart
- (1) A forward rotation start (RYn1) or a reverse rotation start (RYn2) should make the sequence which can be used after the main circuit has been established. These signals are invalid if it is switched on before the main circuit is established.

Normally, it is interlocked with the ready signal (RD).

(2) A start in the driver is made when a forward rotation start (RYn1) or a reverse rotation start (RYn2) changes from OFF to ON. The delay time of the driver's internal processing is max. 3ms. The delay time of other devices is max. 10ms.



- (3) The ON time of a forward rotation start (RYn1), a reverse rotation start (RYn2) or temporary start/stop (RYn7) signal should be 6ms or longer to prevent a malfunction.
- (4) During operation, the forward rotation start (RYn1) or reverse rotation start (RYn2) is not accepted. The next operation should always be started after the rough match (RXn2) is output with the rough match output range set to "0" or after the movement completion (RXnC) is output.



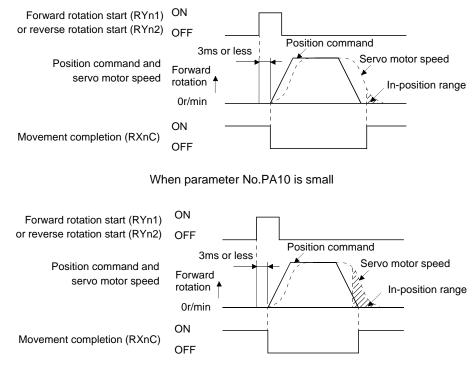
4.6.2 Movement completion • rough match • in position

POINT

• If an alarm cause, etc. are removed and servo-on occurs after a stop is made by servo-off, alarm occurrence or Forced stop (EMG) ON during automatic operation, Movement completion (MEND), Rough-match, (CPO) and In position (INP) are turned on. To resume operation, confirm the current position and the selected point table No. for preventing unexpected operation.

(1) Movement completion

The following timing charts show the output timing relationships between the position command generated in the driver and the movement completion (RYnC). This timing can be changed using parameter No.PA10 (in-position range). RYnC turns ON in the servo-on status.

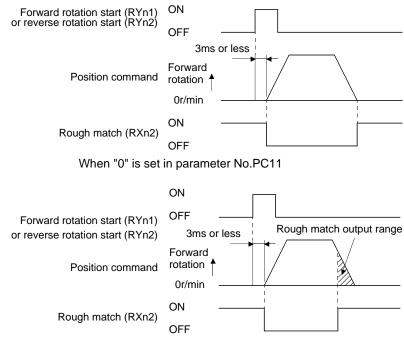


When parameter No.PA10 is large



(2) Rough match

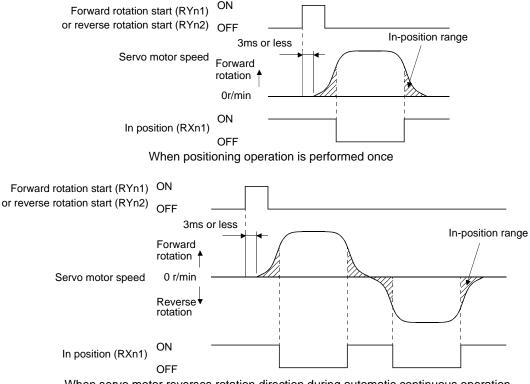
The following timing charts show the relationships between the signal and the position command generated in the driver. This timing can be changed using parameter No.PC11 (rough match output range). RXn2 turns ON in the servo-on status.



When more than "0" is set in parameter No.PC11

(3) In position

The following timing chart shows the relationship between the signal and the feedback pulse of the servo motor. This timing can be changed using parameter No.PA10 (in-position range). turns on RYn1 in the servo-on status.



When servo motor reverses rotation direction during automatic continuous operation

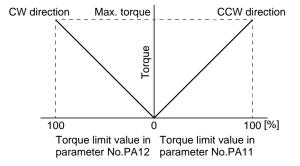


4.6.3 Torque limit

• If the torque limit is canceled during servo lock, the servo motor may suddenly rotate according to position deviation in respect to the command position.

(1) Torque limit and torque

By setting parameter No.PA11 (forward rotation torque limit) or parameter No.PA12 (reverse rotation torque limit), torque is always limited to the maximum value during operation. A relationship between the limit value and servo motor torque is shown below.



(2) Torque limit value selection

As shown below, the forward rotation torque limit (parameter No.PA11), reverse rotation torque limit (parameter No.PA12) or internal torque limit 2 (parameter No.PC35) can be chosen using the external torque limit selection (RY(n+2)6).

				Torque limit to be enabled		
(Note) RY(n+2) 6	Limit va	lue	status	CCW driving/CW	CW driving/CCW	
				regeneration	regeneration	
0				Parameter No.PA11	Parameter No.PA12	
4	Parameter No.PC35	>	Parameter No.PA11 Parameter No.PA12	Parameter No.PA11	Parameter No.PA12	
1	Parameter No.PC35	<	Parameter No.PA11 Parameter No.PA12	Parameter No.PC35	Parameter No.PC35	

Note. 0: OFF 1: ON

(3) Limiting torque (RXn4)

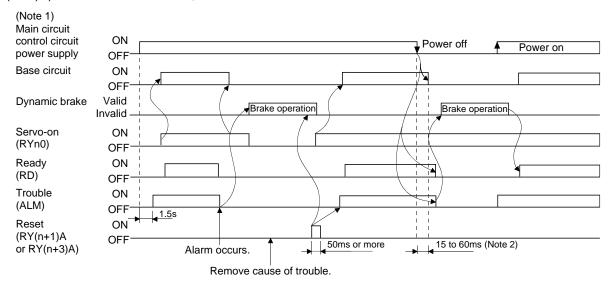
RXn4 turns on when the servo motor torque reaches the torque limited.



4.7 Alarm occurrence timing chart

When an alarm has occurred, remove its cause, make sure that the operation signal is not being input, ensure safety, and reset the alarm before restarting operation.
 As soon as an alarm occurs, turn off Servo-on (RYn0) and power off.

When an alarm occurs in the driver, the base circuit is shut off and the servo motor is coated to a stop. Switch off the main circuit power supply in the external sequence. To reset the alarm, switch the control circuit power supply from off to on, press the "SET" button on the current alarm screen, or turn the reset (RY(n+1)A or RY(n+3)A) from off to on. However, the alarm cannot be reset unless its cause is removed.



Note 1. Shut off the main circuit power as soon as an alarm occurs.

- 2. Changes depending on the operating status.
- (1) Overcurrent, overload 1 or overload 2

If operation is repeated by switching control circuit power off, then on to reset the overcurrent (A32), overload 1 (A50) or overload 2 (A51) alarm after its occurrence, without removing its cause, the driver and servo motor may become faulty due to temperature rise. Securely remove the cause of the alarm and also allow about 30 minutes for cooling before resuming operation.

(2) Regenerative alarm

If operation is repeated by switching control circuit power off, then on to reset the regenerative (A30) alarm after its occurrence, the external regenerative resistor will generate heat, resulting in an accident.

(3) Instantaneous power failure

Undervoltage (A10) occurs when the input power is in either of the following statuses.

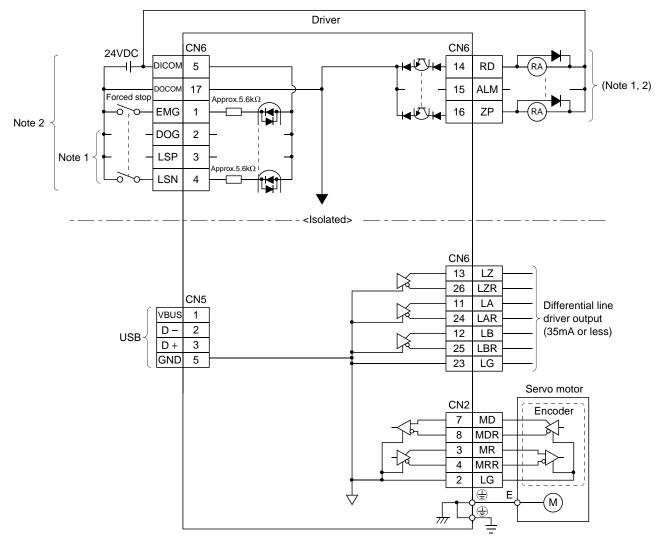
- A power failure of the control circuit power supply continues for 60ms or longer and the control circuit is not completely off.
- During the servo-on status, the bus voltage dropped to 200VDC or less for LECSC2-T \Box .
- (4) Incremental system

When an alarm occurs, the home position is lost. When resuming operation after deactivating the alarm, make a home position return.



4.8 Interface

4.8.1 Internal connection diagram



Note 1. Devices assigned to these pins can be changed in the parameter settings.

2. For this sink I/O interface. For the source I/O interface, refer to section 4.8.3.

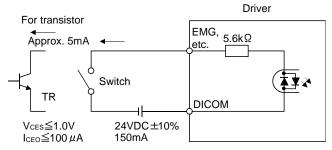


4.8.2 Detailed description of interfaces

This section provides the details of the I/O signal interfaces (refer to the I/O division in the table) given in section 4.5.1. Refer to this section and make connection with the external equipment.

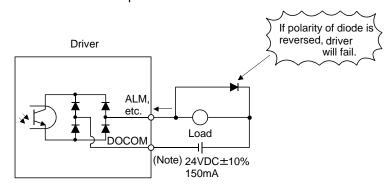
(1) Digital input interface DI-1

Give a signal with a relay or open collector transistor. Refer to section 4.8.3 for the source input.



(2) Digital output interface DO-1

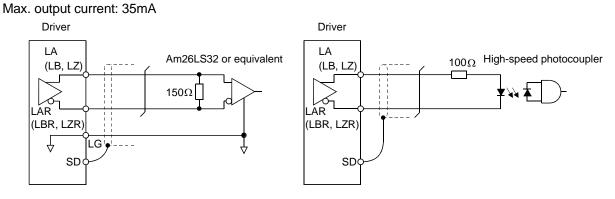
A lamp, relay or photocoupler can be driven. Install a diode (D) for an inductive load, or install an inrush current suppressing resistor (R) for a lamp load. (Rated current: 40mA or less, maximum current: 50mA or less, inrush current: 100mA or less) A maximum of 2.6V voltage drop occurs in the driver. Refer to section 4.8.3 for the source output.



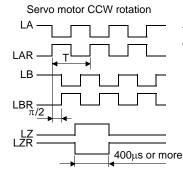
Note. If the voltage drop (maximum of 2.6V) interferes with the relay operation, apply high voltage (up to 26.4V) from external source.



- (3) Encoder output pulse DO-2 (Differential line driver system)
 - (a) Interface



(b) Output pulse



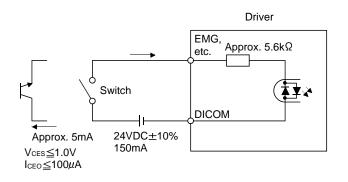
Time cycle (T) is determined by the settings of parameter No.PA15 and PC19.



4.8.3 Source I/O interfaces

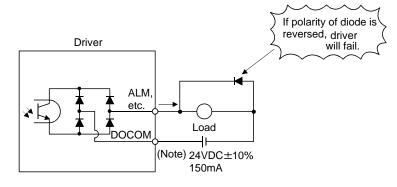
In this driver, source type I/O interfaces can be used. In this case, all DI-1 input signals and DO-1 output signals are of source type. Perform wiring according to the following interfaces.

(1) Digital input interface DI-1



(2) Digital output interface DO-1

A maximum of 2.6V voltage drop occurs in the driver.

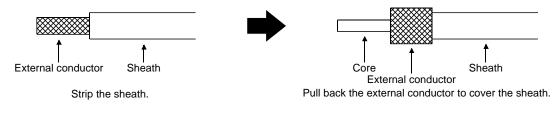


Note. If the voltage drop (maximum of 2.6V) interferes with the relay operation, apply high voltage (up to 26.4V) from external source.

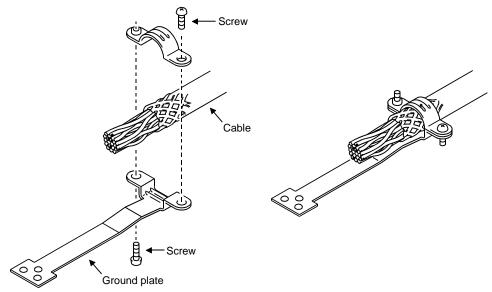


4.9 Treatment of cable shield external conductor

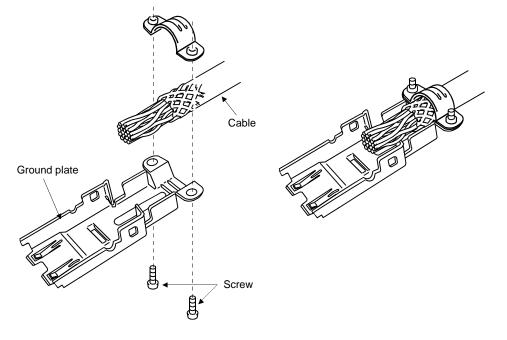
In the case of the CN2 and CN6 connectors, securely connect the shielded external conductor of the cable to the ground plate as shown in this section and fix it to the connector shell.



(1) For CN6 connector (Sumitomo 3M Limited connector)



(2) For CN2 connector (Sumitomo 3M Limited or Molex connector)



4.10 Connection of driv	ver and servo motor		
		•	V, W) to the servo motor power input etic contactor, etc. intervene.
	Driver	Servo motor	Driver U V W W W

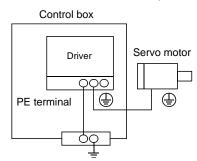
4.10.1 Connection instructions

WARNING	 Insulate the connections of the power supply terminals to prevent an electric shock. 	
	 Connect the wires to the correct phase terminals (U, V, W) of the driver and servo motor. Not doing so may cause unexpected operation. Do not connect AC power supply directly to the servo motor. Otherwise, a fault may occur. 	
	POINT	

• Refer to section 13.1 for the selection of the encoder cable.

This section indicates the connection of the servo motor power (U, V, W). Use of the optional cable and connector set is recommended for connection between the driver and servo motor. When the options are not available, use the recommended products. Refer to section 13.1 for details of the options.

(1) For grounding, connect the earth cable of the servo motor to the protective earth (PE) terminal () of the driver and connect the ground cable of the driver to the earth via the protective earth of the control box. Do not connect them directly to the protective earth of the control panel.

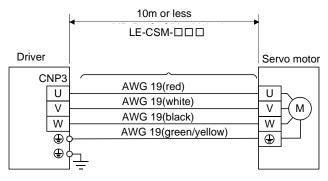


(2) Do not share the 24VDC interface power supply between the interface and lock. Always use the power supply designed exclusively for the lock.



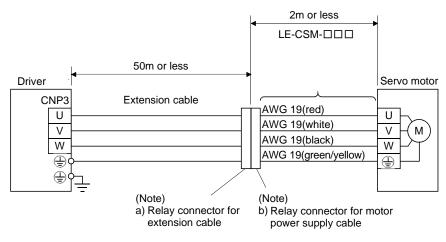
- 4.10.2 Power supply cable wiring diagrams
- (1) LE-D-D series servo motor

(a) When cable length is 10m or less



(b) When cable length exceeds 10m

When the cable length exceeds 10m, fabricate an extension cable as shown below. In this case, the motor power supply cable pulled from the servo motor should be within 2m long. Refer to section 13.4 for the wire used for the extension cable.

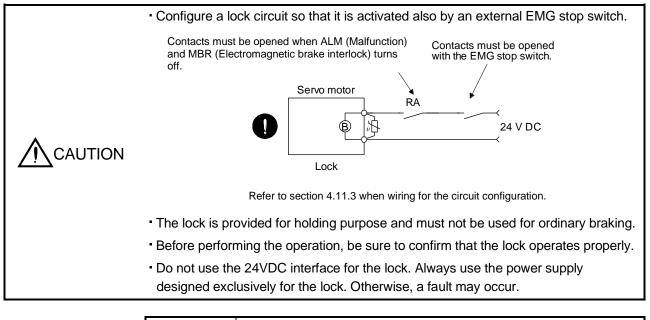


Note. Use of the following connectors is recommended when ingress protection (IP65) is necessary.

Relay connector	Description	Protective structure
a) Relay connector for extension cable	Connector: RM15WTPZ-4P(71) Cord clamp: RM15WTP-CP(5)(71) (Hirose Electric) T Numeral changes depending on the cable OD	IP65
b) Relay connector	Connector: RM15WTJA-4S(71) Cord clamp: RM15WTP-CP(8)(71) (Hirose Electric) ^T Numeral changes depending on the cable OD	IP65

4.11 Servo motor with a lock

4.11.1 Safety precautions



POINT

 Refer to section 16 for specifications such as the power supply capacity and operation delay time of the lock.

Note the following when the servo motor equipped with a lock is used.

- 1) Do not share the 24VDC interface power supply between the interface and lock. Always use the power supply designed exclusively for the lock.
- 2) The lock will operate when the power (24VDC) switches off.
- 3) Switch off the servo-on (RYn0) after the servo motor has stopped.

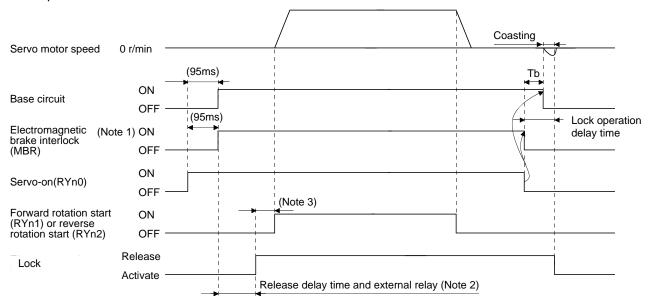
Using parameter No.PC16 (electromagnetic brake sequence output), set a time delay (Tb) at servo-off from lock operation to base circuit shut-off as in the timing chart shown in section 4.11.2 in this section.



4.11.2 Timing charts

(1) Servo-on (RYn0) command (from driver) ON/OFF

Tb [ms] after the servo-on (RYn0) is switched off, the servo lock is released and the servo motor coasts. If the lock is made valid in the servo lock status, the lock life may be shorter. Therefore, when using the lock in a vertical lift application or the like, set Tb to about the same as the lock operation delay time to prevent a drop.

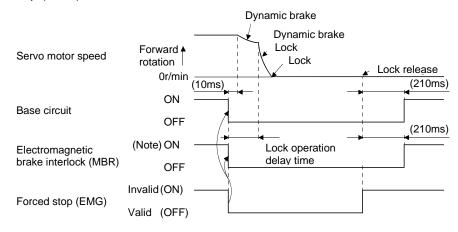


Note 1. ON: Lock is not activated.

OFF: Lock is activated.

- 2. Lock is released after delaying for the release delay time of lock and operation time of external circuit relay. For the release delay time of lock, refer to chapter 16.
- 3. After the lock is released, turn ON the RYn1 or RYn2.

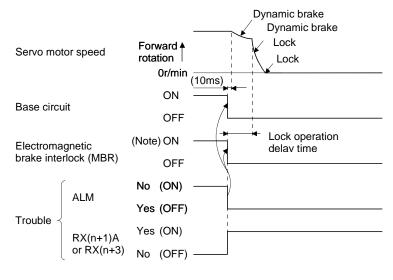
(2) Forced stop (EMG) ON/OFF



Note. ON: Lock is not activated. OFF: Lock is activated.



(3) Alarm occurrence



Note. ON: Lock is not activated. OFF: Lock is activated.

(4) Both main and control circuit power supplies off

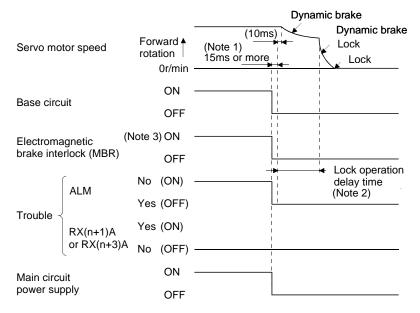
	Dynamic brake
Servo motor speed	Forward (Note 1) rotation 0r/min
.	ON
Base circuit	OFF
Electromagnetic (I	Note 2) ON
brake interlock (MBR)	OFF
	No (ON)
ALM	Yes (OFF)
Trouble RX(n+1)A	Yes (ON)
or RX(n+3)A	No (OFF)
Main circuit	ON
power Control circuit	OFF

Note 1. Changes with the operating status.

2. ON: Lock is not activated. OFF: Lock is activated.



(5) Only main circuit power supply off (control circuit power supply remains on)



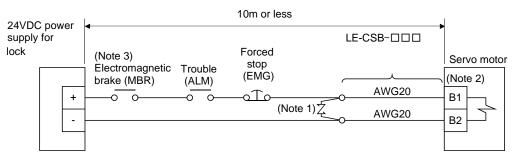
Note 1. Changes with the operating status.

- 2. When the main circuit power supply is off in a motor stop status, the main circuit off warning (AE9) occurs and the trouble (ALM) does not turn off.
- 3. ON: Lock is not activated.

OFF: Lock is activated.



- 4.11.3 Wiring diagrams (LE-□-□series servo motor)
- (1) When cable length is 10m or less



Note 1. Connect a surge absorber as close to the servo motor as possible.

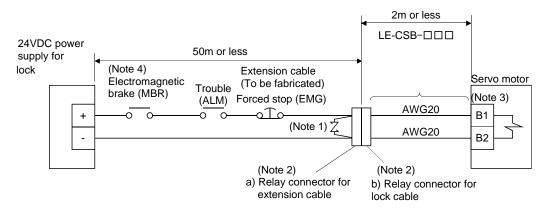
- 2. There is no polarity in lock terminals (B1 and B2).
- 3. When using a servo motor with a locke, assign the electromagnetic brake interlock (MBR) to external output signal in the parameters No.PD09 to PD11.

When fabricating the lock cable LE-CSB-R A, refer to section 13.1.4.

(2) When cable length exceeds 10m

When the cable length exceeds 10m, fabricate an extension cable as shown below on the customer side. In this case, the lock cable should be within 2m long.

Refer to section 13.9 for the wire used for the extension cable.



Note 1. Connect a surge absorber as close to the servo motor as possible.

2. Use of the following connectors is recommended when ingress protection (IP65) is necessary.

Relay connector	Description	Protective structure
a) Relay connector for extension cable	CM10-CR2P-* (DDK) ^T Wire size: S, M, L	IP65
 b) Relay connector for lock cable 	CM10-SP2S- * (DDK) ^T Wire size: S, M, L	IP65

3. There is no polarity in lock terminals (B1 and B2).

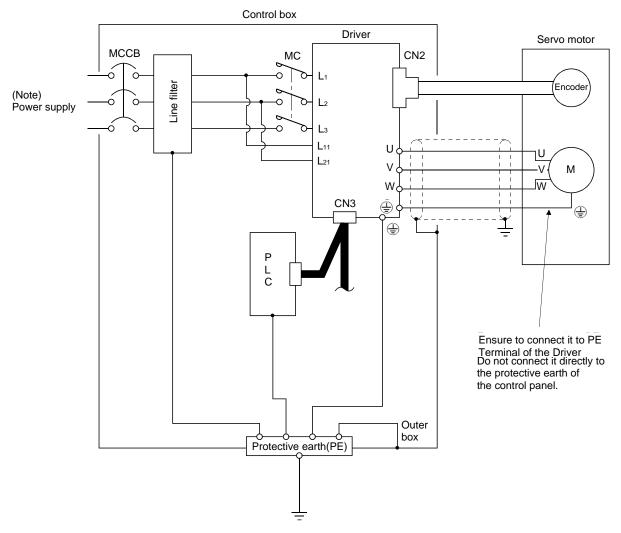
4. When using a servo motor with a lock, assign the electromagnetic brake interlock (MBR) to external output signal in the parameters No.PD09 to PD11.



4.12 Grounding	
	 Ground the driver and servo motor securely.
WARNING	 To prevent an electric shock, always connect the protective earth (PE) terminal
	(terminal marked \oplus) of the driver with the protective earth (PE) of the control box.

The driver switches the power transistor on-off to supply power to the servo motor. Depending on the wiring and ground cable routing, the driver may be affected by the switching noise (due to di/dt and dv/dt) of the transistor. To prevent such a fault, refer to the following diagram and always ground.

To conform to the EMC Directive, refer to the EMC Installation Guidelines (IB(NA)67310).



Note. For 1-phase 200 to 230VAC or 1-phase 100 to 120VAC, connect the power supply to $L_1 \cdot L_2$ and leave L_3 open. There is no L_3 for 1-phase 100 to 120VAC power supply. Refer to section 1.2 for the power supply specification.

5. OPERATION

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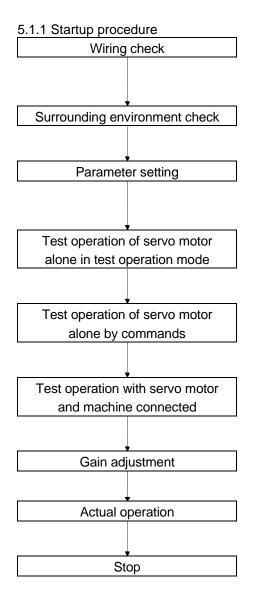


5. OPERATION

	 Do not operate the switches with wet hands. You may get an electric shock.
	 Before starting operation, check the parameters. Some machines may perform unexpected operation.
	 Take safety measures, e.g. provide covers, to prevent accidental contact of hands and parts (cables, etc.) with the driver heat sink, regenerative resistor, servo motor, etc. since they may be hot while power is on or for some time after power-off. Their temperatures may be high and you may get burnt or a parts may damaged.
	 During operation, never touch the rotating parts of the servo motor. Doing so can cause injury.

5.1 Switching power on for the first time

When switching power on for the first time, follow this section to make a startup.



Check whether the driver and servo motor are wired correctly using visual inspection, DO forced output function (Section 7.7.4), etc. (Refer to section 5.1.2.)

Check the surrounding environment of the driver and servo motor. (Refer to section 5.1.3.)

Set the parameters as necessary, such as the used control mode and regenerative option selection with the set up software(MR Configurator2TM). (Refer to chapter 6.)

For the test operation, with the servo motor disconnected from the machine and operated at the speed as low as possible, and check whether the servo motor rotates correctly. (Refer to sections 7.7.)

For the test operation with the servo motor disconnected from the machine and operated at the speed as low as possible, and check whether the servo motor rotates correctly.

Connect the servo motor with the machine, give operation commands from the host command device, and check machine motions.

Make gain adjustment to optimize the machine motions. (Refer to chapter 8.)

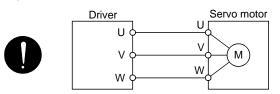
Stop giving commands and stop operation.



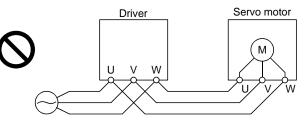
- 5.1.2 Wiring check
- (1) Power supply system wiring

Before switching on the main circuit and control circuit power supplies, check the following items.

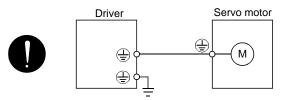
- (a) Power supply system wiring
 The power supplied to the power input terminals (L1, L2, L3, L11, L21) of the driver should satisfy the defined specifications. (Refer to section 1.2.)
 - (b) Connection of driver and servo motor
 - 1) The servo motor power supply terminals (U, V, W) of the driver match in phase with the power input terminals (U, V, W) of the servo motor.



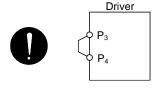
2) The power supplied to the driver should not be connected to the servo motor power supply terminals (U, V, W). To do so will fail the connected driver and servo motor.



3) The earth terminal of the servo motor is connected to the PE terminal of the driver.



4) P3-P4 should be connected.



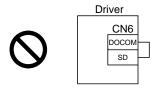
- (c) When option and auxiliary equipment are used
 - 1) When regenerative option is used for 200V class
 - The lead between P terminal and D terminal of CNP2 connector should not be connected.
 - The generative brake option should be connected to P terminal and C terminal.
 - A twisted cable should be used. (Refer to section 13.2.)



- (2) I/O signal wiring
 - (a) The I/O signals should be connected correctly.

Use DO forced output to forcibly turn on/off the pins of the CN6 connector. This function can be used to perform a wiring check. (Refer to section 7.7.4.) In this case, switch on the control circuit power supply only.

- (b) 24VDC or higher voltage is not applied to the pins of connectors CN6.
- (c) SD and DOCOM of connector CN6 is not shorted.



5.1.3 Surrounding environment

(1) Cable routing

- (a) The wiring cables are free from excessive force.
- (b) The encoder cable should not be used in excess of its flex life. (Refer to section 12.4.)
- (c) The connector part of the servo motor should not be strained.
- (2) Environment

Signal cables and power cables are not shorted by wire offcuts, metallic dust or the like.



5.2 Startup

- 5.2.1 Power on and off procedures
- (1) Power-on
 - Switch power on in the following procedure. Always follow this procedure at power-on.
 - 1) Switch off the servo-on (RYn0).
 - 2) Make sure that the Forward rotation start (RYn1) and Reverse rotation start (RYn2) are off.
 - 3) Switch on the main circuit power supply and control circuit power supply.

When main circuit power/control circuit power is switched on, the driver display shows "b01" (if the driver has the station number of 1).



In the absolute position detection system, first power-on results in the absolute position lost (A25) alarm and the servo system cannot be switched on.

The alarm can be deactivated then switching power off once and on again.

Also in the absolute position detection system, if power is switched on at the servo motor speed of 3000r/min or higher, position mismatch may occur due to external force or the like. Power must therefore be switched on when the servo motor is at a stop.

(2) Power-off

- 1) Make sure that the Forward rotation start (RYn1) and Reverse rotation start (RYn2) are off.
- 2) Switch off the Servo-on (RYn0).
- 3) Switch off the main circuit power supply and control circuit power supply.

5.2.2 Stop

In any of the following statuses, the driver interrupts and stops the operation of the servo motor. Refer to section 4.11 for the servo motor equipped with a lock.

(a) Servo-on (RYn0) OFF

The base circuit is shut off and the servo motor coasts.

(b) Alarm occurrence

When an alarm occurs, the base circuit is shut off and the dynamic brake is operated to bring the servo motor to a sudden stop.

(c) Forced stop (EMG) OFF

The base circuit is shut off and the dynamic brake is operated to bring the servo motor to a sudden stop. The servo forced stop warning (AE6) occurs.

(d) Forward rotation stroke end (LSP), reverse rotation stroke end (LSN) OFF

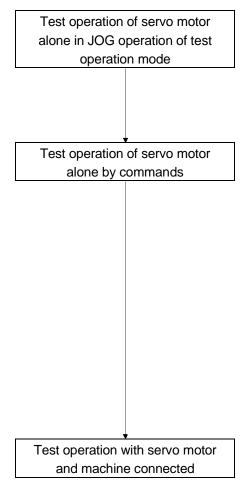
The droop pulse value is erased and the servo motor is stopped and servo-locked. It can be run in the opposite direction.

- (e) Automatic/Manual selection (MD0) OFF In the case of automatic operation, deceleration stops at the deceleration time constant during operation.
- (f) Temporary stop/Restart (TSTP) OFF In the case of automatic operation, deceleration stops at the deceleration time constant during operation.



5.2.3 Test operation

Before starting actual operation, perform test operation to make sure that the machine operates normally. Refer to section 5.2.1 for the power on and off methods of the driver.



In this step, confirm that the driver and servo motor operate normally.

With the servo motor disconnected from the machine, use the test operation mode and check whether the servo motor correctly rotates at the slowest speed. Refer to section 7.7 for the test operation mode.

In this step, confirm that the servo motor correctly rotates at the slowest speed under the commands from the command device. Make sure that the servo motor rotates in the following procedure.

- Switch on the Forced stop (EMG) and Servo-on (RYn0). When the driver is put in a servo-on status, the Ready (RD) switches on.
- 2) Switch on the Forward rotation stroke end (LSP) or Reverse rotation stroke end (LSN).
- 3) When the point table is designated to switch on the forward rotation start (RYn1) or reverse rotation start (RYn2), the servo motor starts rotating. Give a low speed command at first and check the rotation direction, etc. of the servo motor. If the servo motor does not operate in the intended direction, check the input signal.

In this step, connect the servo motor with the machine and confirm that the machine operates normally under the commands from the command device.

Make sure that the servo motor rotates in the following procedure.

- Switch on the Forced stop (EMG) and Servo-on (RYn0). When the driver is put in a servo-on status, the Ready (RD) switches on.
- 2) Switch on the Forward rotation stroke end (LSP) or Reverse rotation stroke end (LSN).
- 3) When the point table is specified from the command device and the forward rotation start (RYn1) or reverse rotation start (RYn2) is turned ON, the servo motor starts rotating. Give a low speed command at first and check the operation direction, etc. of the machine. If the machine does not operate in the intended direction, check the input signal. In the status display, check for any problems of the servo motor speed, load ratio, etc.
- 4) Then, check automatic operation with the program of the command device.



5.2.4 Parameter setting

POINT							
 The er 	The encoder cable LE-CSE-						
require	es the parameter No.Po	C22 setting to be changed de	pending on its				
length	Check whether the pa	arameter is set correctly. If it is	s not set correctly,				
the en	coder error 1 (A16) will	occur at power-on.					
		1	1				
	Encoder cable	Parameter No.PC22 setting					
	LE-CSE- 2						
	LE-CSE-□5□ 0 □ □ □ (initial value)						
	LE-CSE- A						
	Other cable	1000					

The driver can be used by merely changing the basic setting parameters (No.PA $\Box \Box$) mainly. As necessary, set the gain filter parameters (No.PB $\Box \Box$), extension setting parameters (No.PC $\Box \Box$) and I/O setting parameters (No.PD $\Box \Box$).

Parameter group	Main description
Basic setting parameter	Set the basic setting parameters first. Generally, operation can be performed by merely setting this
(No.PA □ □)	parameter group.
	In this parameter group, set the following items.
	Control mode selection (select the position control mode)
	Regenerative option selection
	Absolute position detection system selection
	Setting of command input pulses per revolution
	Electronic gear setting
	Auto tuning selection and adjustment
	In-position range setting
	Torque limit setting
	Command pulse input form selection
	Servo motor rotation direction selection
	Encoder output pulse setting
Gain filter parameter	If satisfactory operation cannot be achieved by the gain adjustment made by auto tuning, execute in-
(No.PB □ □)	depth gain adjustment using this parameter group.
	This parameter group must also be set when the gain changing function is used.
Extension setting parameter	This parameter group is unique to LECSC2-T driver.
(No.PC □ □)	
I/O setting parameter	Used when changing the I/O devices of the driver.
(No.PD □ □)	



5.2.5 Point table setting

Set necessary items to the point table before starting operation. The following table indicates the items that must be set.

Name	Description
Position data	Set the position data for movement.
(Target Position)	
Servo motor speed	Sets the command rotation speed (Motor rotations/min) when positioning is executed.
(Rotation speed)	Please set within allowable speed of each actuator.
Acceleration time constant	Set the time until the servo motor reaches the rated speed. (3000 r/min) Please set within allowable acceleration time constant of each actuator.
Deceleration time constant	Set the time until the servo motor slows down to the rated speed. (<u>3000 r/min)</u> Please set within allowable deceleration time constant of each actuator.
Dwell	Set the waiting time when performing automatic continuous operation.
Auxiliary function	Set when performing automatic continuous operation.

Refer to section 5.4.2 for details of the point table.

5.2.6 Actual operation

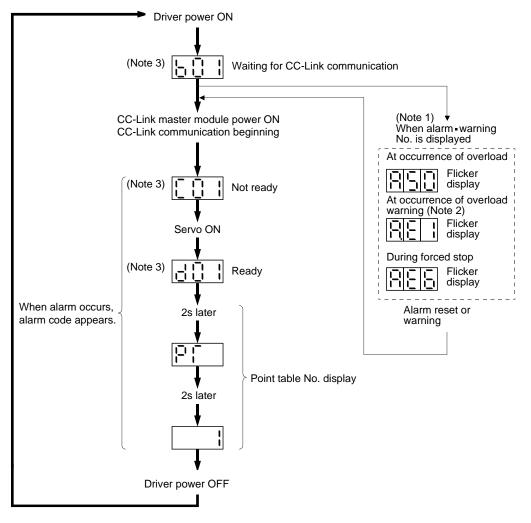
Start actual operation after confirmation of normal operation by test operation and completion of the corresponding parameter settings. Perform a home position return as necessary.



5.3 Driver display

On the driver display (three-digit, seven-segment display), check the status of communication with the CC-Link driver at power-on, check the station number, and diagnose a fault at occurrence of an alarm.

(1) Display sequence



- Note 1. Only alarm and warning No. are displayed, but no station No. is displayed.
 - 2. If warning other than AE6 occurs during the servo on, flickering the second place of decimal point indicates that it is during the servo on.
 - 3. The right-hand segments of b01, c02 and d16 indicate the axis number.

(Below example indicates Station No.1)

581	583	<u>8</u> 84
Station	Station	Station
No.1	No.2	No.64



(2) Indication list

Indication	Status	Description
b##] Waiting for CC-Link communication	 Power of the CC-Link master module was switched on at the condition that the power of CC-Link master module is OFF. The CC-Link master module is faulty.
(Note 1) d # #	Ready	The servo was switched on after completion of initialization and the driver is ready to operate. (This is indicated for 2 seconds.)
(Note 1) C # #] Not ready	The driver is being initialized or an alarm has occurred.
(Note 2) \$\$\$	Ready for operation	Two seconds have passed after the driver is ready to operate by turning ON the servo-on (RYn1).
(Note 3) A * *] Alarm • Warning	The alarm No./warning No. that occurred is displayed. (Refer to section 10.4.)
888	CPU error	CPU watchdog error has occurred.
(Note 4) b00		JOG operation • positioning operation • programmed operation • DO forced output • single- step feed
(Note 1)	l est operation mode	Motor-less operation

Note 1. ## denotes any of numerals 00 to 16 and what it means is listed below.

##	Description		
00	Set to the test operation mode.		
01	Station number 1		
02	Station number 2		
03	Station number 3		
:	:		
:	:		
62	Station number 62		
63	Station number 63		
64	Station number 64		

Note 2. \$\$\$ indicates numbers from 0 to 255, and the number indicates the executing point table number.

- 3. ** indicates the warning/alarm No.
- 4. Requires set up software(MR Configurator 2^{TM}).



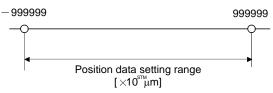
- 5.4 Automatic operation mode
- 5.4.1 What is automatic operation mode?
- (1) Command system

After selection of preset point tables using the input signals or communication, operation is started by the forward rotation start (RYn1) or reverse rotation start (RYn2). Automatic operation has the absolute value command system, incremental value command system.

(a) Absolute value command system

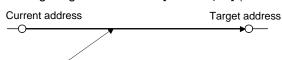
As position data, set the target address to be reached.

Setting range: -9999999 to $9999999 [\times 10^{STM} \mu m]$ (STM = feed length multiplication parameter No.PA05)



(b) Incremental value command system

As position data, set the moving distance from the current address to the target address. Setting range: 0 to 9999999 [$\times 10^{STM} \mu m$] (STM = feed length multiplication parameter No.PA05)



Position data = |target address - current address|

- (2) Point table
 - (a) Point table setting
 - Up to 255 point tables may be set.

Set the point tables using the set up software(MR Configurator2[™]) Software, the CC-Link write instruction code.

The following table lists what to set: Refer to section 5.4.2 for details of the settings.

Name	Description	
Position data (Target Position)	Set the position data for movement.	
Servo motor speed	Sets the command rotation speed (Motor rotations/min) when positioning is executed.	
(Rotation speed)	Please set within allowable speed of each actuator.	
Acceleration time constant	Set the time until the servo motor reaches the rated speed. <u>(3000 r/min)</u> Please set within allowable acceleration time constant of each actuator.	
Deceleration time constant	Set the time until the servo motor slows down to the rated speed. <u>(3000 r/min)</u> Please set within allowable deceleration time constant of each actuator.	
Dwell	Set the waiting time when performing automatic continuous operation.	
Auxiliary function	Set when performing automatic continuous operation.	



(b) Selection of point table

Using the input signal or CC-Link, select the point table No. with the remote input and remote register from the command device (PC or PLC...etc) such as a personal computer.

The following table lists the point table No. selected in response to the remote input. When 2 stations are occupied, the point table No. can be selected by remote register setting. (Refer to section 3.6.3.)

Remote input (0: OFF 1: ON)								
2 stations occupied 1 station occupied						Selected point		
DI7	DI6	DI5	DI4	DI3	DI2	DI1	DI0	table No.
RY(n+2)5	RY(n+2)4	RY(n+2)3	RYnE	RYnD	RYnC	RYnB	RYnA	
0	0	0	0	0	0	0	1	1
0	0	0	0	0	0	1	0	2
0	0	0	0	0	0	1	1	3
0	0	0	0	0	1	0	0	4
•	•	•	•	•	•	•	•	•
· ·	•		•	•		•	•	•
1	1	1	1	1	1	1	0	254
1	1	1	1	1	1	1	1	255



5.4.2 Automatic operation using point table

(1) Absolute value command system

(a) Point table

Set the point table values using the set up software(MR Configurator2[™]), the or the remote register of CC-Link.

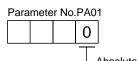
Set the position data, motor speed, acceleration time constant, deceleration time constant, dwell and auxiliary function to the point table. The following table gives a setting example. However, this function cannot be used when the point table No. is selected using the remote register of CC-Link.

Name	Setting range	Unit	Description
Position data -9999999 (Target Position) to 999999		×10 ^{s™} μm	 When using this point table as absolute value command system Set the target address (absolute value). When using this point table as incremental value command system Set the moving distance. A "-" sign indicates a reverse rotation command. Number of decimal places changes according to PA05:STM (Feed length multiplication)
Servo motor speed (Rotation speed)	0 to allowable actuator speed	r/min	Sets the command rotation speed (Motor rotations/min) when positioning is executed. Please set within allowable speed of each actuator.
Acceleration time constant	0 to 20000	ms	Set the time until the servo motor reaches the rated speed. (3000 r/min) Please set within allowable acceleration time constant of each actuator.
Deceleration time constant	0 to 20000	ms	Set the time until the servo motor slows down to the rated speed. (3000 r/min) Please set within allowable deceleration time constant of each actuator.
Dwell	0 to 20000	ms	This function is valid when the point table is selected using the input signal or the remote input of CC-Link. It cannot be used when the point table No. is selected using the remote register of CC-Link. Set "0" in the auxiliary function to make the dwell invalid. Set "1" in the auxiliary function and 0 in the dwell to perform continuous operation. When the dwell is set, the position command of the selected point table is completed, and after the set dwell has elapsed, the position command of the next point table is started.
Auxiliary function	0 to 3		 This function is valid when the point table is selected using the input signal or the remote input of CC-Link. It cannot be used when the point table No. is selected using the remote register of CC-Link. (1) When using this point table in the absolute value command system 0: Automatic operation is performed in accordance with a single point table chosen. 1: Operation is performed in accordance with consecutive point tables without a stop. (2) When using this point table in the incremental value command system 2: Automatic operation is performed in accordance with a single point table chosen. 3: Operation is performed in accordance with consecutive point tables without a stop. When a different rotation direction is set, smoothing zero (command output) is confirmed and the rotation direction is then reversed. Setting "1" or "3" in point table No.255 results in an error.
M code	Do not change.		

(b) Parameter setting

Set the following parameters to perform automatic operation.

1) Command mode selection (parameter No.PA01) Select the absolute value command system.



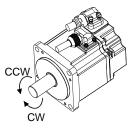
Absolute value command system



2) Rotation direction selection (parameter No.PA14)

Choose the servo motor rotation direction at the time when the forward rotation start (RYn1) is switched on.

Parameter No.PA14 setting	Servo motor rotation direction when forward rotation start (RYn1) is switched on	
0	CCW rotation with + position data CW rotation with - position data	
1	CW rotation with + position data CCW rotation with - position data	



3) Feed length multiplication selection (parameter No.PA05) Set the unit multiplication factor (STM) of position data.

Parameter No.PA05 setting	Feed unit [µm]	Position data input range [mm]	
	1	-999.999 to +999.999	
	10	-9999.99 to +9999.99	
	100	-99999.9 to +99999.9	
	1000	-999999 to +999999	

(c) Operation

Choosing the point table using RYnA to RYnE, RY(n+2)3 to RY(n+2)5 and turning RYn1 ON starts positioning to the position data at the preset speed, acceleration time constant and deceleration time constant. At this time, reverse rotation start (RYn2) is invalid.

Item	Setting method	Description
Automatic operation mode selection	Automatic/manual selection (RYn6)	Turn RYn6 ON.
	Point table No. selection 1 (RYnA)	
	Point table No. selection 2 (RYnB)	
	Point table No. selection 3 (RYnC)	
Point table selection	Point table No. selection 4 (RYnD)	Refer to section 5.4.1(2).
	Point table No. selection 5 (RYnE)	Refer to section 5.4.1(2).
	Point table No. selection 6 (RY(n+2)3)	
	Point table No. selection 7 (RY(n+2)4)	
	Point table No. selection 8 (RY(n+2)5)	
Start	Forward rotation start (RYn1)	Turn RYn1 ON to start.



(2) Incremental value command system

(a) Point table

Set the point table values using the set up software(MR Configurator2[™]), the or the remote register of CC-Link.

Set the position data, motor speed, acceleration time constant, deceleration time constant, dwell and auxiliary function to the point table. The following table gives a setting example.

Name	Setting range	Unit	Description
Position data (Target Position)	0 to 999999	×10 ^{s™} μm	Set the travel distance. <u>Number of decimal places changes according to PA05 : STM (Feel length</u> multiplication)
Servo motor speed (Rotation speed)	0 to permissible speed	r/min	Sets the command rotation speed (Motor rotations/min) when positioning is executed. Please set within allowable speed of each actuator.
Acceleration time constant	0 to 20000	ms	Set the time until the servo motor reaches the rated speed. (3000 r/min) Please set within allowable deceleration time constant of each actuator.
Deceleration time constant	0 to 20000	ms	Set the time until the servo motor slows down to the rated speed. (3000 r/min) Please set within allowable deceleration time constant of each actuator.
Dwell	0 to 20000	ms	This function is valid when the point table is selected using the input signal or the remote input of CC-Link. It cannot be used when the point table No. is selected using the remote register of CC-Link. Set "0" in the auxiliary function to make the dwell invalid. Set "1" in the auxiliary function and 0 in the dwell to perform continuous operation. When the dwell is set, the position command of the selected point table is completed, and after the set dwell has elapsed, the position command of the next point table is started.
Auxiliary function	0 • 1		 This function is valid when the point table is selected using the input signal or the remote input of CC-Link. It cannot be used when the point table No. is selected using the remote register of CC-Link. 0: Automatic operation is performed in accordance with a single point table chosen. 1: Operation is performed in accordance with consecutive point tables without a stop. When a different rotation direction is set, smoothing zero (command output) is confirmed and the rotation direction is then reversed. Setting "1" in point table No.255 results in an error. For full information, refer to (4) in this section.
M code	Do not change.		

(b) Parameter setting

Set the following parameters to perform automatic operation.

1) Command mode selection (parameter No.PA01) Select the incremental value command system.

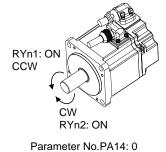


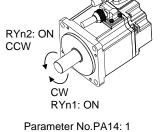


2) Forward rotation direction selection (parameter No.PA14)

Choose the servo motor rotation direction at the time when the forward rotation start (RYn1) signal or reverse rotation start (RYn2) signal is switched on.

Deremeter No DA14 setting	Servo motor rotation direction		
Parameter No.PA14 setting	Forward rotation start (RYn1) ON	Reverse rotation start (RYn2) ON	
0	CCW rotation (address incremented)	CW rotation (address decremented)	
1	CW rotation (address incremented)	CCW rotation (address decremented)	





3) Feed length multiplication selection (parameter No.PA05) Set the unit multiplication factor (STM) of position data.

Parameter No.PA05 setting	Feed unit [µm]	Position data input range [mm]
	1	0 to 999.999
	10	0 to 9999.99
	100	0 to 99999.9
	1000	0 to 999999

(c) Operation

Choosing the point table using RYnA to RYnE, RY(n+2)3 to RY(n+2)5 and turning RYn1 ON starts a motion in the forward rotation direction over the moving distance of the position data at the preset speed and acceleration time constant.

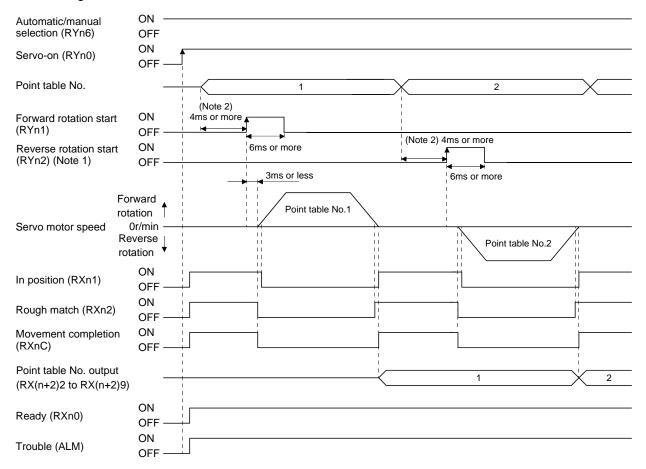
Turning RYn2 ON starts a motion in the reverse rotation direction according to the values set to the selected point table.

Item	Setting method	Description
Automatic operation mode selection	Automatic/manual selection (RYn6)	Turn RYn6 ON.
Point table selection	Point table No. selection 1 (RYnA) Point table No. selection 2 (RYnB) Point table No. selection 3 (RYnC) Point table No. selection 4 (RYnD) Point table No. selection 5 (RYnE) Point table No. selection 6 (RY(n+2)3) Point table No. selection 7 (RY(n+2)4) Point table No. selection 8 (RY(n+2)5)	Refer to section 5.4.1(2).
01-1	Forward rotation start (RYn1)	Turn RYn1 ON to start motion in forward rotation direction.
Start	Reverse rotation start (RYn2)	Turn RYn2 ON to start motion in reverse rotation direction.



(3) Automatic operation timing chart

The timing chart is shown below.



Note 1. Reverse rotation start (RYn2) is invalid in the absolute value command system.

2. Configure a sequence that changes the point table selection earlier, considering the delay time of CC-Link communication.



(4) Automatic continuous operation

POINT	
 This functio 	n is valid when the point table is selected using the input signal or
the remote	input of CC-Link. It cannot be used when the point table No. is
selected us	ing the remote register of CC-Link.
	This functio the remote

(a) What is automatic continuous operation?

By merely choosing one point table and making a start (RYn1 or RYn2), operation can be performed in accordance with the point tables having consecutive numbers.

Automatic operation is available in two types: varied speed operation and automatic continuous positioning operation.

Either type may be selected as follows.

1) In absolute value command specifying system

	Point table setting			
		Auxiliary function		
	Dwell	When position data is	When position data is	
- Speed changing operation		absolute value	incremental value	
Automatic continuous Speed changing operation	0	1	3	
positioning operation	1 or more	1	3	

2) In incremental value command system

		Point table setting
	Dwell	Auxiliary function
Automatic continuous Speed changing operation	0	1
positioning operation	1 or more	1

(b) Varied speed operation

Speed during positioning operation can be changed by setting the auxiliary function of the point table. Use the number of point tables equal to the number of speeds to be set.

By setting "1" to the auxiliary function, operation is performed at the speed set in the next point table during positioning. The position data valid at this time is the data selected at start and the acceleration and deceleration time constants of the subsequent point tables are made invalid.

By setting "1" to the auxiliary function of up to point table No.254, operation can be performed at a maximum of 255 speeds. Set "0" to the auxiliary function of the last point table.

When performing varied speed operation, always set "0" to the dwell. If "1" or more is set, automatic continuous positioning operation is made valid.

The following table gives a setting example.

Point table No.	Dwell [ms] (Note 1)	Auxiliary function	Variable speed operation	
1	0	1		
2	0	1	Consecutive point table data	
3	0	0 (Note 2)		
4	0	1		
5	0	1		
6	0	1	Consecutive point table data	
7	0	0 (Note 2)		

Note 1. Always set "0".

2. Always set "0" or "2" to the auxiliary function of the last point table among the consecutive point tables.



1) Absolute value command specifying system

This system is an auxiliary function for point tables to perform automatic operation by specifying the absolute value command or incremental value command.

Positioning in single direction

The operation example given below assumes that the set values are as indicated in the following table. Here, the point table No.1 uses the absolute value command system, the point table No.2 the incremental value command system, the point table No.3 the absolute value system, and the point table No.4 the incremental value command system.

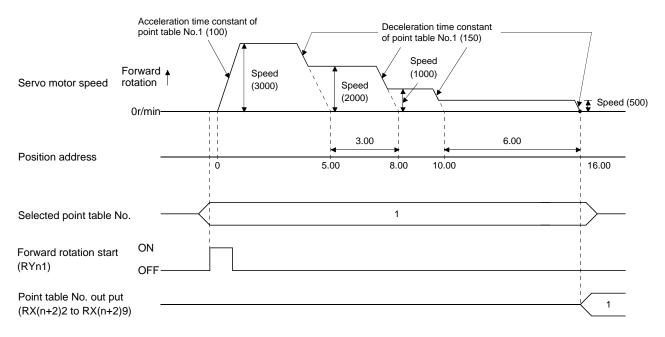
Point table No.	Position data (Target Position) [×10 ^{s™} µm]	Servo motor speed (Rotation speed) [r/min]	Acceleration time constant [ms]	Deceleration time constant [ms]	Dwell [ms] (Note 1)	Auxiliary function
1	5.00	3000	100	150	0	1
2	3.00	2000	Invalid	Invalid	0	3
3	10.00	1000	Invalid	Invalid	0	1
4	6.00	500	Invalid	Invalid	0	0 (Note 2)

Note 1. Always set "0".

2. Always set "0" or "2" to the auxiliary function of the last point table among the consecutive point tables.

0: When point table is used in absolute value command system

1: When point table is used in incremental value command system





· Positioning that reverses the direction midway

The operation example given below assumes that the set values are as indicated in the following table. Here, the point table No.1 uses the absolute value command system, the point table No.2 the incremental value command system, and the point table No.3 the absolute value system.

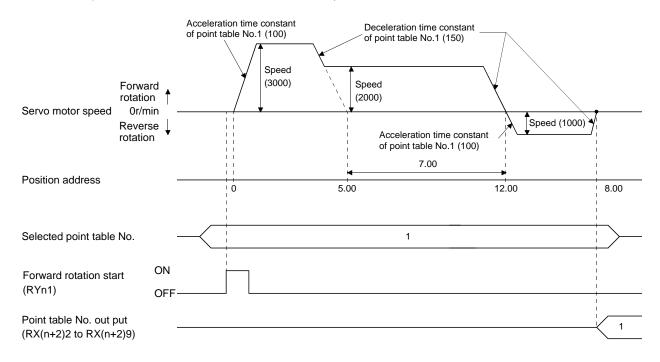
Point table No.	Position data (Target Position) [×10 ^{s™} µm]	Servo motor speed (Rotation speed) [r/min]	Acceleration time constant [ms]	Deceleration time constant [ms]	Dwell [ms] (Note 1)	Auxiliary function
1	5.00	3000	100	150	0	1
2	7.00	2000	Invalid	Invalid	0	1
3	8.00	1000	Invalid	Invalid	0	0 (Note 2)

Note 1. Always set "0".

2. Always set "0" or "2" to the auxiliary function of the last point table among the consecutive point tables.

0: When point table is used in absolute value command system

1: When point table is used in incremental value command system





2) Incremental value command system

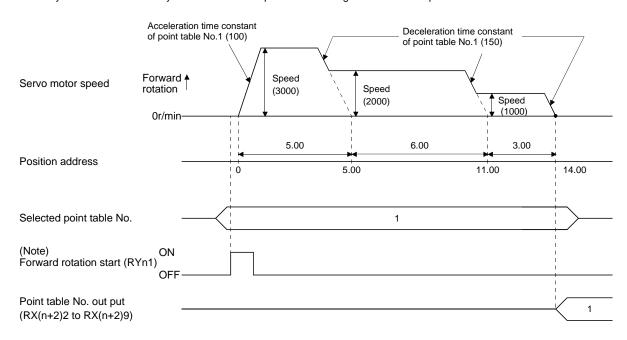
The position data of the incremental value command system is the sum of the position data of the consecutive point tables.

The operation example given below assumes that the set values are as indicated in the following table.

Point table No.	Position data (Target Position) [×10 ^{s™} µm]	Servo motor speed (Rotation speed) [r/min]	Acceleration time constant [ms]	Deceleration time constant [ms]	Dwell [ms] (Note 1)	Auxiliary function
1	5.00	3000	100	150	0	1
2	6.00	2000	Invalid	Invalid	0	1
3	3.00	1000	Invalid	Invalid	0	0 (Note 2)

Note 1. Always set "0".

2. Always set "0" to the auxiliary function of the last point table among the consecutive point tables.



Note. Turning on Reverse rotation start (RYn2) starts positioning in the reverse rotation direction.



(c) Temporary stop/restart

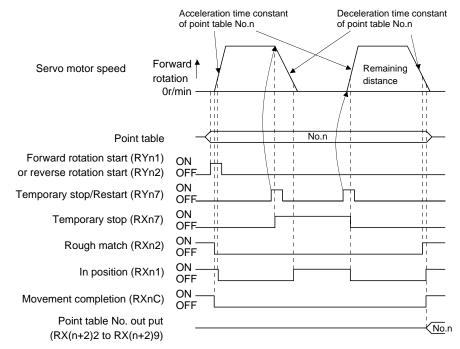
When RYn7 is turned ON during automatic operation, the motor is decelerated to a temporary stop at the deceleration time constant in the point table being executed. When RYn7 is turned ON again, the remaining distance is executed.

If the forward/reverse rotation start signal (RYn1 or RYn2) is ignored if it is switched on during a temporary stop.

The remaining moving distance is cleared when the operation mode is changed from the automatic mode to the manual mode during a temporary stop.

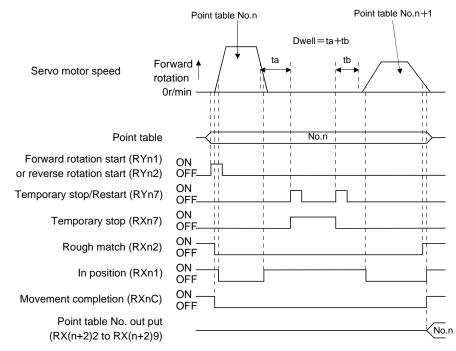
The temporary stop/restart input is ignored during zeroing and jog operation.

1) When the servo motor is rotating





2) During dwell





5.4.3 Remote register-based position/speed setting

This operation can be used when 2 stations are occupied. This section explains operation to be performed when the remote register is used to specify the position command data/speed command data.

(1) Absolute value command positioning in absolute value command system

The position data set in the absolute value command system are used as absolute values in positioning. Set the input devices and parameters as indicated below.

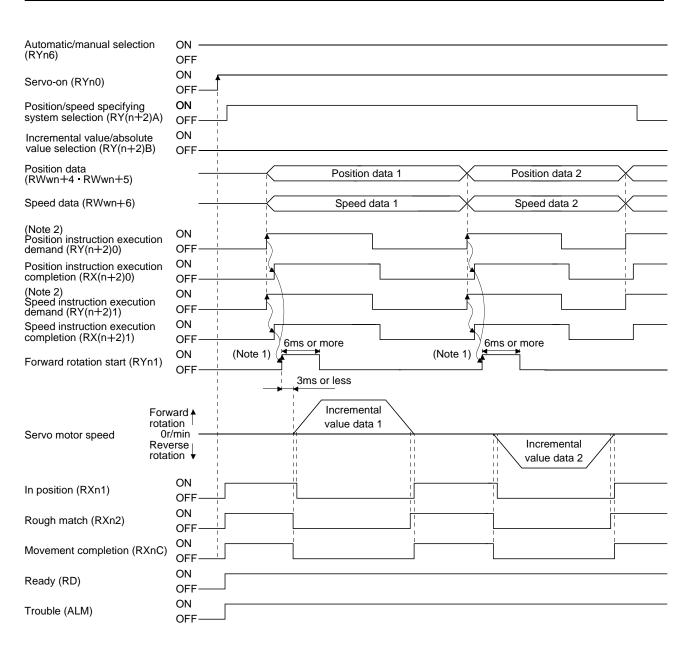
Item	Used device/parameter	Description	
Automatic operation mode	Automatic/manual selection (RYn6)	Turn RYn6 ON.	
Remote register-based position/speed setting	Position/speed specifying system selection (RY(n+2)A)	Turn RY(n+2)A ON.	
Command system	Parameter No.PA01	□□□0 : Absolute value command system is selected.	
Remote register-based position/speed specifying system selection	Parameter No.PC30	□□□2 : Remote register-based position/speed specifying system is selected. In the case, always set an acceleration/deceleration time constant in the point table No.1.	
Position data	Position command data lower 16 bit (RWwn+4) Position command data upper 16 bit (RWwn+5)	Set the lower 16 bits of position data to RWwn+4, and the upper 16 bits to RWwn+5. Setting range: -9999999 to 999999	
Servo motor speed	Speed command data (RWwn+6)	Set the servo motor speed.	

Set the position data to RWwn+4/RWwn+5, and the speed command data to RWwn+6, and store them into the driver.

In the absolute value command system, Absolute value/incremental value selection (RY(n+2)B) can be used to select whether the values set to the position data are absolute values or incremental values. The position data set to RWwn+4/RWwn+5 are handled as absolute values when RY(n+2)B is turned OFF or as incremental values when it is turned ON. During operation, how the position data will be handled (absolute values or incremental values) depends on the status of RY(n+2)B when Forward rotation start (RYn1) is turned ON.

Here, RY(n+2)B is turned OFF since the position data are handled as absolute values.





Note 1. Configure a sequence that changes the point table selection earlier, considering the delay time of CC-Link communication.

2. For details of the operation timing of RY(n+2)0 and RY(n+2)1, refer to the section 3.6.2 (3).



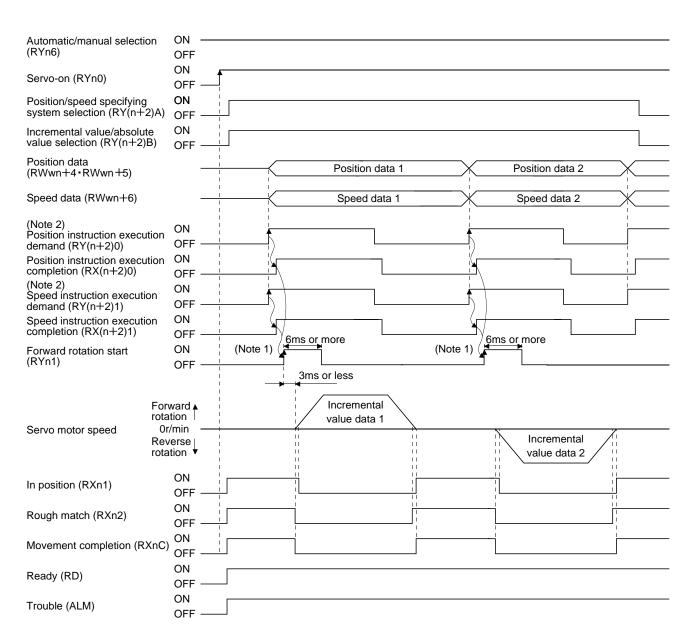
(2) Incremental value command positioning in absolute value command system

The position data set in the absolute value command system are used as incremental values in positioning. Set the input devices and parameters as indicated below.

Item	Used device/parameter Description		
Automatic operation mode	Automatic/manual selection (RYn6)	Turn RYn6 ON.	
Remote register-based position/speed setting	Position/speed specifying system selection (RY(n+2)A) Turn RY(n+2)A ON.		
Command system	Parameter No.PA01	□□□0 : Absolute value command system is selected.	
Remote register-based position/speed specifying system selection	Parameter No.PC30	DDD2 : Remote register-based position/speed specifying system is selected.	
Position data	Position command data lower 16 bit (RWwn+4) Position command data upper 16 bit	Set the lower 16 bits of position data to RWwn+4, and the upper 16 bits to RWwn+5.	
Servo motor speed	(RWwn+5) Speed command data (RWwn+6)	Setting range: -9999999 to 999999 Set the servo motor speed.	

Here, Absolute value/incremental value selection RY(n+2)B is turned ON since the position data are handled as incremental values.





Note 1. Configure a sequence that changes the point table selection earlier, considering the delay time of CC-Link communication.

2. For details of the operation timing of RY(n+2)0 and RY(n+2)1, refer to the section 3.6.2 (3).



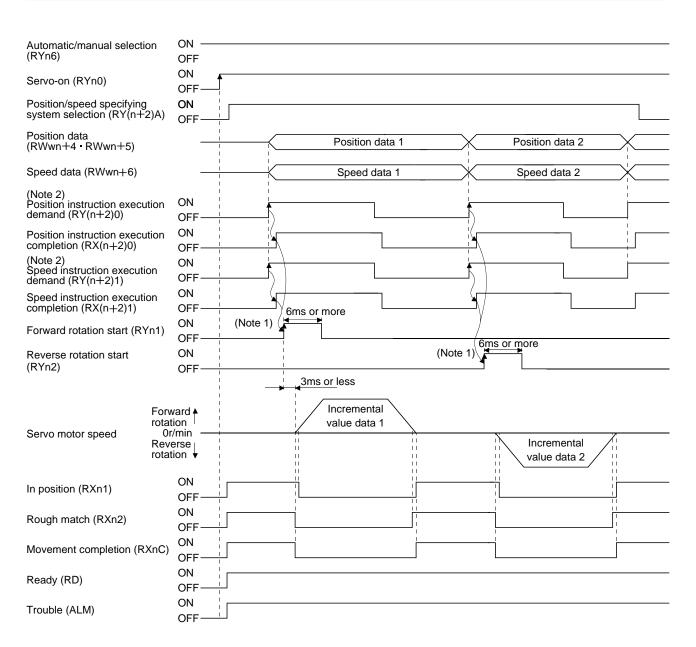
(3) Positioning in incremental value command system

Execute positioning in the incremental value command system. Set the input signals and parameters as indicated below.

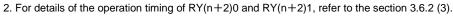
Item	Used device/parameter	Description	
Automatic operation mode	Automatic/manual selection (RYn6)	Turn RYn6 ON.	
Remote register-based position/speed setting	Position/speed specifying system selection (RY(n+2)A)	Turn RY(n+2)A ON.	
Command system	Parameter No.PA01	 Incremental value command system is selected. IIII : Remote register-based position/speed specifying system is selected. In the case, always set an acceleration/deceleration time constant in the point table No.1. Set the lower 16 bits of position data to RWwn+4, and the upper 16 bits to RWwn+5. Setting range: 0 to 999999 	
Remote register-based position/speed specifying system selection	Parameter No.PC30		
Position data	Position command data lower 16 bit (RWwn+4) Position command data upper 16 bit (RWwn+5)		
Servo motor speed	Speed command data (RWwn+6)	Set the servo motor speed.	

Set " $\Box\Box\Box$ 1" in parameter No.PA01 to select the incremental value command system. In the incremental value command system, the position data are handled as incremental values. Hence, Absolute value/incremental value selection (RY(n+2)B) is invalid.





Note 1. Configure a sequence that changes the point table selection earlier, considering the delay time of CC-Link communication.





5.5 Manual operation mode

For machine adjustment, home position matching, etc., jog operation or a manual pulse generator may be used to make a motion to any position.

5.5.1 JOG operation

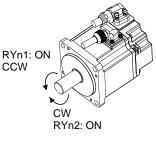
(1) Setting

Set the input device and parameters as follows according to the purpose of use. In this case, the point table No. selection 1 to 8 (RYnA to RYnE, RY(n+2)3 to RY(n+2)5) are invalid.

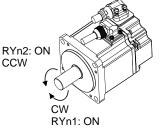
Item	Used device/parameter	Description
Manual operation mode selection	Automatic/manual selection (RYn6)	Turn RYn6 OFF.
Servo motor rotation direction	Parameter No.PA14	Refer to (2) in this section.
Jog speed	Parameter No.PC12	Set the speed of the servo motor.
A seclaration /decalaration time constant	Deint toble No. 4	Use the acceleration/deceleration
Acceleration/deceleration time constant	Point table No.1	time constants in point table No.1.

(2) Servo motor rotation direction

	Servo motor rotation direction			
Parameter No.PA14 setting	Forward rotation start (RYn1) ON Reverse rotation start (RYn2) ON			
0	CCW rotation	CW rotation		
1	CW rotation CCW rotation			







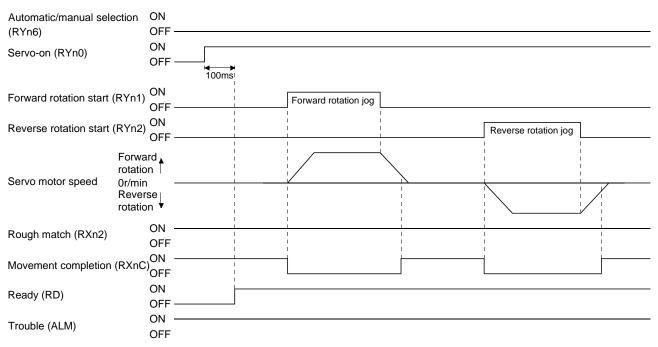
Parameter No.PA14: 1

(3) Operation

By turning RYn1 ON, operation is performed under the conditions of the jog speed set in the parameter and the acceleration and deceleration time constants in set point table No.1. For the rotation direction, refer to (2) in this section. By turning RYn2 ON, the servo motor rotates in the reverse direction to forward rotation start (RYn1).



(4) Timing chart





5.6 Manual home position return mode

5.6.1 Outline of home position return

Home position return is performed to match the command coordinates with the machine coordinates. In the incremental system, home position return is required every time input power is switched on. In the absolute position detection system, once home position return is done at the time of installation, the current position is retained if power is switched off. Hence, home position return is not required when power is switched on again. This driver has the home position return methods given in this section. Choose the most appropriate method for your machine structure and application.

This driver has the home position return automatic return function which executes home position return by making an automatic return to a proper position if the machine has stopped beyond or at the proximity dog. Manual motion by jog operation or the like is not required.



(1) Home position return types

Choose the optimum home position return according to the machine type, etc.

Туре	Home position return method	Features
Dog type home position return	With deceleration started at the front end of a proximity dog, the position where the first Z-phase signal is given past the rear end of the dog or a motion has been made over the home position shift distance starting from the Z-phase signal is defined as a home position.	 General home position return method using a proximity dog. Repeatability of home position return is excellent. The machine is less burdened. Used when the width of the proximity dog can be set greater than the deceleration distance of the servo motor.
Count type home position return	With deceleration started at the front end of a proximity dog, the position where the first Z-phase signal is given after advancement over the preset moving distance after the proximity dog or a motion has been made over the home position shift distance starting from the Z-phase signal is defined as a home position.	 Home position return method using a proximity dog. Used when it is desired to minimize the length of the proximity dog.
Data setting type home position return	An arbitrary position is defined as a home position.	No proximity dog required.
Stopper type home position return	The position where the machine stops when its part is pressed against a machine stopper is defined as a home position.	 Since the machine part collides with the machine be fully lowered. The machine and stopper strength must be increased.
Home position ignorance (Servo-on position as home position)	The position where servo is switched on is defined as a home position.	
Dog type rear end reference	The position where the axis, which had started decelerating at the front end of a proximity dog, has moved the after-proximity dog moving distance and home position shift distance after it passed the rear end is defined as a home position.	 The Z-phase signal is not needed.
Count type front end reference	The position where the axis, which had started decelerating at the front end of a proximity dog, has moved the after-proximity dog moving distance and home position shift distance is defined as a home position.	 The Z-phase signal is not needed.
Dog cradle type	The position where the first Z-phase signal is issued after detection of the proximity dog front end is defined as a home position.	
Dog type first Z-phase reference	After the proximity dog front end is detected, the current position moves away from the proximity dog in the reverse direction. In this movement, the home position is defined to be where the first Z-phase signal is issued or the position that is the home position shift distance away from where the first Z-phase signal is issued.	
Dog type front end reference	The home position is the front end of the proximity dog.	• The Z-phase signal is not needed.
Dogless Z-phase reference	The home position is defined to be where the first Z- phase signal is issued or the position that is the home position shift distance away from where the first Z- phase signal is issued.	



(2) Home position return parameter

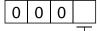
When performing home position return, set each parameter as follows.

(a) Choose the home position return method with parameter No.PC02 (Home position return type).

Para	mete	er No	PC02
0	0	0	

- Home position return method
 - 0: Dog type
 - 1: Count type
 - 2: Data setting type 3: Stopper type
- 4: Home position ignorance (Servo-on position as home position)
- 5: Dog type rear end reference
- 6: Count type front end reference
- 7: Dog cradle type
- 8: Dog type first Z-phase reference
- 9: Dog type front end reference
- A: Dogless Z-phase reference
- (b) Choose the starting direction of home position return with parameter No.PC03 (Home position return direction). Set "0" to start home position return in the direction in which the address is incremented from the current position, or "1" to start home position return in the direction in which the address is decremented.

Parameter No.PC03



Home position return direction 0: Address increment direction 1: Address decrement direction

(c) Choose the polarity at which the proximity dog is detected with parameter No.PD16 (Input polarity setting). Set "0" to detect the dog when the proximity dog device (DOG) is OFF, or "1" to detect the dog when the device is ON.

Parameter No.PD16 0

0

0

Proximity dog input polarity 0: OFF indicates detection of the dog 1: ON indicates detection of the dog

- (3) Instructions
 - 1) Before starting home position return, always make sure that the limit switch operates.
 - 2) Confirm the home position return direction. Incorrect setting will cause the machine to run reversely.
 - 3) Confirm the proximity dog input polarity. Not doing so may cause unexpected operation.



5.6.2 Dog type home position return

A home position return method using a proximity dog. With deceleration started at the front end of the proximity dog, the position where the first Z-phase signal is given past the rear end of the dog or a motion has been made over the home position shift distance starting from the Z-phase signal is defined as a home position.

(1) Devices, parameters

Set the input devices and parameters as follows.

Item	Device/Parameter used	Description	
	Automatic/manual selection (RYn6)	Turn RYn6 ON.	
Manual home position return mode selection	Point table No. selection 1 to 8 (RYnA to RYnE, RY(n+2)3 to RY(n+2)5)	RYnA to RYnE, RY(n+2)3 to RY(n+2)5 are turned off.	
Remote register-based position/speed setting (Only when two stations are occupied)	Position/speed specifying system selection (RY(n+2)A)	ⁿ Turn RY(n+2)A ON.	
Dog type home position return	Parameter No.PC02	DD:Dog type home position return is selected.	
Home position return direction	Parameter No.PC03	Refer to section 5.6.1 (2) and choose home position return direction.	
Dog input polarity	Parameter No.PD16 Refer to section 5.6.1 (2) ar input polarity.		
Home position return speed	Parameter No.PC04	Set speed until detection of dog.	
Creep speed	Parameter No.PC05	Set speed after detection of dog.	
Home position shift distance	Parameter No.PC06	Set when shifting the home position starting at the first Z-phase signal after passage of proximity dog rear end.	
Home position return acceleration/deceleration time constants	Point table No.1	Use the acceleration/deceleration time constants of point table No.1.	
Home position return position data	Parameter No.PC07	Set the current position at home position return completion.	

(2) Length of proximity dog

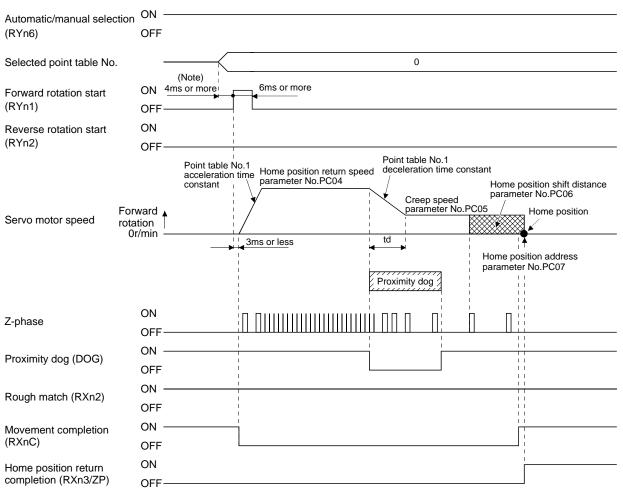
To ensure that the Z-phase signal of the servo motor is generated during detection of the proximity dog (DOG), the proximity dog should have the length which satisfies formulas (5.1) and (5.2).

$$L_1 \geq \frac{V}{60} \cdot \frac{td}{2} \dots (5.1)$$

- L₁ : Proximity dog length [mm]
- V : Home position return speed [mm/min]
- td : Deceleration time [s]
- $L_2 \geq 2 \bullet \Delta S.....(5.2)$
- L2 : Proximity dog length [mm]
- ${\scriptstyle \Delta}S$ ~ : Moving distance per servo motor revolution [mm]



(3) Timing chart



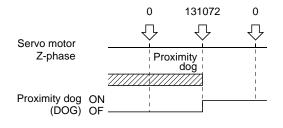
Note. Configure a sequence that changes the point table selection earlier, considering the delay time of CC-Link communication.

The parameter No.PC07 (home position return position data) setting value is the positioning address after the home position return is completed.

(4) Adjustment

In dog type home position return, adjust to ensure that the Z-phase signal is generated during dog detection. Locate the rear end of the proximity dog (DOG) at approximately the center of two consecutive Z-phase signals.

The position where the Z-phase signal is generated can be monitored in "Within one-revolution position" of "Status display" of the set up software(MR Configurator2[™]).



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5.6.3 Count type home position return

In count type home position return, a motion is made over the distance set in parameter No.PC08 (moving distance after proximity dog) after detection of the proximity dog front end. The position where the first Z-phase signal is given after that is defined as a home position. Hence, if the proximity dog (DOG) is 10ms or longer, there is no restriction on the dog length. This home position return method is used when the required proximity dog length cannot be reserved to use dog type home position return or when the proximity dog (DOG) is entered electrically from a PC or PLC...etc or the like.

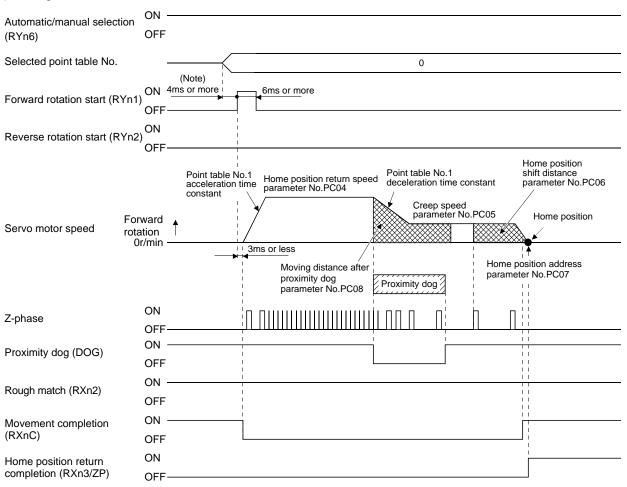
(1) Devices, parameters

Set the input devices and parameters as follows.

Item	Device/Parameter used	Description	
	Automatic/manual selection (RYn6)	Turn RYn6 ON.	
Manual home position return mode selection	Point table No. selection 1 to 8 (RYnA to RYnE, RY(n+2)3 to RY(n+2)5)	RYnA to RYnE, RY($n+2$)3 to RY($n+2$)5 are turned off.	
Remote register-based position/speed setting (Only when two stations are occupied)	Position/speed specifying system selection (RY(n+2)A)	Turn RY(n+2)A ON.	
Count type home position return	Parameter No.PC02	□□□1: Count type home position return is selected.	
Home position return direction	Parameter No.PC03	Refer to section 5.6.1 (2) and choose home position return direction.	
Dog input polarity	Parameter No.PD16	Refer to section 5.6.1 (2) and choose dog input polarity.	
Home position return speed	Parameter No.PC04	Set speed until detection of dog.	
Creep speed	Parameter No.PC05	Set speed after detection of dog.	
Home position shift distance	Parameter No.PC06	Set when shifting the home position, starting at the first Z-phase signal given after passage of the proximity dog front end and movement over the moving distance.	
Moving distance after proximity dog	Parameter No.PC08	Set the moving distance after passage of proximity dog front end.	
Home position return acceleration/deceleration time constants	Point table No.1	Use the acceleration/deceleration time constants of point table No.1.	
Home position return position data	Parameter No.PC07	Set the current position at home position return completion.	



(2) Timing chart



Note. Configure a sequence that changes the point table selection earlier, considering the delay time of CC-Link communication.

The parameter No.PC07 (home position return position data) setting value is the positioning address after the home position return is completed.



5.6.4 Data setting type home position return

Data setting type home position return is used when it is desired to determine any position as a home position. JOG operation can be used for movement.

(1) Devices, parameters

Set the input devices and parameters as follows.

Item	Device/Parameter used	Description	
	Automatic/manual selection (RYn6)	Turn RYn6 ON.	
Manual home position return mode selection	Point table No. selection 1 to 8 (RYnA to RYnE, RY(n+2)3 to RY(n+2)5)	RYnA to RYnE, RY($n+2$)3 to RY($n+2$)5 are turned off.	
Remote register-based position/speed setting (Only when two stations are occupied)	Position/speed specifying system selection (RY(n+2)A)	Turn RY(n+2)A ON.	
Data setting type home position return	Parameter No.PC02	DDD2: Data setting type home position return is selected.	
Home position return position data	Parameter No.PC07	Set the current position at home position return completion.	

(2) Timing chart

Automatic/manual select (RYn6)	tion ON OFF ·		
Selected point table No.	-		0
Forward rotation start (R	(Yn1) ON OFF	(Note) 4ms or more	6ms or more
Reverse rotation start (R	(Yn2) OFF		
	Forward rotation Or/min	3ms or less	Home position address parameter No.PC07
Rough match (RXn2)	ON · OFF		
Movement completion (F	ON RXnC) OFF		
Home position return completion (RXn3/ZP)			j
		Movement to the home position Operation fo	r home position return

Note. Configure a sequence that changes the point table selection earlier, considering the delay time of CC-Link communication.

The parameter No.PC07 (home position return position data) setting value is the positioning address after the home position return is completed.



5.6.5 Stopper type home position return

In stopper type home position return, a machine part is pressed against a stopper or the like by a jog operation to make a home position return and that position is defined as a home position.

After completion of stopper type home position return, please move to any position (Not pressed position) from the pressing position.

If over a certain period of time in the state of the pressing position, an overload alarm (AL 50, AL 51) occurs for driver protection.

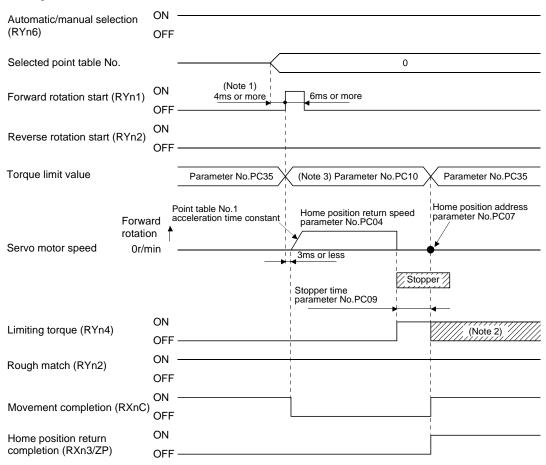
(1) Devices, parameters

Set the input devices and parameters as follows.

Item	Device/Parameter used	Description
Manual home position return	Automatic/manual selection (RYn6)	Turn RYn6 ON.
mode selection	Point table No. selection 1 to 8 (RYnA to RYnE, RY(n+2)3 to RY(n+2)5)	RYnA to RYnE, RY(n+2)3 to RY(n+2)5 are turned off.
Remote register-based position/speed setting (Only when two stations are occupied)	Position/speed specifying system selection (RY(n+2)A)	Turn RY(n+2)A ON.
Stopper type home position return	Parameter No.PC02	□□□3:Stopper type home position return is selected.
Home position return direction	Parameter No.PC03	Refer to section 5.6.1 (2) and choose the home position return direction.
Home position return speed	Parameter No.PC04	Set the speed till contact with the stopper.
Stopper time	Parameter No.PC09	Time from when the part makes contact with the stopper to when home position return data is obtained to output home position return completion (ZP).
Stopper type home position return torque limit value	Parameter No.PC10	Set the servo motor torque limit value for execution of stopper type home position return.
Home position return acceleration time constant	Point table No.1	Use the acceleration time constant of point table No.1.
Home position return position data	Parameter No.PC07	Set the current position at home position return completion.



(2) Timing chart



Note 1. Configure a sequence that changes the point table selection earlier, considering the delay time of CC-Link communication.

- 2. Turns ON when the torque reaches the value set to Forward rotation torque limit (parameter No.PA11), Reverse rotation torque limit (parameter No.PA12) or Internal torque limit (parameter No.PC35).
- 3. The torque limit that is enabled at this point is as follows.

(Note) Internal torque limit selection (RY(n+2)6)	Limit value status			Torque limit to be enabled
0				Parameter No.PC10
1	Parameter No.PC35	>	Parameter No.PC10	Parameter No.PC10
	Parameter No.PC35	<	Parameter No.PC10	Parameter No.PC35

Note. 0: OFF 1: ON

The parameter No.PC07 (home position return position data) setting value is the positioning address after the home position return is completed.



5.6.6 Home position ignorance (servo-on position defined as home position) The position where servo is switched on is defined as a home position.

POINT

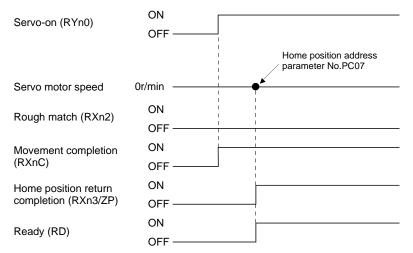
• When executing this home position return, changing to the home position return mode is not necessary.

(1) Devices, parameter

Set the input devices and parameter as follows.

Item	Device/Parameter used	Description
Home position ignorance	Parameter No.PC02	□□□4: Home position ignorance is selected.
Home position return position data	Parameter No.PC07	Set the current position at home position return completion.

(2) Timing chart



The parameter No.PC07 (home position return position data) setting value is the positioning address after the home position return is completed.



5.6.7 Dog type rear end reference home position return

POINT• This home position return method depends on the timing of reading Proximity
dog (DOG) that has detected the rear end of a proximity dog. Hence, if a
home position return is made at the creep speed of 100r/min, an error of
 \pm 400 pulses will occur in the home position. The error of the home position is
larger as the creep speed is higher.

The position where the axis, which had started decelerating at the front end of a proximity dog, has moved the after-proximity dog moving distance and home position shift distance after it passed the rear end is defined as a home position. A home position return that does not depend on the Z-phase signal can be made.

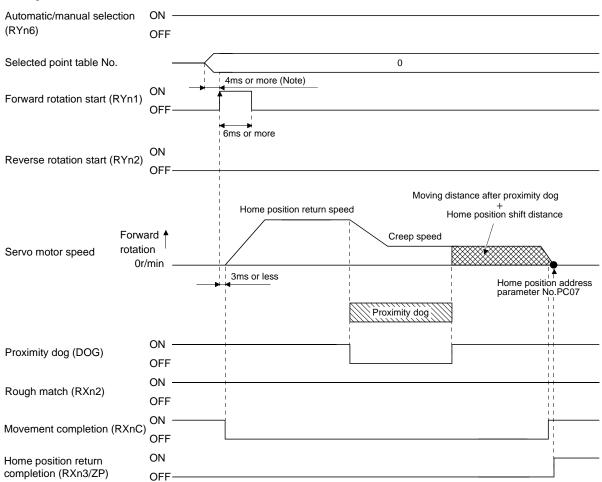
(1) Devices, parameters

Set the input devices and parameters as indicated below.

Item	Device/Parameter used	Description		
	Automatic/manual selection (RYn6)	Turn RYn6 ON.		
Manual home position return mode selection	Point table No. selection 1 to 8 (RYnA to RYnE, RY(n+2)3 to RY(n+2)5)	RYnA to RYnE, RY(n+2)3 to RY(n+2)5 are turned off.		
Remote register-based position/speed setting (Only when two stations are occupied)	Position/speed specifying system selection (RY(n+2)A)	Turn RY(n++2)A ON.		
Dog type rear end reference home position return	Parameter No.PC02	□□□5: Select the dog type rear end reference.		
Home position return direction	Parameter No.PC03	Refer to section 5.6.1 (2) and select the home position return direction.		
Dog input polarity	Parameter No.PD16	Refer to section 5.6.1 (2) and select the dog input polarity.		
Home position return speed	Parameter No.PC04	Set the speed till the dog is detected.		
Creep speed	Parameter No.PC05	Set the speed after the dog is detected.		
Home position shift distance	Parameter No.PC06	Set when the home position is moved from where the axis has passed the proximity dog rear end.		
Moving distance after proximity dog	Parameter No.PC08	Set the moving distance after the axis has passed the proximity dog rear end.		
Home position return acceleration/ deceleration time constants	Point table No.1 Use the acceleration/deceleration to constant of point table No.1.			
Home position return position data	Parameter No.PC07	Set the current position at home position retur completion.		



(2) Timing chart



Note. Configure a sequence that changes the point table selection earlier, considering the delay time of CC-Link communication.

The parameter No.PC17 (home position return position data) setting value is the positioning address after the home position return is completed.



5.6.8 Count type front end reference home position return

POINT
 This home position return method depends on the timing of reading Proximity dog (DOG) that has detected the front end of a proximity dog. Hence, if a home position return is made at the home position return speed of 100r/min, an error of ±400 pulses will occur in the home position. The error of the home position is larger as the home position return speed is higher.

The position where the axis, which had started decelerating at the front end of a proximity dog, has moved the after-proximity dog moving distance and home position shift distance is defined as a home position. A home position return that does not depend on the Z-phase signal can be made. The home position may change if the home position return speed varies.

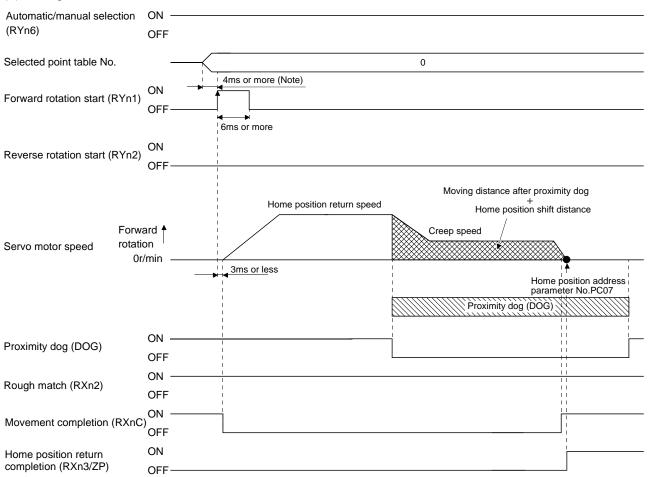
(1) Devices, parameters

Set the input devices and parameters as indicated below.

Item	Device/Parameter used	Description	
Manual home position roturn mode	Automatic/manual selection (RYn6)	Turn RYn6 ON.	
Manual home position return mode selection	Point table No. selection 1 to 8	RYnA to RYnE, RY(n+2)3 to	
	(RYnA to RYnE, RY($n+2$)3 to RY($n+2$)5)	RY(n+2)5 are turned off.	
Remote register-based			
position/speed setting	Position/speed specifying system selection	Turn RY(n+2)A ON.	
(Only when two stations are occupied)	(RY(n+2)A)		
Count type dog front end reference	Parameter No.PC02	□□□6: Select the count type dog	
home position return		front end reference.	
Home position return direction	Parameter No.PC03	Refer to section 5.6.1 (2) and select the	
-		home position return direction.	
Dog input polarity	Parameter No.PD16	Refer to section 5.6.1 (2) and select the	
		dog input polarity.	
Home position return speed	Parameter No.PC04	Set the speed till the dog is detected.	
Creep speed	Parameter No.PC05	Set the speed after the dog is detected	
		Set when the home position is moved	
Home position shift distance	Parameter No.PC06	from where the axis has passed the	
		proximity dog rear end.	
Moving distance after proximity dog	Parameter No.PC08	Set the moving distance after the axis	
Noving distance after proximity dog	Farameter No.FC00	has passed the proximity dog rear end.	
Home position return acceleration/	Point table No.1	Use the acceleration/deceleration time	
deceleration time constants		constant of point table No.1.	
Home position return position data	Parameter No.PC07	Set the current position at home	
Home position return position data		position return completion.	



(2) Timing chart



Note. Configure a sequence that changes the point table selection earlier, considering the delay time of CC-Link communication.

The parameter No.PC07 (home position return position data) setting value is the positioning address after the home position return is completed.



5.6.9 Dog cradle type home position return

The position where the first Z-phase signal is issued after detection of the proximity dog front end can be defined as a home position.

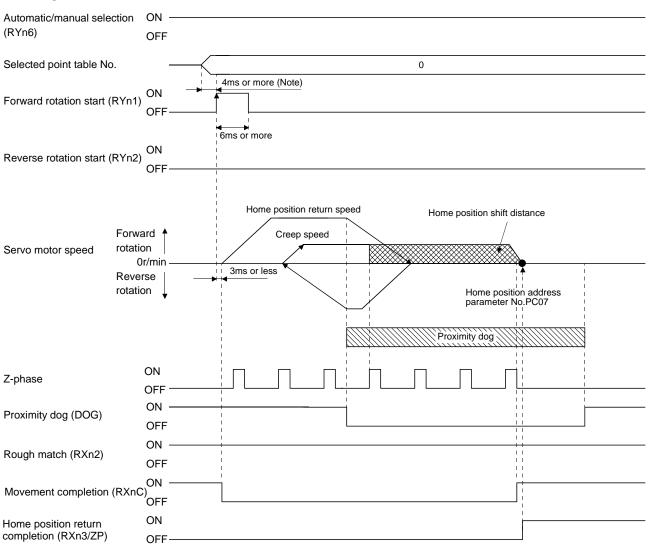
(1) Devices, parameters

Set the input devices and parameters as indicated below.

Item	Device/Parameter used	Description
	Automatic/manual selection (RYn6)	Turn RYn6 ON.
Manual home position return mode selection	Point table No. selection 1 to 8	RYnA to RYnE, RY(n+2)3 to
301001011	(RYnA to RYnE, RY($n+2$)3 to RY($n+2$)5)	RY(n+2)5 are turned off.
Remote register-based		
position/speed setting	Position/speed specifying system selection	Turn $PV(n+2)A ON$
(Only when two stations are	(RY(n++2)A)	Turn RY(n+2)A ON.
occupied)		
Dog cradle type home position return	Parameter No.PC02	$\Box\Box\Box$ 7: Select the dog cradle type.
Home position return direction	Parameter No.PC03	Refer to section 5.6.1 (2) and select the
		home position return direction.
Dog input polarity	Parameter No.PD16	Refer to section 5.6.1 (2) and select the
		dog input polarity.
Home position return speed	Parameter No.PC04	Set the speed till the dog is detected.
Creep speed	Parameter No.PC05	Set the speed after the dog is detected.
Home position shift distance	Parameter No.PC06	Set when the home position is moved
		from the Z-phase signal position.
Home position return		Use the acceleration/deceleration time
acceleration/deceleration time	Point table No.1	constant of point table No.1.
constants		
Home position return position data	Parameter No.PC07	Set the current position at home
		position return completion.







Note. Configure a sequence that changes the point table selection earlier, considering the delay time of CC-Link communication.

The parameter No.PC07 (home position return position data) setting value is the positioning address after the home position return is completed.



5.6.10 Dog type first Z-phase reference home position return

After the proximity dog front end is detected, the current position moves in the reverse direction at creep speed. After this moving away from the proximity dog, the home position is determined to be where the first Z-phase pulse is issued.

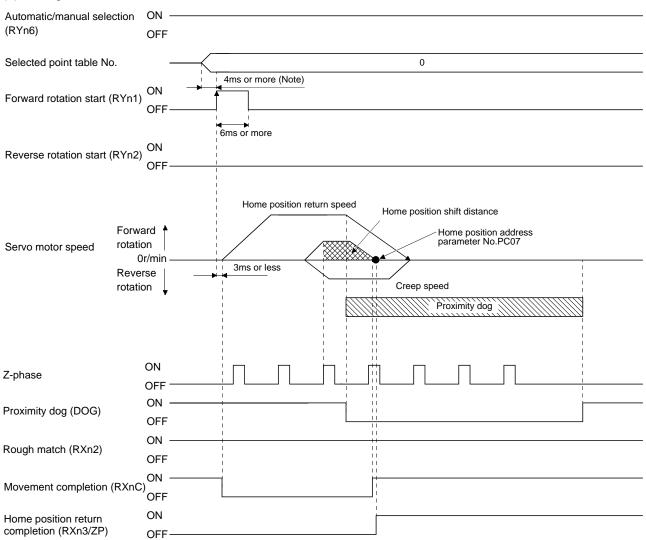
(1) Devices, parameters

Set the input devices and parameters as indicated below.

Item	Device/Parameter used	Description	
	Automatic/manual selection (RYn6)	Turn RYn6 ON.	
Manual home position return mode selection	Point table No. selection 1 to 8	RYnA to RYnE, RY(n+2)3 to	
301001011	(RYnA to RYnE, RY($n+2$)3 to RY($n+2$)5)	RY(n+2)5 are turned off.	
Remote register-based position/speed setting (Only when two stations are	Position/speed specifying system selection (RY(n+2)A)	Turn RY(n+2)A ON.	
occupied) Dog cradle type home position return	Parameter No.PC02	□ □ □ 8: Select the dog cradle type.	
Home position return direction	Parameter No.PC03	Refer to section 5.6.1 (2) and select the home position return direction.	
Dog input polarity	Parameter No.PD16	Refer to section 5.6.1 (2) and select to dog input polarity.	
Home position return speed	Parameter No.PC04	Set the speed till the dog is detected.	
Creep speed	Parameter No.PC05	Set the speed after the dog is detected.	
Home position shift distance	Parameter No.PC06	Set when the home position is moved from the Z-phase signal position.	
Home position return acceleration/deceleration time constants	Point table No.1	Use the acceleration/deceleration time constant of point table No.1.	
Home position return position data	Parameter No.PC07	Set the current position at home position return completion.	







Note. Configure a sequence that changes the point table selection earlier, considering the delay time of CC-Link communication.

The parameter No.PC07 (home position return position data) setting value is the positioning address after the home position return is completed.



5.6.11 Dog type front end reference home position return method

The home position is determined to be the position of the front end of the proximity dog.

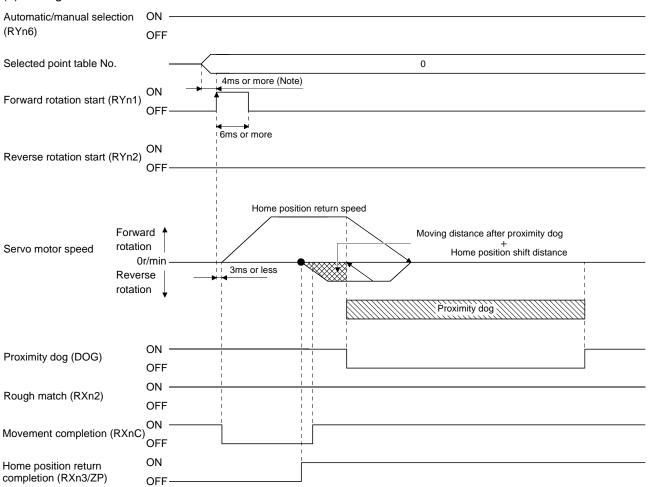
(1) Devices, parameters

Set the input devices and parameters as indicated below.

Item	Device/Parameter used	Description	
Manual home position raturn mode	Automatic/manual selection (RYn6)	Turn RYn6 ON.	
Manual home position return mode selection	Point table No. selection 1 to 8	RYnA to RYnE, $RY(n+2)3$ to	
	(RYnA to RYnE, RY($n+2$)3 to RY($n+2$)5)	RY(n+2)5 are turned off.	
Remote register-based			
position/speed setting	Position/speed specifying system selection	Turn RY(n+2)A ON.	
(Only when two stations are occupied)	(RY(n+2)A)		
Dog cradle type home position return	Parameter No.PC02	\Box \Box \Box 9: Select the dog cradle type.	
Home position return direction	Parameter No.PC03	Refer to section 5.6.1 (2) and select the home position return direction.	
Dog input polarity	Parameter No.PD16	Refer to section 5.6.1 (2) and select the dog input polarity.	
Home position return speed	Parameter No.PC04	Set the speed till the dog is detected.	
Creep speed	Parameter No.PC05	Set the speed after the dog is detected.	
Home position shift distance	Parameter No.PC06	Set when the home position is moved from the Z-phase signal position.	
Home position return acceleration/deceleration time constants	Point table No.1	Use the acceleration/deceleration time constant of point table No.1.	
Home position return position data	Parameter No.PC07	Set the current position at home position return completion.	







Note. Configure a sequence that changes the point table selection earlier, considering the delay time of CC-Link communication.

The parameter No.PC07 (home position return position data) setting value is the positioning address after the home position return is completed.



5.6.12 Dogless Z-phase reference home position return method

The home position is determined to be where the first Z-phase pulse is issued after the home position return is started.

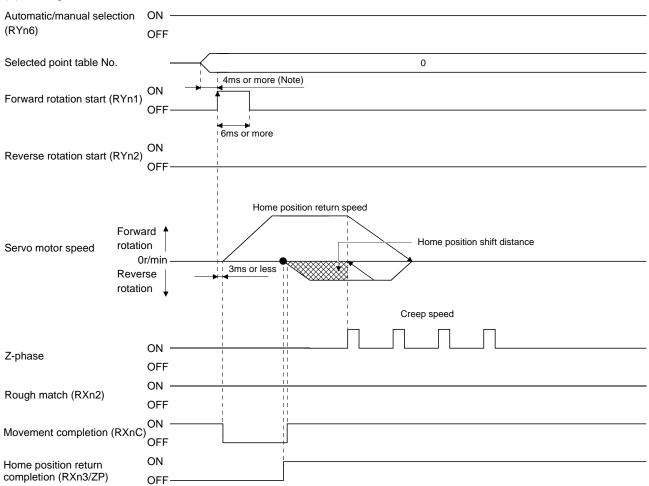
(1) Devices, parameters

Set the input devices and parameters as indicated below.

Device/Parameter used	Description
Automatic/manual selection (RYn6)	Turn RYn6 ON.
Point table No. selection 1 to 8	RYnA to RYnE, RY(n+2)3 to
(RYnA to RYnE, RY($n+2$)3 to RY($n+2$)5)	RY(n+2)5 are turned off.
Position/speed specifying system selection	Turn RY(n+2)A ON.
(RY(n+2)A)	
Parameter No.PC02	\Box \Box \Box A: Select the dog cradle type.
Parameter No PC03	Refer to section 5.6.1 (2) and select
	the home position return direction.
Parameter No.PC04	Set the speed till the dog is detected.
Parameter No PC05	Set the speed after the dog is
	detected.
Parameter No PC06	Set when the home position is moved
	from the Z-phase signal position.
	Use the acceleration/deceleration time
Point table No.1	constant of point table No.1.
Parameter No.PC07	Set the current position at home position return completion.
	Automatic/manual selection (RYn6) Point table No. selection 1 to 8 (RYnA to RYnE, RY(n+2)3 to RY(n+2)5) Position/speed specifying system selection (RY(n+2)A) Parameter No.PC02 Parameter No.PC03 Parameter No.PC04 Parameter No.PC05 Parameter No.PC06 Point table No.1







Note. Configure a sequence that changes the point table selection earlier, considering the delay time of CC-Link communication.

The parameter No.PC07 (home position return position data) setting value is the positioning address after the home position return is completed.

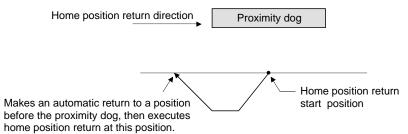


5.6.13 Home position return automatic return function

If the current position is at or beyond the proximity dog in the home position return using the proximity dog, this function starts home position return after making a return to the position where the home position return can be made.

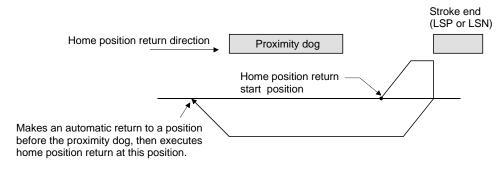
(1) When the current position is at the proximity dog

When the current position is at the proximity dog, an automatic return is made before home position return.



(2) When the current position is beyond the proximity dog

At a start, a motion is made in the home position return direction and an automatic return is made on detection of the stroke end (LSP or LSN). The motion stops past the front end of the proximity dog, and home position return is resumed at that position. If the proximity dog cannot be detected, the motion stops on detection of the LSP or LSN switch and A90 occurs.



Software limit cannot be used with these functions.



5.6.14 Automatic positioning function to the home position

POINT	

 You cannot perform automatic positioning from outside the position data setting range to the home position. In this case, make a home position return again using a manual home position return.

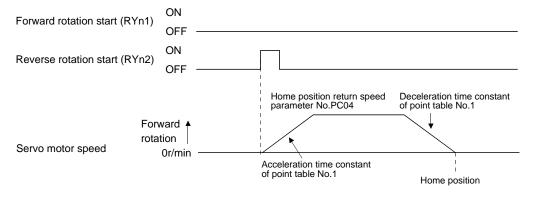
If this function is used when returning to the home position again after performing a manual home position return after a power-on and deciding the home position, automatic positioning can be carried out to the home position at high speed. In an absolute position detection system, manual home position return is not required after power-on.

Please perform a manual home position return beforehand after a power-on.

Set the input signals and parameter as follows.

Item	Device/Parameter used	Description	
Manual home position rature mode	Automatic/manual selection (RYn6)	Turn RYn6 ON.	
Manual home position return mode selection	Point table No. selection 1 to 8	RYnA to RYnE, RY(n+2)3 to RY(n+2)5 are	
Selection	(RYnA to RYnE, RY(n+2)3 to RY(n+2)5)	turned off.	
Home position return speed	Parameter No.PC04	Set the speed till the dog is detected.	
Home position return acceleration/deceleration time	Point table No.1	Use the acceleration/deceleration time constant	
constants		of point table No.1.	

Set up the home position return speed of the automatic positioning function to the home position by parameter No.PC04. Use the data of point table No.1 to set the acceleration time constant and deceleration time constant. When reverse rotation start (RYn2) is ON, it will position automatically at the home position.





5.7 Roll feed display function in roll feed mode

With the roll feed display function, the driver can operate in the roll feed mode. The roll feed mode uses the incremental system.

(1) Parameter settings

No.	Name	Digit to be set	Setting item	Setting value	Description
PA03	Absolute position detection system		Operation system	□□□0 (initial value)	Make sure to set the incremental system. The absolute position detection system cannot be used.
PC28	Function selection C-7		Selection between current position display and command position display	0010	Select roll feed display.

(2) Roll feed display function

At start up, the roll feed display function clears the status display of the current position and command position to zero.



(3) Operation procedure

Changes are made only on the status display of the current position and commanded position. The same operation procedure as that in each operation mode can be used.

Operation procedure		Details
Automatic operation	Automatic operation according to the point table	Section 5.4.2
M 1 <i>c</i>	JOG operation	Section 5.5.1
Manual operation	Manual pulse generator operation	Section 5.5.2
Home position return mode		Section 5.6



5.8 Absolute position detection system

 If an absolute position erase alarm (A25) or an absolute position counter warning
(AE3) has occurred, always perform home position setting again. Not doing so
may cause unexpected operation.

POINT

- When the following parameters are changed, the home position is lost when turning on the power after the change. Execute the home position return again when turning on the power.
 - Parameter No.PA06 (Electronic gear numerator)
 - Parameter No.PA07 (Electronic gear denominator)
 - Parameter No.PA14 (Rotation direction selection)
 - Parameter No.PC07 (Home position return position data)

This driver contains a single-axis driver. Also, all servo motor encoders are compatible with an absolute position detection system. Hence, an absolute position detection system can be configured up by merely loading an absolute position data back-up battery and setting parameter values.

(1) Restrictions

An absolute position detection system cannot be built under the following conditions.

- 1) Stroke-less coordinate system, e.g. rotary shaft, infinite positioning.
- 2) Operation performed in incremental value command type positioning system.

(2) Specifications

Item	Description				
System	Electronic battery backup system.				
Battery	1 piece of lithium battery (primary battery, nominal + 3.6V) Type: LEC-MR-J3BAT.				
Maximum revolution range	Home position ± 32767 rev.				
(Note 1) Maximum speed at power failure	3000r/min				
(Note 2) Battery backup time	Approx. 10,000 hours (battery life with power off)				
(Note 3) Battery storage period	5 years from date of manufacture.				

Note 1. Maximum speed available when the shaft is rotated by external force at the time of power failure or the like.

- 2. Time to hold data by a battery with power off. Replace the batteries within three years since the operation start regardless of the power supply on/off. If the battery is used out of specification, the absolute position erased (A25) may occur.
- 3. Quality of battery degrades by the storage condition. It is recommended that the battery be used within two years from the date of manufacture. The life of battery is five years from the date of manufacture regardless of the connection.



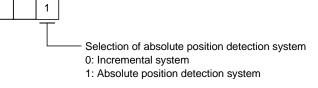
(3) Structure

Component	Description		
Driver			
Servo motor	Use standard models.		
Battery	LEC-MR-J3BAT		
Encoder cable	Use a standard model. (Refer to section 13.1.)		

(4) Parameter setting

Set parameter No.PA03 (Absolute position detection system) as indicated below to make the absolute position detection system valid.

Parameter No.PA03

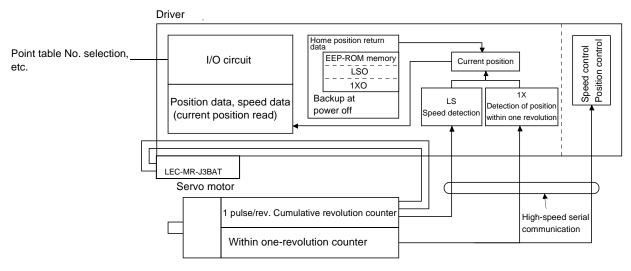


5.8.1 Outline of absolute position detection data communication

For normal operation, as shown below, the encoder consists of a detector designed to detect a position within one revolution and a cumulative revolution counter designed to detect the number of revolutions.

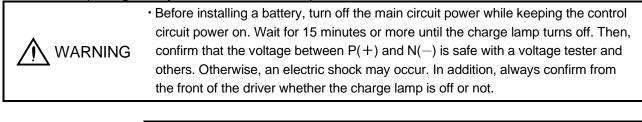
The absolute position detection system always detects the absolute position of the machine and keeps it battery-backed, independently of whether the general-purpose programming PC or PLC...etc power is on or off. Therefore, once the home position is defined at the time of machine installation, home position return is not needed when power is switched on thereafter.

If a power failure or a fault occurs, restoration is easy.





5.8.2 When replacing battery with the control circuit power ON



POINT

• The internal circuits of the driver may be damaged by static electricity. Always take the following precautions.

- Ground human body and work bench.
- Do not touch the conductive areas, such as connector pins and electrical parts, directly by hand.
- Before starting battery changing procedure, make sure that the main circuit power is switched OFF with the control circuit power ON. When battery is changed with the control power OFF, the absolute position data is lost.

(1) When replacing battery with the control circuit power ON

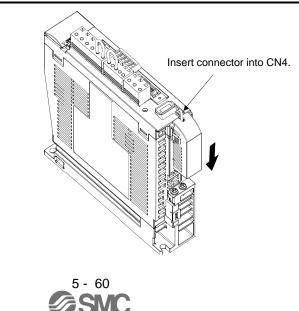
POINT

 Replacing battery with the control circuit power OFF will erase the absolute position data.

Replacing battery with the control circuit power ON will not erase the absolute position data. Refer to section 5.8.3 for installation procedure of battery to the driver.

5.8.3 Battery installation procedure

POINT
 For the driver with a battery holder on the bottom, it is not possible to wire for the earth with the battery installed. Insert the battery after executing the earth wiring of the driver.



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	 Never adjust or change the parameter values extremely as it will make operation instable.
--	---

POINT
For any parameter whose symbol is preceded by *, set the parameter value and switch power off once, then switch it on again to make that parameter setting valid.

In this driver, the parameters are classified into the following groups on a function basis.

Parameter group	Main description			
Basic setting parameters (No.PA □ □)	Make basic setting with these parameters. Generally, the operation is possible only with these parameter settings.			
Gain/filter parameters (No.PB □ □)	Use these parameters when making gain adjustment manually.			
Extension setting parameters (No.PC	These parameters are inherent to the LECSC2-T□ driver.			
I/O setting parameters (No.PD □ □)	Use these parameters when changing the I/O devices of the driver.			

Mainly setting the basic setting parameters (No.PADD) allows the setting of the basic parameters at the time of introduction.

6.1 Basic setting parameters (No.PA

6.1.1 Parameter list	
----------------------	--

No.	Symbol	Name	Initial value	Unit
PA01	*STY	Control mode	0000h	
PA02	*REG	Regenerative option	0000h	
PA03	*ABS	Absolute position detection system	0000h	
PA04	*AOP1	Function selection A-1	0000h	
PA05	*FTY	Feeding function selection	0000h	
PA06	*CMX	Electronic gear numerator	1	
PA07	*CDV	Electronic gear denominator	1	
PA08	ATU	Auto tuning mode	0001h	
PA09	RSP	Auto tuning response	12	
PA10	INP	In-position range	100	μm
PA11	TLP	Forward rotation torque limit	100.0	%
PA12	TLN	Reverse rotation torque limit	100.0	%
PA13	/	For manufacturer setting	0002h	
PA14	*POL	Rotation direction selection	0	
PA15	*ENR	Encoder output pulses	4000	pulse/rev
PA16		For manufacturer setting	0000h	
PA17			0000h	
PA18			0000h	
PA19	*BLK	Parameter write inhibit	000Ch	



6.1.2 Parameter write inhibit

	Parameter		Initial	L lus it	
No.	Symbol	Name	value	Unit	Setting range
PA19	*BLK	Parameter write inhibit	000Ch	/	Refer to the text.

POINT
This parameter is made valid when power is switched off, then on after setting.

In the factory setting, this driver allows changes to the basic setting parameter, gain/filter parameter and extension setting parameter settings. With the setting of parameter No.PA19, write can be disabled to prevent accidental changes.

The following table indicates the parameters which are enabled for reference and write by the setting of parameter No.PA19. Operation can be performed for the parameters marked \bigcirc .

Parameter No.PA19 setting	Setting operation	Basic setting parameters No.PA □ □	Gain/Filter parameters No.PB 🗆 🗆	Extension setting parameters No.PC □ □	I/O setting parameters No.PD
0000	Reference	0			
0000h	Write	0			
0000	Reference	0	0	0	
000Bh	Write	0	0	0	
000Ch	Reference	0	0	0	0
(initial value)	Write	0	0	0	0
	Reference	0			
100Bh	Write	Parameter No. PA19 only			
	Reference	0	0	0	0
100Ch	Write	Parameter No. PA19 only			

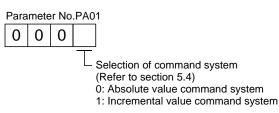


6.1.3 Selection of command system

	Parameter		Initia	ll Lunia	Cotting range
No.	Symbol	Name	valu	e Unit	Setting range
PA01	*STY	Control mode	0000	h	Refer to the text.

POINT
This parameter is made valid when power is switched off, then on after setting.

Select the command system.



6.1.4 Selection of regenerative option

	Parameter		Initial	Unit	Cotting rongo
No.	Symbol	Name	value	Unit	Setting range
PA02	*REG	Regenerative option	0000h		Refer to the text.

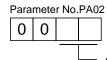
POINT

 This parameter is made valid when power is switched off, then on after setting.

• Wrong setting may cause the regenerative option to burn.

 If the regenerative option selected is not for use with the driver, parameter error (A37) occurs.

Set this parameter when using the regenerative option, brake unit, power regeneration converter, or power regeneration common converter.



Selection of regenerative option 00:Regenerative option is not used

• For driver of 100W, regenerative resistor is not used.

• For driver of 200W to 400W, regenerative resistor is not used. 02:LEC-MR-RB-032

03:LEC-MR-RB-12

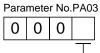


6.1.5 Using absolute position detection system

	Parameter		Initial	L las it	
No.	Symbol	Name	value	Unit	Setting range
PA03	*ABS	*ABS Absolute position detection system		/	Refer to the text.

POINT
 This parameter is made valid when power is switched off, then on after setting.

Set this parameter when using the absolute position detection system.



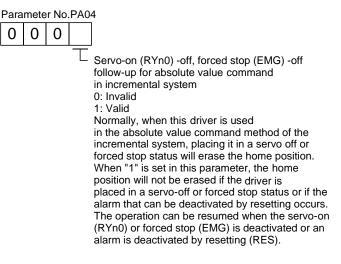
Selection of absolute position detection system (refer to section 5.7)
0: Used in incremental system
1: Used in absolute position detection system

6.1.6 Follow-up for absolute value command system in incremental system

		Parameter	Initial	L las it	
No.	Symbol	Name	value	Unit	Setting range
PA04	*AOP1	Function selection A-1	0000h	/	Refer to the text.

POINT
This parameter is made valid when power is switched off, then on after setting.

If this parameter is made valid, the home position is not lost in the servo-off or forced stop state, and the operation can be resumed when the servo-on (RYn0) or forced stop (EMG) is deactivated.



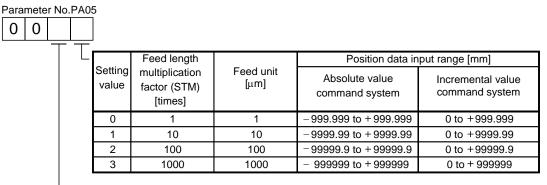


6.1.7 Feeding function selection

		Parameter	Initial	L las it	
No.	Symbol	Name	value	Unit	Setting range
PA05	*FTY	Feeding function selection	0000h	/	Refer to the text.

POINT
 This parameter is made valid when power is switched off, then on after setting.

Select the feed length multiplication and the manual pulse generator input multiplication.



- Manual pulse generator multiplication factor

0: 1 time

1: 10 times

2: 100 times



6.1.8 Electronic gear

	Parameter				
No.	Symbol	Name	value	Unit	Setting range
PA06	*CMX	Electronic gear numerator	1	/	0 to 65535
PA07	*CDV	Electronic gear denominator	1	/	1 to 65535

• False setting will result in unexpected fast rotation, causing injury.

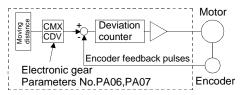
POINT
This parameter is made valid when power is switched off, then on after setting.

- The range of the electronic gear setting is $\frac{1}{10} < \frac{CMX}{CDV} < 2000$. If you set any value outside this range, a parameter error (A37) occurs.
- Setting "0" in parameter No.PA06 automatically sets the encoder resolution pulse.

(1) Concept of electronic gear

Use the electronic gear (parameters No.PA06, PA07) to make adjustment so that the driver setting matches the moving distance of the machine. Also, by changing the electronic gear value, the machine can be moved at any multiplication ratio to the moving distance on the driver.

CMX = Parameters No.PA06 Parameters No.PA07



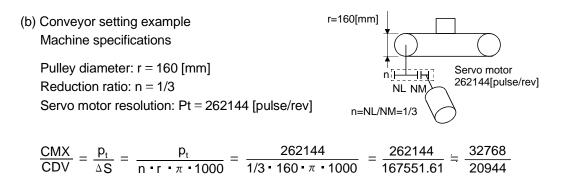
The following examples are used to explain how to calculate the electronic gear value.

POINT	
The following	g specification symbols are needed for electronic gear
calculation.	
Pb : Ball sci	rew lead [mm]
n : Reduct	ion ratio
Pt : Servo ı	notor resolution [pulse/rev]
ΔS : Travel	per servo motor revolution [mm/rev]

(a) Ball screw setting example	n
Machine specifications	n=NL/NM=1/2 NL
Ball screw lead: Pb = 10 [mm]	Pb=10[mm]
Reduction ratio: $n = 1/2$	
Servo motor resolution: Pt = 262144 [pulse/rev]	Servo motor 262144[pulse/rev]
$\frac{CMX}{CDV} = \frac{p_t}{\Delta S} = \frac{p_t}{n \cdot p_b \cdot 1000} = \frac{262144}{1/2 \cdot 10 \cdot 1000} =$	$\frac{-262144}{5000} = \frac{32768}{625}$

Hence, set 32768 to CMX and 625 to CDV.





Reduce CMX and CDV to the setting range or less, and round off the first decimal place. Hence, set 32768 to CMX and 20944 to CDV.

6.1.9 Auto tuning

	Parameter		Initial	L las it	
No.	Symbol	Name	value	Unit	Setting range
PA08	ATU	Auto tuning mode	0001h		Refer to the text.
PA09	RSP	Auto tuning response	12		1 to 32

Make gain adjustment using auto tuning. Refer to section 8.2 for details.

(1) Auto tuning mode (parameter No.PA08)

Select the gain adjustment mode.



Gain adjustment mode setting

Setting	Gain adjustment mode	Automatically set parameter No. (Note)
0	Interpolation mode	PB06 • PB08 • PB09 • PB10
1	Auto tuning mode 1	PB06 • PB07 • PB08 • PB09 • PB10
2	Auto tuning mode 2	PB07 • PB08 • PB09 • PB10
3	Manual mode	

Note. The parameters have the following names.

Parameter No.	Name
PB06	Ratio of load inertia moment to servo motor inertia moment
PB07	Model loop gain
PB08	Position loop gain
PB09	Speed loop gain
PB10	Speed integral compensation



(2) Auto tuning response (parameter No.PA09)

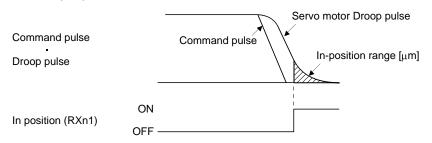
If the machine hunts or generates large gear sound, decrease the set value. To improve performance, e.g. shorten the settling time, increase the set value.

Setting	Response	Guideline for machine resonance frequency [Hz]	Setting	Response	Guideline for machine resonance frequency [Hz]
1	Low response	10.0	17	Low response	67.1
2	↑	11.3	18	↑	75.6
3		12.7	19		85.2
4		14.3	20		95.9
5		16.1	21		108.0
6		18.1	22		121.7
7		20.4	23		137.1
8		23.0	24		154.4
9		25.9	25		173.9
10		29.2	26		195.9
11		32.9	27		220.6
12		37.0	28		248.5
13		41.7	29		279.9
14		47.0	30		315.3
15] 🖌	52.9	31] 🗸	355.1
16	Middle response	59.6	32	Middle response	400.0

6.1.10 In-position range

	Parameter		Initial	Linit	Cotting rongo
No.	Symbol	Name	value	Unit	Setting range
PA10	INP	In-position range	100	μm	0 to 10000

Set the range, where In position (RXn1) and Movement completion (RXnC) are output, in the command pulse unit before calculation of the electronic gear. With the setting of parameter No.PC24, the range can be changed to the encoder output pulse unit.





6.1.11 Torque limit

	Parameter		Initial	L la it	
No.	Symbol	Name	value	Unit	Setting range
PA11	TLP	Forward rotation torque limit	100.0	%	0 to 100.0
PA12	TLN	Reverse rotation torque limit	100.0	%	0 to 100.0

The torque generated by the servo motor can be limited.

(1) Forward rotation torque limit (parameter No.PA11)

Set this parameter on the assumption that the maximum torque is 100[%]. Set this parameter when limiting the torque of the servo motor in the CCW driving mode or CW regeneration mode. Set this parameter to "0.0" to generate no torque.

(2) Reverse rotation torque limit (parameter No.PA12)

Set this parameter on the assumption that the maximum torque is 100[%]. Set this parameter when limiting the torque of the servo motor in the CW driving mode or CCW regeneration mode. Set this parameter to "0.0" to generate no torque.



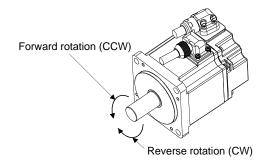
6.1.12 Selection of servo motor rotation direction

	Parameter		Initial Unit		
No.	Symbol	Name	value	Unit	Setting range
PA14	*POL	Rotation direction selection	0		0•1

POINT
 This parameter is made valid when power is switched off, then on after setting.

Select servo motor rotation direction relative to the input pulse train.

	Servo Motor Rotation Direction				
Parameter No.PA14 Setting	Forward rotation start (Ryn1)	Reverse rotation start (Ryn2)			
Setting	ON	ON			
0	CCW	CW			
1	CW	CCW			



6.1.13 Encoder output pulse

	Parameter		Initial	L las it		
No.	Symbol Name		value	Unit	Setting range	
PA15	*ENR	Encoder output pulse	4000	pulse/ rev	1 to 65535	

POINT
This parameter is made valid when power is switched off, then on after setting.

Used to set the encoder pulses (A-phase, B-phase) output by the driver.

Set the value 4 times greater than the A-phase or B-phase pulses.

You can use parameter No.PC19 to choose the output pulse setting or output division ratio setting.

The number of A/B-phase pulses actually output is 1/4 times greater than the preset number of pulses.

The maximum output frequency is 4.6Mpps (after multiplication by 4). Use this parameter within this range.



(1) For output pulse designation

Set " □ □ 0 □ " (initial value) in parameter No.PC19. Set the number of pulses per servo motor revolution. Output pulse = set value [pulses/rev] For instance, set "5600" to Parameter No.PA15, the actually output A/B-phase pulses are as indicated below.

A · B-phase output pulses = $\frac{5600}{4}$ =1400[pulse]

(2) For output division ratio setting

Set "
 1
 1
 " in parameter No.PC19.

The number of pulses per servo motor revolution is divided by the set value.

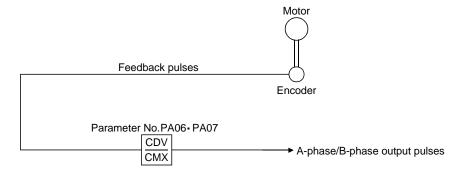
Output pulse = Resolution per servo motor revolution [pulses/rev]

For instance, set "8" to Parameter No.PA15, the actually output A/B-phase pulses are as indicated below.

A·B-phase output pulses = $\frac{262144}{8} \cdot \frac{1}{4} = 8192$ [pulse]

(3) When outputting pulse train similar to command pulses

Set parameter No.PC19 to " $\Box \Box 2 \Box$ ". The feedback pulses from the servo motor encoder are processed and output as shown below. The feedback pulses can be output in the same pulse unit as the command pulses.





6.2 Gain/filter parameters (No.PB □ □) 6.2.1 Parameter list

No.	Symbol	Name	Initial value	Unit
PB01	FILT	Adaptive tuning mode (Adaptive filter II)	0000h	
PB02	VRFT	Vibration suppression control tuning mode	0000h	
F DUZ	VINET	(Advanced vibration suppression control)	000011	
PB03		For manufacturer setting	0000h	
PB04	FFC	Feed forward gain	0	%
PB05	\sim	For manufacturer setting	500	
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment	7.0	Multiplier
1 000	ODZ		7.0	(×1)
PB07	PG1	Model loop gain	24	rad/s
PB08	PG2	Position loop gain	37	rad/s
PB09	VG2	Speed loop gain	823	rad/s
PB10	VIC	Speed integral compensation	33.7	ms
PB11	VDC	Speed differential compensation	980	
PB12		For manufacturer setting	0	\backslash
PB13	NH1	Machine resonance suppression filter 1	4500	Hz
PB14	NHQ1	Notch shape selection 1	0000h	
PB15	NH2	Machine resonance suppression filter 2	4500	Hz
PB16	NHQ2	Notch shape selection 2	0000h	
PB17		Automatic setting parameter	000011	\backslash
PB18	LPF	Low-pass filter	3141	rad/s
PB19	VRF1	Vibration suppression control vibration frequency setting	100.0	Hz
PB20	VRF2	Vibration suppression control resonance frequency setting	100.0	Hz
PB21		For manufacturer setting	0.00	
PB22		Tor manufacturer setting	0.00	
PB23	VFBF	Low-pass filter selection	0000h	\sim
PB24	*MVS	Slight vibration suppression control selection	0000h	\backslash
PB25		For manufacturer setting	0000h	
PB26	*CDP	Gain changing selection	0000h	\sim
PB27	CDL	Gain changing condition	10	
PB28	CDT	Gain changing time constant	1	ms
PB29	GD2B	Gain changing ratio of load inertia moment to servo motor inertia moment	7.0	Multiplier
. 220	0011			(×1)
PB30	PG2B	Gain changing position loop gain	37	rad/s
PB31	VG2B	Gain changing speed loop gain	823	rad/s
PB32	VICB	Gain changing speed integral compensation	33.7	ms
-		Gain changing vibration suppression control vibration frequency setting	100.0	Hz
PB34	VRF2B	Gain changing vibration suppression control resonance frequency setting	100.0	Hz
PB35		For manufacturer setting	0.00	
PB36	\backslash	<u> </u>	0.00	1\
PB37			100	1 \
PB38			0	
PB39			0	
PB40			0	
-				
PB41	\		1125	
PB42	\setminus		1125	
PB43	\		0004h	
PB44	\		0000h	\
PB45	\backslash		0000h	

6.2.2 Detail list

No.	Symbol		Nam	e and function	Initial value	Unit	Setting range
PB01	FILT	Select the (filter tuni	ng mode 1) automatically ion filter 1 (parameter No.	er II) uning. Setting this parameter to "	0000h		
			Response of mechanical system	Machine resonance point			
			Notch depth	Frequency			
			000	Filter tuning mode selection			
		Setting	Filter adjustment mode	Automatically set parameter			
		0	Filter OFF	(Note)			
		1	Filter tuning mode	Parameter No.PB13 Parameter No.PB14			
		2	Manual mode				
		When this positionin period of not neces	s parameter is set to " □ □ g is done the predetermin time, and the setting char ssary, the setting changes	14 are fixed to the initial values.			
				ever, this does not occur when the servo off.			



No.	Symbol	Name and function	Initial value	Unit	Setting range
PB02	VRFT	Vibration suppression control tuning mode (Advanced vibration suppression control) The vibration suppression is valid when the parameter No.PA08 (auto tuning) setting is " □ □ 2" or " □ □ 3". When PA08 is " □ □ 1", vibration suppression is always invalid. Select the setting method for vibration suppression control tuning. Setting this parameter to " □ □ 1" (vibration suppression control tuning mode) automatically changes the vibration suppression control - vibration frequency (parameter No.PB19) and vibration suppression control - vibration frequency (parameter No.PB20) after positioning is done the predetermined number of times. Droop pulse $Automatic adjustment Or op pulse Orommand Orom Pulse Orommand Orom Orom Orom Orom Orom Orom Orom Orom$	0000h		
		Setting Vibration suppression Automatically set control tuning mode parameter			
		0 Vibration suppression control OFF (Note)			
		Vibration suppression control tuning mode Parameter No.PB19 (Advanced vibration Parameter No.PB20 suppression control) Vibration			
		2 Manual mode			
		Note. Parameter No.PB19 and PB20 are fixed to the initial values.			
		When this parameter is set to " \Box \Box 1", the tuning is completed after positioning is done the predetermined number or times for the predetermined period of time, and the setting changes to " \Box \Box 2". When the vibration suppression control tuning is not necessary, the setting changes to " \Box \Box \Box 0". When this parameter is set to " \Box \Box 0", the initial values are set to the vibration suppression control - vibration frequency and vibration suppression control - resonance frequency. However, this does not occur when the servo off			
PB03		For manufacturer setting	0000h		
		Do not change this value by any means.			\square
PB04	FFC	Feed forward gain Set the feed forward gain. When the setting is 100%, the droop pulses during operation at constant speed are nearly zero. However, sudden acceleration/deceleration will increase the overshoot. As a guideline, when the	0	%	0 to 100
		feed forward gain setting is 100%, set 1s or more as the acceleration/deceleration time constant up to the rated speed.			



No.	Symbol	Name and function	Initial value	Unit	Setting range
PB05		For manufacturer setting Do not change this value by any means.	500		
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment Used to set the ratio of the load inertia moment to the servo motor shaft inertia moment. When auto tuning mode 1 and interpolation mode is selected, the result of auto tuning is automatically used. (Refer to section 8.1.1) In this case, it varis between 0 and 100.0.	7.0	Multiplier (×1)	0 to 300.0
PB07	PG1	Model loop gain Set the response gain up to the target position. Increase the gain to improve track ability in response to the command. When auto turning mode 1,2 is selected, the result of auto turning is automatically used.	24	rad/s	1 to 2000
PB08	PG2	Position loop gain Used to set the gain of the position loop. Set this parameter to increase the position response to level load disturbance. Higher setting increases the response level but is liable to generate vibration and/or noise. When auto tuning mode 1,2 and interpolation mode is selected, the result of auto tuning is automatically used.	37	rad/s	1 to 1000
PB09	VG2	Speed loop gain Set this parameter when vibration occurs on machines of low rigidity or large backlash. Higher setting increases the response level but is liable to generate vibration and/or noise. When auto tuning mode 1,2 manual mode and interpolation mode is selected, the result of auto tuning is automatically used.	823	rad/s	20 to 50000
PB10	VIC	Speed integral compensation Used to set the integral time constant of the speed loop. Lower setting increases the response level but is liable to generate vibration and/or noise. When auto tuning mode 1,2 and interpolation mode is selected, the result of auto tuning is automatically used.	33.7	ms	0.1 to 1000.0
PB11	VDC	Speed differential compensation Used to set the differential compensation. Made valid when the proportion control (RY(n+2)7) is switched on.	980		0 to 1000
PB12	$\overline{\ }$	For manufacturer setting Do not change this value by any means.	0		
PB13	NH1	Machine resonance suppression filter 1 Set the notch frequency of the machine resonance suppression filter 1. Setting parameter No.PB01 (filter tuning mode 1) to " □ □ □ 1" automatically changes this parameter. When the parameter No.PB01 setting is " □ □ □ 0", the setting of this parameter is ignored.	4500	Hz	100 to 4500



No.	Symbol	Name and function	Initial value	Unit	Setting range
PB14	NHQ1	Notch shape selection 1 Used to selection the machine resonance suppression filter 1. O O Notch depth selection Setting value Depth Gain O Deep -40dB 1 to -8dB 3 Shallow -4dB Notch width Setting value Width 0 Standard 1 to 3 Wide Setting parameter No.PB01 (filter tuning mode 1) to " □□□ 1" automatically changes this parameter. When the parameter No.PB01 setting is " □□□ 0", the setting of this parameter	0000h		Refer to name and function column.
PB15	NH2	is ignored. Machine resonance suppression filter 2 Set the notch frequency of the machine resonance suppression filter 2. Set parameter No.PB16 (notch shape selection 2) to "	4500	Hz	100 to 4500
PB16	NHQ2	parameter valid. Notch shape selection 2 Select the shape of the machine resonance suppression filter 2. Machine resonance suppression filter 2 selection 0: Invalid 1: Valid Notch depth selection Setting value Deep -40dB -4dB 3: Shallow -4dB Notch width Notch width Setting value Width α 0 Standard 2 1 to 4 3 Wide 5	0000h		Refer to name and function column.
PB17		Automatic setting parameter The value of this parameter is set according to a set value of parameter No.PB06 (Ratio of load inertia moment to servo motor inertia moment).			



No.	Symbol	Name and function	Initial value	Unit	Setting range
PB18	LPF	Low-pass filter Set the low-pass filter. Setting parameter No.PB23 (low-pass filter selection) to "	3141	rad/s	100 to 18000
PB19	VRF1	Vibration suppression control vibration frequency setting Set the vibration frequency for vibration suppression control to suppress low- frequency machine vibration, such as enclosure vibration. Setting parameter No.PB02 (vibration suppression control tuning mode) to " 1" automatically changes this parameter. When parameter No.PB02 is set to " D 2", this parameter can be set manually.	100.0	Hz	0.1 to 100.0
PB20	VRF2	Vibration suppression control resonance frequency setting Set the resonance frequency for vibration suppression control to suppress low- frequency machine vibration, such as enclosure vibration. Setting parameter No.PB02 (vibration suppression control tuning mode) to " 1" automatically changes this parameter. When parameter No.PB02 is set to " D 2", this parameter can be set manually.	100.0	Hz	0.1 to 100.0
PB21		For manufacturer setting	0.00		
PB22 PB23	VFBF	Do not change this value by any means. Low-pass filter selection	0.00 0000h	$ \rightarrow $	Refer to
		Select the low-pass filter. $ \begin{array}{c c} \hline 0 & 0 & 0 \\ \hline & & \\$			name and function column.
PB24	*MVS	Slight vibration suppression control selection Select the slight vibration suppression control. When parameter No.PA08 (auto tuning mode) is set to " □ □ □ 3", this parameter is made valid. 0 0 0Slight vibration suppression control selection 0: Invalid 1: Valid	0000h		Refer to name and function column.



No.	Symbol	Name and function	Initial value	Unit	Setting range
PB25		For manufacturer setting Do not change this value by any means.	0000h		
PB26	*CDP	Gain changing selection Select the gain changing condition. (Refer to section 9.6.) Gain changing selection Under any of the following conditions, the gains change on the basis of the parameter No.PB29 to PB32 settings. 0: Invalid 1: Gain changing (RX(n+2)8) is ON 2: Command frequency (Parameter No.PB27 setting) 3: Droop pulse value (Parameter No.PB27 setting) 4: Servo motor speed (Parameter No.PB27 setting) 4: Servo motor speed (Parameter No.PB27 setting) Gain changing condition 0: Valid at more than condition (Valid when gain changing (RX(n+2)8) is ON) 1: Valid at less than condition (Valid when gain changing (RX(n+2)8) is OFF)	0000h		Refer to name and function column.
PB27	CDL	Gain changing condition Used to set the value of gain changing condition (command frequency, droop pulses, servo motor speed) selected in parameter No.PB26. The set value unit changes with the changing condition item. (Refer to section 9.6.)	10	kpps pulse r/min	0 to 9999
PB28	CDT	Gain changing time constant Used to set the time constant at which the gains will change in response to the conditions set in parameters No.PB26 and PB27. (Refer to section 9.6.)	1	ms	0 to 100
PB29	GD2B	Gain changing ratio of load inertia moment to servo motor inertia moment Used to set the ratio of load inertia moment to servo motor inertia moment when gain changing is valid. This parameter is made valid when the auto tuning is invalid (parameter No. PA08: $\Box \Box \Box \Box$ 3).	7.0	Multiplier (×1)	0 to 300.0
PB30	PG2B	Gain changing position loop gain Set the position loop gain when the gain changing is valid. This parameter is made valid when the auto tuning is invalid (parameter No. PA08: □□□3).	37	rad/s	1 to 2000
PB31	VG2B	Gain changing speed loop gain Set the speed loop gain when the gain changing is valid. This parameter is made valid when the auto tuning is invalid (parameter No. PA08: □□□3).	823	rad/s	20 to 20000
PB32	VICB	Gain changing speed integral compensation Set the speed integral compensation when the gain changing is valid. This parameter is made valid when the auto tuning is invalid (parameter No. PA08:	33.7	ms	0.1 to 5000.0



No.	Symbol	Name and function	Initial value	Unit	Setting range
PB33	VRF1B	Gain changing vibration suppression control vibration frequency setting Set the vibration frequency for vibration suppression control when the gain changing is valid. This parameter is made valid when the parameter No.PB02 setting is " 2" and the parameter No.PB26 setting is " 1". When using the vibration suppression control gain changing, always execute the changing after the servo motor has stopped.	100.0	Hz	0.1 to 100.0
PB34	VRF2B	Gain changing vibration suppression control resonance frequency setting Set the resonance frequency for vibration suppression control when the gain changing is valid. This parameter is made valid when the parameter No.PB02 setting is " □ □ □ 2" and the parameter No.PB26 setting is " □ □ □ 1". When using the vibration suppression control gain changing, always execute the changing after the servo motor has stopped.	100.0	Hz	0.1 to 100.0
PB35 PB36 PB37 PB38 PB39 PB40 PB41 PB42 PB43 PB44 PB44 PB45		For manufacturer setting Do not change this value by any means.	0.00 0.00 100 0 0 1125 1125 0004h 0000h 0000h		



6.3 Extension setting parameters (No.PC

6.3.1 Parameter list Unit No. Symbol Name and function Initial value PC01 For manufacturer setting 0000h PC02 *ZTY 0000h Home position return type PC03 *ZDIR Home position return direction 0001h PC04 ZRF 500 Home position return speed r/min PC05 CRF 10 r/min Creep speed PC06 ZST Home position shift distance 0 μm ×10^{s™}μm PC07 *ZPS 0 Home position return position data imes10^{STM} μ m 1000 PC08 DCT Moving distance after proximity dog PC09 ZTM Stopper type home position return stopper time 100 ms PC10 ZTT Stopper type home position return torque limit value 15.0 % PC11 CRP Rough match output range 0 imes10^{STM} μ m PC12 100 JOG Jog speed r/min PC13 *STC S-pattern acceleration/deceleration time constant 0 ms PC14 *BKC Backlash compensation 0 pulse PC15 For manufacturer setting 0000h PC16 MBR Electromagnetic brake sequence output 100 ms PC17 ZSP 50 r/min Zero speed **PC18** *BPS Alarm history clear 0000h PC19 *ENRS 0000h Encoder output pulse selection PC20 *SNO Station number setting 0 station PC21 *SOP RS-422 communication function selection 000<u>0h</u> PC22 *COP1 Function selection C-1 0000h PC23 For manufacturer setting 0000h *COP3 PC24 Function selection C-3 0000h PC25 For manufacturer setting 0000h PC26 *COP5 Function selection C-5 0000h PC27 For manufacturer setting 0000h PC28 *COP7 Function selection C-7 0000h PC29 For manufacturer setting 0000h PC30 *DSS 0000h Remote register-based position/speed specifying system selection ×10^{sтм}µm PC31 LMPL Software limit + 0 PC32 LMPH imes10^{STM} μ m PC33 LMNL Software limit -0 PC34 LMNH PC35 100.0 TL2 Internal torque limit 2 % PC36 0000h For manufacturer setting *LPPL ×10^{s™}μm PC37 Position range output address + 0 PC38 *LPPH ×10^{s™}μm PC39 *LNPL 0 Position range output address -*LNPH PC40 PC41 For manufacturer setting 0000h PC42 0000h PC43 0000h PC44 0000h PC45 0000h PC46 0000h PC47 0000h PC48 0000h



No.	Symbol	Name and function	Initial value	Unit
PC49		For manufacturer setting	0000h	
PC50			0000h	

6.3.2 Detail list

No.	Symbol	Name and function	Initial value	Unit	Setting range
PC01		For manufacturer setting	0000h		
		Do not change this value by any means.			
PC02	*ZTY	Home position return type	0000h	Ι	Refer to
		Used to set the home position return system. (Refer to section 5.6.)		$ \rangle$	name and
					function
					column.
		Home position return system			
		0: Dog type			
		1: Count type			
		2: Data setting type 3: Stopper type			
		4: Home position ignorance			
		(Servo-on position as home position)			
		5: Dog type rear end reference 6: Count type front end reference			
		7: Dog cradle type			
		8: Dog type right-before Z-phase reference			
		9: Dog type front end reference A: Dogless Z-phase reference			
PC03	*ZDIR	Home position return direction	0001h		Refer to
		Used to set the home position return direction.		$\left \right\rangle$	name and
					function
		0 0 0			column.
		Home position return direction			
		0: Address increment direction			
		1: Address decrement direction			
PC04	ZRF	Home position return speed	500	r/min	0 to
		Used to set the servo motor speed for home position return.			permissible
		(Refer to section 5.6.)			speed
PC05	CRF	Creep speed	10	r/min	0 to
		Used to set the creep speed after proximity dog detection.			permissible
		(Refer to section 5.6.)			speed
PC06	ZST	Home position shift distance	0	μm	0
		Used to set the shift distance starting at the Z-phase pulse detection position			to
PC07	*ZPS	inside the encoder. (Refer to section 5.6.)	0	×10 ^{s™} μm	65535
PC07	225	Home position return position data Used to set the current position on completion of home position return.	0	× 10°···µm	-32768 to
		(Refer to section 5.6.)			32767
PC08	DCT	Moving distance after proximity dog	1000	×10 ^{s™} μm	0
. 000	201	Used to set the moving distance after proximity dog in count type home	1000		to
		position return. (Refer to section 5.6.)			65535
PC09	ZTM	Stopper type home position return stopper time	100	ms	5
		In stopper type home position return, used to set the time from when the			to
		machine part is pressed against the stopper and the torque limit set in			1000
		parameter No.PC10 is reached to when the home position is set.			
		(Refer to section 5.6.5.)			



	Symbol	Name and function	Initial value	Unit	Setting range
PC10	ZTT	Stopper type home position return torque limit value	15.0	%	1
		Used to set the torque limit value relative to the max. torque in [%] in stopper			to
		type home position return. (Refer to section 5.6.5.)			100.0
PC11	CRP	Rough match output range	0	×10 ^{s™} μm	0
		Used to set the command remaining distance range where the rough match			to
		(RXn2) is output.			65535
PC12	JOG	Jog speed	100	r/min	0
		Used to set the jog speed command.			to permissible
					speed
PC13	*STC	S-pattern acceleration/deceleration time constant	0	ms	0
		Set when inserting S-pattern time constant into the acceleration/deceleration	_		to
		time constant of the point table. (Refer to section 6.3.3.)			1000
		This time constant is invalid for home position return.			
PC14	*BKC	Backlash compensation	0	pulse	0
	Ditto	Used to set the backlash compensation made when the command	Ũ	puloo	to
		direction is reversed.			32000
		This function compensates for the number of backlash pulses in the			02000
		opposite direction to the home position return direction.			
		For the home position ignorance (servo-on position as home position), this			
		function compensates for the number of backlash pulses in the opposite			
		direction to the first rotating direction after establishing the home position			
		by switching ON the servo-on (RYn0).			
		In the absolute position detection system, this function compensates for			
		the backlash pulse count in the direction opposite to the operating direction			
		at power-on.			
PC15			0000h		
FUIS		For manufacturer setting Do not change this value by any means.	000011		
D040			400		
PC16	MBR	Electromagnetic brake sequence output	100	ms	0
		Used to set the delay time (Tb) between when the electromagnetic brake			to
		interlock (MBR) switches off and when the base circuit is shut off.			1000
PC17	ZSP	Zero speed	50	r/min	0
		Used to set the output range of the zero speed (ZSP).			to
		Zero speed signal detection has hysteresis width of 20r/min.			10000
PC18	*BPS	Alarm history clear	0000h	\backslash	Refer to
		Used to clear the alarm history.		\setminus	name and
		0 0 0			function
					column.
		Alarm history clear		\setminus	
		0: Invalid		\setminus	
		1: Valid			
		When alarm history clear is made valid,			
		the alarm history is cleared at next power-on. After the alarm history is cleared, the setting			
		is automatically made invalid (reset to 0).			
i			1	۱ ۱ ۱	



No.	Symbol	Name and function	Initial value	Unit	Setting range
PC19	*ENRS	Encoder output pulse selection Use to select the, encoder output pulse direction and encoder output pulse setting.	0000h		Refer to name and function column.
PC20	*SNO	Station number setting Used to specify the station number for RS-422 serial communication and USB communication. Always set one station to one axis of driver. If one station number is set to two or more stations, normal communication cannot be made.	0	station	0 to 31
PC21	*SOP	RS-422 communication function selection Select the communication I/F and select the RS-422 communication conditions.	0000h		Refer to name and function column.
PC22	*COP1	Function selection C-1 Select the encoder cable communication system selection. Image: Communication system selection on the system selection of the system selection of the system selection of the system selection of the system selection on the system selection of the system selection of the system selection of the system selection on the system selection of the system selectin the system selection of the system selection of the sy	0000h		Refer to the name and function field.



No.	Symbol			Na	me and function		Initial value	Unit	Setting range
PC23		For manufa	acturer se	tting			0000h		
		Do not cha	ange this v	alue by an	y means.				
PC24	*COP3	Function s Select the	e unit of the	e in-positio In-position	n range. range unit selection id input unit		0000h		Refer to name and function column.
					otor encoder unit				
PC25		For manut		etting value by ar	iv means.		0000h		
PC26	*COP5	Function s	selection (stroke lin	C-5 hit warning Stroke limit 0: Valid 1: Invalid When this occur if the	-	"1", A99 will not ke end (LSP) or	0000h		Refer to name and function column.
PC27		For manufa		U			0000h		
PC28	*COP7	Do not cha Function so Select the	election C display m	-7 ethod of the Electronic (0: Invalid 1: Valid By setting i by the elec automatic o	e current position and gear fraction clear se t to "1", the fraction of tronic gear is cleared	lection of the last command when starting	0000h		Refer to name and function column.
		d 1 R	Display method Positioning lisplay Roll feed	Operation mode Automatic Manual Automatic	Current position The actual current position where the machine home position is assumed as 0 is displayed. The actual current	Command position The command current position where the machine home position is assumed as 0 is displayed. The count starts from			
		d	lisplay	Manual	position where the automatic operation start position is assumed as 0 is displayed.	0 when the start signal is turned on, and the command current position to the target position is displayed. During a stop, the command position of the selected point table is displayed. The command position of the selected point table is displayed.			



No.	Symbol			Name and function	n	Initial value	Unit	Setting range
PC29		For manuf	acturer setting			0000h		$\overline{}$
		Do not cha	ange this value by	any means				
PC30	*DSS	Remote re	gister-based positi	on/speed specifyin	g system selection	0000h	Ν	Refer to
		-			eed specification selection		\backslash	name and
		(RY(n+2)A) is turned ON with 2 stations occupied. Select how to receive the						function
		-	mmand and speed					column.
				selection of "0001"	or "0002" will result in a			
		parameter	enor.					
		Parameter						
		Falameter						
			<u> </u>					
		Set	Position	Speed	Acceleration time			
		valure	command	command	constant / Deceleration			
					time constant			
		0	Specify the point	table No.				
		1	Set the	Specify the point	table No.			
		2	position data.	Set the servo	Use the value set in			
				motor speed	point table No.1.			
PC31	LMPL	Software li	mit +			0		- 999999
PC32				ement side software	e stroke limit. The software	0	×10 μ	to
1 002					in "software limit $-$ ".			999999
		(Refer to se	ection 6.3.6.)					
		Set the sar	me sign to parame	ters No.PC31 and	No.PC32. Setting of different			
		signs will re	esult in a paramete	er error.				
			Set address:□					
				er 3 Lower 3				
			digit	ts digits				
					meter No.PC31			
				Parar	meter No.PC32			
		The softwa	are limit+ is a set o	of upper digits and	lower digits. To change the			
		value, set	in the order of low	er digits to upper o	digits.			
PC33	LMNL	Software li				0	×10 ^{s™} μm	-999999
PC34	LMNH				are stroke limit. The software			to
				alue is the same as	s in "software limit +".			999999
		•	ection 6.3.6.)	aters No PC33 and	d PC34. Setting of different			
			esult in a paramet					
			Set address:					
			· · · · · · · · · · · · · · · · · · ·	ber 3 Lower 3				
			digi					
					meter No.PC33			
				Para	meter No.PC34			
		The coffur	are limit— is a act	of upper digite and	l lower digits. To change the			
				or upper digits and er digits to upper of				
	l	value, sel			aigno.	1		

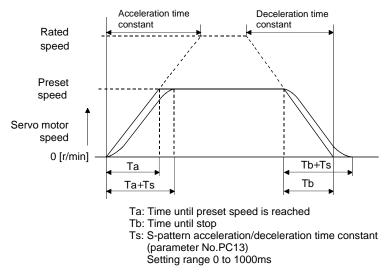


No.	Symbol	Name and function	Initial value	Unit	Setting range
PC35	TL2	Internal torque limit 2	100.0	%	0
		Set this parameter to limit servo motor torque on the assumption that the			to
		maximum torque is 100[%].			100.0
		When 0 is set, torque is not produced.			
PC36		For manufacturer setting	0000h		
		Do not change this value by any means.			
PC37	*LPPL	Position range output address +	0	×10 ^{s™} μm	-999999
PC38	*LPPH	Used to set the address increment side position range output address. Set			to
		the same sign to parameters No.PC37 and PC38. Setting of different signs			999999
		will result in a parameter error.			
		In parameters No.PC37 to PC40, set the range where position range (RXnE)			
		turns on.			
		Set address:			
		Upper 3 Lower 3			
		digits digits			
		Parameter No.PC37			
		Parameter No.PC38			
		Position range output address + is a set of upper digits and lower digits. To			
		change the value, set in the order of lower digits to upper digits.			
PC39	*LNPL	Position range output address —	0	imes10 ^{stm} µm	-999999
PC40	*LNPH	Used to set the address decrement side position range output address. Set			to
		the same sign to parameters No.PC39 and PC40. Setting of different signs			999999
		will result in a parameter error.			
		Set address:			
		Upper 3 Lower 3			
		digits digits			
		Parameter No.PC39			
		Parameter No.PC40			
		Position range output address $-$ is a set of upper digits and lower digits.			
		To change the value, set in the order of lower digits to upper digits.			
PC41	Ν	For manufacturer setting	0000h	\backslash	Ν
PC42	\	Do not change this value by any means.	0000h	\backslash	\backslash
PC43		5 , ,	0000h	\backslash	\backslash
PC44			0000h		
PC45			0000h		\setminus
PC46			0000h		
PC47			0000h		
PC48			0000h		
PC49	\		0000h		
PC50	\		0000h		



6.3.3 S-pattern acceleration/deceleration

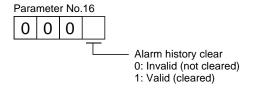
In servo operation, linear acceleration/deceleration is usually made. By setting the S-pattern acceleration/ deceleration time constant (parameter No.PC13), a smooth start/stop can be made. When the S-pattern time constant is set, smooth positioning is executed as shown below. Note that the time equivalent to the S-pattern time constant setting increases until positioning (RXnC) is complete.



6.3.4 Alarm history clear

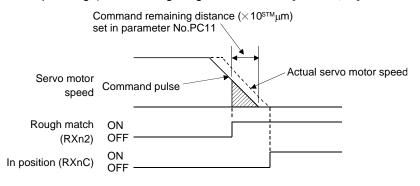
The alarm history can be confirmed by using the set up software(MR Configurator2TM). The driver stores one current alarm and five past alarms from when its power is switched on first. To control alarms which will occur during operation, clear the alarm history using parameter No.PC18 (alarm history clear) before starting operation. Clearing the alarm history automatically returns to " \Box \Box \Box \Box 0".

This parameter is made valid by switching power off, then on after setting.



6.3.5 Rough match output

Rough match (RXn2) is output when the command remaining distance reaches the value set in parameter No.PC11 (rough match output range). The setting range is 0 to 65535 [$\times 10^{STM}\mu m$].





6.3.6 Software limit

A limit stop using a software limit (parameter No.PC31 to PC34) is made as in stroke end operation. When a motion goes beyond the setting range, the motor is stopped and servo-locked. This function is made valid at power-on but made invalid during home position return. This function is made invalid when the software limit + setting is the same as the software limit – setting. A parameter error (A37) will occur if the software limit + setting is less than the software limit – setting.

Inhibited are Movable area Movable Unmovable Current position Software limit



6.4 I/O setting parameters (No.PD □ □) 6.4.1 Parameter list

No.	Symbol	Name	Initial value	Unit
PD01	*DIA1	Input signal automatic ON selection 1	0000h	
PD02		For manufacturer setting	0000h	
PD03	*DIA3	Input signal automatic ON selection 3	0000h	
PD04	*DIA4	Input signal automatic ON selection 4	0000h	
PD05		For manufacturer setting	0000h	
PD06	*DI2	Input signal device selection 2 (CN6-2)	002Bh	
PD07	*DI3	Input signal device selection 3 (CN6-3)	000Ah	
PD08	*DI4	Input signal device selection 4 (CN6-4)	000Bh	
PD09	*DO1	Output signal device selection 1 (CN6-14)	0002h	
PD10	*DO2	Output signal device selection 2 (CN6-15)	0003h	
PD11	*DO3	Output signal device selection 3 (CN6-16)	0024h	
PD12	DIN1	External DI function selection 1	0C00h	
PD13		For manufacturer setting	0000h	
PD14	DIN3	External DI function selection 3	0800h	
PD15		For manufacturer setting	0000h	
PD16	*DIAB	Input polarity selection	0000h	
PD17		For manufacturer setting	0000h	
PD18			0000h	
PD19	*DIF	Response level setting	0002h	
PD20	*DOP1	Function selection D-1	0010h	
PD21		For manufacturer setting	0000h	
PD22	*DOP3	Function selection D-3	0000h	
PD23		For manufacturer setting	0000h	
PD24	*DOP5	Function selection D-5	0000h	
PD25	\setminus	For manufacturer setting	0000h	\backslash
PD26	\setminus		0000h	\backslash
PD27	\setminus		0000h	\backslash
PD28	\setminus		0000h	\backslash
PD29	\setminus		0000h	\backslash
PD30	\setminus		0000h	·



6.4.2 Detail list

No.	Symbol	Name and function	Initial value	Unit	Setting range
PD01	*DIA1	Input signal automatic ON selection 1 Select the input devices to be automatically turned ON. part is for manufacturer setting. Do not set the value by any means.	0000h		Refer to name and function column.
		Device name Initial value BIN HEX			
		0 0 Servo-on (SON) 0 0 0			
		Device name Initial value BIN HEX			
		Proportion control (PC) 0 0 0 0			
		Device name Initial value BIN HEX			
		Forward rotation 0 stroke end (LSP) 0			
		Reverse rotation stroke end (LSN)0			
		Device name Initial value BIN HEX			
		Forced stop (EMG) 0 0 0 0 0			
		BIN 0: Used in CC-Link or as external input signal. BIN 1: Automatic ON			
PD02		For example, to turn ON SON, the setting is " □ □ □ 4". For manufacturer setting	0000h		
		Do not change this value by any means.			



No.	Symbol	Name and function	Initial value	Unit	Setting range
PD03	*DIA3	Input signal automatic ON selection 3 Select the input devices to be automatically turned ON. part is for manufacturer setting. Do not set the value by any means. Device name Initial value BIN HEX Automatic/manual 0 selection (MD0) 0 0 0 0 0 0 0 0 0 0 0 0 0 0	0000h		Refer to name and function column.
PD04	*DIA4	Input signal automatic ON selection 4 Select the input devices to be automatically turned ON.	0000h		Refer to name and function column.
PD05		For manufacturer setting Do not change this value by any means.	0000h		



No.	Symbol		Name and function			Initial value	Unit	Setting range
PD06	*DI2	Any input of	nal device selection 2 (CN6-2) device can be assigned to the CN6-2 pin.			002Bh		Refer to name and function column.
		Setting	Input device					
		(Note)	Name	Abbreviation				
		00	No assignment function					
		02	Servo-on	SON	1			
		03	Reset	RES	1			
		04	Proportion control	PC	1			
		06	Clear	CR				
		07	Forward rotation start	ST1				
		08	Reverse rotation start	ST2	1			
		09	Internal torque limit selection	TL1				
		0A	Forward rotation stroke end	LSP	1			
		0B	Reverse rotation stroke end	LSN				
		0D	Gain changing	CDP				
		20	Automatic/manual selection	MD0				
		24	Manual pulse generator multiplication 1	TP0				
		25	Manual pulse generator multiplication 2	TP1				
		27	Temporary stop/restart	TSTP				
		2B	Proximity dog	DOG				
PD07	*DI3	setti	other setting values than shown in this table ng. nal device selection 3 (CN6-3)	e are for manufact	urer	000Ah		Refer to
1 207	20	Any input	device can be assigned to the CN6-3 pin. es that can be assigned and the setting		same as in	UUUAII		name and function column.
PD08	*DI4	Any input	nal device selection 4 (CN6-4) device can be assigned to the CN6-4 pin. es that can be assigned and the setting No.PD06.		same as in	000Bh		Refer to name and function column.



No.	Symbol		Name and funct	ion		Initial value	Unit	Setting range
PD09	*DO1		Output signal device selection 1 (CN6-14) Any output signal can be assigned to the CN6-14 pin.			0002h		Refer to name and function
		0 0						column.
		LI						
			Select the output device of th	ie CN6-14 pin				
		The device	es that can be assigned are indicated	in the following table				
		Setting	Output device					
		(Note)	Name	Symbol				
		00	Always OFF					
		02	Ready	RD				
		03	Trouble	ALM				
		04	In position	INP				
		05	Electromagnetic brake interlock	MBR				
		06	Dynamic brake interlock	DB				
		07	Limiting torque	TLC				
		08	Warning	WNG				
		09	Battery warning	BWNG				
		0A	Speed command reached	SA				
		0C	Zero speed	ZSP				
		0F	Variable gain selection	CDPS				
		23	Rough match	CPO				
		24	Home position return completion	ZP				
		25	Position range	POT				
		26	Temporary stop	PUS				
		27	Movement completion	MEND				
		38	Point table No. output 1	PT0 PT1				
		39 3A	Point table No. output 2 Point table No. output 3	PT1 PT2				
		3A 3B	Point table No. output 3	PT3				
		3D 3C	Point table No. output 4	PT4				
		3D	Point table No. output 6	PT5				
		3E	Point table No. output 7	PT6				
		3F	Point table No. output 8	PT7				
		Note. The setti	other setting values than shown in this	s table are for manufacturer	r			
PD10	*DO2		nal device selection 2 (CN6-15)			0003h		Refer to
			t signal can be assigned to the CN6-1					name and
			es that can be assigned and the se	etting method are the sam	ie as in			function
		parameter	No.PD09.					column.
		0 0						
			Select the output device of the	e CN6-15 pin				



No.	Symbol	Name and function	Initial value	Unit	Setting range
PD11	*DO3	Output signal device selection 3 (CN6-16) Any output signal can be assigned to the CN6-16 pin. The devices that can be assigned and the setting method are the same as in parameter No.PD09. 0 0 Select the output device of the CN6-16 pin	0024h		Refer to name and function column.
PD12	DIN1	External DI function selection 1 This function sets any signal imported from the CN6 connector. part is for manufacturer setting. Do not set the value by any means.	0C00h		Refer to name and function column.
PD13		For manufacturer setting Do not change this value by any means.	0000h		

No.	Symbol	Name and function	Initial value	Unit	Setting range
PD14	DIN3	External DI function selection 3 This function sets any signal imported from the CN6 connector.	0800h		Refer to name and function column.
PD15		For manufacturer setting Do not change this value by any means.	0000h		
PD16	*DIAB	Input polarity selection Used to set the proximity dog input polarity. (Refer to section 5.6.) O O O Proximity dog input polarity 0: OFF indicates detection of the dog 1: ON indicates detection of the dog	0000h		Refer to name and function column.
PD17 PD18		For manufacturer setting Do not change this value by any means.	0000h 0000h		



No. Symbo	Name and function	Initial value	Unit	Setting range
PD19 *DIF	Response level setting Used to select the input. Input filter If external input signal causes chattering due to noise, etc., input filter is used to suppress it. 0: None 1: 0.88[ms] 2: 1.77[ms] 3: 2.66[ms] 4: 3.55[ms] 5: 4.44[ms]	0002h		Refer to name and function column.
PD20 *DOP1	Function selection D-1 Select the stop processing at forward rotation stroke end (LSN)/reverse rotation stroke end (LSN) OFF and the base circuit status at reset (RY(N+1)A or RY(n+3)A) ON. 0	0010h		Refer to name and function column.



No.	Symbol	Name and function	Initial value	Unit	Setting range
PD21		For manufacturer setting	0000h		
		Do not change this value by any means.			
PD22	*DOP3	Function selection D-3 Set the clear (RYnF).	0000h	\backslash	Refer to name and
					function
		0 0 0			column.
		Clear (RYnF) selection			
		0: Droop pulses are cleared on the leading			
		edge. 1: While on, droop pulses are always cleared.			
				$ \rangle$	
PD23		For manufacturer setting	0000h		
DD04	*0005	Do not change this value by any means.	00001		
PD24	*DOP5	Function selection D-5 Select the output status of the warning (WNG).	0000h		
		Selection of output device at warning occurrence			
		Select the warning (RXnA) and trouble (RX(n+1)A or RX(n+3)A) output status at warning occurrence.			
		Setting (Note) Device status			
		Remote RXnA 1			
		output RX(n+1)A or 1			
		OFF Marning occurred.			
		Remote RX(n+1)A or 1			
		Output RX(n+3)A 0 RX(n+3)A 0			
		1 Output WNG OFF			
		device ALM OFF			
		C Warning occurred.			
		Note. 0: OFF			
		1: ON			
PD25		For manufacturer setting	0000h		
PD26	\setminus	Do not change this value by any means.	0000h	\setminus	\backslash
PD27	\setminus		0000h		\backslash
PD28			0000h		\backslash
PD29			0000h		\backslash
PD30			0000h		



6.4.3 Stopping method when the forward stroke end (LSP) or reverse stroke end (LSN) is valid The setting of the first digit of parameter No.PD20 enables to select a stopping method of the servo motor when the forward rotation stroke end (LSP) or reverse rotation stroke end (LSN) turns off.



Stopping method used when forward rotation stroke end (LSP) or reverse rotation stroke end (LSN) is valid

0: Sudden stop (home position erased) 1: Slow stop (home position erased) 2: Slow stop (Deceleration to a stop by deceleration time constant) 3: Sudden stop (Stop by remaining move distance clear)

Setting value of	Operation sta	atus	Demeric
parameter No.PD20	When rotating at constant speed	When decelerating to stop	Remarks
□□□0 (Initial value)	Servo motor Servo motor Se	O motor O Motor O M OFF	Clears droop pulses and stops. Erases the home position. A difference occurs between the command position and the current position. Execute a home position return again.
0001	Servo motor speed 0r/min 0 LSP 0N 0FF 0 Without S-pattern acceleration/deceleratior Amount of droop pulse Amount of droop pulse LSP 0N LSP or LSN 0FF	O motor O Motor O M OFF	Moves for the amount of droop pulse and stops. Erases the home position. A difference occurs between the command position and the current position. Execute a home position return again.
	Servo motor speed 0r/min OFF 0N Correction OFF 0N Correction Corre	O motor d O Motor O N OFF O Without S-pattern acceleration/deceleration 	Decelerates to stop at the deceleration time constant. Continues to rotate for the amount of S-pattern acceleration/decelerati on time constant delay. Keeps the home position.
	Without S-pattern acceleration/deceleration — With S-pattern acceleration/deceleration S-pattern acceleration/deceleration S-pattern acceleration/ deceleration time constant amount of droop pulse Amount of droop pulse LSP or LSN OFF LSN	Mithout S-pattern acceleration/deceleration With S-pattern acceleration/deceleration S-pattern acceleration/ deceleration/ d	Moves for the amount of droop pulse and stops. Continues to rotate for the amount of S-pattern acceleration/decelerati on time constant delay. Keeps the home position.



6.4.4 Stopping method when a software limit is detected

A stopping method of the servo motor when a software limit (parameter No.PC31 to PC34) is detected can be selected. The software limit imposes a limit on the command position, which is controlled in the driver. Therefore, actual stop position does not reach to the software limit set position.



Stopping method used when software limit is detected 0: Sudden stop (home position erased) 1: Slow stop (home position erased) 2: Slow stop (Deceleration to a stop by deceleration time constant) 3: Sudden stop (Stop by remaining move distance clear)

Setting value of	Operatio	on status	
parameter No.PD20	When rotating at constant speed	When decelerating to stop	Remarks
□0□□ (Initial value)	Without S-pattern acceleration/deceleratior With S-pattern acceleration/deceleratior with S-pattern acceleration/deceleratior // Servo motor speed Or/min I Software limit detected	Servo motor speed 0r/m in Software limit detected	Clears droop pulses and stops. Erases the home position. A difference occurs between the command position and the current position. Execute a home position return again.
	Servo motor speed 0r/min Software limit detected	Servo motor speed 0r/min 0r/min Software limit detected	Moves for the amount of droop pulse and stops. Erases the home position. A difference occurs between the command position and the current position. Execute a home position return again.
	Servo motor speed 0r/m in 0r/m in 00 0r/m in 00 00 00 00 00 00 00 00 00 00 00 00 00	Servo motor speed 0r/min 0r/min Continues Continues Software limit detected	Decelerates to stop at the deceleration time constant. Continues to rotate for the amount of S-pattern acceleration/decelerati on time constant delay. Keeps the home position.
	Without S-pattern acceleration/deceleration With S-pattern acceleration/deceleration spattern acceleration/ deceleration/ deceleration time constant acceleration time constant acc	Without S-pattern acceleration/deceleration With S-pattern acceleration/deceleration S-pattern acceleration/ deceleration/ deceleration time constant droop pulse Servo motor speed 0r/min Software limit detected	Moves for the amount of droop pulse and stops. Continues to rotate for the amount of S-pattern acceleration/decelerati on time constant delay. Keeps the home position.

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7. Setup software(MR Configurator2[™])

The setup software (MR Configurator2[™] : LEC-MRC2E) uses the communication function of the driver to perform parameter setting changes, graph display, test operation, etc. on a personal computer. When setup software (MR Configurator2[™]) is used, the selection of the model of LECSC2-T□ is needed. Please select 'MR-J3-T' by "Model" - "New" - "Project".

7.1 Specifications

Item Description		
Compatibility with a	The set up software(MR Configurator2 TM) software version compatible with the driver is Ver.1.52E or	
driver	later.	
Monitor	Display, Input/Output I/F display, high speed monitor, graph display	
WONITO	(Minimum resolution changes with the processing speed of the personal computer.)	
Alarm	Display, history, driver data	
Diagnostic	No motor rotation, system information display, tuning data, Axis name setting.	
Parameters	Parameter list, turning, change list, detailed information	
Test operation	Jog operation, positioning operation, motor-less operation, Do forced output, program operation.	
File operation	Data read, save, delete, print	
Others	Help display	



7.2 System configuration

(1) Components

To use this software, the following components are required in addition to the driver and servo motor.

Equipmont		Set up software(MR Configurator2 TM)		
Equipment		LEC-MRC2E		
Personal computer (Note 1, 2, 3, 4 5, 6, 7, 8, 9)	OS	Microsoft ® Windows © 10 Edition, Microsoft ® Windows © 10 Enterprise, Microsoft ® Windows © 10 Pro, Microsoft ® Windows © 10 Home, Microsoft ® Windows © 8.1 Enterprise Microsoft ® Windows © 8.1 Pro Microsoft ® Windows © 8.1 Microsoft ® Windows © 8 Enterprise, Microsoft ® Windows © 8 Pro, Microsoft ® Windows © 8 Pro, Microsoft ® Windows © 7 Ultimate Microsoft ® Windows © 7 Enterprise Microsoft ® Windows © 7 Enterprise Microsoft ® Windows © 7 Forfessional Microsoft ® Windows © 7 Enterprise Microsoft © Windows © 7 Starter Microsoft © Windows Vista ® Ultimate Microsoft © Windows Vista ® Enterprise Microsoft © Windows Vista ® Enterprise Microsoft © Windows Vista © Enterprise Microsoft © Windows Vista © Enterprise Microsoft © Windows Vista © Home Premium Microsoft © Windows Vista © Home Edition, Service Pack2 or later Microsoft © Windows © XP Home Edition, Service Pack2 or later IBM PC/AT compatible PC		
	Hard Disk	1GB or more of free space		
Display		One whose resolution is 1024×768 or more and that can provide a high color (16 bit) display. Connectable with the above personal computer.		
Keyboard		Connectable with the above personal computer.		
Mouse		Connectable with the above personal computer.		
Printer		Connectable with the above personal computer.		
USB cab (Note 10	-	LEC-MR-J3USB		

Note 1. Using a PC for setting Windows [®] 10, upgrade to version 1.52E.

Using a PC for setting Windows [®] 8.1, upgrade to version 1.25B.

Using a PC for setting Windows [®] 8, upgrade to version 1.20W.

Refer to Mitsubishi Electric Corporation's website for version upgrade information.

2. Windows [®] and Windows Vista [®] is the registered trademarks of Microsoft Corporation in the United States and other countries.

3. On some personal computers, set up software (MR Configurator2[™]) may not run properly.

4. The following functions cannot be used. If any of the following functions is used, this product may not operate normally.

- \cdot Start of application in Windows® compatible mode.
- Fast User Switching.
- Remote Desktop.
- · Windows XP Mode.
- · Windows Touch or Touch.
- · Modern UI
- Client Hyper-V
- · Tablet Mode
- Virtual desktop
- \cdot Does not support 64-bit Operating System, except for Microsoft $^{\otimes}\,$ Windows $^{\otimes}\,$ 7 or later.

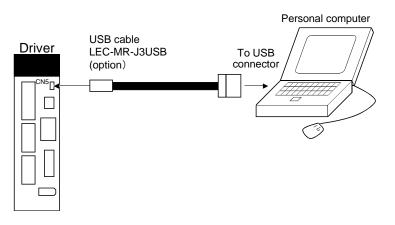


- 5. Multi-display is set, the screen of this product may not operate normally.
- 6. The size of the text or other items on the screen is not changed to the specified value (96DPI, 100%, 9pt, etc.), the screen of this product may not operate normally.
- 7. Changed the resolution of the screen during operating, the screen of this product may not operate normally.
- 8. Please use by "Standard User", "Administrator" in Windows Vista® or later.
- 9. If .NET Framework 3.5 (including .NET 2.0 and 3.0) have been disabled in Windows[®]7 or later, it is necessary to enable it. 10.Order USB cable separately.

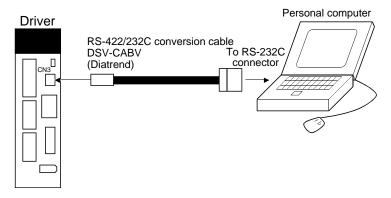
This cable is shared with Set up software (MR Configurator[™] : LEC-MR-SETUP221E).

(2) Connection with driver

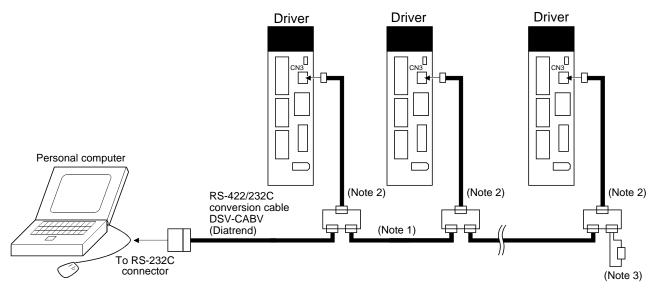
(a) For use of USB



(b) For use of RS-422







(c) For use of RS-422 to make multidrop connection

Note 1. Refer to section 141 for cable wiring.

2. The BMJ-8 (Hakko Electric Machine Works) is recommended as the branch connector.

3. The final axis must be terminated between RDP (pin No. 3) and RDN (pin No.6) on the receiving side (driver) with a 150Ω resistor.



7.3 Station selection

Click "Project" on the menu bar and click "New" on the menu.

Proj	ect	View	Parameter	Safety		
	Nev	v		Ctrl+N		
B	Open			Ctrl+O		
	Clos	se				

When the above choices are made, the following window appears.

	New Project				
а	Model	MR-J3-T	~		
	Operation mode		~		
	Multi-ax. unification		~		
b	Station	00	~		
	Option unit	No Connection	~		
	Servo amplifier connection USB Servo amplifier connection RS-422 (RS-232C) Com. speed AUTO				
	Port No.	AUTO			
		t will be opened whenever			
			incel		

- (1) Model selection (a) Choose the "MR-J3-T".
- (2) Station number selection (b) Choose the station number.

POINT

• This setting should be the same as the station number which has been set in the parameter (PC20) in the driver used for communication.

Please select the station "00", if you want to use for the first time.

(3) Closing of the window

Click the "OK" button to close the window.



7.4 Parameters

Click "Parameters" on the menu bar and click "Parameter Setting" on the menu.



When the above choices are made, the following window appears.

Parameter Settir		g			
	ad 🕑 Set To Default 🙀 Verify 📋 Parameter Copy 📄 Pa	rameter Bk	lock		
Dpen Save As			ad		
Function display Common	Common - Basic		Selected Items Write Single Axis Write		
- Basic - Extension	Control mode(*STY)	Encoder output pulse(*ENRS)			
Extension 2	Command method selection	Encoder output pulse phase			
- Component parts	Absolute value command system	~	Advance A-phase 90° by CCW Phase Setting		
- Position control	Operation method	Number of encoder output pulse			
Point table Basic	Point table positioning operation	M	4000 pulse Encoder Output Pulse		
- Extension	Rotation direction(*POL)	Torque limit(TLP, TLN, TL2)			
- Indexer - Home position return	Rotation/station No. direction selection		Forward torgue limit 100.0 % (0.0-100.0)		
 Servo adjustments 	CCW dir. at addr. increase, CW dir. at addr. decrease	×	Reverse torque limit 100.0 % (0.0-100.0)		
- Basic					
- Extension	Forced stop(*AOP1)		Internal torque limit 2 100.0 % (0.0-100.0)		
- Gain changing Digital I/O	Follow-up for servo off/emergency stop	Zero speed(ZSP)			
E Ist display	Disabled		Zero speed 50 r/min (0-10000)		
Basic			Zero speed		
- Gain/filter					
- Extension					
-1/0					
<					

(1) Parameter value write (a)

f

Click the parameter whose setting was changed and press the "Selected Items write" button to write the new parameter setting to the driver.

(2) Parameter value verify (b)

Click the "Verify" button to verify all parameter values being displayed and the parameter values of the driver.

(3) Parameter value batch-read (c)

Click the "Read" button to read and display all parameter values from the driver.

- (4) Parameter value batch-write (d)Click the "Single Axis Write" button to write all parameter values to the driver.
- (5) Parameter default value indication (e)Click the "Set to default" button to show the initial value of each parameter.



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- (7) Parameter list display (f) Show the each parameter value in the form of a list.
- (8) Parameter block (g)Used to set the availability of parameter write.
- (9) Parameter data file read (h)Used to read and display the parameter values stored in the file.
- (10) Parameter value storage (i)Used to store all parameter values being displayed on the window into the specified file.

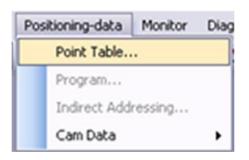


7.5 Point table

POINT

• The value of the parameter No. PA05 set on the parameter setting screen is not engaged with the STM (feed length multiplication) value on the point table list screen. Set the STM (feed length multiplication) value to the same as set in the parameter No. PA05 on the point table list screen.

Click "Point-data" on the menu bar and click "Point table" on the menu.



When the above choices are made, the following window appears.

Po	nt Table	n i	С	b				
A	ds1 💉 🔁 이	pen 💾 Save As 🤞	📲 Read 🚺 Set to d	lefault 🙀 Verify 🖹 D	etailed Setting 🔀	Single-step Feed		
000	py 📑 Paste 📥 Ins	ert 👄 Delete 👩	Restore MRedo			a	ł	
oint I	able positioning	ation (At the value	command system)		Selected	Items Write Write	e All Update P	roject
	Target position	Rotation speed	Accel. time const.	Decel. time const.	Dwell time	Auxiliary func.	M code	
	-999.999-999.999	0-65535	0-20000	0-20000	0-20000	0-3	0-99	
No.	mm	r/min	ms	ms	ms			
1	0.000	0	0	0	0	0	0	
2	0.000	0	0	0	0	0	0	
3	0.000	0	0	0	0	0	0	
- 4	0.000	0	0	0	0	0	0	
5	0.000	0	0	0	0	0	0	
6	0.000	0	0	0	0	0	0	g
7	0.000	0	0	0	0	0	0	
8	0.000	0	0	0	0	0	0	
9	0.000	0	0	0	0	0	0	
10	0.000	0	0	0	0	0	0	
11	0.000	0	0	0	0	0	0	
12	0.000	0	0	0	0	0	0	
13	0.000	0	0	0	0	0	0	
	0.000	0	0	0	0	0	0	

(1) Point table data write (a)

Click the point table data changed and press the "Selected Items write" button to write the new point table data to the driver.

- (2) Point table data verify (b)Click the "Verify" button to verify all data being displayed and the data of the driver.
- (3) Point table data batch-read (c)Click the "Read" button to read and display all point table data from the driver.
- (4) Point table data batch-write (d)Click the "Write All" button to write all point table data to the driver.



(5) Point table data insertion (e)

Click the "Insert" button to insert one block of data into the position before the point table No. chosen. The blocks after the chosen point table No. are shifted down one by one.

(6) Point table data deletion (f)

Click the "Delete" button to delete all data in the point table No. chosen. The blocks after the chosen point table No. are shifted up one by one.

- (7) Point table data change (g) Click the data to be changed, enter a new value into the "Enter" input field, and press the enter key or Enter Data button.
- (8) Point table data file read (h)Used to read and display the point table data stored in the file.
- (9) Point table data storage (i)Used to store all point table data being displayed on the window into the specified file.



7.6 Test operation

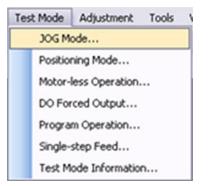
	· When confirming the machine operation in the test operation mode, use the
	machine after checking that the safety mechanism such as the forced stop (EMG)
	operates.
	 If any operational fault has occurred, stop operation using the forced stop (EMG).

7.6.1 Jog operation

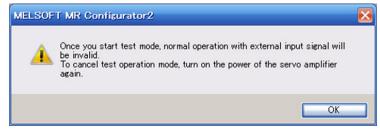
POINT

- For the program operation, refer to the manual of setup software(MR Configurator2[™]).
 - The servo motor will not operate if the forced stop (EMG), forward rotation stroke end (LSP) and reverse rotation stroke end (LSN) are off. Make automatic ON setting to turn on these devices or make device setting to assign them as external input signals and turn on across these signals and SG. (Refer to section 7.6.)
- When an alarm occurs, the JOG operation is automatically canceled.

Click "Test Mode" on the menu bar and choose "Jog Mode" on the menu.



Clicking displays the confirmation window for switching to the test operation mode.



Click the "OK" button to display the setting screen of the Jog operation.



JOG Mode	🔀				
Axis1					
Setting					
a Motor speed	200 📚 r/min				
	(1-6900)				
b Accel./decel. time constant	1000 📚 ms				
	(0-50000)				
LSP, LSN auto ON					
	e g				
Forward CCW Reverse CW Stop					
Rotation only while the CCW or CW button is being pushed					
The SHIFT key can be used for forced stop.					

(1) Servo motor speed setting (a)

Enter a new value into the "Motor speed" input field and press the enter key.

- (2) Acceleration/deceleration time constant setting (b) Enter a new value into the "Accel. / decal. time constant" input field and press the enter key.
- (3) Start button operation selection (c)

Check the check box for operating the servo motor only while pressing the button. Uncheck the check box for stopping the operation by pressing the "Stop" or "Forced stop" button.

(4) Servo motor start (d)

* When stopping the operation by pressing the "Stop" or "Forced stop" button Click the "Forward CCW" button to rotate the servo motor in the CCW rotation direction. Click the "Reverse CW" button to rotate the servo motor in the CW rotation direction.

- * When operating the servo motor only while pressing the button While pressing the "Forward CCW" button, the servo motor rotates in the CCW rotation direction. While pressing the "Reverse CW" button, the servo motor rotates in the CW rotation direction.
- (5) Servo motor stop (e, g)
 - * When stopping the operation by pressing the "Stop" or "Forced stop" button Click the "Stop" or "Forced stop" button to stop the rotation of the servo motor.
 - * When operating the servo motor only while pressing the button Release the "Forward CCW" or "Reverse CW" button to stop the rotation of the servo motor.
- (6) LSP/LSN (stroke end) automatic ON setting (f)) Put a check mark in the check box to automatically turn ON LSP/LSN. After selecting the check box, the LSP and the LSN of external signal are ignored.



(7) Servo motor Forced stop (g)

Click the "Forced stop" button to stop the servo motor rotation immediately. When the "Forced stop" button is enabled, the "Forward CCW" and "Reverse CW" buttons cannot be used. Click the "Cancel stop" button to make the "Forward CCW" and "Reverse CW" buttons enabled.

(8) Switching to CC-Link operation mode

To switch from the test operation mode to the CC-Link operation mode, turn OFF the power of the driver.

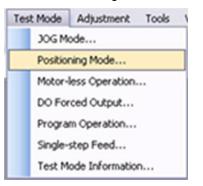


7.6.2 Positioning operation

POINT	
• The servo motor will not operate if the forced stop (EMG), forward rota	tion
stroke end (LSP) and reverse rotation stroke end (LSN) are off. M	ake
automatic ON setting to turn on these devices or make device setting	g to
assign them as external input signals and turn on across these signals	and
DOCOM. (Refer to section 7.6.)	

· When an alarm occurs, the positioning operation is automatically canceled.

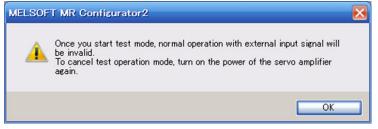
Click "Test Mode" on the menu bar and click "Positioning Mode" on the menu.



Click "Positioning Mode " on the menu bar and click "Move Distance Unit Selectiom" on the menu. Check Command pulse unit (Electronic gear valid) and click OK. Electronic gear ratio that is set in the PA05 / PA06 / PA07 is enabled.

Select the n	nove distance unit for positioning operation.
	and pulse unit (Electronic gear valid)
-	
O Encod	er pulse unit (Electronic gear invalid)

Clicking displays the confirmation window for switching to the test operation mode.



Click the "OK" button to display the setting screen of the Positioning operation.



		Make the rep	peated operation valid	
Motor speed	200 💽 r/min (1-6900)	Repeat pattern	Fwd. rot. (CCW)->Rev. rot. (CW)	2
Accel./decel. time constant	1000 💮 ms (0-50000)	Dwell time	2.0 (0.1-50.0)	s
Move distance (Cmd. pulse unit)	262144 🔄 pulse	Operation count		times
LSP, LSN auto ON Z-phase signal movement Move distance unit selection © Command pulse unit (Electr Encoder pulse unit (Electr	tronic gear valid)	Operating status: Operation count:	g function valid	times
Eorward CCW	Beverse CW	200	Forced Stgp	
Payse		f	g	

(1) Servo motor speed setting (a)

Enter a new value into the "Motor speed" input field and press the enter key.

- (2) Acceleration/deceleration time constant setting (b) Enter a new value into the "Accel. / decal. time constant" input field and press the enter key.
- (3) Moving distance setting (c)Enter a new value into the "Move distance" input field and press the enter key.
- (4) Servo motor start (d)

Click the "Forward CCW" button to rotate the servo motor in the forward rotation direction. Click the "Reverse CW" button to rotate the servo motor in the reverse rotation direction.

- (5) Temporary stop of servo motor (e) Click the "Pause" button to stop the servo motor temporarily.
 Click the "Forward CCW" button or "Reverse CW" button during the temporary stop to restart the rotations for the remaining move distance.
- (6) Servo motor stop (f, g))Click the "Stop" button or "Forced stop" button to stop the servo motor rotation.
- (7) Servo motor Forced stop (g)

Click the "Forced stop" button to stop the servo motor rotation immediately. When the "Forced stop" button is enabled, the "Forward CCW" and "Reverse CW" buttons cannot be used. Click the "Cancel stop" button to make the "Forward CCW" and "Reverse CW" buttons enabled.

(8) LSP/LSN (stroke end) automatic ON setting (h) Put a check mark in the check box to automatically turn ON LSP/LSN. After selecting the check box, the LSP and the LSN of external signal are ignored.



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(9) Automatic ON setting for the movement to the Z-phase signal (i)

To move to the first Z-phase signal of the move distance + move direction, put a check mark in the check box.

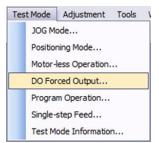
- (10) Pulse move distance unit selection (j) Select with the option buttons whether the moving distance set is in the command input pulse unit or in the encoder pulse unit.
- (11) Switching to CC-Link operation mode To switch from the test operation mode to the CC-Link operation mode, turn OFF the power of the driver.



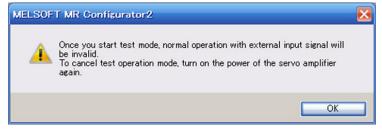
7.6.3 Output signal (DO) forced output

, 1	
POINT	
• When an a	larm occurs, the DO forced output is automatically canceled.

Each driver output signal is forcibly switched on/off independently of the output condition of the output signal. Click "Test Mode" on the menu bar and click "Forced output" on the menu.

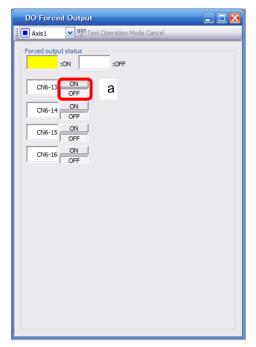


Clicking displays the confirmation window for switching to the test operation mode.



Click the "OK" button to display the setting screen of the DO forced output.

After confirming that the operation is in the stop status, click the "OK" button to display the setting screen for the DO forced output.





(1) Signal ON/OFF setting (a)

Choose the signal name or pin number and click the "ON" or "OFF" button to write the corresponding signal status to the driver.

(2) Switching to CC-Link operation mode

To switch from the test operation mode to the CC-Link operation mode, turn OFF the power of the driver.

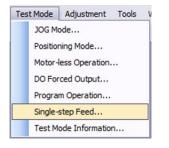


7.6.4 Single-step feed

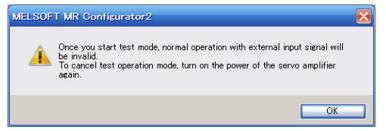
- POINT
 The servo motor will not operate if the forced stop (EMG), forward rotation stroke end (LSP) and reverse rotation stroke end (LSN) are off. Make automatic ON setting to turn on these devices or make device setting to assign them as external input signals and turn on across these signals and SG. (Refer to section 7.6.)
- When an alarm occurs, the 1-step feed is automatically canceled.

Operation is performed in accordance with the preset point table No.

Click "Test Mode" on the menu bar and click "Single-step Feed" on the menu.



Clicking displays the confirmation window for switching to the test operation mode.



Click the "OK" button to display the setting screen of the Single-step feed.

Single-step Fe	ed		_ 🗆 🔀
Axis1			
Point	table No.	1 🐑 (1-255)	а
b	С	d	е
> Operation Start	Pa <u>u</u> se	Stop	Forced Stop
Do not use Single-	n be used for forced st step feed during Index eration by BCD input.	op. er positioning operation	

(1) Point table No. setting (a)

Enter the point table No. into the "Point table No." input field and press the enter key.

(2) Servo motor start (b)

Click the "Operation Start" button to rotate the servo motor.



(3) Temporary stop of servo motor (c)

Press the "Pause" button to stop the servo motor temporarily.

Click the "Operation Start" button during the temporary stop to restart the rotations for the remaining move distance.

Click the "Stop" button or "Forced Stop" button during the temporary stop to clear the remaining move distance.

- (4) Servo motor stop (d, e)Click the "Stop" or "Forced stop" button to stop the rotation of the servo motor.
- (5) Servo motor software forced stop (e)

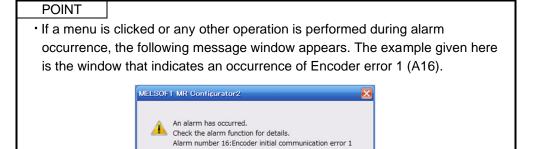
Click the "Software forced stop" button to stop the servo motor rotation immediately. When the "Software forced stop" button is enabled, the "Operation Start" button cannot be used. Click the "Cancel stop" button again to make the "Operation Start" button enabled.

(6) Switching to CC-Link operation mode To switch from the test operation mode to the CC-Link operation mode, turn OFF the power of the driver.



7.7 Alarm

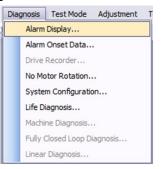
7.7.1 Alarm display



OK

The current alarm can be displayed.

To display the current alarm, click "Diagnosis" on the menu bar and click "Alarm Display" on the menu.



When the above choices are made, the following window appears.

-	Display				🛛
Axis1	~	а			
0.	Name		Est. occurrence time	Est. elapsed time (h)	Detailed information
AL.16	Encoder error	1 (At power on)	2016/06/01 11:06:20	0	44
incoder c	onnector (CN2) d	isconnected.			
ncoder f	ault.				
	able is faulty. akage or shorted.)			
	-	, 4-wire) selection was wrong in parameter setting			
			•		
	noise caused the o a method>	communication error.			
Check t	hat the encoder of	able and the power cables are wired side by side.			
		lifier is not influenced by noise of magnetic valves	, magnetic contactors or rel	ays.	
		ne servo amplifier and the servo motor. use of static electricity around.			
Check the second s	hat the shield of t	the second se			
	lac die snield of d	he encoder cable is made correctly.			
	information:(Alar	,			
		,			
Additional	information:(Alar	m reset disable)	net Data Direday	Causes Again	Occurred Alarm Reset
Additional	information:(Alar ory	m reset disable)	set Data Display		Occurred Alarm Reset
Additional Narm hist	information:(Alar ory Number	m reset disable)		Time (h)	Detailed information
Additional	information:(Alar ory Number AL.20	m reset disable)	ime)	Time (h) 33	Detailed information 47
Additional Alarm hist New 1	ory Number AL.20 AL.16	m reset disable) Alarm One Name Encoder error 2 (During runti Encoder error 1 (At power of	ime)	Time (h) 33 33	Detailed information 47 44
Additional Alarm hist New 1 2	ory Number AL.20 AL.16 AL.8D	m reset disable) Name Encoder error 2 (During runt Encoder error 1 (At power o CC-Link alarm	ime)	Time (h) 33 33 33	Detailed information 47 44 01
Additional Alarm hist New 1 2 3	Number AL.20 AL.16 AL.8D AL.8D	m reset disable) Name Encoder error 2 (During runti Encoder error 1 (At power o CC-Link alarm CC-Link alarm	ime)	Time (h) 33 33 33 33 33	Detailed information 47 44 01 01
Additional Alarm hist New 1 2 3 4	Number AL.20 AL.16 AL.8D AL.8D AL.8D	m reset disable) Name Encoder error 2 (During runti Encoder error 1 (At power o CC-Link alarm CC-Link alarm	ime) yn)	Time (h) 33 33 33 33 33 33 33	Detailed information 47 44 01 01 01 01
Additional Alarm hist New 1 2 3	Number AL.20 AL.16 AL.8D AL.8D	m reset disable) Name Encoder error 2 (During runti Encoder error 1 (At power o CC-Link alarm CC-Link alarm	ime) yn)	Time (h) 33 33 33 33 33	Detailed information 47 44 01 01



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(1) Current alarm display (a)

The window shows the alarm number, name, cause and occurrence time.

The following example is the window that indicates an occurrence of Encoder error 1 (A16).

(2) Alarm reset (b)

Click the "Occurred Alarm Reset" button to reset the current alarm and clear alarms on the window. The alarm at this time is stored as the latest alarm.

In the case of a reset not the alarm, "Occurred Alarm Reset" button is disabled.

(3) Alarm history display (c)

The most recent six alarms are displayed. The smaller numbers indicate newer alarms.

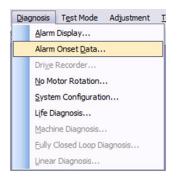
(4) Alarm history clear (d)

Click the "Clear" button to clear the alarm history stored in the driver.

7.7.2 Batch display of data at alarm occurrence

Monitor data during alarm occurrence is displayed.

To display monitor data, click " Diagnosis" on the menu bar and click "Alarm Onset Data" on the menu.



When the above choices are made, the following window appears.

Numb			Occurrence time (h)	
AL. 16	Encoder error 1 (At power on)		33	44
No.	Item	Units	Axis1	
1	Current position	mm	0.000	
2	Command position	mm	0.000	
3	Remaining command distance	mm	0.000	
4	Point table No.		0	
5	Cumulative feedback pulses	pulse	0	
6	Servo motor speed	r/min	0	
7	Droop pulse	pulse	0	
8	Override voltage	V	0.00	
9	Override	%	0	
10	Analog torque limit voltage	V	0.00	
11	Regenerative load ratio	%	0	
12	Effective load ratio	%	0	
13	Peak load ratio	%	0	
14	Instantaneous torque	%	0	
15	Within one-revolution position	pulse	0	
16	ABS counter	rev	0	
17	Load inertia moment ratio	times	0.0	
18	Bus voltage	V	0	
22	Station No.		0	

Click the "Read" button to read the monitor data at error occurrence from the driver. Read results are displayed as follows.



7.8 Precautions for using USB communication function

Note the following to prevent an electric shock and malfunction of the driver.

- (1) Power connection of personal computers Connect your personal computer with the following procedures.
 - (a) When you use a personal computer with AC power supply
 1) When using a personal computer with a three-core power plug or power plug with grounding wire, use a three-pin socket or ground the grounding wire.
 - 2) When your personal computer has two-core plug and has no grounding wire, connect the personal computer to the driver with the following procedures.
 - a) Disconnect the power plug of the personal computer from an AC power socket.
 - b) Check that the power plug was disconnected and connect the device to the driver.
 - c) Connect the power plug of the personal computer to the AC power socket.
 - (b) When you use a personal computer with battery You can use as it is.
- (2) Connection with other devices using driver communication function When the driver is charged with electricity due to connection with a personal computer and the charged driver is connected with other devices, the driver or the connected devices may malfunction. Connect the driver and other devices with the following procedures.
 - (a) Shut off the power of the device for connecting with the driver.
 - (b) Shut off the power of the driver which was connected with the personal computer and check the charge lamp is off.
 - (c) Connect the device with the driver.
 - (d) Turn on the power of the driver and the device.



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8. GENERAL GAIN ADJUSTMENT

8.1 Different adjustment methods

8.1.1 Adjustment on a single driver

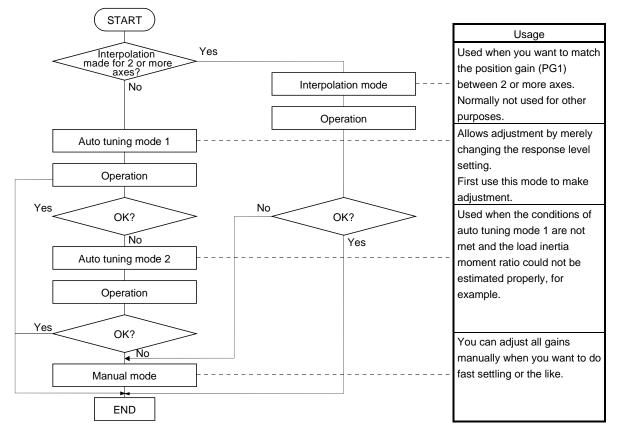
The gain adjustment in this section can be made on a single driver. For gain adjustment, first execute auto tuning mode 1. If you are not satisfied with the results, execute auto tuning mode 2 and manual mode in this order.

(1) Gain adjustment mode explanation

Gain adjustment mode	Parameter No. PA08 setting	Estimation of load inertia moment ratio	Automatically set parameters	Manually set parameters
Auto tuning mode 1 (initial value)	0001	Always estimated	GD2 (parameter No.PB06) PG2 (parameter No.PB08) PG1 (parameter No.PB07) VG2 (parameter No.PB09)	RSP (parameter No.PA09)
Auto tuning mode 2	0002	Fixed to parameter No.	VIC (parameter No.PB10) PG2 (parameter No.PB08)	GD2 (parameter No.PB06)
		PB06 value	PG1 (parameter No.PB07) VG2 (parameter No.PB09) VIC (parameter No.PB10)	RSP (parameter No.PA09)
Manual mode	0003			PG1 (parameter No.PB07) GD2 (parameter No.PB06) VG2 (parameter No.PB09) VIC (parameter No.PB10)
Interpolation mode	0000	Always estimated	GD2 (parameter No.PB06) PG2 (parameter No.PB08) VG2 (parameter No.PB09) VIC (parameter No.PB10)	PG1 (parameter No.PB07) RSP (parameter No.PA09)



(2) Adjustment sequence and mode usage



8.1.2 Adjustment using set up software (MR Configurator2[™])

This section gives the functions and adjustment that may be performed by using the driver with the set up software (MR Configurator2[™]) which operates on a personal computer.

Function	Description	Adjustment
Machine analyzer	With the machine and servo motor coupled, the characteristic of the mechanical system can be measured by giving a random vibration command from the personal computer to the servo and measuring the machine response.	suppression filter. You can automatically set the optimum gains in response
Gain search	Executing gain search under to-and-fro positioning command measures settling characteristic while simultaneously changing gains, and automatically searches for gains which make settling time shortest.	 You can automatically set gains which make positioning settling time shortest.
Machine simulation	Response at positioning settling of a machine can be simulated from machine analyzer results on personal computer.	 You can optimize gain adjustment and command pattern on personal computer.



8.2 Auto tuning

8.2.1 Auto tuning mode

The driver has a real-time auto tuning function which estimates the machine characteristic (load inertia moment ratio) in real time and automatically sets the optimum gains according to that value. This function permits ease of gain adjustment of the driver.

(1) Auto tuning mode 1

The driver is factory-set to the auto tuning mode 1.

In this mode, the load inertia moment ratio of a machine is always estimated to set the optimum gains automatically.

The following parameters are automatically adjusted in the auto tuning mode 1.

Parameter No.	Abbreviation	Name
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment
PB07	PG1	Model loop gain
PB08	PG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

POINT

- The auto tuning mode 1 may not be performed properly if the following conditions are not satisfied.
- Time to reach 2000r/min is the acceleration/deceleration time constant of 5s or less.
- Speed is 150r/min or higher.
- The ratio of load inertia moment to servo motor inertia moment is 100 times or less.
- The acceleration/deceleration torque is 10% or more of the rated torque.
- Under operating conditions which will impose sudden disturbance torque during acceleration/deceleration or on a machine which is extremely loose, auto tuning may not function properly, either. In such cases, use the auto tuning mode 2 or manual mode to make gain adjustment.

(2) Auto tuning mode 2

Use the auto tuning mode 2 when proper gain adjustment cannot be made by auto tuning mode 1. Since the load inertia moment ratio is not estimated in this mode, set the value of a correct load inertia moment ratio (parameter No.PB06).

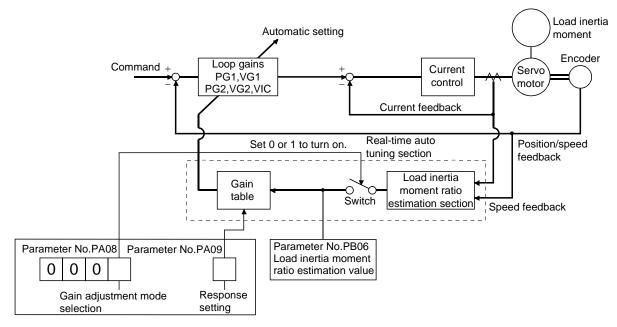
The following parameters are automatically adjusted in the auto tuning mode 2.

Parameter No.	Abbreviation	Name
PB07	PG1	Model loop gain
PB08	PG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation



8.2.2 Auto tuning mode operation

The block diagram of real-time auto tuning is shown below.



When a servo motor is accelerated/decelerated, the load inertia moment ratio estimation section always estimates the load inertia moment ratio from the current and speed of the servo motor. The results of estimation are written to parameter No.PB06 (the ratio of load inertia moment to servo motor). These results can be confirmed on the status display screen of the set up software (MR Configurator2[™]) section.

If the value of the load inertia moment ratio is already known or if estimation cannot be made properly, chose the "auto tuning mode 2" (parameter No.PA08: 0002) to stop the estimation of the load inertia moment ratio (Switch in above diagram turned off), and set the load inertia moment ratio (parameter No.34) manually.

From the preset load inertia moment ratio (parameter No.PB06) value and response level (parameter No.PA09), the optimum loop gains are automatically set on the basis of the internal gain tale.

The auto tuning results are saved in the EEP-ROM of the driver every 60 minutes since power-on. At power-on, auto tuning is performed with the value of each loop gain saved in the EEP-ROM being used as an initial value.

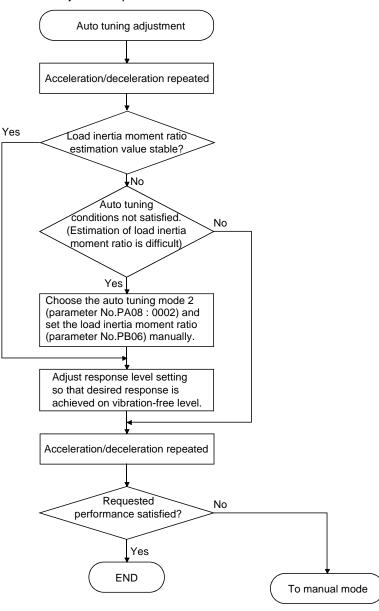
POINT

- If sudden disturbance torque is imposed during operation, the estimation of the inertia moment ratio may malfunction temporarily. In such a case, choose the "auto tuning mode 2" (parameter No.PA08: 0002) and set the correct load inertia moment ratio in parameter No.PB06.
- When any of the auto tuning mode 1 and auto tuning mode settings is changed to the manual mode 2 setting, the current loop gains and load inertia moment ratio estimation value are saved in the EEP-ROM.



8.2.3 Adjustment procedure by auto tuning

Since auto tuning is made valid before shipment from the factory, simply running the servo motor automatically sets the optimum gains that match the machine. Merely changing the response level setting value as required completes the adjustment. The adjustment procedure is as follows.





8.2.4 Response level setting in auto tuning mode

Set the response (The first digit of parameter No.PA09) of the whole servo system. As the response level setting is increased, the track ability and settling time for a command decreases, but a too high response level will generate vibration. Hence, make setting until desired response is obtained within the vibration-free range. If the response level setting cannot be increased up to the desired response because of machine resonance beyond 100Hz, filter tuning mode (parameter No.PB01) or machine resonance suppression filter (parameter No.PB13 to PB16) may be used to suppress machine resonance. Suppressing machine resonance may allow the response level setting to increase. Refer to section 9.3 for filter tuning mode and machine resonance suppression filter.

	Machine characteristic		
Response level setting	Machine rigidity	Machine resonance frequency guideline	Guideline of corresponding machine
1	Low	10.0	
2		11.3	
3		12.7	
4		14.3	
5] [16.1	
6		18.1	
7		20.4	
8		23.0	
9		25.9	
10		29.2	
11		32.9	Large conveyor
12		37.0	Large conveyor
13		41.7	
14	+	47.0	Arm robot
15		52.9	
16	Middle	59.6	General machine
17		67.1	tool conveyor
18	▲	75.6	Precision
19		85.2	working machine
20		95.9	
21		108.0	Inserter Mounter
22		121.7	Bonder
23		137.1	
24		154.4	
25		173.9	
26		195.9	
27		220.6	
28		248.5	
29		279.9	
30	•	315.3	
31		355.1	
32	High	400.0	

Setting of parameter No.PA09



8.3 Manual mode 1 (simple manual adjustment)

If you are not satisfied with the adjustment of auto tuning, you can make simple manual adjustment with three parameters.

 POINT
 If machine resonance occurs, filter tuning mode (parameter No.PB01) or machine resonance suppression filter (parameter No.PB13 to PB16) may be used to suppress machine resonance. (Refer to section 9.1.)

(1) For speed control

(a) Parameters

The following parameters are used for gain adjustment.

Parameter No.	Abbreviation	Name
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment
PB07	PG1	Model loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

(b) Adjustment procedure

Step	Operation	Description
1	Brief-adjust with auto tuning. Refer to section 8.2.3.	
2	Change the setting of auto tuning to the manual mode (Parameter No.PA08: 0003).	
3	Set an estimated value to the ratio of load inertia moment to servo motor inertia moment. (If the estimate value with auto tuning is correct, setting change is not required.)	
4	Set a slightly smaller value to the model loop gain Set a slightly larger value to the speed integral compensation.	
5	Increase the speed loop gain within the vibration- and unusual noise-free range, and return slightly if vibration takes place.	Increase the speed loop gain.
6	Decrease the speed integral compensation within the vibration-free range, and return slightly if vibration takes place.	Decrease the time constant of the speed integral compensation.
7	Increase the model loop gain, and return slightly if overshooting takes place.	Increase the model loop gain.
8	If the gains cannot be increased due to mechanical system resonance or the like and the desired response cannot be achieved, response may be increased by suppressing resonance with filter tuning mode or machine resonance suppression filter and then executing steps 2 and 3.	Suppression of machine resonance. Refer to section 9.2, 9.3.
9	While checking the settling characteristic and rotational status, fine-adjust each gain.	Fine adjustment



(c) Adjustment description

1) Speed loop gain (parameter No.PB09)

This parameter determines the response level of the speed control loop. Increasing this value enhances response but a too high value will make the mechanical system liable to vibrate. The actual response frequency of the speed loop is as indicated in the following expression.

Speed loop response _	_ Speed loop gain setting	
frequency(Hz)	(1+ratio of load inertia moment to servo motor inertia moment) $\times 2\pi$	

2) Speed integral compensation (VIC: parameter No.PB10)

To eliminate stationary deviation against a command, the speed control loop is under proportional integral control. For the speed integral compensation, set the time constant of this integral control. Increasing the setting lowers the response level. However, if the load inertia moment ratio is large or the mechanical system has any vibratory element, the mechanical system is liable to vibrate unless the setting is increased to some degree. The guideline is as indicated in the following expression.

3) Model loop gain (PG1: Parameter No.PB07)

This parameter determines the response level to a position command. Increasing the model loop gain improves track ability to a position command, but a too high value will make overshooting liable to occur at the time of setting.

Model loop gain	Speed loop gain setting	$\sim (1 + 1)$
guideline \geq	(1 + ratio of load inertia moment to servo mortar inertia moment)	$-\times \left(\frac{1}{4} \operatorname{to} \frac{1}{8}\right)$



(2) For position control

(a) Parameters

The following parameters are used for gain adjustment.

Parameter No.	Abbreviation	Name
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment
PB07	PG1	Model loop gain
PB08	PG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

(b) Adjustment procedure

Step	Operation	Description
1	Brief-adjust with auto tuning. Refer to section 8.2.3.	
2	Change the setting of auto tuning to the manual mode (Parameter No.PA08: 0003).	
3	Set an estimated value to the ratio of load inertia moment to servo motor inertia moment. (If the estimate value with auto tuning is correct, setting change is not required.)	
4	Set a slightly smaller value to the model loop gain and the position loop gain. Set a slightly larger value to the speed integral compensation.	
5	Increase the speed loop gain within the vibration- and unusual noise-free range, and return slightly if vibration takes place.	Increase the speed loop gain.
6	Decrease the speed integral compensation within the vibration-free range, and return slightly if vibration takes place.	Decrease the time constant of the speed integral compensation.
7	Increase the position loop gain, and return slightly if vibration takes place.	Increase the position loop gain.
8	Increase the model loop gain, and return slightly if overshooting takes place.	Increase the position loop gain.
9	If the gains cannot be increased due to mechanical system resonance or the like and the desired response cannot be achieved, response may be increased by suppressing resonance with filter tuning mode or machine resonance suppression filter and then executing steps 3 to 5.	Suppression of machine resonance. Refer to section 9.2 • 9.3.
10	While checking the settling characteristic and rotational status, fine-adjust each gain.	Fine adjustment.



(c) Adjustment description

1) Speed loop gain (VG2: parameter No.PB09)

This parameter determines the response level of the speed control loop. Increasing this value enhances response but a too high value will make the mechanical system liable to vibrate. The actual response frequency of the speed loop is as indicated in the following expression.

Speed loop response frequency(Hz) = $\frac{\text{Speed loop gain 2 setting}}{(1 + \text{ratio of load inertia moment to servo motor inertia moment}) \times 2\pi}$

2) Speed integral compensation (VIC: parameter No.PB10)

To eliminate stationary deviation against a command, the speed control loop is under proportional integral control. For the speed integral compensation, set the time constant of this integral control. Increasing the setting lowers the response level. However, if the load inertia moment ratio is large or the mechanical system has any vibratory element, the mechanical system is liable to vibrate unless the setting is increased to some degree. The guideline is as indicated in the following expression.

Speed integral compensation setting(ms) $\geq \frac{2000 \text{ to } 3000}{\text{Speed loop gain 2 setting/(1+ratio of load inertia moment to servo motor inertia moment 2 setting)}$

3) Model loop gain (PG1: Parameter No.PB07)

This parameter determines the response level to a position command. Increasing the model loop gain improves track ability to a position command, but a too high value will make overshooting liable to occur at the time of setting.

 $\begin{array}{l} \text{Model control gain} \\ \text{guideline} \\ \end{array} \leq \frac{\text{Speed loop gain setting}}{(1 + \text{ratio of load inertia moment to servo mortar inertia moment)}} \times \left(\frac{1}{4} \text{ to } \frac{1}{8}\right)$

4) Model loop gain (PG1: parameter No.PB07)

This parameter determines the response level to a position command. Increasing model loop gain improves track ability to a position command but a too high value will make overshooting liable to occur at the time of settling.

 $\begin{array}{l} \mbox{Model loop gain} \leq \frac{\mbox{Speed loop gain 2 setting}}{(1 + \mbox{ratio of load inertia moment to servo motor inertia moment)}} \times \left(\frac{1}{4} \mbox{ to } \frac{1}{8}\right)$



8.4 Interpolation mode

The interpolation mode is used to match the position loop gains of the axes when performing the interpolation operation of servo motors of two or more axes for an X-Y table or the like. In this mode, manually set the model loop gain that determines command track ability. Other parameters for gain adjustment are set automatically.

(1) Parameter

(a) Automatically adjusted parameters

The following parameters are automatically adjusted by auto tuning.

Parameter No.	Abbreviation	Name
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment
PB08	PG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

(b) Manually adjusted parameters

The following parameters are adjustable manually.

Parameter No.	Abbreviation	Name
PB07	PG1	Model loop gain

(2) Adjustment procedure

Step	Operation	Description
1	Set to the auto tuning mode.	Select the auto tuning mode 1.
2	During operation, increase the response level setting (parameter No.PA09), and return the setting if vibration occurs.	Adjustment in auto tuning mode 1.
3	Check the values of model loop gain.	Check the upper setting limits.
4	Set the interpolation mode (parameter No.PA08: 0000).	Select the interpolation mode.
5	Set the model loop gain of all the axes to be interpolated to the same value. At that time, adjust to the setting value of the axis, which has the smallest model loop gain.	Set position loop gain.
6	Looking at the interpolation characteristic and rotation status, fine-adjust the gains and response level setting.	Fine adjustment.

(3) Adjustment description

(a) Model loop gain (parameter No.PB07)

This parameter determines the response level of the position control loop. Increasing model loop gain improves track ability to a position command but a too high value will make overshooting liable to occur at the time of settling. The droop pulse value is determined by the following expression.

Droop pulse value (pulse) = $\frac{\frac{\text{Rotation speed (r/min)}}{60} \times 262144(\text{pulse})}{\text{Model loop gain setting}}$



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9.6.4 Gain changing operation	



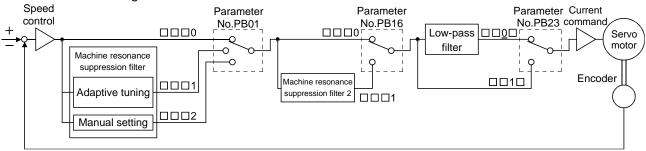
9. SPECIAL ADJUSTMENT FUNCTIONS

POINT

• The functions given in this chapter need not be used generally. Use them if you are not satisfied with the machine status after making adjustment in the methods in chapter 8.

If a mechanical system has a natural resonance point, increasing the servo system response level may cause the mechanical system to produce resonance (vibration or unusual noise) at that resonance frequency. Using the machine resonance suppression filter and adaptive tuning can suppress the resonance of the mechanical system.

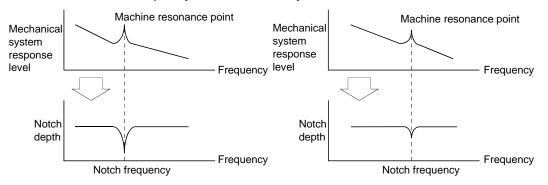
9.1 Function block diagram



9.2 Adaptive filter II

(1) Function

Adaptive filter II (adaptive tuning) is a function in which the driver detects machine vibration for a predetermined period of time and sets the filter characteristics automatically to suppress mechanical system vibration. Since the filter characteristics (frequency, depth) are set automatically, you need not be conscious of the resonance frequency of a mechanical system.



When machine resonance is large and frequency is low When machine resonance is small and frequency is high

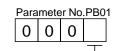
POINT

- The machine resonance frequency which adaptive tuning mode can respond to is about 100 to 2.25kHz. Adaptive vibration suppression control has no effect on the resonance frequency outside this range.
- Adaptive vibration suppression control may provide no effect on a mechanical system which has complex resonance characteristics.



(2) Parameters

The operation of adaptive tuning mode (parameter No.PB01).



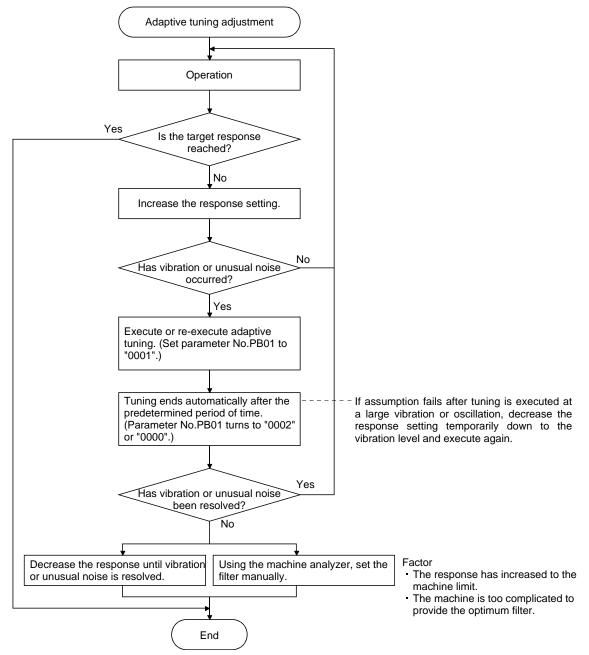
Filter tuning mode selection

Setting	Filter adjustment mode	Automatically set parameter
0	Filter OFF	(Note)
1	Filter turing mode	Parameter No.PB13
I	Filter tuning mode	Parameter No.PB14
2	Manual mode	

Note. Parameter No.PB19 and PB20 are fixed to the initial values.



(3) Adaptive tuning mode procedure

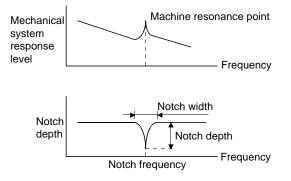




POINT

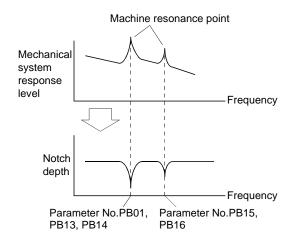
- · "Filter OFF" enables a return to the factory-set initial value.
- When adaptive tuning is executed, vibration sound increases as an excitation signal is forcibly applied for several seconds.
- When adaptive tuning is executed, machine resonance is detected for a maximum of 10 seconds and a filter is generated. After filter generation, the adaptive tuning mode automatically shifts to the manual mode.
- Adaptive tuning generates the optimum filter with the currently set control gains. If vibration occurs when the response setting is increased, execute adaptive tuning again.
- During adaptive tuning, a filter having the best notch depth at the set control gain is generated. To allow a filter margin against machine resonance, increase the notch depth in the manual mode.
- 9.3 Machine resonance suppression filter
- (1) Function

The machine resonance suppression filter is a filter function (notch filter) which decreases the gain of the specific frequency to suppress the resonance of the mechanical system. You can set the gain decreasing frequency (notch frequency), gain decreasing depth and width.



You can use the machine resonance suppression filter 1 (parameter No.PB13, PB14) and machine resonance suppression filter 2 (parameter No.PB15, PB16) to suppress the vibration of two resonance frequencies. Execution of adaptive tuning in the filter tuning mode automatically adjusts the machine resonance suppression filter. When adaptive tuning is ON, the adaptive tuning mode shifts to the manual mode after the predetermined period of time. The manual mode enables manual setting using the machine resonance suppression filter 1.





(2) Parameters

(a) Machine resonance suppression filter 1 (parameter No.PB13, PB14)

Set the notch frequency, notch depth and notch width of the machine resonance suppression filter 1 (parameter No.PB13, PB14)

When you have made adaptive filter tuning mode (parameter No.PB01) "manual mode", set up the machine resonance suppression filter 1 becomes effective.

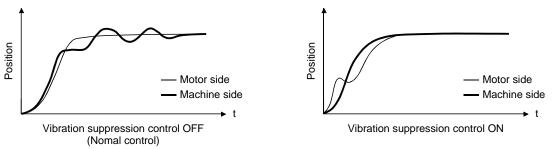
POINT

- The machine resonance suppression filter is a delay factor for the servo system. Hence, vibration may increase if you set a wrong resonance frequency or a too deep notch.
- If the frequency of machine resonance is unknown, decrease the notch frequency from higher to lower ones in order. The optimum notch frequency is set at the point where vibration is minimal.
- A deeper notch has a higher effect on machine resonance suppression but increases a phase delay and may increase vibration.
- A deeper notch has a higher effect on machine resonance suppression but increases a phase delay and may increase vibration.
- The machine characteristic can be grasped beforehand by the machine analyzer on the set up software(MR Configurator2[™]). This allows the required notch frequency and depth to be determined.



- 9.4 Advanced vibration suppression control
- (1) Operation

Vibration suppression control is used to further suppress machine side vibration, such as workpiece end vibration and base shake. The motor side operation is adjusted for positioning so that the machine does not shake.

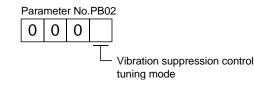


When the advanced vibration suppression control (vibration suppression control tuning mode parameter No.PB02) is executed, the vibration frequency at machine side can automatically be estimated to suppress machine side vibration.

In the vibration suppression control tuning mode, this mode shifts to the manual mode after operation is performed the predetermined number of times. The manual mode enables manual setting using the vibration suppression control vibration frequency setting (parameter No.PB19) and vibration suppression control resonance frequency setting (parameter No.PB20).

(2) Parameter

Select the operation of the vibration suppression control tuning mode (parameter No.PB02).



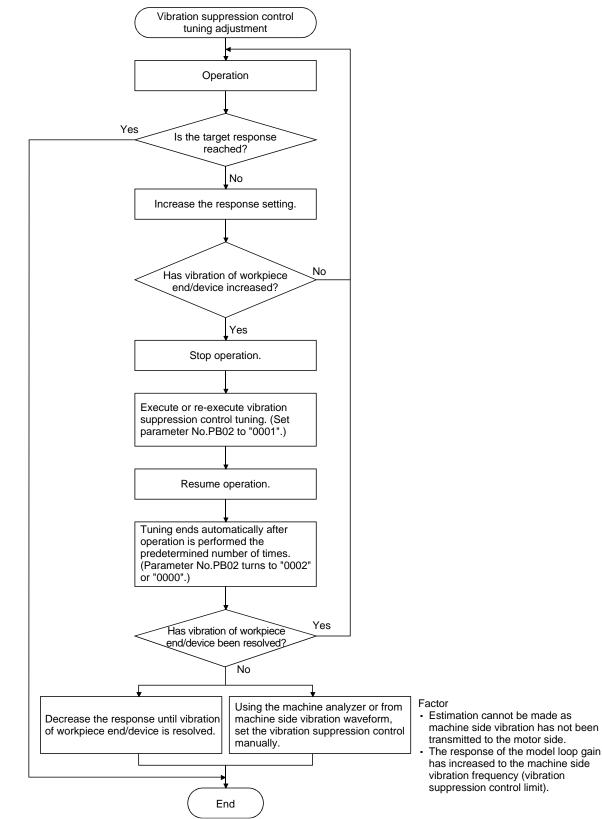
Setting	Vibration suppression control tuning mode	Automatically set parameter
0	Vibration suppression control OFF	(Note)
1	Vibration suppression control tuning mode	Parameter No.PB19
	(Advanced vibration suppression control)	Parameter No.PB20
2	Manual mode	

Note. Parameter No.PB19 and PB20 are fixed to the initial values.

POINT	
-------	--

- The function is made valid when the auto tuning mode (parameter No.PA08) is the auto tuning mode 2 ("0002") or manual mode ("0003").
- The machine resonance frequency supported in the vibration suppression control tuning mode is 1.0Hz to 100.0Hz. The function is not effective for vibration outside this range.
- Stop the motor before changing the vibration suppression control-related parameters (parameter No.PB02, PB19, PB20, PB33, PB34). A failure to do so will cause a shock.
- For positioning operation during execution of vibration suppression control tuning, provide a stop time to ensure a stop after full vibration damping.
- Vibration suppression control tuning may not make normal estimation if the residual vibration at the motor side is small.
- Vibration suppression control tuning sets the optimum parameter with the currently set control gains. When the response setting is increased, set vibration suppression control tuning again.





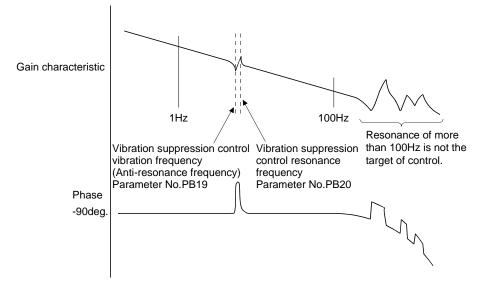
(3) Vibration suppression control tuning mode procedure



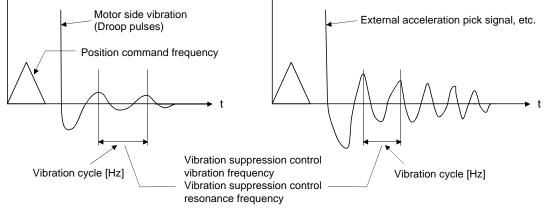
(4) Vibration suppression control manual mode

Measure work side vibration and device shake with the machine analyzer or external measuring instrument, and set the vibration suppression control vibration frequency (parameter No.PB19) and vibration suppression control resonance frequency (parameter No.PB20) to set vibration suppression control manually.

(a) When a vibration peak can be confirmed using set up software (MR Configurator2[™]), machine analyzer or external FFT equipment



(b) When vibration can be confirmed using monitor signal or external sensor



Set the same value.



POINT

- When machine side vibration does not show up in motor side vibration, the setting of the motor side vibration frequency does not produce an effect.
- When the anti-resonance frequency and resonance frequency can be confirmed using the machine analyzer or external FFT device, do not set the same value but set different values to improve the vibration suppression performance.
- A vibration suppression control effect is not produced if the relationship between the model loop gain (parameter No.PB07) value and vibration frequency is as indicated below. Make setting after decreasing PG1, e.g. reduce the response setting.

 $\frac{1}{2\pi}$ (1.5×PG1) > vibration frequency



9.5 Low-pass filter

(1) Function

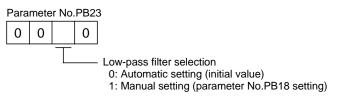
When a ball screw or the like is used, resonance of high frequency may occur as the response level of the servo system is increased. To prevent this, the low-pass filter is factory-set to be valid for a torque command. The filter frequency of this low-pass filter is automatically adjusted to the value in the following expression.

Filter frequency(rad/s) =
$$\frac{VG2}{1 + GD2} \times 10$$

When parameter No.PB23 is set to "
□ □ 1 □ ", manual setting can be made with parameter No.PB18.

(2) Parameter

Set the operation of the low-pass filter selection (parameter No.PB23.)



9.6 Gain changing function

This function can change the gains. You can change between gains during rotation and gains during stop or can use an input device to change gains during operation.

9.6.1 Applications This function is used when.

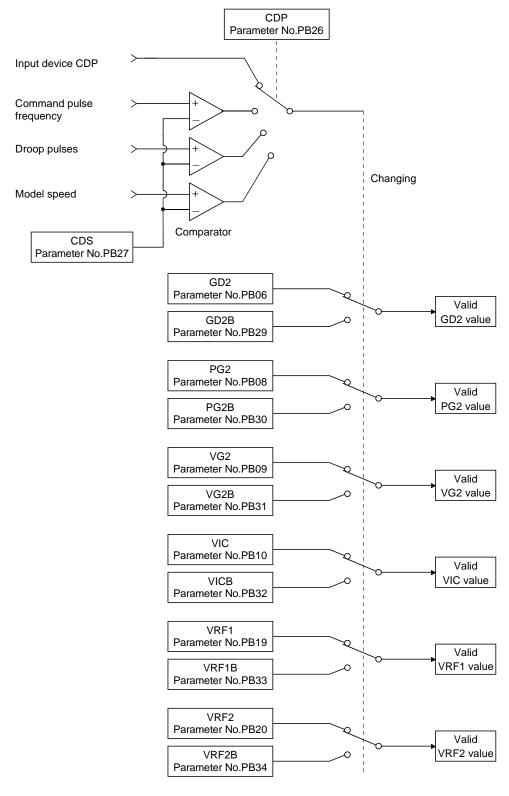
(1) You want to increase the gains during servo lock but decrease the gains to reduce noise during rotation.

- (2) You want to increase the gains during settling to shorten the stop settling time.
- (3) You want to change the gains using an input device to ensure stability of the servo system since the load inertia moment ratio varies greatly during a stop (e.g. a large load is mounted on a carrier).



9.6.2 Function block diagram

The valid loop gains PG2, VG2, VIC and GD2 of the actual loop are changed according to the conditions selected by gain changing selection CDP (parameter No.PB26) and gain changing condition CDS (parameter No.PB27).





9.6.3 Parameters

When using the gain changing function, always set "DDD3" in parameter No.PA08 (auto tuning) to choose the manual mode of the gain adjustment modes. The gain changing function cannot be used in the auto tuning mode.

Parameter No.	Abbreviation	Name	Unit	Description
		Ratio of load inertia moment to	Multi-	Control parameters before changing.
PB06	GD2	servo motor inertia moment	plier (×1)	
PB07	PG1	Model loop gain	rad/s	Position and speed gains of a model used to set the response level to a command. Always valid.
PB08	PG2	Position loop gain	rad/s	
PB09	VG2	Speed loop gain	rad/s	
PB10	VIC	Speed integral compensation	ms	
		Gain changing ratio of load inertia	Multi-	Used to set the ratio of load inertia moment to servo motor
PB29	GD2B	moment to servo motor inertia	plier	inertia moment after changing.
		moment	(×1)	
PB30	PG2B	Gain changing position loop gain	rad/s	Used to set the value of the after-changing position loop gain.
PB31	VG2B	Gain changing speed loop gain	rad/s	Used to set the value of the after-changing speed loop gain.
PB32	VICB	Gain changing speed integral compensation	ms	Used to set the value of the after-changing speed integral compensation.
PB26	CDP	Gain changing selection		Used to select the changing condition.
PB27	CDS	Gain changing condition	kpps pulse r/min	Used to set the changing condition values.
PB28	CDT	Gain changing time constant	ms	You can set the filter time constant for a gain change at changing.
		Gain changing vibration		Used to set the value of the after-changing vibration
PB33	VRF1B	suppression control vibration	Hz	suppression control vibration frequency setting.
		frequency setting		
		Gain changing vibration		Used to set the value of the after-changing vibration
PB34	VRF2B	suppression control resonance frequency setting	Hz	suppression control resonance frequency setting.



(1) Parameters No.PB06 to PB10

These parameters are the same as in ordinary manual adjustment. Gain changing allows the values of ratio of load inertia moment to servo motor inertia moment, position loop gain, speed loop gain and speed integral compensation to be changed.

- (2) Gain changing ratio of load inertia moment to servo motor inertia moment (GD2B: parameter No.PB29) Set the ratio of load inertia moment to servo motor inertia moment after changing. If the load inertia moment ratio does not change, set it to the same value as ratio of load inertia moment to servo motor inertia moment (parameter No.PB06).
- (3) Gain changing position loop gain (parameter No.PB30), Gain changing speed loop gain (parameter No.PB31), Gain changing speed integral compensation (parameter No.PB32) Set the values of after-changing position loop gain, speed loop gain and speed integral compensation.
- (4) Gain changing selection (parameter No.PB26) Used to set the gain changing condition. Choose the changing condition in the first digit and second digit. If you set "1" in the first digit here, you can use the gain changing (RY(n+2)) input device for gain changing.

0	0	
		Gain changing selection Under any of the following conditions, the gains change on the basis of the parameter No.PB29 to PB32 settings. 0: Invalid 1: Gain changing (RY(n+2)) is ON 2: Command frequency (Parameter No.PB27 setting) 3: Droop pulse value (Parameter No.PB27 setting)
		 4: Servo motor speed (Parameter No.PB27 setting) Gain changing condition 0: Valid at more than condition (Valid when gain changing (RY(n+2) is ON) 1: Valid at less than condition (Valid when gain changing (RY(n+2) is OFF)

(5) Gain changing condition (parameter No.PB27)

When you selected "command frequency", "droop pulses" or "servo motor speed" in gain changing selection (parameter No.PB26), set the gain changing level.

The setting unit is as follows.

Gain changing condition	Unit
Command frequency	kpps
Droop pulses	pulse
Servo motor speed	r/min

(6) Gain changing time constant (parameter No.PB28)

You can set the primary delay filter to each gain at gain changing. This parameter is used to suppress shock given to the machine if the gain difference is large at gain changing, for example.

(7) Gain switching vibration suppression control

The gain switching vibration suppression control is available only when switching ON / OFF with input devices.



9.6.4 Gain changing operation

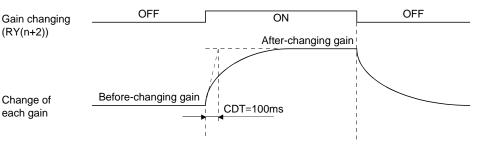
This operation will be described by way of setting examples.

(1) When you choose changing by input device

(a) Setting

Parameter No.	Abbreviation	Name	Setting	Unit
PB07	PG1	Model loop gain	100	rad/s
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment	4.0	Multiplier (×1)
PB08	PG2	Position loop gain	120	rad/s
PB09	VG2	Speed loop gain	3000	rad/s
PB10	VIC	Speed integral compensation	20	ms
PB29	GD2B	Gain changing ratio of load inertia moment to servo motor inertia moment	10.0	Multiplier (×1)
PB30	PG2B	Gain changing position loop gain	84	rad/s
PB31	VG2B	Gain changing speed loop gain	4000	rad/s
PB32	VICB	Gain changing speed integral compensation	50	ms
PB26	CDP	Gain changing selection	0001 (Changed by ON/OFF of Input device)	
PB28	CDT	Gain changing time constant	100	ms
PB33	VRF1B	Gain changing vibration suppression control vibration frequency setting	Used to set the value of the after-changing vibration suppression control vibration frequency setting.	Hz
PB34	VRF2B	Gain changing vibration suppression control resonance frequency setting	Used to set the value of the after-changing vibration suppression control resonance frequency setting.	Hz

(b) Changing operation



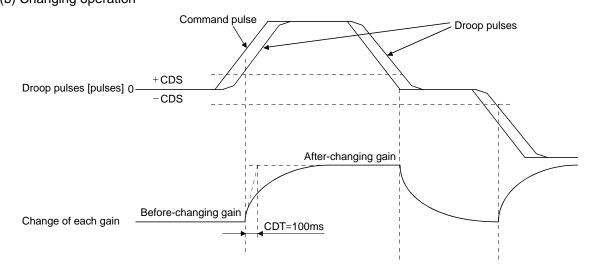
Model loop gain 1			100		
Ratio of load inertia moment to servo motor inertia moment	4.0	\rightarrow	10.0	\rightarrow	4.0
Position loop gain	120	\rightarrow	84	\rightarrow	120
Speed loop gain	3000	\rightarrow	4000	\rightarrow	3000
Speed integral compensation	20	\rightarrow	50	\rightarrow	20



(2) When you choose changing by droop	pulses
(a) Setting	

Parameter No.	Abbreviation	Name	Setting	Unit
PB07	PG1	Model loop gain	100	rad/s
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment	4.0	Multiplier (×1)
PB08	PG2	Position loop gain	120	rad/s
PB09	VG2	Speed loop gain	3000	rad/s
PB10	VIC	Speed integral compensation	20	ms
PB29	GD2B	Gain changing ratio of load inertia moment to servo motor inertia moment	10.0	Multiplier (×1)
PB30	PG2B	Gain changing position loop gain	84	rad/s
PB31	VG2B	Gain changing speed loop gain	4000	rad/s
PB32	VICB	Gain changing speed integral compensation	50	ms
PB26	CDP	Gain changing selection	0003 (Changed by droop pulses)	
PB27	CDS	Gain changing condition	50	pulse
PB28	CDT	Gain changing time constant	100	ms

(b) Changing operation



Model loop gain			100)			
Ratio of load inertia moment to servo motor inertia moment	4.0	\rightarrow	10.0	\rightarrow	4.0	\rightarrow	10.0
Position loop gain	120	\rightarrow	84	\rightarrow	120	\rightarrow	84
Speed loop gain	3000	\rightarrow	4000	\rightarrow	3000	\rightarrow	4000
Speed integral compensation	20	\rightarrow	50	\rightarrow	20	\rightarrow	50



10. TROUBLESHOOTING	2
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10.1 Trouble at start-up

 Excessive adjustment or change of parameter setting must not be made as it will make operation instable.

POINT
 • Using the set up software(MR Configurator2[™]), you can refer to unrotated servo motor reasons, etc.

The following faults may occur at start-up. If any of such faults occurs, take the corresponding action.

No.	Start-up sequence	Fault	Investigation	Possible cause	Reference
1	Power on	 LED is not lit. LED flickers. 	Not improved if connectors CN2, CN3 and CN6 are disconnected. Improved when connectors CN6 is disconnected. Improved when connector	 Power supply voltage fault Driver is faulty. Power supply of CN6 cabling is shorted. Power supply of encoder 	
			CN2 is disconnected.	cabling is shorted. 2. Encoder is faulty. Power supply of CN3 cabling is	
			CN3 is disconnected.	shorted.	
-	0 1: 1	Alarm occurs.	Refer to section 14.4 and remo		Section 10.4
2	Switch on servo-on (RYn0) signal.	Alarm occurs. Servo motor shaft is not servo-locked (is free).	 Refer to section 14.4 and remote Check the display to see if the driver is ready to operate. Check the external I/O signal indication to see if the servo-on (RYn0) signal 	 Servo-on (RYn0) is not input. (Wiring mistake) 2. 24VDC power is not supplied to DICOM. 	Section 10.4
3	Gain adjustment	Rotation ripples	is ON. Make gain adjustment in the	Gain adjustment fault	Chapter 8
		(speed fluctuations) are large at low speed.	 following procedure. Increase the auto tuning response level. Repeat acceleration and deceleration several times to complete auto tuning. 		
		Large load inertia moment causes the servo motor shaft to oscillate side to side.	If the servo motor may be run with safety, repeat acceleration and deceleration several times to complete auto tuning.	Gain adjustment fault	Chapter 8
4	Cyclic operation	Position shift occurs	Confirm the cumulative command pulses, cumulative feedback pulses and actual servo motor position.	Pulse counting error, etc. due to noise.	



10.2 Operation at error occurrence

An error occurring during operation will result in any of the statuses indicated in the following table.

Emer le setier	Description	Operati	on mode
Error location	Description	Test operation	CC-Link operation
Servo side alarm	Servo operation	Stop	Stop
occurrence	CC-Link data communication	Continued	Continued
Option unit	Servo operation	Stop	Stop
communication error	CC-Link data communication	Stop	Stop
CC-Link	Servo operation	Stop	Stop
communication error	CC-Link data communication	Stop	Stop
PC or PLC	Servo operation	Continued	Stop
error/STOP	CC-Link data communication	Stop	Stop
Servo side warning	Servo operation	Stop	Continued
occurrence	CC-Link data communication	Continued	Continued

10.3 CC-Link communication error

This section gives the definitions of the indications given in the communication alarm display section. The driver has four LED indications.

L.RUN : Lit at normal receive of refresh data. Extinguished when data is not received for a given period of time.

- SD : Lit when send data is "0".
- RD : Lit when the carrier of receive data is detected.

L.ERR : Lit when the data addressed to the host is in CRC or abort error.

(Note) Cor	nmunicatio	on alarm di	splay LED	Operation
L.RUN	SD	RD	L.ERR	Operation
0	0	0	0	Normal communication is made, but a CRC error sometimes occurs due to noise.
0	0	0		Normal communication
0	0	•	0	Hardware fault
0	0	•		Hardware fault
0		0	0	Receive data results in CRC error, disabling a response.
0	•	0		Data does not reach the host.
0		•	0	Hardware fault
0		•		Hardware fault
•	\odot	0		Hardware fault
•	0	0	0	Polling response is made, but refresh receive is in CRC error.
•	0	0		Hardware fault
•	0	•	0	Hardware fault
•	0	•		Hardware fault
•		0	0	Data addressed to the host resulted in CRC error.
		0		Data does not reach the host, or the data addressed to the host cannot be received due to
		0		noise.
		•	\odot	Hardware fault
	•		0	Baud rate setting illegal
	•	0	0	Station number setting illegal
	0	0	0	Baud rate or station number setting changed midway (ERROR flickers for about 4s)
				Data cannot be received due to power-off, power supply failure, open cable, etc.
-		-	-	WDT error occurrence (hardware fault)

Note. \bigcirc : Lit \bullet : Extinguished \bigcirc : Flicker



10.4 When alarm or warning has occurred

POINT
 Configure up a circuit which will detect the trouble (ALM) signal and turn off the servo-on (RYn0) at occurrence of an alarm.

10.4.1 Alarms and warning list

When a fault occurs during operation, the corresponding alarm or warning is displayed. If any alarm or warning has occurred, refer to section 10.4.2 or 10.4.3 and take the appropriate action. When an alarm occurs, ALM turns off.

After its cause has been removed, the alarm can be deactivated in any of the methods marked \bigcirc in the alarm deactivation column.

				Alarm deactivation		
	Display	Name	Power OFF→ON	(Note3) MR Configurator2™	(Note2) Alarm reset (RES)	(Note4) Stop Method
	A10	Undervoltage	0	0	0	EDB
	A12	Memory error 1 (RAM)	0			DB
	A13	Clock error	0			DB
	A15	Memory error 2 (EEP-ROM)	0			DB
	A16	Encoder error 1 (At power on)	0			DB
	A17	Board error	0			DB
	A19	Memory error 3 (Flash-ROM)	0			DB
	A1A	Motor combination error	0			DB
	A20	Encoder error 2 (during runtime)	0			EDB
	A21	Encoder error 3 (during runtime)	0			EDB
	A24	Main circuit error	0	0	0	DB
	A25	Absolute position erase	0			DB
	A30	Regenerative error	(Note 1)	(Note 1)	(Note 1)	DB
	A31	Overspeed	0	0	0	EDB
	A32	Overcurrent	0			DB
Alarms	A33	Overvoltage	0	0	0	EDB
Ala	A35	Command pulse frequency alarm	0	0	0	EDB
	A37	Parameter error	0			DB
	A45	Main circuit device overheat	(Note 1)	(Note 1)	(Note 1)	EDB
	A46	Servo motor overheat	(Note 1)	(Note 1)	(Note 1)	DB
	A47	Cooling fan alarm	0			EDB
	A50	Overload 1	(Note 1)	(Note 1)	(Note 1)	EDB
	A51	Overload 2	(Note 1)	(Note 1)	(Note 1)	DB
	A52	Error excessive	0	0	0	EDB
	A61	Operation alarm	0	0	0	DB
	A8A	Serial communication time-out	0	0	0	EDB
	A8D	CC-Link alarm	0	0	0	EDB
	A8E	Serial communication error	0	0	0	EDB
	888	Watchdog	0			DB



Ν				Alarm deactivation		
	Display	Name	Power OFF→ON	(Note3) MR Configurator2™	(Note2) Alarm reset (RES)	(Note4) Stop Method
	A90	Home positioning incomplete Warning				
					/	
	A92	Open battery cable warning			\backslash	
	A96	Home position setting error				
	A98	Software limit warning				
	A99	Stroke limit warning				
	A9D	CC-Link warning 1				
ngs	A9E	CC-Link warning 2				
Warnings	A9F	Battery warning				
Wa	AE0	Excessive regeneration warning				
	AE1	Overload warning 1				
	AE3	Absolute position counter warning				
	AE6	Servo emergency stop warning				EDB
	AE8	Cooling fan speed reduction warning				
	AE9 Main circuit off warning					DB
	AEC	Overload warning 2				
	AED	Output watt excess warning				

Note 1. Deactivate the alarm about 30 minutes of cooling time after removing the cause of occurrence.

2. Turns on RY(n+1)A or RY(n+3)A.

Clicking the "Alarm reset" button on the "Alarm display" screen of set up software (MR Configurator2[™]) allows an alarm to be deactivated. Pressing the "Occurred Alarm Reset" key of the parameter unit allows an alarm to be deactivated.

4. Stop method indicates as follows:

· DB: Stops with dynamic brake.

EDB: Stops with electronic dynamic brake for 400 W or less drivers

Stops with dynamic brake for 750 W drivers



10.4.2 Remedies for alarms				
	 When any alarm has occurred, eliminate its cause, ensure safety, then reset the alarm, and restart operation. Otherwise, injury may occur. If an absolute position erase (A25) occurred, always make home position setting again. Not doing so may cause unexpected operation. As soon as an alarm occurs, turn off Servo-on (RYn0) and power off. 			
	POINT			
	 When any of the following alarms has occurred, do not deactivate the alarm 			
	and resume operation repeatedly. To do so will cause the driver/servo motor			
	to fail. Remove the cause of occurrence, and leave a cooling time of more			
	than 30 minutes before resuming operation.			
	 Regenerative error (A30) 			
	Overload 1 (A50)			
	Overload 2 (A51)			
	 For the alarm deactivation method, refer to section 10.4.1. 			
	 Parameter error (A37) is not recorded in the alarm history 			

When an alarm occurs, the trouble (ALM) switches off and the dynamic brake is operated to stop the servo motor. At this time, the display indicates the alarm No.

The servo motor comes to a stop. Remove the cause of the alarm in accordance with this section. Use the set up software (MR Configurator2[™]) to refer to a factor of alarm occurrence.

Display	Name	Definition	Cause	Action
A10	Undervoltage	Power supply voltage dropped. LECSC2-T□: 160VAC or less	 Power supply voltage is low. There was an instantaneous control power failure of 60ms or longer. Shortage of power supply capacity caused the power supply voltage to drop at start, etc. The bus voltage dropped to the following value or less. LECSC2-T□: 200VDC 	Check the power supply.
			5. Faulty parts in the driver. Checking method Alarm (A10) occurs if power is switched on after disconnection of all cables but the control circuit power supply cables.	Change the driver.
A12	Memory error 1 (RAM)	RAM, memory fault	Faulty parts in the driver. Checking method	Change the driver.
A13	Clock error	Printed board fault	Alarm (any of A12 and A13) occurs if power is switched on after disconnection of all cables but the control circuit power supply cables.	

Display	Name	Definition	Cause	Action
A15	Memory error 2 (EEP-ROM)	EEP-ROM fault	 Faulty parts in the driver Checking method Alarm (A15) occurs if power is switched on after disconnection of all cables but the control circuit power supply cables. The number of write times to EEP- 	Change the driver.
A16	Encoder error 1 (At power on)	occurred between	ROM exceeded 100,000. 1. Encoder connector (CN2) disconnected.	Connect correctly.
		encoder and driver.	 Encoder fault Encoder cable faulty (Wire breakage or shorted) 	Change the servo motor. Repair or change the cable.
			 Encoder cable type (2-wire, 4-wire) selection was wrong in parameter setting. 	Correct the setting in the fourth digit of parameter No.PC22.
A17 A19	Board error Memory error 3 (Flash ROM)	CPU/parts fault ROM memory fault	Faulty parts in the driver Checking method Alarm (A17 or A19) occurs if power is switched on after disconnection of all cables but the control circuit power supply cable.	Change the driver.
A1A	Motor combination error	Wrong combination of driver and servo motor.	Wrong combination of driver and servo motor connected.	Use correct combination.
A20	Encoder error 2 (during runtime)	occurred between	 Encoder connector (CN2) disconnected. Encoder cable faulty (Wire breakage or shorted) 	Connect correctly. Repair or change the cable.
			3. Encoder fault	Change the servo motor.
A21	Encoder error 3 (during runtime)	Error occurred in encoder.	 Excessive acceleration is detected by oscillation, etc. Detection circuit error in encoder. 	Operate with the loop gain decreased. Operate with the auto tuning response. Change the servo motor.
A24	Main circuit error	occurred at the servo	 Power input wires and servo motor power wires are in contact. Sheathes of servo motor power cables deteriorated, resulting in ground fault. 	Connect correctly. Change the cable.
			3. Main circuit of driver failed. Checking method Alarm (A24) occurs if the servo is switched on after disconnecting the U, V, W power cables from the driver.	Change the driver.



Display	Name	Definition	Cause	Action
A25	Absolute	Absolute position	1. Voltage drop in encoder	Change the battery and
	position erase	data in error	(Battery disconnected.)	make home position setting again.
			2. Battery voltage fell to about 2.8V or	Change the battery.
			less.	Always make home position setting again.
			3. Battery cable or battery is faulty.	
			4. Encoder cable fault.	Repair or change the encoder cable.
			5. Encoder fault.	Change the servo motor.
		Power was switched	6. Home position not set.	Change the battery and
		on for the first time in		make home position setting again.
		the absolute position		
		detection system.		
A30	Regenerative	Permissible	1. Wrong setting of parameter No.	Set correctly.
	error	regenerative power	PA02	
		of the built-in	2. Built-in regenerative resistor or	Connect correctly
		regenerative resistor	regenerative option is not	
		or regenerative	connected.	
		option is exceeded.	3. High-duty operation or continuous	1. Reduce the frequency of positioning.
			regenerative operation caused the	2. Use the regenerative option of larger
			permissible regenerative power of	capacity.
			the regenerative option to be	3. Reduce the load.
			exceeded.	
			Checking method Call the status display and check	
			the regenerative load ratio.	
			4. Power supply voltage is abnormal.	Check the power supply
			LECSC2-T : 260VAC or more	
			5. Built-in regenerative resistor or	Change the driver or regenerative option.
			regenerative option faulty.	
		Regenerative	6. Regenerative transistor faulty.	Change the driver.
		transistor fault	Checking method	
			1) The regenerative option has	
			overheated abnormally.	
			 The alarm occurs even after removal of the built-in 	
			regenerative resistor or	
			regenerative option.	
A31	Overspeed	Speed has	1. Input command pulse frequency	Set command pulses correctly.
		exceeded the	exceeded the permissible	
		instantaneous	instantaneous speed frequency.	
		permissible speed.	2. Small acceleration/deceleration time	Increase acceleration/deceleration time
			constant caused overshoot to be	constant.
			large.	
			3. Servo system is instable to cause	1. Re-set servo gain to proper value.
			overshoot.	2. If servo gain cannot be set to proper
				value.
				1) Reduce load inertia moment ratio; or
				2) Reexamine acceleration/
				deceleration time constant.
			4. Electronic gear ratio is large	Set correctly.
			(parameters No.PA06, PA07)	
			5. Encoder faulty.	Change the servo motor.



Display	Name	Definition	Cause	Action
A32	Overcurrent	Current that flew is higher than the permissible current of the driver. (If the alarm (A32) occurs again when turning ON the servo after resetting the alarm by turning OFF/ON the power when the alarm (A32) first occurred, the transistor (IPM, IGBT) of the driver may be at fault. In the case, do not repeat to turn OFF/ON the power. Check the transistor	 Short occurred in servo motor power (U, V, W). Transistor (IPM, IGBT) of the driver faulty. Checking method Alarm (A32) occurs if power is switched on after U,V and W are disconnected. Ground fault occurred in servo motor power (U, V, W). External noise caused the overcurrent detection circuit to misoperate. 	Change the driver.
A33	Overvoltage	with the checking method of "Cause 2".) The following shows the input value of converter bus voltage. LECSC2-T□: 400VDC or more	 Regenerative option is not used. Though the regenerative option is used, the parameter No.PA02 setting is " 00 (not used)". Lead of built-in regenerative resistor 	Use the regenerative option. Set correctly.
			or regenerative option is open or disconnected. 4. Regenerative transistor faulty. 5. Wire breakage of built-in regenerative resistor or regenerative option.	 Connect correctly. Change the driver For wire breakage of built-in regenerative resistor, change the driver. For wire breakage of regenerative option, change the regenerative option.
			 Capacity of built-in regenerative resistor or regenerative option is insufficient. Power supply voltage high. Ground fault occurred in servo motor power (U, V, W). 	Add regenerative option or increase capacity. Check the power supply. Correct the wiring.
A35	Command pulse frequency error	Input pulse frequency of the command pulse is too high.	, , , ,	Change the pulse frequency to a proper value. Take action against noise. Change the manual pulse generator.



Display	Name	Definition	Cause	Action
A37	Parameter error	Parameter setting is	1. Driver fault caused the parameter	Change the driver.
		wrong.	setting to be rewritten.	
			2. Regenerative option not used with	Set parameter No.PA02 correctly.
			driver was selected in parameter	
			No.PA02.	
			3. Value outside setting range has	Set parameters No.PA06, PA07 correctly.
			been set in electronic gear.	
			4. Opposite sign has been set in software limit increasing side	Set parameters No.PC31 to PC34 correctly.
			(parameters No.PC31, PC32).	
			Similarly, opposite sign has been set	
			in software limit decreasing side	
			(parameters No.PC33, PC34).	
			5. Opposite sign has been set in	Set parameters No.PC37 to PC40 correctly.
			position range output address	
			increasing side (parameters No. PC37, PC38). Similarly, opposite	
			sign has been set in position range	
			output address decreasing side	
			(parameters No.PC39, PC40).	
			6. The number of write times to EEP-	Change the driver.
			ROM exceeded 100,000 due to	
			parameter write, etc.	
			7. The torque limit switching dog	These home position return types cannot be
			system or torque limit switching data	used. Set the parameter No.PC02 correctly.
			set system is selected for home	
			position return in the point table	
			positioning operation. (Parameter	
			No.PC02)	
		-	8. Setting value is out of the setting	Set it correctly.
		wrong.	range.	
A45	Main circuit	Main circuit device	1. Driver faulty.	Change the driver.
	device overheat	overheat.		The define we then does we does a
			2. The power supply was turned on	The drive method is reviewed.
			and off continuously by overloaded status.	
			3. Ambient temperature of servo	Check environment so that ambient
			motor is over 55°C (131°F).	temperature is 0 to 55° C (32 to 131° F).
			4. Used beyond the specifications of	Use within the range of specifications.
			close mounting.	ose within the range of specifications.
A46	Servo motor	Servo motor	1. Ambient temperature of servo	Check environment so that ambient
	overheat	temperature rise	motor is over 40°C (104°F).	temperature is 0 to 40° C (32 to 104° F).
		actuated the thermal	2. Servo motor is overloaded.	1. Reduce load.
		sensor.		2. Check operation pattern.
				3. Use servo motor that provides larger
				output.
			3. Thermal sensor in encoder is faulty.	Change the servo motor.
A47	Cooling fan alarm	The cooling fan of the driver stopped,	1. Cooling fan life expiration (Refer to section 2.5.)	Change the cooling fan of the driver.
		or its speed decreased to or	2. Foreign matter caught in the cooling fan stopped rotation.	Remove the foreign matter.
		below the alarm level.	3. The power supply of the cooling fan failed.	Change the driver.



Display	Name	Definition	Cause	Action
A50	Overload 1	Load exceeded overload protection characteristic of driver.	 Driver is used in excess of its continuous output current. 	 Reduce load. Check operation pattern. Use servo motor that provides larger output.
			2. Servo system is instable and hunting.	 Repeat acceleration/deceleration to execute auto tuning. Change auto tuning response setting. Set auto tuning to OFF and make gain adjustment manually.
			3. Machine struck something.	 Check operation pattern. Install limit switches.
			 Wrong connection of servo motor. Driver's output terminals U, V, W do not match servo motor's input terminals U, V, W. 	Connect correctly.
			5. Encoder faulty. Checking method When the servo motor shaft is rotated with the servo off, the cumulative feedback pulses do not vary in proportion to the rotary angle of the shaft but the indication skips or returns midway.	Change the servo motor.
			 After Overload 2 (A51) occurred, turn OFF/ON the power supply to clear the alarm. Then the overload operation is repeated. 	 Reduce load. Check operation pattern. Use servo motor that provides larger output.
A51	Overload 2	Machine collision or the like caused max.	1. Machine struck something.	1. Check operation pattern. 2. Install limit switches.
		For the time of the alarm occurrence, refer to the section 12.1.	 Wrong connection of servo motor. Driver's output terminals U, V, W do not match servo motor's input terminals U, V, W. 	Connect correctly.
			3. Servo system is instable and hunting.	 Repeat acceleration/deceleration to execute auto tuning. Change auto tuning response setting. Set auto tuning to OFF and make gain adjustment manually.
			4. Encoder faulty. Checking method When the servo motor shaft is rotated with the servo off, the cumulative feedback pulses do not vary in proportion to the rotary angle of the shaft but the indication skips or returns midway.	Change the servo motor.



Display	Name	Definition	Cause	Action
A52	Error excessive	The difference	1. Acceleration/deceleration time	Increase the acceleration/deceleration time
		between the model	constant is too small.	constant.
		position and the	2. Forward rotation torque limit	Increase the torque limit value.
		actual servo motor	(parameter No.PA11) or reverse	
		position exceeds	rotation torque limit (parameter	
		three rotations.	No.PA12) are too small.	
			3. Motor cannot be started due to	1. Check the power supply capacity.
		block diagram in section 1.1.2.)	torque shortage caused by power	2. Use servo motor which provides larger
		Section 1.1.2.)	supply voltage drop. 4. Position loop gain (parameter	output. Increase set value and adjust to ensure
			No.PB08) value is small.	proper operation.
			5. Servo motor shaft was rotated by	1. When torque is limited, increase the limit
			external force.	value.
				2. Reduce load.
				3. Use servo motor that provides larger
				output.
			6. Machine struck something.	1. Check operation pattern.
				2. Install limit switches.
			7. Encoder faulty.	Change the servo motor.
			8. Wrong connection of servo motor.	Connect correctly.
			Driver's output terminals U, V, W do	
			not match servo motor's input	
A61	Operation alarm	Setting mistake of	terminals U, V, W. "1" or "3" is set for the auxiliary	Set "0" or "2" for the value of auxiliary
701	operation alarm	auxiliary function.	function of point table No.255.	function.
A8A	Serial	Communication	1. Communication cable breakage.	Repair or change the communication cable.
	communication	stopped for longer	2. Communication cycle longer than	Shorten the communication cycle.
	time-out error	than the specified	regulated time.	,
		time.	3. Wrong protocol.	Correct protocol.
A8D	CC-Link alarm	Normal	1. The station number switch	Set the station number to within the range 1
		communication with	(STATION NO.) setting is 0 or not	to 64, and switch power on.
		the master station	less than 65.	
		cannot be made.	2. The baud rate switch (MODE)	Set the baud rate switch (MODE) to within
			setting is outside the range 0 to 4.	the range 0 to 4.
			3. The transmission status is	Reexamine the wiring.
			abnormal. 4. CC-Link twisted cable wiring	1. Repair or change the CC-Link twisted
			incorrect.	cable.
			5. CC-Link twisted cable faulty.	2. Connect the cable or connector correctly.
			6. The CC-Link connector has come	
			off.	
			7. The terminating resistor is not	Connect the terminating resistor correctly.
			connected.	
			 Noise entered the CC-Link twisted cable. 	
			 The programmable driver CC-Link master unit was reset. 	
			10. The manufacturer setting switch	Please change the manufacturer setting
			(SW 2) was changed from the	switch (SW 2) to the shipping state (left side)
			shipping state (left side).	
			(Refer to section 3.2.5.)	



Display	Name	Definition	Cause	Action
48E	Serial communication error	Serial communication error occurred between driver and communication device (e.g. personal computer).	1. Communication cable fault (Open cable or short circuit).	Repair or change the cable.
			 Communication device (e.g. personal computer) faulty. 	Change the communication device (e.g. personal computer).
(Note) 888	Watchdog	CPU, parts faulty.	Fault of parts in driver. Checking method Alarm (888) occurs if power is switched on after disconnection of all cables but the control circuit power supply cable.	Change the driver.

Note. At power-on, "888" appears instantaneously, but it is not an error.



10.4.3 Remedies for warnings

 If an absolute position counter warning (AE3) occurred, always make home
position setting again. Not doing so may cause unexpected operation.

POINT

• When any of the following alarms has occurred, do not resume operation by switching power of the driver OFF/ON repeatedly. The driver and servo motor may become faulty. If the power of the driver is switched OFF/ON during the alarms, allow more than 30 minutes for cooling before resuming operation.

Excessive regenerative warning (AE0)

Overload warning 1 (AE1)

If AE6 occur, the servo off status is established. If any other warning occurs, operation can be continued but an alarm may take place or proper operation may not be performed.

Remove the cause of warning according to this section. Use the set up software(MR Configurator2[™]) to refer to a factor of warning occurrence.

Display	Name		Definition	Cause	Action
A90	Home position return incomplete	system	Positioning operation was performed without home position return.	 Positioning operation was performed without home position return. 	Perform home position return.
		In incremental	ended abnormally.	 Home position return speed could not be decreased to creep speed. The stroke end (LSP or LSN) was actuated during home position return starting at other than position beyond dog. 	Check home position return speed/creep speed/moving distance after proximity dog.
		system	Positioning operation was performed without home position setting.	 Positioning operation was performed without home position setting. 	Perform home position setting.
		position detection sys	Home position setting ended abnormally.	 Home position setting speed could not be decreased to creep speed. The stroke end (LSP or LSN) was actuated during home position setting starting at other than position beyond dog. 	Check home position setting speed/creep speed/moving distance after proximity dog.
			Operation was performed without	 Voltage drop in encoder (Battery disconnected.) 	Connect the battery make home position setting again.
		In absolute	making home position setting while an absolute position erase (A25) is being occurred.	5. Battery voltage fell to about 2.8V or less. 6. Battery cable or battery is faulty.	Change the battery. Always make home position setting again.



Display	Name	Definition	Cause	Action
A92	Open battery cable	Absolute position	1. Battery cable is open.	Repair cable or changed.
	warning	detection system battery voltage is low.	 Battery voltage supplied from the driver to the encoder fell to about 3V or less. (Detected with the encoder) 	Change the battery.
			3. An encoder cable is broken.	Repair or replace the encoder cable.
A96	Home position setting warning	Home position setting could not be made.	1. Droop pulses remaining are greater than the in-position range setting.	Remove the cause of droop pulse occurrence
			 Command pulse entered after clearing of droop pulses. 	Do not enter command pulse after clearing of droop pulses.
			3. Creep speed high.	Reduce creep speed.
A98	Software limit warning	Software limit set in parameter is reached.	1. Software limit was set within actual operation range.	Set parameter No.PC31 to PC34 correctly.
			 Point table of position data in excess of software limit was executed. 	Set point table correctly.
			 Software limit was reached during JOG operation or manual pulse generator operation. 	Perform operation within software limit range.
A99	Stroke limit warning	The limit switch become valid.	The stroke end (LSP or LSN) of the direction which gave instructions was turned off.	Reexamine the operation pattern to turn LSP/LSN ON.
A9D	CC-Link warning 1	The station number switch or baud rate switch position was changed from the setting at power- on.	 The station number switch position was changed from the setting at power-on. The baud rate switch position was changed from the setting at power-on. The occupied station count switch position was changed from the setting at 	Return to the setting at power-on.
A05			power-on.	
A9E	CC-Link warning 2	Communication error of cable.	1. The transmission status is abnormal.	Take measures against noise.
			 2. CC-Link twisted cable wiring incorrect. 3. CC-Link twisted cable faulty. 	 Change the CC-Link twisted cable.
			4. The CC-Link connector has come off.	 Connect the cable or connector correctly.
			 The terminating resistor is not connected. Noise entered the CC-Link twisted cable. 	Connect the terminating resistor correctly.
A9F	Battery warning	Voltage of battery for absolute position detection system reduced.	Battery voltage fell to 3.2V or less. (Detected with the driver)	Change the battery.
AE0	Excessive regenerative warning	,	Regenerative power increased to 85% or more of permissible regenerative power of built-in regenerative resistor or regenerative option. Call the status display and check regenerative load ratio.	 Reduce frequency of positioning. Change the regenerative option for the one with larger capacity. Reduce load.
AE1	Overload warning 1	There is a possibility that overload alarm 1 or 2 may occur.	Load increased to 85% or more of overload alarm 1 or 2 occurrence level. Cause, checking method Refer to A50, A51.	Refer to A50, A51.
AE3	Absolute position counter warning	Absolute position encoder pulses faulty.	1. Noise entered the encoder.	Take noise suppression measures.
	<u> </u>		2. Encoder faulty.	Change the servo motor.
		The multi-revolution counter value of the absolute position encoder exceeded the maximum revolution range.	3. The movement amount from the home position exceeded a 32767 rotation or 37268 rotation in succession.	Make home position setting again.



Display	Name	Definition	Cause	Action
AE6	Servo forced stop warning	EMG is off.	External forced stop was made valid. (EMG was turned off.)	Ensure safety and deactivate forced stop.
AE8	Cooling fan speed reduction warning	The speed of the driver decreased to or below the warning level.	Cooling fan life expiration (Refer to section 2.5.)	Change the cooling fan of the driver.
			The power supply of the cooling fan is broken.	Change the driver.
AE9	Main circuit off warning	Servo-on (SON) was switched on with main circuit power off.		Switch on main circuit power.
AEC	Overload warning 2	current exceeding the rating flew intensively in	During a stop, the status in which a current flew intensively in any of the U, V and W phases of the servo motor occurred repeatedly, exceeding the warning level.	 Reduce the positioning frequency at the specific positioning address. Reduce the load. Replace the driver/ servo motor with the one of larger capacity.
AED	Output watt excess warning	output wattage (speed $ imes$ torque) of the servo motor	Continuous operation was performed with the output wattage (speed \times torque) of the servo motor exceeding 150% of the rated output.	 Reduce the servo motor speed. Reduce the load.

10.5 Point table error

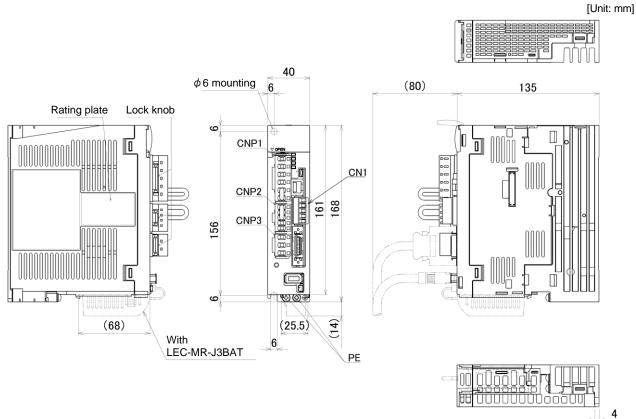
When a point table error occurs, the parameter error (A37) occurs. After the parameter No. of parameter error (A37), the point table error details are displayed.



11. OUTLINE DRAWINGS	2
11.1 Driver	
11.2 Connector	
	•

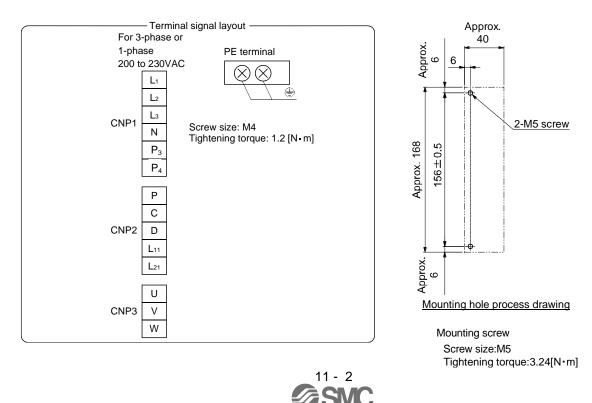


- 11.1 Driver
- (1) LECSC2-T5
 - LECSC2-T7



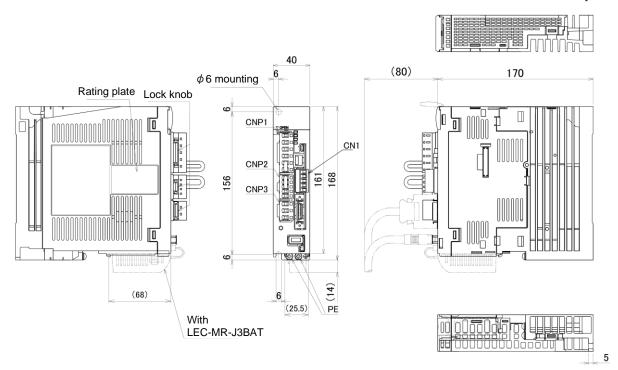
Note. This data applies to the 3-phase or 1-phase 200 to 230VAC power supply models.

Mass: 0.8 [kg]

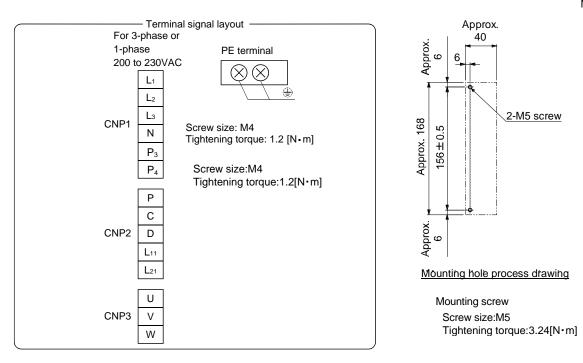


(2) LECSC2-T8

[Unit: mm]



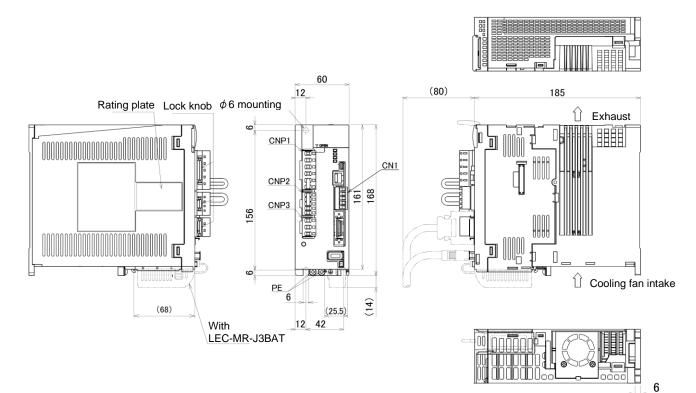
Note. This data applies to the 3-phase or 1-phase 200 to 230VAC power supply models.



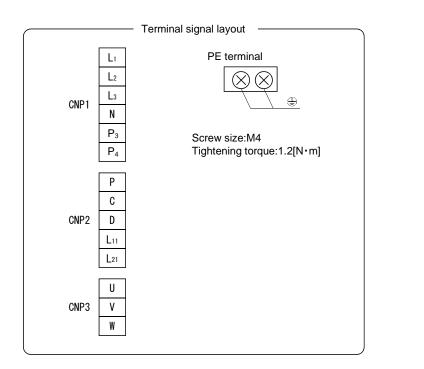
Mass: 1.0 [kg]

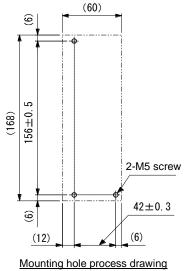
(3) LECSC2-T9

[Unit: mm]



Mass: 1.4 [kg]



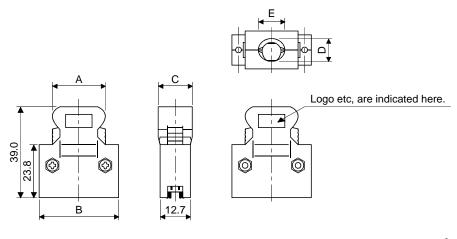


Mounting screw Screw size:M5 Tightening torque:3.24[N·m]



11.2 Connector

- (1) Miniature delta ribbon (MDR) system (Sumitomo 3M Limited)
 - (a) One-touch lock type



Connector	Shell kit	Each type of dimension				
Connector		А	В	С	D	Е
10150-3000PE 10350-52F0-008		41.1	52.4	18.0	14.0	17.0
Applicable wire size: AMC24, 20						

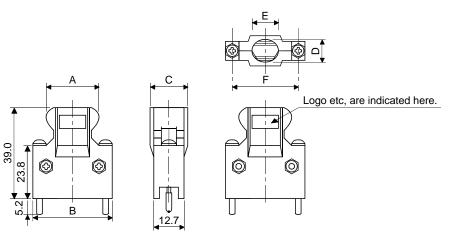
Applicable wire size: AWG24~30

(b) Jack screw M2.6 type

This is not available as option.

[Unit: mm]

[Unit: mm]



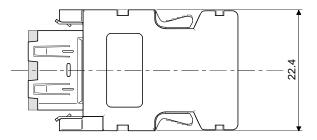
Connector Shell kit			E	ach type o	f dimensio	on	
Connector	Shell kit	А	В	С	D	ш	F
10150-3000PE 10350-52A0-008		41.1	52.4	18.0	14.0	17.0	46.5
Applicable wire size: AM/C24, 20							

Applicable wire size: AWG24~30

(2) SCR connector system (Sumitomo 3M Limited) Receptacle: 36210-0100PL

Shell kit : 36310-3200-008







12. CHARACTERISTICS	2
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12.2 Power supply equipment capacity and generated loss	
12.3 Dynamic brake characteristics	
12.3.1 Dynamic brake operation	
12.3.2 The dynamic brake at the load inertia moment	
12.4 Cable flexing life	
12.5 Inrush currents at power-on of main circuit and control circuit	



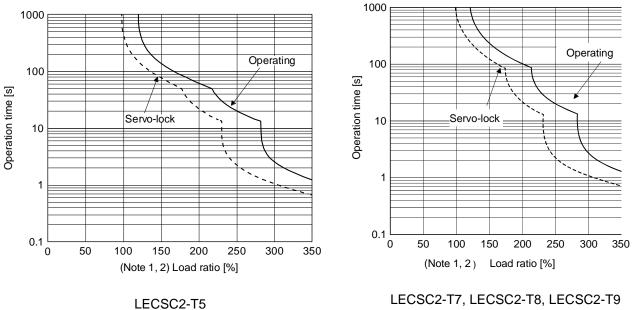
12. CHARACTERISTICS

12.1 Overload protection characteristics

An electronic thermal relay is built in the driver to protect the servo motor and driver from overloads. Overload 1 alarm (A50) occurs if overload operation performed is above the electronic thermal relay protection curve shown in any of Figs 12.1. Overload 2 alarm (A51) occurs if the maximum current flew continuously for several seconds due to machine collision, etc. Use the equipment on the left-hand side area of the continuous or broken line in the graph.

In a machine like the one for vertical lift application where unbalanced torque will be produced, it is recommended to use the machine so that the unbalanced torque is 70% or less of the rated torque.

When you carry out adhesion mounting of the driver, make circumference temperature into 0 to $45^{\circ}C$ (32 to $113^{\circ}F$), or use it at 75% or smaller effective load ratio.



The following graphs show overload protection characteristics.

Note2. The load ratio ranging from 300% to 350% applies to the LE-D-D servo motor.

Fig 12.1 Electronic thermal relay protection characteristics



Note1. If operation that generates torque more than 100% of the rating is performed with an abnormally high frequency in a servo motor stop status (servo lock status) or in a 30r/min or less low-speed operation status, the driver may fail even when the electronic thermal relay protection is not activated.

12.2 Power supply equipment capacity and generated loss

(1) Amount of heat generated by the driver

Table 12.1 indicates drivers' power supply capacities and losses generated under rated load. For thermal design of an enclosure, use the values in Table 12.1 in consideration for the worst operating conditions. The actual amount of generated heat will be intermediate between values at rated torque and servo off according to the duty used during operation. When the servo motor is run at less than the maximum speed, the power supply capacity will be smaller than the value in the table, but the driver's generated heat will not change.

Driver	Servo motor	(Note 1) Power supply	(Note 2) Driver-generated heat [W]		Area required for heat dissipation
		capacity [kVA]	At rated torque	With servo off	[m²]
LECSC2-T5	LE-T6-	0.3	25	15	0.5
LECSC2-T7	LE-T7-	0.5	25	15	0.5
LECSC2-T8	LE-T8-🗆	0.9	35	15	0.7
LECSC2-T9	LE-T9-🗆	1.3	50	15	1.0

Table 12.1 Power supply capacity and generated heat per driver at rated output

Note 1. Note that the power supply capacity will vary according to the power supply impedance. This value is applicable when the power factor improving AC reactor or power factor improving DC reactor is not used.

2. Heat generated during regeneration is not included in the driver-generated heat.



(2) Heat dissipation area for enclosed driver

The enclosed control box (hereafter called the control box) which will contain the driver should be designed to ensure that its temperature rise is within $+10^{\circ}C$ ($+50^{\circ}F$) at the ambient temperature of $40^{\circ}C$ ($104^{\circ}F$). (With a 5°C ($41^{\circ}F$) safety margin, the system should operate within a maximum 55°C ($131^{\circ}F$) limit.) The necessary enclosure heat dissipation area can be calculated by Equation 12.1.

 $A = \frac{P}{K \cdot \Delta T}$ (12.1)

- where, A : Heat dissipation area [m²]
 - P : Loss generated in the control box [W]
 - ΔT $\;$: Difference between internal and ambient temperatures [°C] $\;$
 - K : Heat dissipation coefficient [5 to 6]

When calculating the heat dissipation area with Equation 12.1, assume that P is the sum of all losses generated in the enclosure. Refer to Table 12.1 for heat generated by the driver. "A" indicates the effective area for heat dissipation, but if the enclosure is directly installed on an insulated wall, that extra amount must be added to the enclosure's surface area.

The required heat dissipation area will vary wit the conditions in the enclosure. If convection in the enclosure is poor and heat builds up, effective heat dissipation will not be possible. Therefore, arrangement of the equipment in the enclosure and the use of a cooling fan should be considered.

Table 12.1 lists the enclosure dissipation area for each driver when the driver is operated at the ambient temperature of 40°C (104°F) under rated load.

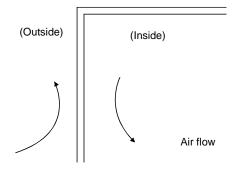


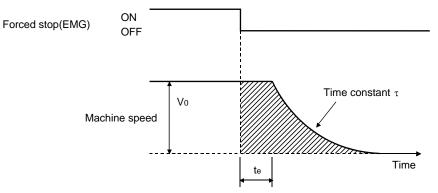
Fig. 12.2 Temperature distribution in enclosure

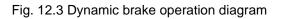
When air flows along the outer wall of the enclosure, effective heat exchange will be possible, because the temperature slope inside and outside the enclosure will be steeper.



- 12.3 Dynamic brake characteristics
- 12.3.1 Dynamic brake operation
- (1) Calculation of coasting distance

Fig. 13.3 shows the pattern in which the servo motor comes to a stop when the dynamic brake is operated. Use Equation 12.2 to calculate an approximate coasting distance to a stop. The dynamic brake time constant τ varies with the servo motor and machine operation speeds. (Refer to (2)(a), (b) in this section.)



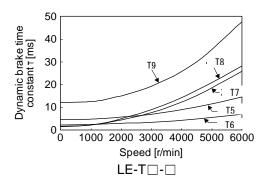


L _{max} =	$= \frac{V_0}{60} \cdot \left\{ t_e + \tau \left[1 + \frac{J_L}{J_M} \right] \right\} \dots (12.2)$
Lmax	: Maximum coasting distance[mm][in]
Vo	: Machine rapid feed rate[mm/min][in/min]
Јм	: Servo motor inertial moment
J∟	: Load inertia moment converted into equivalent value on servo motor shaft
τ	: Brake time constant[s]
te	: Delay time of control section[s]
	There is internal relay delay time of about 30ms.

(2) Dynamic brake time constant

The following shows necessary dynamic brake time constant τ for the equations (12.2).

(a) 200V class servo motor



12.3.2 The dynamic brake at the load inertia moment

Use the dynamic brake under the load inertia moment ratio indicated in the following table. If the load inertia moment is higher than this value, the built-in dynamic brake may burn. If there is a possibility that the load inertia moment may exceed the value, contact your local sales office.

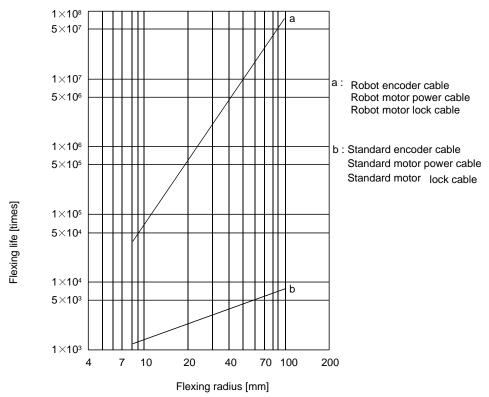
The values of the load inertia moment ratio in the table are the values at the maximum rotation speed of the servo motor.

Drivor	Servo motor
Driver	LE-TD-D
LECSC2-T	30



12.4 Cable flexing life

The flexing life of the cables is shown below. This graph calculated values. Since they are not guaranteed values, provide a little allowance for these values. The minimum bending radius : Min. 45mm.



12.5 Inrush currents at power-on of main circuit and control circuit

POINT
 ●For a servo amplifier of 600 W or less, the inrush current values can change depending on frequency of turning on/off the power and ambient temperature.

Since large inrush currents flow in the power supplies, always use molded-case circuit breakers and magnetic contactors. (Refer to section 13.5.)

When circuit protectors are used, it is recommended that the inertia delay type, which is not tripped by an inrush current, be used.

(1) 200 V class

The following shows the inrush currents (reference data) that will flow when 240 V AC is applied at the power supply capacity. When you use a 1-phase 200 V AC power supply, the inrush currents of the main circuit power supply are the same.

Driver	Inrush currents (A ₀ - _p)	
Diivei	Main circuit power supply (L ₁ , L ₂ , L ₃)	Control circuit power supply (L ₁₁ , L ₂₁)
LECSC2-T5 LECSC2-T6 LECSC2-T7 LECSC2-T8	30 A (attenuated to approx. 3 A in 20 ms)	20 A to 30 A (attenuated to approx. 1 A in 20 ms)
LECSC2-T9	34 A (attenuated to approx. 7 A in 20 ms)	



13. OPTIONS AND AUXILIARY EQUIPMENT

13. OPTIONS AND AUXILIARY EQUIPMENT	2
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13.1.1 Combinations of cable/connector sets	
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13.1.3 Motor cables	7
13.1.4 Lock cables	
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13.4 Selection example of wires	
13.5 No-fuse breakers, fuses, magnetic contactors	17
13.6 Noise reduction techniques.	
13.7 Leakage current breaker	
13.8 EMC filter (recommended)	



13. OPTIONS AND AUXILIARY EQUIPMENT

	 Before connecting any option or peripheral equipment, turn off the power and wait
	for 15 minutes or more until the charge lamp turns off. Then, confirm that the
WARNING	voltage between $P(+)$ and $N(-)$ is safe with a voltage tester and others.
	Otherwise, an electric shock may occur. In addition, always confirm from the front
	of the driver whether the charge lamp is off or not.

CAUTION • Use the specified auxiliary equipment and options. Unspecified ones may lead to a fault or fire.

POINT

•We recommend using HIV wires to wire the drivers, options, and peripheral equipment. Therefore, the recommended wire sizes may differ from those used for the previous drivers.

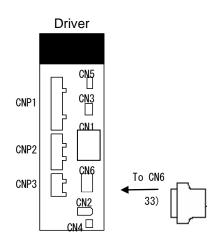
13.1 Cable/connector sets

POINT	
The IP rating	indicated for cables and connectors is their protection against ingress
of dust and ra	aindrops when they are connected to a driver or servo motor.
If the IP rating	g of the cable, connector, driver and servo motor vary,
the overall IP	rating depends on the lowest IP rating of all components.

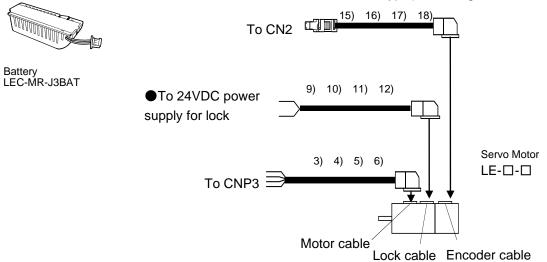
Purchase the cable and connector options indicated in this section.



13.1.1 Combinations of cable/connector sets



Direct connection type(cable length 10m or less, IP65)





13. OPTIONS AND AUXILIARY EQUIPMENT

No.	Product	Model	Description	Application
3)	Motor cable	LE-CSM-S⊡A Cable length: 2 • 5 • 10m	Motor cable ^{LE-D-D}	IP65 Axis side lead
4)	Motor cable	LE-CSM-R□A Cable length: 2 · 5 · 10m	Refer to section 13.1.3 for details.	IP65 Axis side lead Robot cable
5)	Motor cable	LE-CSM-S□B Cable length: 2 • 5 • 10m	→ LE-□-□ Motor cable series	IP65 Counter axis side lead
6)	Motor cable	LE-CSM-R□B Cable length: 2 · 5 · 10m	Refer to section 13.1.3 for details.	IP65 Counter axis side lead Robot cable
9)	Lock cable	LE-CSB-S⊡A Cable length: 2 • 5 • 10m	Lock cable series	IP65 Axis side lead
10)	Lock cable	LE-CSB-R□A Cable length: 2 • 5 • 10m	Refer to section 13.1.4 for details.	IP65 Axis side lead Robot cable
11)	Lock cable	LE-CSB-S□B Cable length: 2 • 5 • 10m	LE-D-D Lock cable series	IP65 Counter axis side lead
12)	Lock cable	LE-CSB-R□B Cable length: 2 • 5 • 10m	Refer to section 13.1.4 for details.	IP65 Counter axis side lead Robot cable
15)	Encoder cable	LE-CSE-S□A Cable length: 2 • 5 • 10m		IP65 Axis side lead
16)	Encoder cable	LE-CSE-R⊡A Cable length: 2 • 5 • 10m	Refer to section 13.1.2 (1) for details.	IP65 Axis side lead Robot cable
17)	Encoder cable	LE-CSE-S⊡B Cable length: 2 • 5 • 10m	Encoder cable LE-D-D	IP65 Counter axis side lead
18)	Encoder cable	LE-CSE-R□B Cable length: 2 • 5 • 10m	Refer to section 13.1.2 (1) for details.	IP65 Counter axis side lead Robot cable
33)	Connector set	LE-CSNA	Connector: 10126-3000PE Shell kit: 10326-52F0-008(Sumitomo 3M Limited or equivalent)	



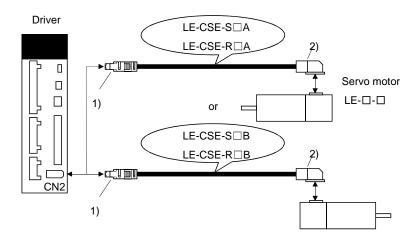
13.1.2 Encoder cable/connector sets

(1) LE-CSE- $\Box\Box$ A · LE-CSE- $\Box\Box$ B

These cables are encoder cables for the, LE- \Box - \Box series servo motors. The numerals in the Cable Length field of the table are the symbols entered in the \Box part of the cable model. The cables of the lengths with the symbols are available.

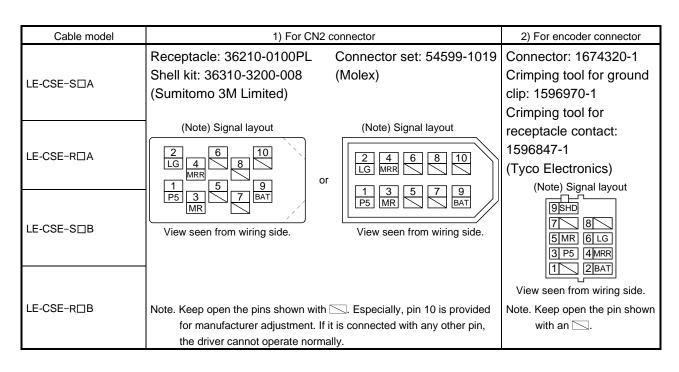
Cable model	Cable length			Protective	Flex life	Application
	2m	5m	10m	structure		
LE-CSE-S□A	2	5	A	IP65	Standard	For LE-□-□ servo motor Axis side lead
LE-CSE-R□A	2	5	А	IP65	Robot cable	
LE-CSE-S□B	2	5	A	IP65	Standard	For LE-□-□ servo motor Counter axis side lead
LE-CSE-R□B	2	5	А	IP65	Robot cable	

(a) Connection of driver and servo motor

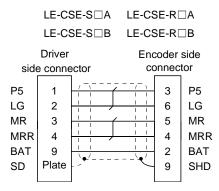




13. OPTIONS AND AUXILIARY EQUIPMENT



(b) Cable internal wiring diagram





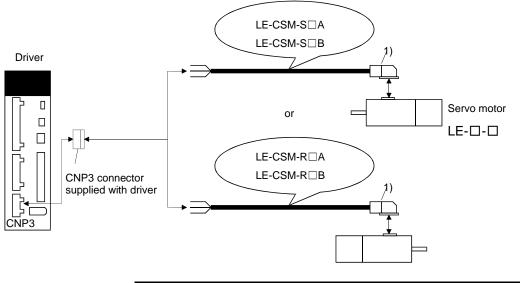
13.1.3 Motor cables

These cables are motor power supply cables for the LE- \Box - \Box series servo motors. The numerals in the Cable Length field of the table are the symbols entered in the \Box part of the cable model. The cables of the lengths with the symbols are available.

Refer to section 4.10 when wiring.

Cable model	Cable length		IP rating	Cable	Application	
Cable model	2m	5m	10m	ii raang	type	Application
LE-CSM-S□A	2	5	А	IP65	Standard	For LE-□-□ servo motor Axis side lead
LE-CSM-S□B	2	5	А	IP65	Standard	For LE- - servo motor Counter axis side lead
LE-CSM-R □A	2	5	А	IP65	Robot cable	For LE-□-□ servo motor Axis side lead
LE-CSM-R□B	2	5	А	IP65	Robot cable	For LE-□-□ servo motor Counter axis side lead

(1) Connection of driver and servo motor



Cable model	1) For motor power supply connector					
LE-CSM−S⊟A		Signal layout				
LE-CSM-S⊟B						
LE-CSM-R□A	Connector: JN4FT04SJ1-R Hood, socket insulator	1 🖶				
LE-CSM-R□B	Bushing, ground nut Contact: ST-TMH-S-C1B-100-(A534G) Crimping tool: CT160-3-TMH5B (Japan Aviation Electronics Industry)	View seen from wiring side.				



(2) Internal wiring diagram

LE-CSM-S□A	LE	-CSM-R□A
LE-CSM-S□B	LE	-CSM-R□B
	$\Delta M = 10$ (Red)	(Note)

	AWG 19 (Red) (Note)	
	AWG 19 (White)	
Ĵ	AWG 19 (Black)	
	AWG 19 (Green/yellow)	

Note. These are not shielded cables.

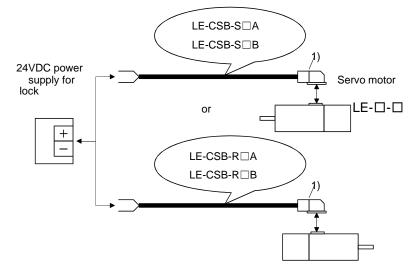


13.1.4 Lock cables

These cables are motor brake cables for the LE- \Box - \Box series servo motors. The numerals in the Cable Length field of the table are the symbols entered in the \Box part of the cable model. The cables of the lengths with the symbols are available. Refer to section 4.11 when wiring.

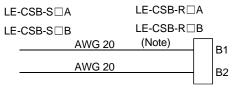
Cable medal	Ca	ble len	gth	Protective Flex life		Application	
Cable model	2m	5m	10m	structure	T IEX IIIE	Application	
LE-CSB-S□A	2	5	А	IP65	Standard	For LE-□-□ servo motor Axis side lead	
LE-CSB-S□B	2	5	А	IP65	Standard	For LE-□-□ servo motor Counter axis side lead	
LE-CSB-R□A	2	5	А	IP65	Robot cable	For LE-□-□ servo motor Axis side lead	
LE-CSB-R□B	2	5	А	IP65	Robot cable	For LE- - - Servo motor Counter axis side lead	

(1) Connection of power supply for lock and servo motor



Cable model	1) For motor power supply connector					
LE-CSB-S□A		Signal layout				
LE-CSB-S⊟B		g				
LE-CSB-R□A	Connector: JN4FT04SJ1-R Hood, socket insulator					
LE-CSB-R□B	Bushing, ground nut Contact: ST-TMH-S-C1B-100-(A534G) Crimping tool: CT160-3-TMH5B (Japan Aviation Electronics Industry)	View seen from wiring side.				

(2) Internal wiring diagram



Note. These are not shielded cables.

13. OPTIONS AND AUXILIARY EQUIPMENT

13.2 Regenerative options

The specified combinations of regenerative options and drivers may only be used.
Otherwise, a fire may occur.

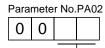
(1) Combination and regenerative power

The power values in the table are resistor-generated powers and not rated powers.

	Regenerative power [W]						
Driver	Built-in regenerative	LEC-MR-RB-032	LEC-MR-RB-12				
	resistor	[40Ω]	[40Ω]				
LECSC2-T5		30					
LECSC2-T7	10	30	100				
LECSC2-T8	10	30	100				
LECSC2-T9	20	30	100				

(2) Parameter setting

Set parameter No.PA02 according to the option to be used.



Selection of regenerative option

00:Regenerative option is not used

- For driver of 100W, regenerative resistor is not used.
- \cdot For driver of 200W to 400W, regenerative resistor is not used.

02:LEC-MR-RB-032

03:LEC-MR-RB-12



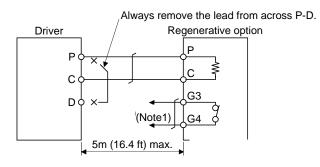
(3) Connection of the regenerative option

POINT
For the sizes of wires used for wiring, refer to section 13.4.

The regenerative option will cause a temperature rise of $+100^{\circ}$ C relative to the ambient temperature. Fully examine heat dissipation, installation position, used cables, etc. before installing the option. For wiring, use flame-resistant cables and keep them clear of the regenerative option body. Always use twisted cables of max. 5m length for connection with the driver.

(a) LECSC2-T□

Always remove the wiring from across P-D and fit the regenerative option across P-C. The G3 and G4 terminals act as a thermal sensor. G3-G4 is disconnected when the regenerative option overheats abnormally.



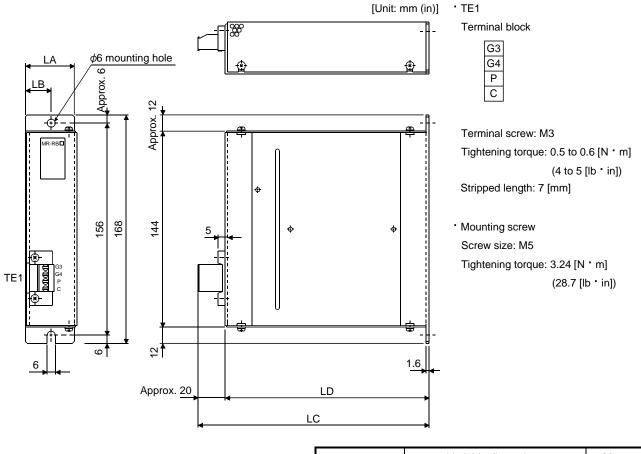
Note 1. Make up a sequence which will switch off the magnetic contactor (MC) when abnormal heating occurs.

G3-G4 contact specifications Maximum voltage: 120V AC/DC Maximum current: 0.5A/4.8VDC Maximum capacity: 2.4VA



(4) Outline dimension drawings

(a) LEC-MR-RB-032 · LEC-MR-RB-12

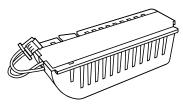


Regenerative	١ ١	Mass				
option	LA	LB	LC	LD	[kg]	[lb]
LEC-MR-RB-032	30	15	119	99	0.5	1.1
LEC-MR-RB-12	40	15	169	149	1.1	2.4

13.3 Battery LEC-MR-J3BAT

(1) Purpose of use for LEC-MR-J3BAT

This battery is used to construct an absolute position detection system. Refer to section 5.7 for the fitting method, etc.



(2) Year and month when LEC-MR-J3BAT is manufactured

The year and month when LEC-MR-J3BAT is manufactured are written down in Serial No. on the rating plate of the battery back face.

The year and month of manufacture are indicated by the last one digit of the year and 1 to 9, X(10), Y(11), Z(12).

For October 2004, the Serial No. is like, "SERIAL 4X 4X 4X 4.

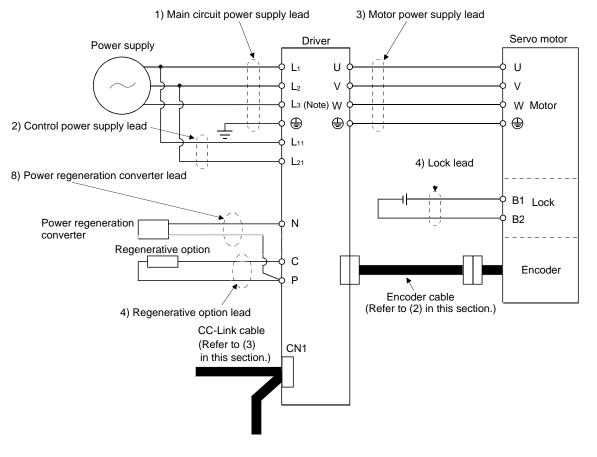


13.4 Selection example of wires

POINT
 To comply with the IEC/EN/UL/CSA standard, use the wires shown in app. 11 for wiring. To comply with other standards, use a wire that is complied with each standard.
 Selection condition of wire size is as follows.
Construction condition: One wire is constructed in the air
Wire length: 30m or less

(1) Wires for power supply wiring

The following diagram shows the wires used for wiring. Use the wires given in this section or equivalent.



Use the 600 V Grade heat-resistant polyvinyl chloride insulated wire (HIV wire) for wiring. The following shows the wire size selection example.

	Wires [mm ²]						
Driver	1) L1 • L2 • L3 •⊕	2)	3) (Note 1) U · V · W · ⊕		4)	4) 5) (Note 2 4) B1 • B2	
		L11 • L21	10m or less	Extension cable	P·C	10m or less	Extension cable
LECSC2-T5							
LECSC2-T7	2(AWG14)	1.25(AWG16)	0.75(AWG18)	1.25(AWG16)	2(AWG14)	0.5(AWG20)	1.25(AWG16)
LECSC2-T8							
LECSC2-T8							

Table 13.2 Wire size selection example 2 (HIV wire)

Note 1. Be sure to use the size of 2 mm² (AWG14) when corresponding to IEC/EN/UL/CSA standard.

Note 2. Be sure to use the size of 1.25 mm² (AWG16) when corresponding to IEC/EN/UL/CSA standard.

Use wires 8) of the following sizes with the power regeneration converter (FR-RC-(H) :Mitsubishi Electric Corporation).

Model	Wires[mm ²]
FR-RC-15K	14(AWG6)
FR-RC-30K	14(AWG6)
FR-RC-55K	22(AWG4)
FR-RC-H15K	14(AWG6)
FR-RC-H30K	14(AWG6)
FR-RC-H55K	14(AWG6)



(2) Wires for cables

When fabricating a cable, use the wire models given in the following table or equivalent.

_	Table 13.3 Wires for option cables									
			Core size [mm²]	Number of Cores	Characteristics of one core					
TypeEncod er cable	Model	Length [m]			Structure [Wires/mm]	Conductor resistance [Ω/mm]	Insulation coating OD d [mm] (Note 1)	(Note 3) Finishing OD [mm]	Wire model	
	LE-CSE-S□A	2 to 10	AWG22	6	7/0.26	53	1.2	7.1±0.3	(Note 3) VSVP 7/0.26 (AWG#22 or	
Encoder Cable	LE-CSE−S□B	2 10 10	AVVG22	(3 pairs)	7/0.26	or less	1.2	7.1±0.5	equivalent)-3P Ban-gi-shi-16823	
Cable	LE-CSE-R□A	2 to 10	AWG22	6 (3 pairs)	70/0.08	56 or less	1.2	7.1±0.3	(Note 3) ETFE SVP 70/0.08 (AWG#22 or	
	LE-CSE-R□B		-						equivalent)-3P Ban-gi-shi-16824	
	LE-CSM-S⊟A	2 to 10	AWG18 4	34/0.18	21.8	1.71	62±0.3	HRZFEV-A(CL3) AWG18 4-cores		
	LE-CSM-S□B	2 to 10		4	34/0.18	or less	1.71	02-0.3	TINZI E V-A(CE3) AVVG 18 4-COIES	
Motor cable	LE-CSM-R□A	2 to 10	(Note 5)	4	150/0.08	29.1	1.63	5.7±0.5	(Note 4) RMFES-A(CL3X) AWG19 4-cores	
	LE-CSM-R□B	2 to 10	AWG19 (0.75mm ²)			or less				
	LE-CSB-S□A	2 to 10	AWG20	2	21/0.18	34.6	1.35	4.7±0.1	(Note 4)	
	LE-CSB-S⊟B	2 to 10	AVVG20	2	21/0.10	or less	1.35	4.7 - 0.1	HRZFEV-A(CL3) AWG20 2-cores	
Lock cable	LE-CSB-R□A	2 to 10	(Note 5) AWG20	2	110/0.08	39.0	1 37	.37 4.5±0.3	RMFES-A(CL3X) AWG20 2-cores	
	LE-CSB-R□B	2 to 10	(0.75mm ²)	-	110/0.00	or less	3		1001 20-A(020X) AWG20 2-COles	

Note 1. d is as shown below.



Conductor Insulation sheath

2. Purchased from Toa Electric Industry

3. Standard OD. Max. OD is about 10% greater.

4. Kurabe

5. These wire sizes assume that the UL-compliant wires are used at the wiring length of 10m.



(3) CC-Link twisted cable

The specifications of the twisted cable usable in CC-Link and the recommended cable are indicated below. If the cable used is other than the recommended cable indicated in the following table, we cannot guarantee the performance of CC-Link. For inquiries on CC-Link compatible cables, contact the nearest SMC.

Item	Specifications
Model	FANC-110SBH
Manufacturer	Kuramo Electric
Application	For fixed parts
Size	20AWG×3
Insulator material	Polyethylene foam
Insulator color	Blue, white, and yellow
Sheath material	Oil resistant vinyl
Sheath color	Brown
Operating temperature range (Note)	0 to 75 °C (32 to 167°F)
Tensile strength	49N
Minimum bend radius	35mm
Outline dimension	Approx. 7.6mm
Approximate mass	70kg/km
Conductor resistance (20°C)	$34.5\Omega/km$ or lower
Characteristic impedance	110±15Ω
	UL AWM Style 2464
Applicable specification	CAN/CSA-C22.2
	No.210.2-M90(cUL)

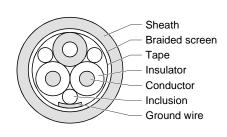


Fig. 13.1 Structure

Note. An upper limit of the operating temperature range shows a heat-resistant temperature of the cable material. In high-temperature environment, the transmittable distance may be reduced.

13.5 No-fuse breakers, fuses, magnetic contactors

Always use one no-fuse breaker and one magnetic contactor with one driver. When using a fuse instead of the no-fuse breaker, use the one having the specifications given in this section.

	No-fuse	breaker					
Driver	Not using power factor improving reactor	Using power factor improving reactor	Class (Note1)	Current [A]	Voltage AC [V]	Magnetic contactor (Note2)	
LECSC2-T5	30A frame 5A	30A frame 5A		10		S-N10	
LECSC2-T7	30A frame 5A	30A frame 5A	т	10	250	S-T10	
LECSC2-T8	30A frame 10A	30A frame 5A	I	15	250	(Mitsubishi Electric	
LECSC2-T8	30A frame 15A	30A frame 10A		20		Corporation)	

Note 1. When having the servo amplifier comply with the IEC/EN/UL/CSA standard, refer to app. 11.

2. Use a magnetic contactor with an operation delay time (interval between current being applied to the coil until closure of contacts) of 80 ms or less.



13.6 Noise reduction techniques

Noises are classified into external noises which enter the driver to cause it to malfunction and those radiated by the driver to cause peripheral devices to malfunction. Since the driver is an electronic device which handles small signals, the following general noise reduction techniques are required.

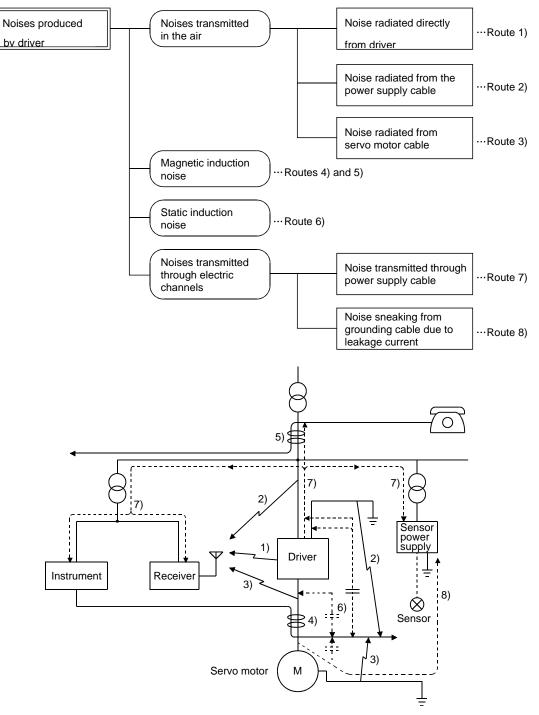
Also, the driver can be a source of noise as its outputs are chopped by high carrier frequencies. If peripheral devices malfunction due to noises produced by the driver, noise suppression measures must be taken. The measures will vary slightly with the routes of noise transmission.

(1) Noise reduction techniques

- (a) General reduction techniques
 - Avoid laying power lines (input and output cables) and signal cables side by side or do not bundle them together. Separate power lines from signal cables.
 - Use shielded, twisted pair cables for connection with the encoder and for control signal transmission, and connect the shield to the SD terminal.
 - Ground the driver, servo motor, etc. together at one point (refer to section 4.12).
- (b) Reduction techniques for external noises that cause the driver to malfunction
 - If there are noise sources (such as a magnetic contactor, a lock, and many relays which make a large amount of noise) near the driver and the driver may malfunction, the following countermeasures are required.
 - Provide surge absorbers on the noise sources to suppress noises.
 - Attach data line filters to the signal cables.
 - Ground the shields of the encoder connecting cable and the control signal cables with cable clamp fittings.
 - Although a surge absorber is built into the driver, to protect the driver and other equipment against large exogenous noise and lightning surge, attaching a varistor to the power input section of the equipment is recommended.



(c) Techniques for noises radiated by the driver that cause peripheral devices to malfunction Noises produced by the driver are classified into those radiated from the cables connected to the driver and its main circuits (input and output circuits), those induced electromagnetically or statically by the signal cables of the peripheral devices located near the main circuit cables, and those transmitted through the power supply cables.





13. OPTIONS AND AUXILIARY EQUIPMENT

Noise transmission route	Suppression techniques
1) 2) 3)	 When measuring instruments, receivers, sensors, etc. which handle weak signals and may malfunction due to noise and/or their signal cables are contained in a control box together with the driver or run near the driver, such devices may malfunction due to noises transmitted through the air. The following techniques are required. 1. Provide maximum clearance between easily affected devices and the driver. 2. Provide maximum clearance between easily affected signal cables and the l/O cables of the driver. 3. Avoid laying the power lines (Input cables of the driver) and signal cables side by side or bundling them together. 4. Insert a line noise filter to the I/O cables or a radio noise filter on the input line. 5. Use shielded wires for signal and power cables or put cables in separate metal conduits.
4) 5) 6)	 When the power lines and the signal cables are laid side by side or bundled together, magnetic induction noise and static induction noise will be transmitted through the signal cables and malfunction may occur. The following techniques are required. 1. Provide maximum clearance between easily affected devices and the driver. 2. Provide maximum clearance between easily affected signal cables and the I/O cables of the driver. 3. Avoid laying the power lines (I/O cables of the driver) and signal cables side by side or bundling them together. 4. Use shielded wires for signal and power cables or put the cables in separate metal conduits.
7)	 When the power supply of peripheral devices is connected to the power supply of the driver system, noises produced by the driver may be transmitted back through the power supply cable and the devices may malfunction. The following techniques are required. 1. Insert the radio noise filter (FR-BIF:Mitsubishi Electric Corporation) on the power cables (Input cables) of the driver. 2. Insert the line noise filter (FR-BSF01 • FR-BLF:Mitsubishi Electric Corporation) on the power cables of the driver.
8)	When the cables of peripheral devices are connected to the driver to make a closed loop circuit, leakage current may flow to malfunction the peripheral devices. If so, malfunction may be prevented by disconnecting the grounding cable of the peripheral device.

(2) Noise reduction products

(a) Data line filter (Recommended)

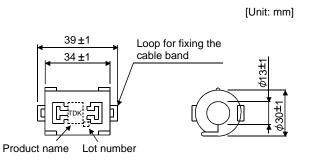
Noise can be prevented by installing a data line filter onto the encoder cable, etc.

For example, the ZCAT3035-1330 of TDK and the ESD-SR-25 of NEC TOKIN make are available as data line filters.

As a reference example, the impedance specifications of the ZCAT3035-1330 (TDK) are indicated below.

This impedance is reference values and not guaranteed values.

Impedance[Ω]				
10 to 100MHz	100 to 500MHz			
80	150			

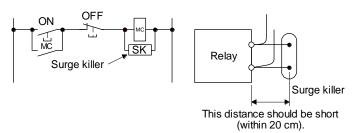


Outline drawing (ZCAT3035-1330)

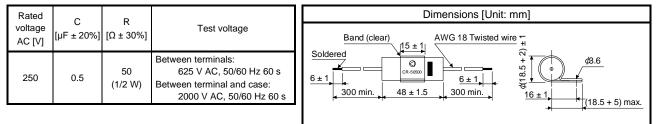


(b) Surge suppressor

The recommended surge suppressor for installation to an AC relay, AC valve, or the like near the driver is shown below. Use this product or equivalent.



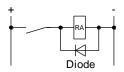
(Ex.) CR-50500 Okaya Electric Industries)



Note that a diode should be installed to a DC relay or the like.

Maximum voltage: Not less than 4 times the drive voltage of the relay or

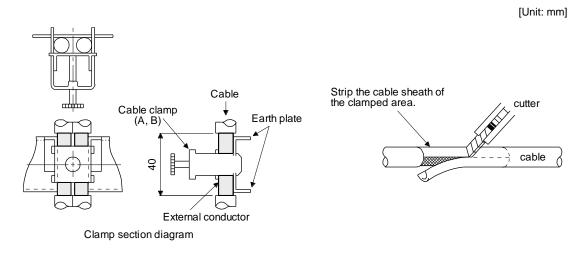
the like Maximum current: Not less than twice the drive current of the relay or the like



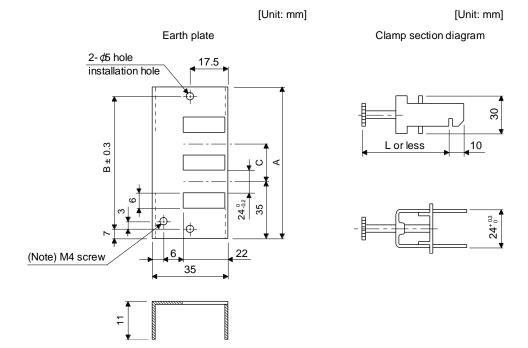


(c) Cable clamp fitting (AERSBAN - SET (Mitsubishi Electric Corporation))

Generally, the earth of the shielded cable may only be connected to the connector's SD terminal. However, the effect can be increased by directly connecting the cable to an earth plate as shown below. Install the earth plate near the driver for the encoder cable. Peel part of the cable sheath to expose the external conductor, and press that part against the earth plate with the cable clamp. If the cable is thin, clamp several cables in a bunch. The clamp comes as a set with the earth plate.



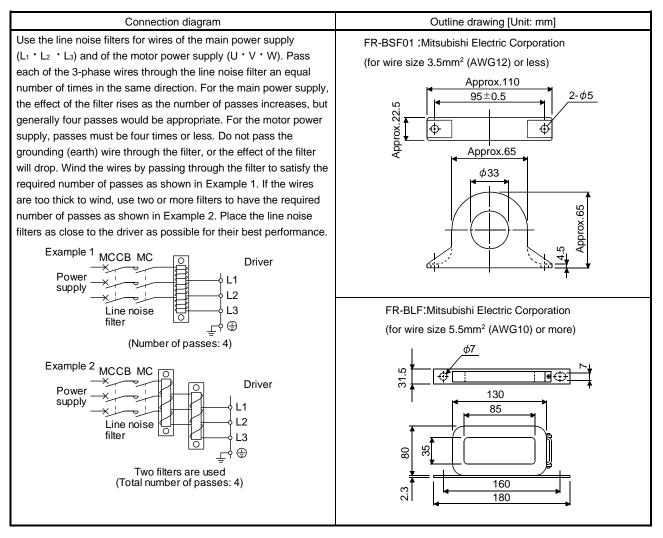
Dimensions



Note. Screw hole for grounding. Connect it to the grounding plate of the cabinet.

Model	А	В	С	Accessory fittings	Clamp fitting	L
AERSBAN-DSET	100	86	30	Clamp A: 2 pcs.	А	70
AERSBAN-ESET	70	56		Clamp B: 1 pc.	В	45

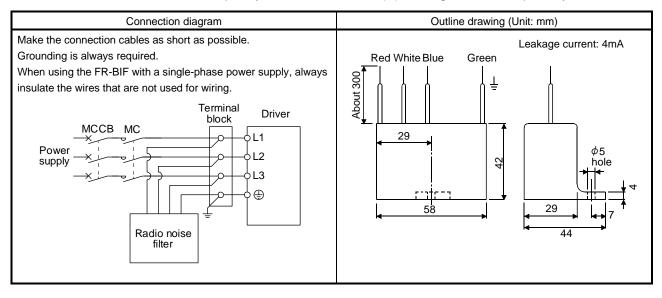
(d) Line noise filter (FR-BSF01, FR-BLF:Mitsubishi Electric Corporation) This filter is effective in suppressing noises radiated from the power supply side and output side of the driver and also in suppressing high-frequency leakage current (zero-phase current) especially within 0.5MHz to 5MHz band.





(e) Radio noise filter (FR-BIF-(H):Mitsubishi Electric Corporation)

This filter is effective in suppressing noises radiated from the power supply side of the driver especially in 10MHz and lower radio frequency bands. The FR-BIF-(H) is designed for the input only.



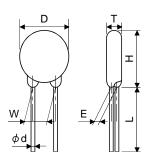


(f) Varistors for input power supply (Recommended)

Varistors are effective to prevent exogenous noise and lightning surge from entering the driver. When using a varistor, connect it between each phase of the input power supply of the equipment. For varistors, the TND20V-431K, TND20V-471K and TND20V-102K, manufactured by NIPPON CHEMI-CON, are recommended. For detailed specification and usage of the varistors, refer to the manufacturer catalog.

			Maximum rating						Static	Variator valtaga
Power supply voltage	Varistor	Permissik volta		Surge current immunity	Energy immunity	Rated pulse power	Maximu volt		capacity (reference value)	Varistor voltage rating (range) V1mA
		AC[Vrms]	DC[V]	8/20µs[A]	2ms[J]	[W]	[A]	[V]	[pF]	[V]
2001/ alasa	TND20V-431K	275	350	10000/1 time	195	4.0	100	710	1300	430(387 to 473)
200V class	TND20V-471K	300	385	7000/2 time	215	1.0	100	775	1200	470(423 to 517)

[Unit: mm]



D	Н	Т	Е	(Note)L	φd	W
Max.	Max.	Max.	±1.0	min.	±0.05	±1.0
01 5	04 E	6.4	3.3	20	0.8	10.0
21.5	1.0 24.5	6.6	3.5			
22.5	25.5	9.5	6.4			
	Max. 21.5	Max. Max. 21.5 24.5	Max. Max. Max. 21.5 24.5 6.4 6.6 6.6 6.6	$\begin{array}{c ccccccccccccccccccccccccccccccccccc$	Max. Max. Max. ±1.0 min. 21.5 24.5 6.4 3.3 20	$\begin{array}{c ccccccccccccccccccccccccccccccccccc$

Note. For special purpose items for lead length (L), contact the manufacturer.



13.7 Leakage current breaker

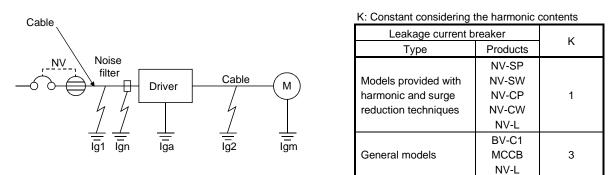
(1) Selection method

High-frequency chopper currents controlled by pulse width modulation flow in the AC servo circuits. Leakage currents containing harmonic contents are larger than those of the motor which is run with a commercial power supply.

Select a leakage current breaker according to the following formula, and ground the driver, servo motor, etc. securely.

Make the input and output cables as short as possible, and also make the grounding cable as long as possible (about 30cm) to minimize leakage currents.

Rated sensitivity current \geq 10 · {Ig1+Ign+Iga+K · (Ig2+Igm)} [mA] (14.1)



Ig1: Leakage current on the electric channel from the leakage current breaker to the input terminals of the driver (Found from Fig. 13.4.)

Ig2: Leakage current on the electric channel from the output terminals of the driver to the servo motor (Found from Fig. 13.4.)

- Ign: Leakage current when a filter is connected to the input side (4.4mA per one FR-BIF-(H) :Mitsubishi Electric Corporation)
- Iga: Leakage current of the driver (Found from Table 13.5.)
- Igm: Leakage current of the servo motor (Found from Table 13.4.)

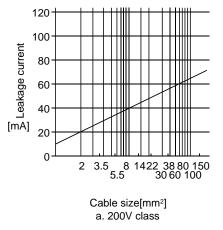


Fig. 13.4 Leakage current example (Ig1, Ig2) for CV cable run in metal conduit



Table 13.4 Servo motor's leakage current example (Igm)

Servo motor output [kW]	Leakage current [mA]
100 / 200 / 400 / 750	0.1

Table 13.5 Driver's leakage current example (Iga)

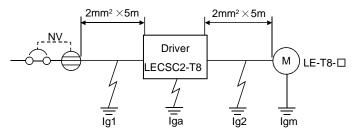
Driver capacity [kW]	Driver capacity [kW]
100 / 200 / 400	0.1
750	0.15

Table 13.6 Leakage circuit breaker selection example

Driver	Driver		
LECSC2-T	15		

(2) Selection example

Indicated below is an example of selecting a leakage current breaker under the following conditions.



Use a leakage current breaker generally available. Find the terms of Equation (13.1) from the diagram.

$$Ig1 = 20 \cdot \frac{5}{1000} = 0.1 \text{ [mA]}$$
$$Ig2 = 20 \cdot \frac{5}{1000} = 0.1 \text{ [mA]}$$

Ign = 0 (not used)

Iga = 0.1 [mA]

Igm = 0.1 [mA]

Insert these values in Equation (13.1).

 $\begin{array}{l} Ig \geq 10 \cdot \{0.1 + 0 + 0.1 + 1 \cdot (0.1 + 0.1)\} \\ \geq & 4.0 \ [mA] \\ \geq & \end{array}$

According to the result of calculation, use a leakage current breaker having the rated sensitivity current (Ig) of 4.0[mA] or more. A leakage current breaker having Ig of 15[mA] is used with the NV-SP/SW/CP/CW/HW series.



13.8 EMC filter (recommended)

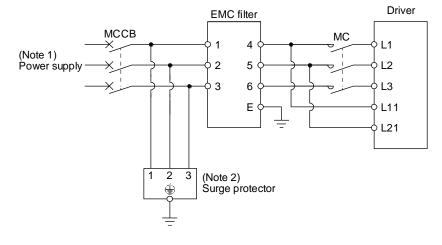
For compliance with the EMC directive of the EN Standard, it is recommended to use the following filter. Some EMC filters are large in leakage current.

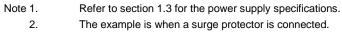
(1) Combination with the driver

Con (o omplifier		Maga [kg]			
Servo amplifier	Model	Rated current [A]	Rated voltage [VAC]	Leakage current [mA]	Mass [kg]
LECSC2-T	HF3010A-UN (Note)	10	250	5	3.5

Note. To use any of these EMC filters, the surge protector RSPD-500-U4 (Okaya Electric Industries) is required.

(2) Connection example



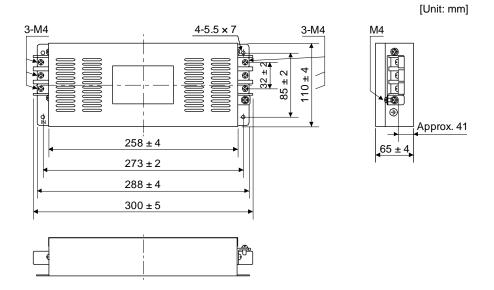


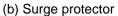


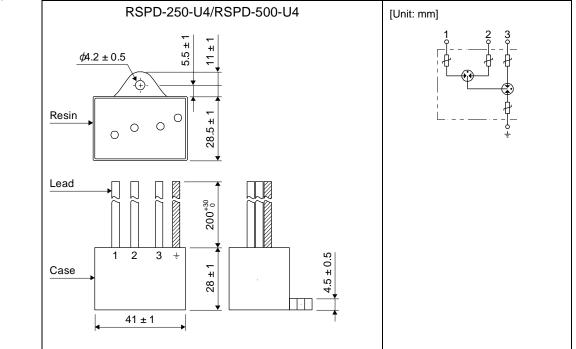
(3) Outline drawing

(a) EMC filter

HF3010A-UN







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14. COMMUNICATION FUNCTION

	The CN3 connector is designed for RS-422/RS-485 communication and parameter unit only. Do not connect the CN3 connector to an Ethernet port, etc. Doing so may cause a malfunction.
--	---

POINT

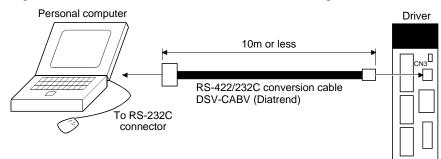
The USB communication function (CN5 connector) and the RS-422 communication function (CN3 connector) are mutually exclusive functions. They cannot be used together.

Using the serial communication function of RS-422, this driver enables servo operation, parameter change, monitor function, etc.

14.1 Configuration

(1) Single axis

Operate the single-axis driver. It is recommended to use the following cable.

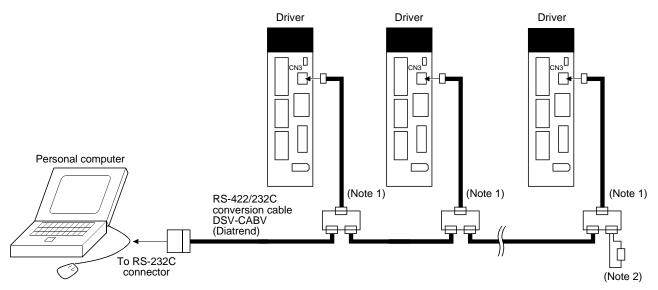




(2) Multidrop connection

(a) Diagrammatic sketch

Up to 32 axes of drivers from stations 0 to 31 can be operated on the same bus.



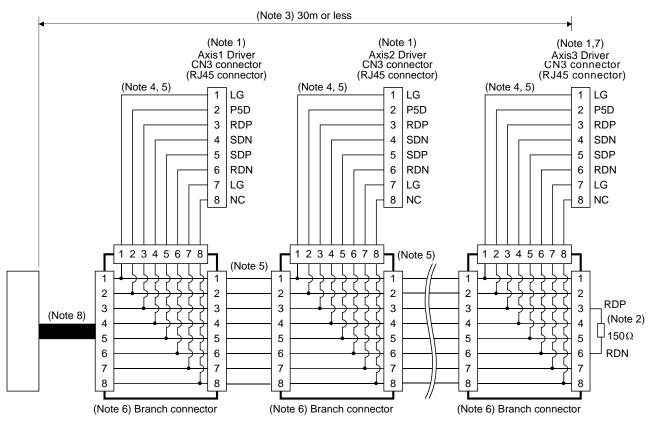
Note 1. The BMJ-8 (Hakko Electric Machine Works) is recommended as the branch connector.

2. The final axis must be terminated between RDP (pin No.3) and RDN (pin No.6) on the receiving side (driver) with a 150Ω resistor.



(b) Cable connection diagram

Wire the cables as shown below.



Note 1. Recommended connector (Hirose Electric)

Plug: TM10P-88P

Connection tool: CL250-0228-1

- 2. The final axis must be terminated between RDP (pin No.3) and RDN (pin No.6) on the receiving side (driver) with a 150Ω resistor.
- 3. The overall length is 30m or less in low-noise environment.
- 4. The wiring between the branch connector and driver should be as short as possible.
- 5. Use the EIA568-compliant cable (10BASE-T cable, etc.).
- 6. Recommended branch connector: BMJ-8 (Hakko Electric Machine Works)
- 7. $n \leq$ 32 (Up to 32 axes can be connected.)
- 8. RS-422/232C conversion cable DSV-CABV (Diatrend).

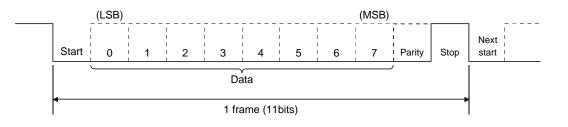


14.2 Communication specifications

14.2.1 Communication overview

This driver is designed to send a reply on receipt of an instruction. The device which gives this instruction (e.g. personal computer) is called a master station and the device which sends a reply in response to the instruction (driver) is called a slave station. When fetching data successively, the master station repeatedly commands the slave station to send data.

Item		Description							
Baud rate	9600/19200/3	0600/19200/38400/57600/115200 asynchronous system							
	Start bit	: 1 bit							
Transformered	Data bit	: 8 bits							
Transfer code	Parity bit	: 1 bit (even)							
	Stop bit	: 1 bit							
Transfer protocol	Character sys	Character system, half-duplex communication system							





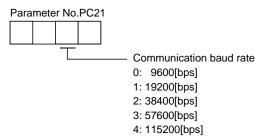
14.2.2 Parameter setting

When the USB/RS-422 communication function is used to operate the driver, set the communication specifications of the driver in the corresponding parameters.

After setting the values of these parameters, they are made valid by switching power off once, then on again.

(1) Serial communication baud rate

Choose the communication speed. Match this value to the communication speed of the sending end (master station).



(2) RS-422 communication response delay time

Set the time from when the driver (slave station) receives communication data to when it sends back data. Set "0" to send back data in less than $800\mu s$ or "1" to send back data in $800\mu s$ or more.



RS-422 communication response delay time
 0: Invalid
 1: Valid, reply sent in 800µs or more

(3) Station number setting

Set the station number of the driver in parameter No.PC20. The setting range is station 0 to 31.



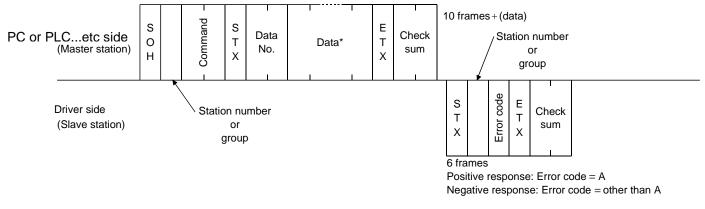
14.3 Protocol

14.3.1 Transmission data configuration

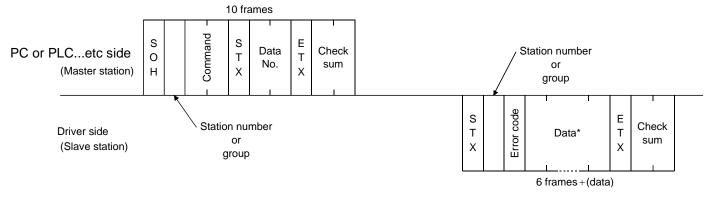
Since up to 32 axes may be connected to the bus, add a station number or group to the command, data No., etc. to determine the destination driver of data communication. Set the station number to each driver using the parameter and set the group to each station using the communication command. Transmission data is valid for the driver of the specified station number or group.

When "*" is set as the station number added to the transmission data, the transmission data is made valid for all drivers connected. However, when return data is required from the driver in response to the transmission data, set "0" to the station number of the driver which must provide the return data.

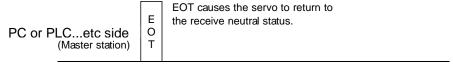
(1) Transmission of data from the PC or PLC...etc to the driver



(2) Transmission of data request from the PC or PLC...etc to the driver



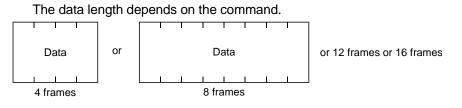
(3) Recovery of communication status by time-out



Driver side (Slave station)



(4) Data frames



14 - 8

14.3.2 Character codes

(1) Control codes

Code name	Hexadecimal (ASCII code)	Description	Personal computer terminal key operation (General)
SOH	01H	start of head	ctrl + A
STX	02H	start of text	ctrl + B
ETX	03H	end of text	ctrl + C
EOT	04H	end of transmission	ctrl + D

(2) Codes for data

ASCII codes are used.

 \longrightarrow
 \longrightarrow
 \longrightarrow
 \longrightarrow
-

b8	0	0	0	0	0	0	0	0
b7	0	0	0	0	1	1	1	1
b6	0	0	1	1	0	0	1	1
b5	0	1	0	1	0	1	0	1

b ₈ to b ₅	b4	b3	b2	b1
	0	0	0	0
	0	0	0	1
	0	0	1	0
	0	0	1	1
	0	1	0	0
	0	1	0	1
	0	1	1	0
	0	1	1	1
	1	0	0	0
	1	0	0	1
	1	0	1	0
	1	0	1	1
	1	1	0	0
	1	1	0	1
	1	1	1	0
	1	1	1	1

C R	0	1	2	3	4	5	6	7
0	NUL	DLE	Space	0	@	Ρ	•	р
1	SOH	DC1	!	1	А	Q	а	q
2	STX	DC ₂	"	2	В	R	b	r
3	ETX	DC ₃	#	3	С	S	с	S
4			\$	4	D	Т	d	t
5			%	5	ш	J	¢	u
6			&	6	F	V	f	v
7			"	7	G	W	g	w
8			(8	Н	Х	h	х
9)	9	Ι	Υ	i	у
10			*	•••	J	Ζ	j	Z
11			+	•,	к	[k	{
12			,	۷	Ц	¥	—	
13			-	Ш	М]	m	}
14				>	Ν	^	n	-
15			/	?	0	_	0	DEL

(3) Station numbers

You may set 32 station numbers from station 0 to station 31 and the ASCII unit codes are used to specify the stations.

Station number	0	1	2	3	4	5	6	7	8	9	10	11	12	13	14	15
ASCII code	0	1	2	3	4	5	6	7	8	9	А	В	С	D	Е	F

Station number	16	17	18	19	20	21	22	23	24	25	26	27	28	29	30	31
ASCII code	G	Н	Ι	J	К	L	М	Ν	0	Ρ	Q	R	S	Т	U	V

For example, "30H" is transmitted in hexadecimal for the station number of "0" (axis 1).

(4) Group

Group	а	b	С	d	e	f	All group
ASCII code	а	b	С	d	е	f	*

For example, "61H" is transmitted in hexadecimal for group a.



14.3.3 Error codes

Error codes are used in the following cases and an error code of single-code length is transmitted.

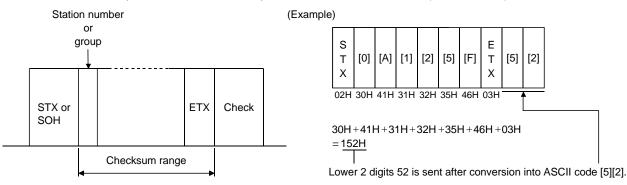
On receipt of data from the master station, the slave station sends the error code corresponding to that data to the master station.

The error code sent in upper case indicates that the driver is normal and the one in lower case indicates that an alarm occurred.

Error	code	Error name	Description	Remarks			
Driver normal	Driver alarm	Error name	Description	Remarks			
[A]	[a]	Normal operation	Data transmitted was processed properly.	Positive response			
[B]	[b]	Parity error	Parity error occurred in the transmitted data.				
[C]	[c]	Checksum error	Checksum error occurred in the transmitted data.				
[D]	[d]	Character error	Character not existing in the specifications was				
[5]	[G]		transmitted.				
[E]	[e]	Command error	Command not existing in the specifications was	Negative response			
[-]	[6]	Command entor	transmitted.				
[F]	[f]	Data No. error	Data No. not existing in the specifications was				
[1]	נין	Data No. enoi	transmitted.				

14.3.4 Checksum

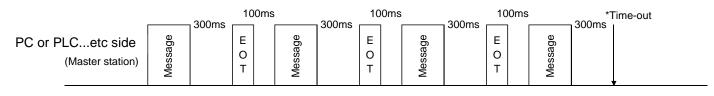
The checksum is a ASCII-coded hexadecimal representing the lower two digits of the sum of ASCII-coded hexadecimal numbers up to ETX, with the exception of the first control code (STX or SOH).





14.3.5 Time-out operation

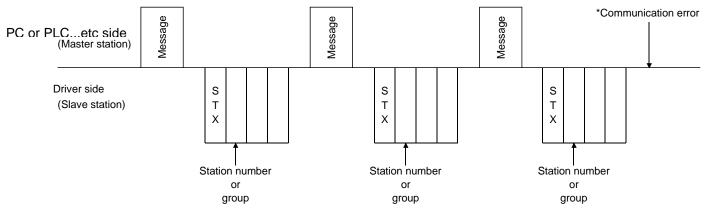
The master station transmits EOT when the slave station does not start reply operation (STX is not received) 300ms after the master station has ended communication operation. 100ms after that, the master station retransmits the message. Time-out occurs if the slave station does not answer after the master station has performed the above operation three times. (Communication error)



Driver side (Slave station)

14.3.6 Retry operation

When a fault occurs in communication between the master and slave stations, the error code in the response data from the slave station is a negative response code ([B] to [F], [b] to [f]). In this case, the master station retransmits the message which was sent at the occurrence of the fault (Retry operation). A communication error occurs if the above operation is repeated and results in the error three or more consecutive times.



Similarly, when the master station detects a fault (e.g. checksum, parity) in the response data from the slave station, the master station retransmits the message which was sent at the occurrence of the fault. A communication error occurs if the retry operation is performed three times.



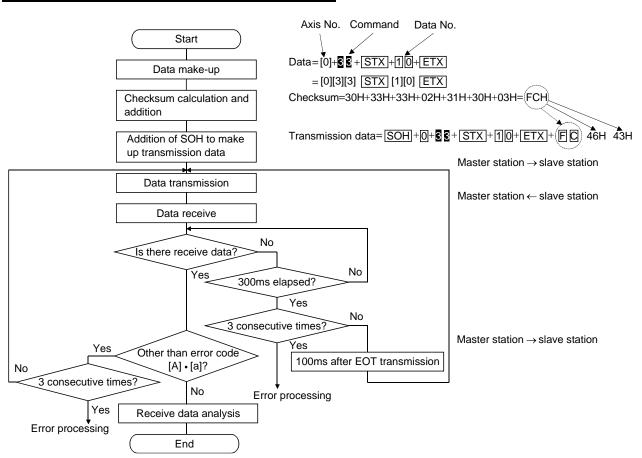
14.3.7 Initialization

After the slave station is switched on, it cannot reply to communication until the internal initialization processing terminates. Hence, at power-on, ordinary communication should be started after.

- (1) 1s or more time has elapsed after the slave station is switched on; and
- (2) Making sure that normal communication can be made by reading the parameter or other data which does not pose any safety problems.
- 14.3.8 Communication procedure example

The following example reads the set value of alarm history (last alarm) from the driver of station 0.

Data item	Value	Description
Station number	0	Driver station 0
Command	33	Read command
Data No.	10	Alarm history (last alarm)



14.4 Command and data No. list

POINT	
 If the con 	mmand and data No. are the same, the description may be different
dependin	g on models of drivers.

14.4.1 Read commands

(1)) Status display	(Command	[0][1])
-----	------------------	----------	---------

Command	Data No.	Description	Display item	Frame length
[0] [1]	[0] [0]	Status display name and unit	Current position	16
	[0] [1]		Command position	
	[0] [2]		Command remaining distance	
	[0] [3]		Point table No.	
	[0] [4]		Cumulative feedback pulses	
	[0] [5]		Driver motor speed	
	[0] [6]		Droop pulses	
	[0] [7]			
	[0] [8]			
	[0] [9]			
	[0] [A]		Regenerative load ratio	
	[0] [B]		Effective load ratio	
	[0] [C]		Peak load ratio	
	[0] [D]	-	Instantaneous torque	
	[0] [E]		Within one-revolution position	
	[0] [F]		ABS counter	
	[1] [0]		Load inertia moment ratio	
	[1][1]		Bus voltage	
	[8] [0]	Status display data value and	Current position	12
	[8] [1]	processing information	Command position	
	[8] [2]		Command remaining distance	
	[8] [3]		Point table No.	
	[8] [4]		Cumulative feedback pulses	
	[8] [5]		Servo motor speed	-
	[8] [6]		Droop pulses	
	[8] [7]			
	[8] [8]	-		
	[8] [9]	-		
	[8] [A]		Regenerative load ratio	
	[8] [B]	-	Effective load ratio	
	[8] [C]]	Peak load ratio	
	[8] [D]]	Instantaneous torque	-
	[8] [E]	1	Within one-revolution position	
	[8] [F]]	ABS counter	
	[9] [0]]	Load inertia moment ratio	
	[9] [1]	1	Bus voltage	1



(2) Parameters (Command [0][4] • [0][5] • [0][6] • [0][7] • [0][8] • [0][9])

Command	Data No.	Description	Frame length
[0] [4]	[0] [1]	Parameter group read 0000: Basic setting parameter (No.PA _) 0001: Gain filter parameter (No.PB _) 0002: Extension setting parameter (No.PC _) 0003: I/O setting parameter (No.PD _)	4
[0] [5]	[0] [1] to [F] [F]	Current values of parameters Reads the current values of the parameters in the parameter group specified with the command [8][5] + data No. [0][0]. Before reading the current values, therefore, always specify the parameter group with the command [8][5] + data No. [0][0]. The decimal equivalent of the data No. value (hexadecimal) corresponds to the parameter number.	8
[0] [6]	[0] [1] to [F] [F]	Upper limit values of parameter setting ranges Reads the permissible upper limit values of the parameters in the parameter group specified with the command [8][5] + data No. [0][0]. Before reading the upper limit values, therefore, always specify the parameter group with the command [8][5] + data No. [0][0]. The decimal equivalent of the data No. value (hexadecimal) corresponds to the parameter number.	8
[0] [7]	[0] [1] to [F] [F]	Lower limit values of parameter setting ranges Reads the permissible lower limit values of the parameters in the parameter group specified with the command [8][5] + data No. [0][0]. Before reading the lower limit values, therefore, always specify the parameter group with the command [8][5] + data No. [0][0]. The decimal equivalent of the data No. value (hexadecimal) corresponds to the parameter number.	8
[0] [8]	[0] [1] to [F] [F]	Abbreviations of parameters Reads the abbreviations of the parameters in the parameter group specified with the command [8][5] + data No. [0][0]. Before reading the abbreviations, therefore, always specify the parameter group with the command [8][5] + data No. [0][0]. The decimal equivalent of the data No. value (hexadecimal) corresponds to the parameter number.	12
[0] [9]	[0] [1] to [F] [F]	Write enable/disable of parameters Reads write enable/disable of the parameters in the parameter group specified with the command [8][5] + data No. [0][0]. Before reading write enable/disable, therefore, always specify the parameter group with the command [8][5] + data No. [0][0]. 0000: Write enabled 0001: Write disabled	4

(3) External I/O signals (Command [1][2])

Command	Data No.	Description	Frame length
[1] [2]	[1] [2] [0] [0] Input device status		8
	[0] [1]		
	[4] [0]	External input pin status	
	[6] [0]		
	[6] [1]	Status of input device turned ON by communication	
	[8] [0]		
	[8] [1]	Output device status	
	[C] [0]	External output pin status	

Command	Data No.	Description	Alarm occurrence sequence	Frame length
[3] [3]	[1] [0]	Alarm number in alarm history	most recent alarm	4
	[1] [1]		first alarm in past	
	[1] [2]		second alarm in past	
	[1] [3]		third alarm in past	
	[1] [4]		fourth alarm in past	
	[1] [5]		fifth alarm in past	
	[2] [0]	Alarm occurrence time in alarm history	most recent alarm	8
	[2] [1]		first alarm in past	
	[2] [2]		second alarm in past	
	[2] [3]		third alarm in past	
	[2] [4]		fourth alarm in past	
	[2] [5]		fifth alarm in past	

(4) Alarm history (Command [3][3])

(5) Current alarm (Command [0][2], [3][5])

Command	Data No.		Description	Frame length
[0] [2]	[0][0]	Current alarm number		4
[3] [5]	[0][0]	Status display name and unit at	Current position	16
	[0][1]	alarm occurrence	Command position	
	[0][2]		Command remaining distance	
	[0][3]		Point table No.	
	[0][4]		Cumulative feedback pulses	
	[0][5]		Servo motor speed	
	[0][6]		Droop pulses	
	[0][7]			
	[0][8]			
	[0][9]			
	[0][A]		Regenerative load ratio	
	[0][B]		Effective load ratio	
	[0][C]		Peak load ratio	
	[0][D]		Instantaneous torque	
	[0][E]		Within one-revolution position	
	[0][F]		ABS counter	
	[1][0]		Load inertia moment ratio	
	[1][1]		Bus voltage	
	[0][0]	Status display data value and	Current position	12
	[0][1]	occurrence C	Command position	
	[0][2]		Command remaining distance	
	[0][3]		Point table No.	
	[0][4]		Cumulative feedback pulses	
	[0][5]		Servo motor speed	
	[0][6]		Droop pulses	
	[0][7]			
	[0][8]			
	[0][9]			
	[0][A]		Regenerative load ratio	
	[0][B]		Effective load ratio	
	[0][C]		Peak load ratio	
	[0][D]		Instantaneous torque	
	[0][E]		Within one-revolution position	
	[0][F]		ABS counter	
	[1][0]		Load inertia moment ratio	
	[1][1]]	Bus voltage	



(6) Point table/position data (Command [4][0])

Command	Data No.	Description	Frame length
[4][0]	[0][1] to [F][F]	Position data read	8
		The decimal equivalent of the data No. value (hexadecimal) corresponds to the Point	
		table No.	

(7) Point table/speed data (Command [5][0])

Command	Data No.	Description	Frame length
[5][0]	[0][1] to [F][F]	Speed data read	8
		The decimal equivalent of the data No. value (hexadecimal) corresponds to the Point	
		table No.	

(8) Point table/acceleration time constant (Command [5][4])

Command	Data No.	Description	Frame length
[5][4]	[0][1] to [F][F]	Acceleration time constant read	8
		The decimal equivalent of the data No. value (hexadecimal) corresponds to the Point	
		table No.	

(9) Point table/deceleration time constant (Command [5][8])

Command	Data No.	Description	Frame length
[5][8]	[0][1] to [F][F]	Deceleration time constant read	8
		The decimal equivalent of the data No. value (hexadecimal) corresponds to the Point	
		table No.	

(10) Point table/dwell (Command [6][0])

Command	Data No.	Description	Frame length
[6][0]	[0][1] to [F][F]	Dwell read	8
		The decimal equivalent of the data No. value (hexadecimal) corresponds to the Point	
		table No.	

(11) Point table/auxiliary function (Command [6][4])

Command	Data No.	Description	Frame length
[6][4]	[0][1] to [F][F]	Auxiliary function read	8
		The decimal equivalent of the data No. value (hexadecimal) corresponds to the Point	
		table No.	

(12) Group setting (Command [1][F])

Command	Data No.	Description	Frame length
[1][F]	[0][0]	Reading of group setting value	4

(13) Test operation mode (Command [0][0])

Command	Data No.	Description	Frame length
[0] [0]	[1] [2]	Test operation mode read	4
		0000: Normal mode (not test operation mode)	
		0001: JOG operation	
		0002: Positioning operation	
		0003: Motorless operation	
		0004: Output signal (DO) forced output	
		0005: Single-step feed	

(14) Others

Command	Data No.	Description	Frame length
[0] [2]	[9] [0]	Servo motor side pulse unit absolute position	8
	[9] [1]	Command unit absolute position	8
	[7] [0]	Software version	16

14.4.2 Write commands

(1) Status display (Command [8][1])

Command	Data No.	Description	Setting range	Frame length
[8] [1]	[0] [0]	Status display data erasure	1EA5	4

(2) Parameters (Command [8][4] • [8][5])

Command	Data No.	Description	Setting range	Frame length
[8] [4]	[0][1] to [F][F]	Write of parameters Writes the values of the parameters in the parameter group specified with the command [8][5] + data No. [0][0]. Before writing the values, therefore, always specify the parameter group with the command [8][5] + data No. [0][0]. The decimal equivalent of the data No. value (hexadecimal) corresponds to the parameter number.	Depending on the parameter	8
[8] [5]	[0] [0]	Parameter group write 0000: Basic setting parameter (No.PA	0000 to 0003	4

(3) External I/O signal (Command [9][2])

Command	Data No.	Description	Setting range	Frame length
[9] [2]	[6] [0]	Communication input device signal	Refer to section 14.5.5	8
	[6] [1]			

(4) Alarm history (Command [8][2])

Comman	Data No.	Description	Setting range	Frame length
[8] [2]	[2] [0]	Alarm history erasure	1EA5	4

(5) Current alarm (Command [8][2])

Command	Data No.	Description	Setting range	Frame length
[8] [2]	[0] [0]	Alarm erasure	1EA5	4

(6) Point table/position data (Command [C][0])

Command	Data No.	Description	Setting range	Frame length
[C][0]	[0][1] to [F][F]	Position data write	-9999999 to 999999	8
		The decimal equivalent of the data No. value		
		(hexadecimal) corresponds to the Point table No.		



(7) Point table/speed data (Command [C][6])

Command	Data No.	Description	Setting range	Frame length
[C][6]	[0][1] to [F][F]	Speed data write	0 to Permissible	8
		The decimal equivalent of the data No. value	instantaneous speed	
		(hexadecimal) corresponds to the Point table No.		

(8) Point table/acceleration time constant (Command [C][7])

Command	Data No.	Description	Setting range	Frame length
[C][7]	[0][1] to [F][F]	Acceleration time constant write	0 to 20000	8
		The decimal equivalent of the data No. value		
		(hexadecimal) corresponds to the Point table No.		

(9) Point table/deceleration time constant (Command [C][8])

Command	Data No.	Description	Setting range	Frame length
[C][8]	[0][1] to [F][F]	Deceleration time constant write	0 to 20000	8
		The decimal equivalent of the data No. value		
		(hexadecimal) corresponds to the Point table No.		

(10) Point table/dwell (Command [C][A])

Command	Data No.	Description	Setting range	Frame length
[C][A]	[0][1] to [F][F]	Dwell write	0 to 20000	8
		The decimal equivalent of the data No. value		
		(hexadecimal) corresponds to the Point table No.		

(11) Point table/auxiliary function (Command [C][B])

Command	Data No.	Description	Setting range	Frame length
[C][B]	[0][1] to [F][F]	Auxiliary function write	0 to 3	8
		The decimal equivalent of the data No. value		
		(hexadecimal) corresponds to the Point table No.		

(12) External input signal disable (Command [9][0])

Command	Data No.	Description	Setting range	Frame length
[9][0]	[0][0]	Turns off the input devices, external analog input signals	1EA5	4
		and pulse train inputs with the exception of EMG, LSP and		
		LSN, independently of the external ON/OFF statuses.		
[9][0]	[0][3]	Disables all output devices (DO).	1EA5	4
[9][0]	[1][0]	Enables the disabled input devices (DI), external analog	1EA5	4
		input signals and pulse train inputs with the exception of		
		EMG, LSP and LSN.		
[9][0]	[1][3]	Enables the disabled output devices (DO).	1EA5	4



Command	Data No.	Description	Setting range	Frame length
[8] [B]	[0] [0]	Operation mode switching	0000 to 0005	4
		0000: Test operation mode cancel		
		0001: JOG operation		
		0002: Positioning operation		
		0003: Motorless operation		
		0004: Output signal (DO) forced output		
		0005: Single-step feed		

(13) Operation mode selection (Command [8][B])

(14) Test operation mode data (Command [9][2] · [A][0])

Command	Data No.	Description	Setting range	Frame length
[9] [2]	[0] [0]	Input signal for test operation	Refer to section 14.5.7.	8
	[0] [1]			
	[A] [0]	Forced output of signal pin	Refer to section 14.5.9.	8
[A] [0]	[1] [0]	Writes the speed in the test operation mode (JOG operation, positioning operation).	0000 to 7FFF	4
	[1] [1]	Writes the acceleration/deceleration time constant in the test operation mode (JOG operation, positioning operation).	00000000 to 7FFFFFF	8
	[2] [0]	Sets the moving distance in the test operation mode (JOG operation, positioning operation).	00000000 to 7FFFFFF	8
	[2] [1]	Selects the positioning direction of test operation (positioning operation). OOOO OOO OOO OOO OOO OOOOOOOOOOOOOOO	0000 to 0001	4
	[4] [0]	Test operation (positioning operation) start command.	1EA5	4
	[4] [1]	Used to make a temporary stop during test operation (positioning operation). □ in the data indicates a blank. STOP: Temporary stop G0 □ □: Restart for remaining distance CLR □: Remaining distance clear.	STOP G0 CLR	4

(15) Group setting (Command [9][F])

Command	Data No.	Description	Setting range	Frame length
[9] [F]	[0] [0]	Setting of group	a to f	4

14.5 Detailed explanations of commands

14.5.1 Data processing

When the master station transmits a command + data No. or a command + data No. + data to a slave station, the driver returns a reply or data according to the purpose.

When numerical values are represented in these send data and receive data, they are represented in decimal, hexadecimal, etc.

Therefore, data must be processed according to the application.

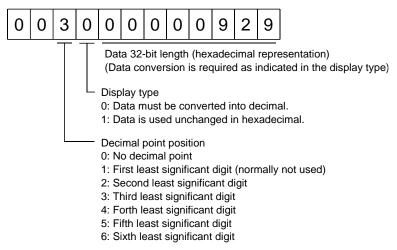
Since whether data must be processed or not and how to process data depend on the monitoring, parameters, etc., follow the detailed explanation of the corresponding command.

The following methods are how to process send and receive data when reading and writing data.

(1) Processing the read data

When the display type is 0, the eight-character data is converted from hexadecimal to decimal and a decimal point is placed according to the decimal point position information. When the display type is 1, the eight-character data is used unchanged.

The following example indicates how to process the receive data "003000000929" given to show. The receive data is as follows.



Since the display type is "0" in this case, the hexadecimal data is converted into decimal. 00000929H \rightarrow 2345

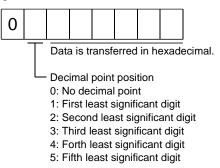
As the decimal point position is "3", a decimal point is placed in the third least significant digit. Hence, "23.45" is displayed.



(2) Writing the processed data

When the data to be written is handled as decimal, the decimal point position must be specified. If it is not specified, the data cannot be written. When the data is handled as hexadecimal, specify "0" as the decimal point position.

The data to be sent is the following value.



By way of example, here is described how to process the set data when a value of "15.5" is sent. Since the decimal point position is the second digit, the decimal point position data is "2". As the data to be sent is hexadecimal, the decimal data is converted into hexadecimal. $155\rightarrow 9B$

Hence, "0200009B" is transmitted.



14.5.2 Status display

(1) Reading the status display name and unit

Read the status display name and unit.

(a) Transmission

Transmit command [0][1] and the data No. corresponding to the status display item to be read, [0][0] to [0][E]. (Refer to section 14.4.1.)

(b) Reply

The slave station sends back the status display name and unit requested.

0	0													
		Unit	chara	octers	s (5 d	ligits)	N	lame	char	acte	rs (9	digits	5)	

(2) Status display data read

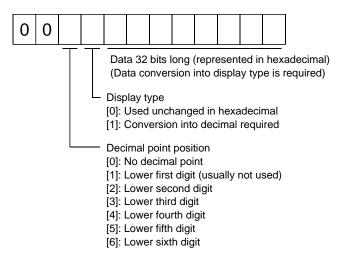
Read the status display data and processing information.

(a) Transmission

Transmit command [0][1] and the data No. corresponding to the status display item to be read. Refer to section 14.4.1.

(b) Reply

The slave station sends back the status display data requested.



(3) Status display data clear

The cumulative feedback pulse data of the status display is cleared. Send this command immediately after reading the status display item. The data of the status display item transmitted is cleared to zero.

Command	Data No.	Data
[8][1]	[0][0]	[1][E][A][5]

For example, after sending command [0][1] and data No. [8][0] and receiving the status display data, send command [8][1], data No. [0][0] and data [1EA5] to clear the cumulative feedback pulse value to zero.



14.5.3 Parameters

(1) Specify the parameter group

The group of the parameters to be operated must be specified in advance to read or write the parameter settings, etc. Write data to the driver as described below to specify the parameter group to be operated.

Command	Data No.	Transmission data	Parameter group	
[8] [5]	[0] [0]	0000	Basic setting parameter (No.PA)	
		0001	Gain filter parameter (No.PB 🗆 🗆)	
		0002	Extension setting parameter (No.PC)	
		0003	I/O setting parameter (No.PD□ □)	

(2) Reading the parameter group

Read the parameter group.

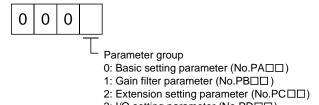
(a) Transmission

Send command [0][4] and data No.[0][1].

Command	Data No.
[0] [4]	[0] [1]

(b) Reply

The slave station sends back the preset parameter group.



3: I/O setting parameter (No.PD□□)

(3) Reading the symbol

Read the parameter name. Specify the parameter group in advance (refer to (1) in this section).

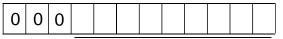
(a) Transmission

Transmit command [0][8] and the data No. corresponding to the parameter No., [0][0] to [F][F]. (Refer to section 14.4.1.)

The data No. is expressed in hexadecimal. The decimal equivalent of the data No. value corresponds to the parameter number.

(b) Reply

The slave station sends back the name of the parameter No. requested.



Name characters (9 digits)



(4) Reading the setting

Read the parameter setting. Specify the parameter group in advance (refer to (1) in this section).

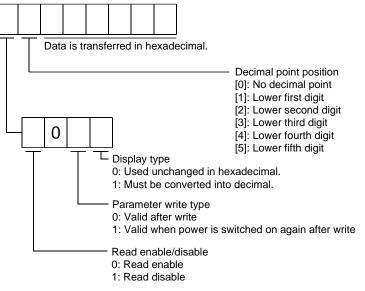
(a) Transmission

Transmit command [0][5] and the data No. corresponding to the parameter No., [0][0] to [F][F]. (Refer to section 14.4.1.)

The data No. is expressed in hexadecimal. The decimal equivalent of the data No. value corresponds to the parameter number.

(b) Reply

The slave station sends back the data and processing information of the parameter No. requested.



For example, data "1200270F" means 999.9 (decimal display format) and data "0003ABC" means 3ABC (hexadecimal display format).

When the display type is "0" (hexadecimal) and the decimal point position is other than 0, the display type is a special hexadecimal display format and "F" of the data value is handled as a blank. Data "01FFF053" means 053 (special hexadecimal display format).

"1 (Read disable)" is transferred to the "Read enable/disable" section and "000000" is transferred to the data section when the parameter that was read is the one inaccessible for write/reference in the parameter write disable setting of parameter No.PA19.

(5) Reading the setting range

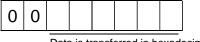
Read the parameter setting range. Specify the parameter group in advance (refer to (1) in this section). (a) Transmission

When reading the upper limit value, transmit command [0][6] and the data No. corresponding to the parameter No., [0][0] to [F][F]. When reading the lower limit value, transmit command [0][7] and the data

No. corresponding to the parameter No., [0][0] to [F][F]. (Refer to section 15.4.1.) The data No. is expressed in hexadecimal. The decimal equivalent of the data No. value corresponds to the parameter number.

(b) Reply

The slave station sends back the data and processing information of the parameter No. requested.



Data is transferred in hexadecimal.

For example, data "10FFFFEC" means -20.



(6) Parameter write

POINT

 If setting values need to be changed with a high frequency (i.e. one time or more per one hour), write the setting values to the RAM, not the EEP-ROM. The EEP-ROM has a limitation in the number of write times and exceeding this limitation causes the driver to malfunction. Note that the number of write times to the EEP-ROM is limited to approximately 100, 000.

Write the parameter setting into EEP-ROM of the driver. Specify the parameter group in advance (refer to (1) in this section).

Write the value within the setting enabled range. For the setting enabled range, refer to chapter 6 or read the setting range by performing operation in (3) in this section.

Transmit command [8][4], the data No. , and the set data.

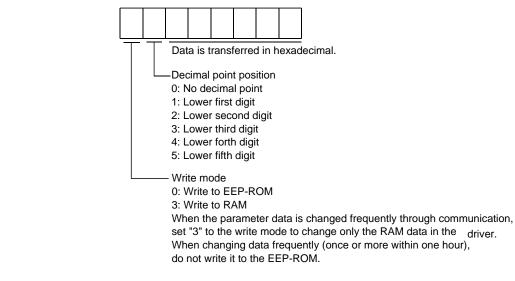
The data No. is expressed in hexadecimal. The decimal equivalent of the data No. value corresponds to the parameter number.

When the data to be written is handled as decimal, the decimal point position must be specified. If it is not specified, data cannot be written. When the data is handled as hexadecimal, specify 0 as the decimal point position.

Write the data after making sure that it is within the upper/lower limit value range.

Read the parameter data to be written, confirm the decimal point position, and create transmission data to prevent error occurrence. On completion of write, read the same parameter data to verify that data has been written correctly.

Command	Data No.	Set data
[8][4]	[0][1] to [F][F]	See below.





14.5.4 External I/O signal statuses (DIO diagnosis)

(1) Reading of input device statuses

Read the statuses of the input devices.

(a) Transmission

Transmit command [1][2] and the data No. corresponding to the input device.

Command	Data No.
[1][2]	[0][0]
	[0][1]

(b) Reply

The slave station sends back the statuses of the input pins.

b3	1 -	 	b1	bC)													
Γ																		1:ON
																		0:OFF

Command of each bit is transmitted to the master station as hexadecimal data.

h.14	Data No. [0][0]		Data No. [0][1]	
bit	Device name	Symbol	Device name	Symbol
0	Servo-on	SON	Ν	
1	Forward rotation stroke end	LSP	$ \rangle$	
2	Reverse rotation stroke end	LSN		
3		/		
4	Internal torque limit selection	TL1		
5	Proportion control	PC		
6	Reset	RES		
7	Clear	CR		
8				
9		\backslash		
10				
11	Forward rotation start	ST1		
12	Reverse rotation start	ST2		
13		\backslash		
14		\backslash		
15				
16		\backslash		
17	Automatic/manual selection	MD0		
18	Proximity dog	DOG		
19		\backslash		
20		\backslash		
21				
22		$ \land$		
23	Override selection	OVR	\	
24	Temporary stop/Restart	TSTP	Point table No. selection 1	DI0
25		\searrow	Point table No. selection 2	DI1
26			Point table No. selection 3	DI2
27	Gain changing	CDP	Point table No. selection 4	DI3
28		\backslash	Point table No. selection 5	DI4
29			Point table No. selection 6	DI5
30			Point table No. selection 7	DI6
31			Point table No. selection 8	DI7



(2) External input pin status read

Read the ON/OFF statuses of the external output pins.

(a) Transmission

Transmit command [1][2] and data No. [4][0].

Command	Data No.
[1][2]	[4][0]

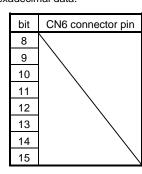
(b) Reply

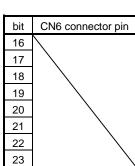
The ON/OFF statuses of the input pins are sent back.



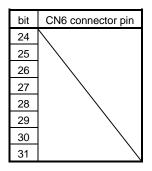
Command of each bit is transmitted to the master station as hexadecimal data.

bit	CN6 connector pin
0	1
1	2
2	3
3	4
4	
5	
6	
7	





0:OFF





(3) Read of the statuses of input devices switched on through communication

Read the ON/OFF statuses of the input devices switched on through communication. (a) Transmission

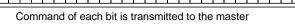
Transmit command [1][2] and the data No. corresponding to the input device.

Command	Data No.
[1][2]	[6][0]
	[6][1]

(b) Reply

The slave station sends back the statuses of the input pins.





station as hexadecimal data.

bit	Data No. [6][0]		Data No. [6][1]	
DIL	Device name	Symbol	Device name	Symbol
0	Servo-on	SON	Ν	
1	Forward rotation stroke end	LSP] \	
2	Reverse rotation stroke end	LSN		
3		/		1
4	Internal torque limit selection	TL1		
5	Proportion control	PC		
6	Reset	RES		
7	Clear	CR		
8		\setminus		
9				
10				
11	Forward rotation start	ST1		
12	Reverse rotation start	ST2		
13		\backslash		
14				
15				
16				
17	Automatic/manual selection	MD0		
18	Proximity dog	DOG		
19		\land		
20				
21				
22				
23	Override selection	OVR		
24	Temporary stop/Restart	TSTP	Point table No. selection 1	DI0
25		\searrow	Point table No. selection 2	DI1
26			Point table No. selection 3	DI2
27	Gain changing	CDP	Point table No. selection 4	DI3
28		\backslash	Point table No. selection 5	DI4
29			Point table No. selection 6	DI5
30			Point table No. selection 7	DI6
31			Point table No. selection 8	DI7



- (4) External output pin status read
 - Read the ON/OFF statuses of the external output pins.
 - (a) Transmission

Transmit command [1][2] and data No. [C][0].

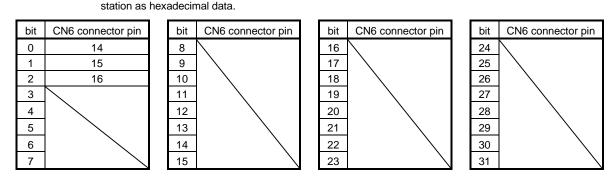
Command	Data No.
[1][2]	[C][0]

(b) Reply

The slave station sends back the ON/OFF statuses of the output pins.



Command of each bit is transmitted to the master





(5) Read of the statuses of output devices

Read the ON/OFF statuses of the output devices.

(a) Transmission

Transmit command [1][2] and the data No. corresponding to the output device.

Command	Data No.
[1][2]	[8][0]
	[8][1]

(b) Reply

The slave station sends back the statuses of the output devices.

b3	1 - •	 	b1	bC)													
																		1:ON
																		0:OFF

Command of each bit is transmitted to the master	
station as hexadecimal data.	

1.11	Data No. [8][0]		Data No. [8][1]	
bit	Device name	Symbol	Device name	Symbol
0	Ready	RD	Ν	
1		/	1\	
2	Zero speed	ZSP	1 \	1
3	Limiting torque	TLC		
4				
5	In position	INP		
6		/		
7	Warning	WNG		
8	Trouble	ALM		
9				
10	Electromagnetic brake interlock	MBR		
11	dynamic brake interlock	DB		
12		\mathbf{i}		
13				
14				
15	Battery warning	BWNG		
16	Rough match	CPO		
17	Home position return completion	ZP		
18	Position range output	POT		
19	Temporary stop	PUS		
20				
21		\backslash		
22				
23		\backslash		
24		\backslash	Point table No. output 1	PT0
25	Variable gain selection	CDPS	Point table No. output 2	PT1
26		\searrow	Point table No. output 3	PT2
27			Point table No. output 4	PT3
28	Movement completion	MEND	Point table No. output 5	PT4
29		\mathbf{i}	Point table No. output 6	PT5
30			Point table No. output 7	PT6
31			Point table No. output 8	PT7

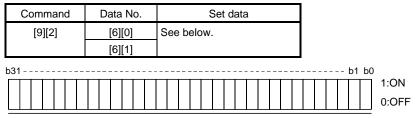


14.5.5 Device ON/OFF

POINT
 The ON/OFF states of all devices in the driver are the states of the data received last. Hence, when there is a device which must be kept ON, send data which turns that device ON every time.

Each input device can be switched on/off. However, when the device to be switched off exists in the external input signal, also switch off that input signal.

Send command [9][2], data No. corresponding to the input device and data.



Command of each bit is transmitted to the slave station as hexadecimal data.

bit	Data No. [6][0]		Data No. [6][1]	
DIL	Device name	Symbol	Device name	Symbol
0	Servo-on	SON	Ν	
1	Forward rotation stroke end	LSP		
2	Reverse rotation stroke end	LSN		
3		/		
4	Internal torque limit selection	TL1		
5	Proportion control	PC		
6	Reset	RES		
7	Clear	CR		
8		\mathbf{N}		
9				
10				
11	Forward rotation start	ST1		
12	Reverse rotation start	ST2		
13		\backslash		
14		\backslash		
15				
16			$\langle \rangle$	
17	Automatic/manual selection	MD0		
18	Proximity dog	DOG		
19		\backslash		
20		\backslash		
21				
22				
23	Override selection	OVR	\\	
24	Temporary stop/Restart	TSTP	Point table No. selection 1	DI0
25		$\left \right\rangle$	Point table No. selection 2	DI1
26			Point table No. selection 3	DI2
27	Gain changing	CDP	Point table No. selection 4	DI3
28		\backslash	Point table No. selection 5	DI4
29			Point table No. selection 6	DI5
30			Point table No. selection 7	DI6
31			Point table No. selection 8	DI7



14.5.6 Disable/enable of I/O devices (DIO)

Inputs can be disabled independently of the I/O devices ON/OFF. When inputs are disabled, the input signals (devices) are recognized as follows. Among the input devices, EMG, LSP and LSN cannot be disabled.

Signal	Status
Input devices (DI)	OFF

(1) Disabling/enabling the input devices (DI), external analog input signals and pulse train inputs with the exception of EMG, LSP and LSN.

Transmit the following communication commands.

(a) Disable

Command	Data No.	Data
[9][0]	[0][0]	1EA5

(b) Enable

Command	Data No.	Data
[9][0]	[1][0]	1EA5

(2) Disabling/enabling the output devices (DO) Transmit the following communication commands.

(a) Disable

Command	Data No.	Data
[9][0]	[0][3]	1EA5

(b) Enable

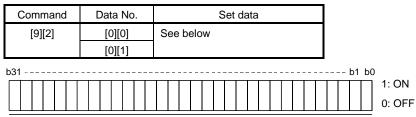
Command	Data No.	Data
[9][0]	[1][3]	1EA5



14.5.7 Input devices ON/OFF (test operation)

Each input devices can be turned on/off for test operation. when the device to be switched off exists in the external input signal, also switch off that input signal.

Send command [9] [2], data No. corresponding to the input device and data.



Command of each bit is transmitted to the slave station as hexadecimal data.

h.14	Data No. [0][0]		Data No. [0][1]	
bit	Device name	Symbol	Device name	Symbol
0	Servo-on	SON	Ν	
1	Forward rotation stroke end	LSP	$ \rangle$	
2	Reverse rotation stroke end	LSN		
3				
4	Internal torque limit selection	TL1		
5	Proportion control	PC		
6	Reset	RES		
7	Clear	CR		
8				
9		\mathbf{i}		
10		\backslash		
11	Forward rotation start	ST1		
12	Reverse rotation start	ST2		
13		\backslash		
14		\backslash		
15				
16		$ \land$		
17	Automatic/manual selection	MD0		
18	Proximity dog	DOG		
19		\backslash		
20		\backslash		
21				
22				
23	Override selection	OVR	\	
24	Temporary stop/Restart	TSTP	Point table No. selection 1	DI0
25		$\overline{}$	Point table No. selection 2	DI1
26			Point table No. selection 3	DI2
27	Gain changing	CDP	Point table No. selection 4	DI3
28		\backslash	Point table No. selection 5	DI4
29			Point table No. selection 6	DI5
30			Point table No. selection 7	DI6
31			Point table No. selection 8	DI7



14.5.8 Test operation mode

PC	INT

- The test operation mode is used to confirm operation. Do not use it for actual operation.
- If communication stops for longer than 0.5s during test operation, the driver decelerates to a stop, resulting in servo lock. To prevent this, continue communication all the time, e.g. monitor the status display.
- Even during operation, the driver can be put in the test operation mode.
- In this case, as soon as the test operation mode is selected, the base circuit is shut off, coasting the driver.

(1) Preparation and cancel of test operation mode

(a) Preparation of test operation mode

Set the test operation mode type in the following procedure.

Send the command [8][B] + data No. [0][0] to select the test operation mode.

Command	Data No.	Transmission Data	Test Operation Mode Selection
[8][B]	[0][0]	0001	JOG operation
		0002	Positioning operation
		0003	Motorless operation
		0004	DO forced output
		0005	Single-step feed

2) Confirmation of test operation mode

Read the test operation mode set for the slave station, and confirm that it is set correctly.

a. Transmission

Send the command [0][0] + data No. [1][2].

Command	Data No.
[0][0]	[1][2]

b. Return

The slave station returns the set test operation mode.



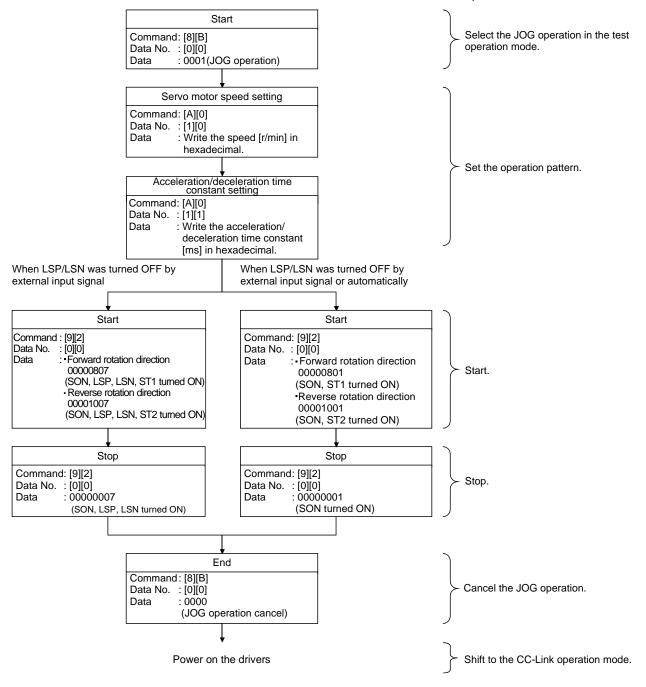
- Test operation mode read

- 0: Normal mode (not test operation mode)
- 1: JOG operation
- 2: Positioning operation
- 3: Motorless operation
- 4: DO forced output
- 5: Single-step feed



(2) JOG operation

Send the command, data No. and data as indicated below to execute JOG operation.

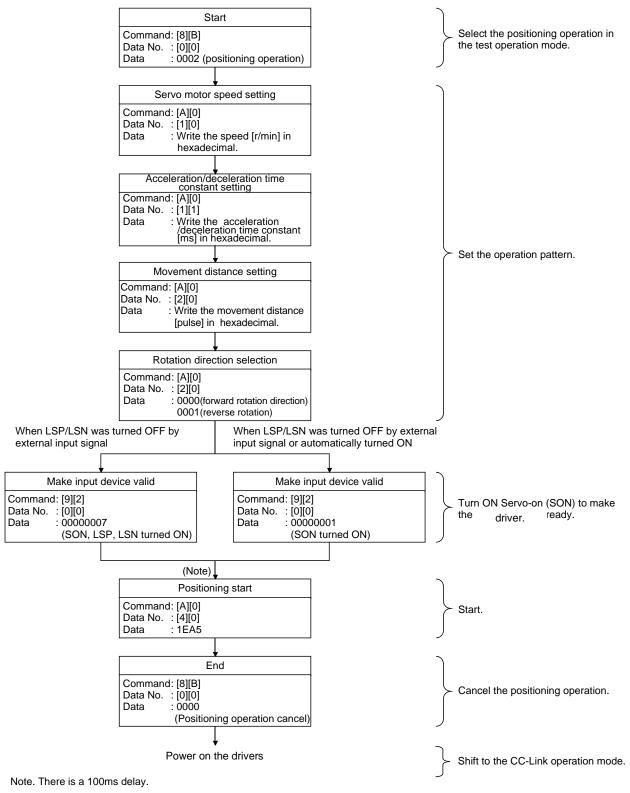




(3) Positioning operation

(a) Operation procedure

Send the command, data No. and data as indicated below to execute positioning operation.



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(b) Temporary stop/restart/remaining distance clear

Send the following command, data No. and data during positioning operation to make deceleration to a stop.

Command	Data No.	Data
[A][0]	[4][1]	STOP

Send the following command, data No. and data during a temporary stop to make a restart.

Command	Data No.	(Note) Data
[A][0]	[4][1]	GO

Note. \Box indicates a blank.

Send the following command, data No. and data during a temporary stop to stop positioning operation and erase the remaining movement distance.

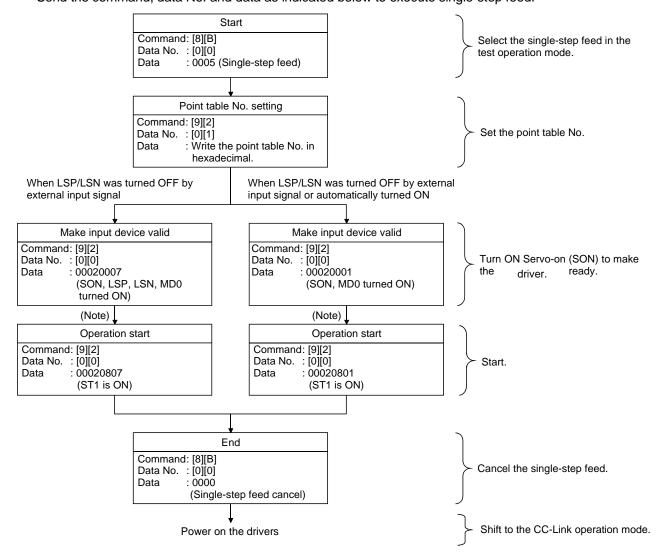
Command	Data No.	(Note) Data
[A][0]	[4][1]	

Note. \Box indicates a blank.



(4) Single-step feed

Set necessary items to the point table before starting the single-step feed. Send the command, data No. and data as indicated below to execute single-step feed.



Note. Start operation after home position return completion (ZP) is confirmed. Refer to 17th bit of the data read with command [1][2] and data No.[8][0].



(5) Output signal pin ON/OFF output signal (DO) forced output

In the test operation mode, the output signal pins can be turned on/off independently of the servo status. Using command [9][0], disable the output signals in advance.

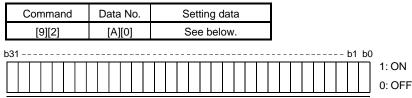
- (a) Choosing DO forced output in test operation mode
 - Transmit command [8][B] + data No. [0][0] + data "0004" to choose DO forced output.



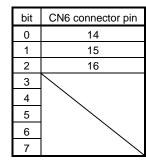
Selection of test operation mode 4: DO forced output (output signal forced output)

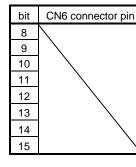
(b) External output signal ON/OFF

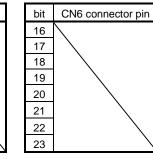
Transmit the following communication commands.

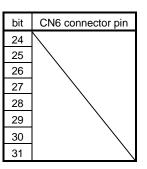


Command of each bit is sent to the slave station in hexadecimal.









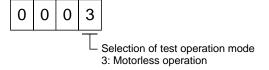
(c) Canceling DO forced output

Transmit command [8][B] + data No. [0][0] + data to cancel DO forced output.

Command	Data No.	Transmission data	Description
[8][B]	[0][0]	0000	Cancel DO forced output

(6) Motorless operation

- (a) Performing motorless operation
 - Transmit command [8][B] + data No. [0][0] + data "0003" to perform motorless operation.



To perform operation after performing the motorless operation, issue a command from the host PC or PLC...etc.

(b) Canceling motorless operation

The motorless operation cannot be canceled in the same way as the test operation mode (transmit command [8][B] + data No. [0][0] + data "0000"). To cancel the motorless operation, power on the driver and shift to the CC-Link operation mode beforehand.



14.5.9 Alarm history

(1) Alarm No. read

Read the alarm No. which occurred in the past. The alarm numbers and occurrence times of No. 0 (last alarm) to No. 5 (sixth alarm in the past) are read.

(a) Transmission

Send command [3][3] and data No. [1][0] to [1][5]. Refer to section 14.4.1.

(b) Reply

The alarm No. corresponding to the data No. is provided.



- Alarm No. is transferred in hexadecimal.

For example, "0032" means A32 and "00FF" means A_ _ (no alarm).

(2) Alarm occurrence time read

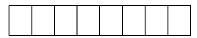
Read the occurrence time of alarm which occurred in the past.

The alarm occurrence time corresponding to the data No. is provided in terms of the total time beginning with operation start, with the minute unit omitted.

(a) Transmission

Send command [3][3] and data No. [2][0] to [2][5]. Refer to section 14.4.1.

(b) Reply



The alarm occurrence time is transferred in hexadecimal. Hexadecimal must be converted into decimal.

For example, data "01F5" means that the alarm occurred in 501 hours after start of operation.

(3) Alarm history clear

Erase the alarm history.

Send command [8][2] and data No. [2][0].

Command	Data No.	Data	
[8][2]	[2][0]	1EA5	



14.5.10 Current alarm

(1) Current alarm read

Read the alarm No. which is occurring currently.

(a) Transmission

Send command [0][2] and data No. [0][0].

Command	Data No.
[0][2]	[0][0]

(b) Reply

The slave station sends back the alarm currently occurring.

0	0		

Alarm No. is transferred in hexadecimal.

For example, "0032" means A32 and "00FF" means A_ _ (no alarm).

(2) Read of the status display at alarm occurrence

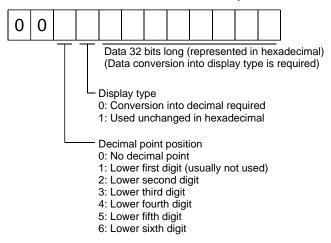
Read the status display data at alarm occurrence. When the data No. corresponding to the status display item is transmitted, the data value and data processing information are sent back.

(a) Transmission

Send command [3][5] and any of data No. [8][0] to [8][E] corresponding to the status display item to be read. Refer to section 15.4.1.

(b) Reply

The slave station sends back the requested status display data at alarm occurrence.



(3) Current alarm clear

As by the reset (RES) on, reset the driver alarm to make the driver ready to operate. After removing the cause of the alarm, reset the alarm with no command entered.

Command	Data No.	Data
[8][2]	[0][0]	1EA5

14.5.11 Point table

(1) Data read

(a) Position data

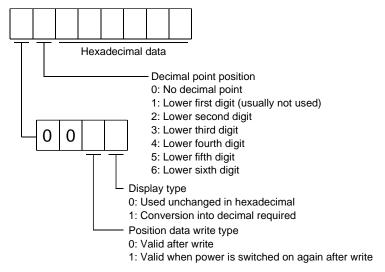
Read the position data of the point table.

1) Transmission

Transmit command [4][0] and any of data No. [0][1] to [F][F] corresponding to the point table to be read. Refer to section 14.4.1.

2) Reply

The slave station sends back the position data of the requested point table.



(b) Speed data

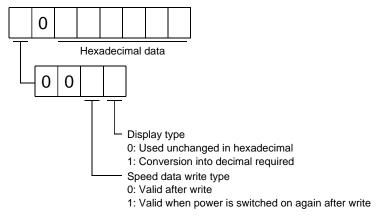
Read the speed data of the point table.

1) Transmission

Transmit command [5][0] and any of data No. [0][1] to [F][F] corresponding to the point table to be read. Refer to section 14.4.1.

2) Reply

The slave station sends back the speed data of the requested point table.





(c) Acceleration time constant

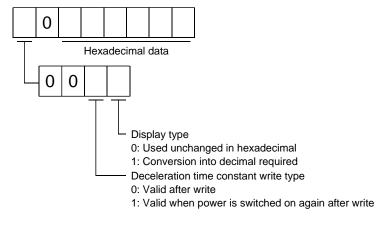
Read the acceleration time constant of the point table.

1) Transmission

Transmit command [5][4] and any of data No. [0][1] to [F][F] corresponding to the point table to be read. Refer to section 14.4.1.

2) Reply

The slave station sends back the acceleration time constant of the requested point table.



(d) Deceleration time constant

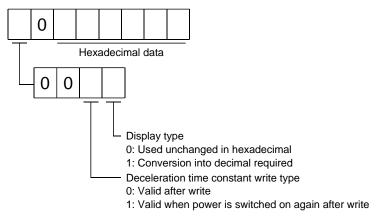
Read the deceleration time constant of the point table.

1) Transmission

Transmit command [5][8] and any of data No. [0][1] to [F][F] corresponding to the point table to be read. Refer to section 14.4.1.

2) Reply

The slave station sends back the deceleration time constant of the requested point table.





(e) Dwell

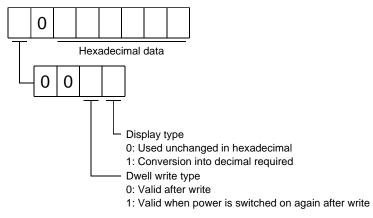
Read the dwell of the point table.

1) Transmission

Transmit command [6][0] and any of data No. [0][1] to [F][F] corresponding to the point table to be read. Refer to section 14.4.1.

2) Reply

The slave station sends back the dwell of the requested point table.



(f) Auxiliary function

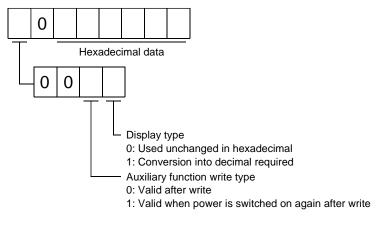
Read the auxiliary function of the point table.

1) Transmission

Transmit command [6][4] and any of data No. [0][1] to [F][F] corresponding to the point table to be read. Refer to section 14.4.1.

2) Reply

The slave station sends back the auxiliary function of the requested point table.





(2) Data write

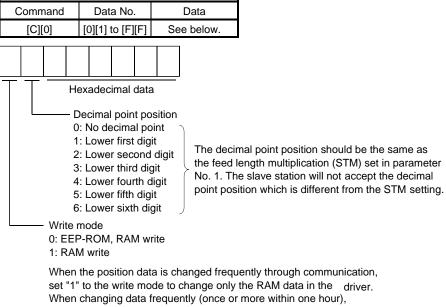
POINT

 If setting values need to be changed with a high frequency (i.e. one time or more per one hour), write the setting values to the RAM, not the EEP-ROM. The EEP-ROM has a limitation in the number of write times and exceeding this limitation causes the driver to malfunction. Note that the number of write times to the EEP-ROM is limited to approximately 100, 000.

(a) Position data

Write the position data of the point table.

Transmit command [C][0], any of data No. [0][1] to [F][F] corresponding to the point table to be written to, and the data. Refer to section 14.4.2.

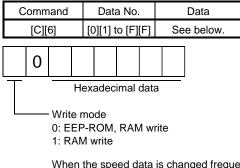


do not write it to the EEP-ROM.

(b) Speed data

Write the speed data of the point table.

Transmit command [C][6], any of data No. [0][1] to [F][F] corresponding to the point table to be written to, and the data. Refer to section 14.4.2.



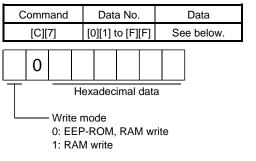
When the speed data is changed frequently through communication, set "1" to the write mode to change only the RAM data in the driver. When changing data frequently (once or more within one hour), do not write it to the EEP-ROM.



(c) Acceleration time constant

Write the acceleration time constant of the point table.

Transmit command [C][7], any of data No. [0][1] to [F][F] corresponding to the point table to be written to, and the data. Refer to section 14.4.2.



When the acceleration time constant is changed frequently through communication, set "1" to the write mode to change only the RAM data in the driver. When changing data frequently (once or more within one hour), do not write it to the EEP-ROM.

(d) Deceleration time constant

Write the deceleration time constant of the point table.

Transmit command [C][8], any of data No. [0][1] to [F][F] corresponding to the point table to be written to, and the data. Refer to section 14.4.2.

С	Command			Data No.				Data
	[C][8]		[[0][1] to [F][F]		Se	e below.	
	0							
Hexadecimal data								
Write mode 0: EEP-ROM, RAM write								

1: RAM write

When the deceleration time is changed frequently through communication, set "1" to the write mode to change only the RAM data in the driver. When changing data frequently (once or more within one hour), do not write it to the EEP-ROM.



(e) Dwell

Write the dwell of the point table.

Transmit command [C][A], any of data No. [0][1] to [F][F] corresponding to the point table to be written to, and the data. Refer to section 14.4.2.

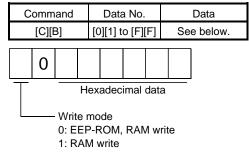
									_
С	omm	and		Data No.		Data			
	[C][/	4]	[0	[0][1] to [F][F]			Se	See below.	
	0]	
	Hexadecimal data Write mode 0: EEP-ROM, RAM write 1: RAM write								
	When the dwell constant is changed frequently set "1" to the write mode to change only the R								

When the dwell constant is changed frequently through communication, set "1" to the write mode to change only the RAM data in the driver. When changing data frequently (once or more within one hour), do not write it to the EEP-ROM.

(f) Auxiliary function

Write the auxiliary function of the point table.

Transmit command [C][B], any of data No. [0][1] to [F][F] corresponding to the point table to be written to, and the data. Refer to section 14.4.2.



When the auxiliary function constant is changed frequently through communication, set "1" to the write mode to change only the RAM data in the driver. When changing data frequently (once or more within one hour), do not write it to the EEP-ROM.



14.5.12 Driver group designation

With group setting made to the slave stations, data can be transmitted simultaneously to two or more slave stations set as a group.

(1) Group setting write

Write the group designation value to the slave station.

(a) Transmission

Transmit command [9][F], data No. [0][0] and data.

						-		
С	omm	and		Data No.	Data			
	[9][F]		[0][0]	See below.			
0		0						
	Group designation 0: No group designation 1: Group a 2: Group b 3: Group c 4: Group d 5: Group e 6: Group f Response command enable							
			re O	esponse to the Response dis	able be set back. able	ck or not in of the master station.		

(2) Group setting read

Read the set group designation value from the slave station.

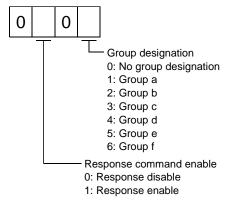
(a) Transmission

Transmit command [1][F] and data No. [0][0].

Command	Data No.
[1][F]	[0][0]

(b) Reply

The slave station sends back the group setting of the point table requested.





14.5.13 Other commands

(1) Servo motor side pulse unit absolute position

Read the absolute position in the servo motor side pulse unit.

Note that overflow will occur in the position of 8192 or more revolutions from the home position.

(a) Transmission

Send command [0][2] and data No. [9][0].

Command	Data No.
[0][2]	[9][0]

(b) Reply

The slave station sends back the requested servo motor side pulses.

Absolute value is sent back in hexadecimal in the servo motor side pulse unit. (Must be converted into decimal)

For example, data "000186A0" is 100000 [pulse] in the motor side pulse unit.

(2) Command unit absolute position

Read the absolute position in the command unit.

(a) Transmission

Send command [0][2] and data No. [9][1].

Command	Data No.
[0][2]	[9][1]

(b) Reply

The slave station sends back the requested command pulses.

1				
1				
1				
1				
1				
1				

Absolute value is sent back in hexadecimal in the command unit. (Must be converted into decimal)

For example, data "000186A0" is 100000 [pulse] in the command unit.

(3) Software version

Reads the software version of the driver.

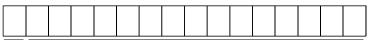
(a) Transmission

Send command [0][2] and data No.[7][0].

Command	Data No.
[0][2]	[7][0]

(b) Reply

The slave station returns the software version requested.



Space

Software version (15 digits)



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POINT

 To execute the indexer positioning operation, parameter needs to be changed. Set the parameter No.PA01 to "1000".

This chapter provides the indexer positioning operation method using LECSC2-T \Box driver. Any matters not described in this chapter are the same as those of the point table positioning operation. For more information, refer to chapters up to 14.

15.1 Function

15.1.1 Overview

Using the next station selection 1 (RYnA) to the next station selection 8 (RY(n+2)5) devices, stations from No.0 to No.254 can be specified.

Settings of servo motor speed and acceleration/deceleration time constant are carried out by specifying the point table number from 1 to 8 using the speed selection 1 (RY(n+2)C) to the speed selection 3 (RY(n+2)E) devices. Speed command data can be directly specified by using the remote register when two stations are occupied.

Item Description Available with CC-Link communication Station command CC-Link communication (1 station occupied): 31 stations input CC-Link communication (2 stations occupied): 255 stations Command Available with CC-Link communication (2 stations occupied) Remote system Speed Set the speed command data (speed) by the remote register. register command Speed input Select a speed and acceleration/deceleration time constant by the point table No. input Rotation direction Automatic Positioning operation is executed to the set station. Rotation direction can be specified. specifying indexer operation Shortest rotating Positioning operation is executed to the set station. The servo motor rotates in the closest mode indexer direction from current position. Turning on the start signal (RYn1) makes the servo motor rotate in the direction specified by Indexer JOG the rotation direction specifying. Manual operation Turning off the start signal (RYn1) makes the servo motor perform positioning operation to the operation closest station where the motor can decelerate to stop. mode Operation mode In accordance with the speed data set in parameters, JOG operation is performed by using JOG operation CC-Link communication Home position return is performed by the Z-phase pulse count after passing proximity dog. Home position address may be set. Home position shift distance may be set. Home position Torque limit return direction may be selected. changing dog type Home Automatic at-dog home position return return/automatic stroke return function. position Automatic torque limit changing function return Home position return is made without dog. mode Torque limit Home position may be set at any position by manual operation, etc. Home position address may changing data be set. setting type Automatic torque limit changing function Automatic positioning to home High-speed automatic return to a defined home position. position

15.1.2 Driver standard specifications (functions only)



15.1.3 Function list

The following table lists the functions of this servo. For details of the functions, refer to the reference field.

Function	Description	Reference
Automatic operation mode 1 (Rotation direction specifying indexer)	In this operation mode, the servo motor rotates in the specified direction and performs a positioning operation to the next station divided in 2 to 255.	Section 15.7.2
Automatic operation mode 2 (Shortest rotating indexer)	In this operation mode, the servo motor rotates in the shortest direction and performs a positioning operation to the next station divided in 2 to 255.	Section 15.7.3
Manual operation mode	 Indexer JOG operation When stopping, this JOG operation enables the servo motor to perform positioning to the station where the servo motor can decelerate to stop. JOG operation When stopping, this JOG operation enables the servo motor to decelerate to stop regardless of stations. 	Section 15.8
Home position return	Torque limit changing dog type, torque limit changing data setting type	Section 15.9
High-resolution encoder	High-resolution encoder of 262144 pulses/rev is used as a servo motor encoder.	
Absolute position detection system	By merely setting the home position once, home position return need not be done at each power on.	Section 15.10
Gain changing function	You can switch between gains during rotation and gains during stop or use an input device to change gains during operation.	Section 9.6
Advanced vibration suppression control	This function suppresses vibration at the arm end or residual vibration.	Section 9 .4
Adaptive filter II	Driver detects mechanical resonance and sets filter characteristics automatically to suppress mechanical vibration.	Section 9 .2
Low-pass filter	Suppresses high-frequency resonance which occurs as servo system response is increased.	Section 9 .5
Machine analyzer function	Analyzes the frequency characteristic of the mechanical system by simply connecting a set up software(MR Configurator2 [™]) installed personal computer and driver. Set up software(MR Configurator2 [™]) is necessary for this function.	
Machine simulation	Can simulate machine motions on a personal computer screen on the basis of the machine analyzer results. Set up software(MR Configurator2 [™]) is necessary for this function.	
Gain search function	Personal computer changes gains automatically and searches for overshoot-free gains in a short time. Set up software(MR Configurator2 [™]) is necessary for this function.	
Slight vibration suppression control	Suppresses vibration of ± 1 pulse produced at a servo motor stop.	Parameters No. PB24
Electronic gear	The electronic gear is used to make adjustment so that the driver setting matches the machine moving distance. Also, changing the electronic gear value allows the machine to be moved at any multiplication ratio to the moving distance using the driver.	Parameter No. PA06, PA07
Auto tuning	Automatically adjusts the gain to optimum value if load applied to the servo motor shaft varies.	Section 8.2
Regenerative option	Used when the built-in regenerative resistor of the driver does not have sufficient regenerative capability for the regenerative power generated.	Section 13.2
Brake unit	Used when the regenerative option cannot provide enough regenerative power. Can be used with the driver of 5kW or more.	Section 13.3
Regeneration converter	Used when the regenerative option cannot provide enough regenerative power. Can be used with the driver of 5kW or more.	Section 13.4
Alarm history clear	Alarm history is cleared.	Parameter No. PC18



Function	Description	Reference
Torque limit	Servo motor-torque is limited.	Section 15.3.2 (3) Section 15.11.1 (9)
Output signal (DO) forced output	Output signal can be forced on/off independently of the servo status. Use this function for output signal wiring check, etc.	Section 7.7.4
Test operation mode	JOG operation [•] positioning operation [•] DO forced output. Set up software(MR Configurator2 [™]) is necessary for this function.	Section 7.7
Limit switch	The servo motor travel region can be limited using the forward rotation stroke end (LSP)/reverse rotation stroke end (LSN).	

15.2 I/O signals (I/O devices) transferred to/from the PC or PLC...etc

15.2.1 I/O signals (I/O devices)

(1) When 1 station is occupied

RYn/RXn: 32 points each, RWrn/RWwn: 4 points each

	PC or PLCetc \rightarrow Driver (RYn)		Driver \rightarrow PC or PLCetc (RXn)
(Note) Device No.	Device name	(Note) Device No.	Device name
RYn0	Servo-on	RXn0	Ready
RYn1	Start	RXn1	In position
RYn2	Rotation direction specifying	RXn2	Rough match
RYn3		RXn3	Home position return completion
to	Not available	RXn4	Limiting torque
RYn5		RXn5	Not available
RYn6	Operation mode selection 1	RXn6	Electromagnetic brake interlock
RYn7	Operation mode selection 2	RXn7	Temporary stop
RYn8	Monitor output execution demand	RXn8	Monitoring
RYn9	Instruction code execution demand	RXn9	Instruction code execution completion
RYnA	Next station selection 1	RXnA	Warning
RYnB	Next station selection 2	RXnB	Battery warning
RYnC	Next station selection 3	RXnC	Movement completion
RYnD	Next station selection 4	RXnD	Dynamic brake interlock
RYnE	Next station selection 5	RXnE	
RYnF		to	Not available
to	Not available	RX(n+1)9	
RY(n+1)9		RX(n+1)A	Trouble
RY(n+1)A	Reset	RX(n+1)B	Remote station communication ready
RY(n+1)B		RX(n+1)C	
to	Not available	to	Not available
RY(n+1)F		RX(n+1)F	

	PC or PLCetc \rightarrow Driver (RWwn)	
Address No.	Signal	
RWwn	Monitor 1	
RWwn+1	Monitor 2	
RWwn+2	Instruction code	
RWwn+3	Writing data	

	Driver \rightarrow PC or PLCetc (RWrn)
Address No.	Signal
RWrn	Monitor 1 data
RWrn+1	Monitor 2 data
RWrn+2	Respond code
RWrn+3	Reading data

Note. "n" depends on the station number setting.



(2) When 2 stations are occupied

RXn/RYn: 64 points each, RWrn/RWwn: 8 points each

	PC or PLCetc \rightarrow Driver (RYn)		Driver \rightarrow PC or PLCetc (RXn)
(Note)		(Note)	
Device No.	Device name	Device No.	Device name
RYn0	Servo-on	RXn0	Ready
RYn1	Start	RXn1	In position
RYn2	Rotation direction specifying	RXn2	Rough match
RYn3		RXn3	Home position return completion
to	Not available	RXn4	Limiting torque
RYn5		RXn5	Not available
RYn6	Operation mode selection 1	RXn6	Electromagnetic brake interlock
RYn7	Operation mode selection 2	RXn7	Temporary stop
RYn8	Monitor output execution demand	RXn8	Monitoring
RYn9	Instruction code execution demand	RXn9	Instruction code execution completion
RYnA	Next station selection 1	RXnA	Warning
RYnB	Next station selection 2	RXnB	Battery warning
RYnC	Next station selection 3	RXnC	Movement completion
RYnD	Next station selection 4	RXnD	Dynamic brake interlock
RYnE	Next station selection 5	RXnE	
RYnF		to	Not available
to	Not available	RX(n+1)F	
RY(n+1)F		RX(n+2)0	Position instruction execution completion
RY(n+2)0	Position instruction execution demand	RX(n+2)1	Speed instruction execution completion
RY(n+2)1	Speed instruction execution demand	RX(n+2)2	Station output 1
RY(n+2)2	Not available	RX(n+2)3	Station output 2
RY(n+2)3	Next station selection 6	RX(n+2)4	Station output 3
RY(n+2)4	Next station selection 7	RX(n+2)5	Station output 4
RY(n+2)5	Next station selection 8	RX(n+2)6	Station output 5
RY(n+2)6	Internal torque limit selection	RX(n+2)7	Station output 6
RY(n+2)7	Proportion control	RX(n+2)8	Station output 7
RY(n+2)8	Gain changing	RX(n+2)9	Station output 8
RY(n+2)9	Not available	RX(n+2)A	
, ,	Position/speed specifying system selection	to	Not available
	Not available	RX(n+3)9	
	Speed selection 1	RX(n+3)A	
. ,	Speed selection 2		Remote station communication ready
, ,	Speed selection 3	RX(n+3)C	
RY(n+2)F		to	Not available
to	Not available	RX(n+3)F	
RY(n+3)9			
RY(n+3)A	Reset		
RY(n+3)B			
to	Not available		
RY(n+3)F			

Note. "n" depends on the station number setting.



	PC or PLCetc \rightarrow Driver (RWwn)		Driver \rightarrow PC or PLCetc (RWrn)
(Note 1) Address No.	Signal	(Note 1) Address No.	Signal
RWwn	Monitor 1 (Note 2)	RWrn	Monitor 1 data lower 16 bit
RWwn+1	Monitor 2 (Note 2)	RWwn+1	Monitor 1 data upper 16 bit
RWwn+2	Instruction code	RWwn+2	Respond code
RWwn+3	Writing data	RWwn+3	Reading data
RWwn+4	Next station	RWwn+4	
RWwn+5		RWwn+5	Monitor 2 data lower 16 bit
RWwn+6	Point table No./Speed command data (Note 3)	RWwn+6	Monitor 2 data upper 16 bit
RWwn+7	Not available	RWwn+7	Not available

Note 1. "n" depends on the station number setting.

2. Specify the code of the lower 16 bit as the monitor code of 32-bit data.

3. When the parameter No.PC30 setting is "□□0□", specify the point table No. in RWwn+6. When the parameter No.PC30 setting is "□□1□", specify the speed data in RWwn+6, and turn ON Speed instruction execution demand (RY(n+2)1). When setting the parameter No.PC30 to "□□1□", always set the acceleration/deceleration time constant in the point table No.1.

15.2.2 Detailed explanation of I/O signals

(1) Input signals (Input devices)

The note signs in the remarks column indicates the following descriptions.

*: Can be automatic turned ON internally by setting parameters No.PD01.

Signal name		Devid	e No.	
Signal name (Device name)	Description	1 station	2 stations	Remarks
(Device name)		occupied	occupied	
Servo-on	Turning RYn0 ON powers on the base circuit, making	RYn0	RYn0	*
	operation ready to start. (Servo on status)			
	Turning it OFF powers off the base circuit, coasting the servo			
	motor. (Servo off status)			
Start	1. Automatic operation mode 1 and 2	RYn1	RYn1	
	Turning on RYn1 performs positioning operation once to the			\backslash
	specified station number.			$\langle \rangle$
	2. Manual operation mode			
	Turning on RYn1 in the indexer JOG operation makes the			
	servo motor rotate in the RYn2 specified direction only while			
	RYn1 is on. Turning it off makes the servo motor perform			
	positioning to the station where the servo motor can			
	decelerate to stop.			
	Turning on RYn1 in JOG operation makes the servo motor			
	rotate in the RYn2 specified direction only while RYn1 is on.			
	Turning it off makes the servo motor decelerate to stop			
	regardless of stations.			
	3. Home position return mode			
	Turning on RYn1 immediately starts a home position return.			



Cignal name				Devie	ce No.	
Signal name (Device name)		Description		1 station occupied	2 stations occupied	Remarks
Rotation direction specifying	1. Automatic opera Rotation directio No.PA14 setting operation mode	tion mode 1 n changes according . RYn2 is used only 1 (Rotation direction automatic operation	for the automatic specifying indexer). It i	RYn2	RYn2	
	(Note) RYn2	Parameter No.PA14	Servo motor rotation direction			
	0	0	CCW CW			
	1	0	CW CCW			
	Note. 0: OFF 1: ON					
	2. Manual operatio It is not affected	n mode by the parameter No				
	(Note) RYn2	Parameter No.PA14	Servo motor rotation direction			
	0	0	CCW			
	1	0	CW			
	Note. 0: OFF 1: ON					
		eturn mode Specify the rotation o node by using the pa				
Operation mode selection 1	Select the operation			RYn6	RYn6	
Operation mode selection 2	(Note) Remote input	Operati	ion mode	RYn7	RYn7	
	Ryn7 Ryn6					
	0 0	Home position retur	n mode			
		Manual operation m				
	1 0	Automatic operation (Rotation direction s	specifying indexer)			
		Automatic operation (Shortest rotating in				
	Note. 0: OFF 1: ON					

Signal name							Devid	ce No.	_			
Signal name (Device name)				De	escripti	on				1 station occupied	2 stations occupied	Remarks
Monitor output execution demand	Rem 2) Whe Rem Rem Rem	the san r values in 1 sta ote reg ote reg ote reg	ne time s are ke tion is o ister R ister R ister R tions a ister R ister R ister R	e, RXn8 ept upd occupie Wrn: D. (F Wrn+1 Wrn+2 wrn+2 Wrn+2 Wrn+2 Wrn+5 Wrn+6	ated. ated. at a der (Wwn) : Data (RWv 2: Resp or err pied ower 16 onitor 1 : Uppe by Mo 5: Lowe by M 5: Uppe by M	ON. Wh nanded deman wn+1) ond co for 6 bits of 1 (RWw er 16 bit onitor 1 er 16 bit onitor 2 er 16 bit onitor 2	hile RYi l by Mc ded by de india f data c m s of da (RWw s of da 2 (RWw s of da 2 (RWw	n8 is O nitor 1 Monito cating r lemand ta dem n) ta dem n+2) ta dem n+2)	N, the or 2 hormal led by anded anded anded	RYn8	RYn8	
Instruction code execution demand	Turning the inst After co code in time, R	g RYn9 ruction ompletion	ON ex code s on of in g norm	ecutes stored in structional or er	or err the pro n remo	or ocessin te regis e execu	g corre ster RW tion, th	spondii /wn+2 e respo	ng to ond	RYn9	RYn9	
Next station selection 1	Refer to Select					RYnA	to RY(ı	1+2)5.		RYnA	RYnA	
Next station selection 2				(No	ote 1) Re	emote ir	put			RYnB	RYnB	
Next station selection 3	Station No.	RY	RY (n+2)4	RY		RYnD	RYnC	RYnB	RYnA	RYnC	RYnC	
Next station selection 4	0	0	0	0	0	0	0	0	0	RYnD	RYnD	
	2	0	0	0	0	0	0	1	0	Rine	KIIID	
Next station selection 5	3	0	0	0	0	0	0	1	1	RYnE	RYnE	
Next station selection 6	4	0	0	0	0	0	1	0	0		RY(n+2)3	
Next station selection 7			•			•	.	•	•	$\left \right\rangle$	RY(n+2)4	
Next station selection 8	254 (Note 2) Note 1	1	1 1 F	1	1	1	1	1	0		RY(n+2)5	
	2		setting	g "1" foi 5, the s					n+2)3			

O'mark a sure		Devid	ce No.	
Signal name (Device name)	Description	1 station	2 stations	Remarks
(Device name)		occupied	occupied	
Position instruction execution	When $RY(n+2)$ is turned on, the next station number set in the	\backslash	RY(n+2)0	\backslash
demand	remote register RWwn+4 is set.			
	When it is set to the driver, the respond code indicating normal			
	or error is set to RWrn+2. At the same time, $RX(n+2)0$ turns			
	ON.			
	Refer to section 3.6.3 for details.			
Speed instruction demand	When $RY(n+2)1$ is turned ON, the point table No. or speed	\backslash	RY(n+2)1	\backslash
	command data set to remote register RWwn+6 is set.			
	When it is set to the driver, the respond code indicating normal			
	or error is set to RWrn+2. At the same time, $RX(n+2)1$ turns			
	ON.			
	Refer to section 3.6.3 for details.			
Internal torque limit selection	Turning $RY(n+2)6$ OFF makes the torque limit value of		RY(n+2)6	
	parameter No.PA11 (forward rotation torque limit) • parameter			
	No.PA12 (reverse rotation torque limit) valid, and turning it ON			
	makes that of parameter No.PC35 (internal torque limit). (Refer			
	to section 15.3.2 (3))			
Proportion control	When $RY(n+2)7$ is turned ON, the speed amplifier is switched	\	RY(n+2)7	*
	from the proportional integral type to the proportional type.	1		
	If the servo motor at a stop is rotated even one pulse by an			
	external factor, it develops torque in an attempt to compensate			
	for a position shift. When the shaft is locked mechanically after			
	Movement completion (RXnC) is turned OFF, for example,			
	turning Proportion control ($RY(n+2)7$) ON as soon as			
	Movement completion (RXnC) turns OFF allows control of			
	unnecessary torque developed in an attempt to compensate for			
	a position shift.			
	When the shaft is to be locked for an extended period of time,			
	turn Internal torque limit selection $(RY(n+2)6)$ ON			
	simultaneously with Proportion control $(RY(n+2)7)$ to make the			
	torque not more than the rated torque using Internal torque			
	limit (parameter No.PC35).			
Gain changing	When $RY(n+2)8$ is turned ON, the load inertia moment ratio		RY(n+2)8	
2 2	and the corresponding gain values change to the values of			
	parameter No.PB29 to PB32. To change the gain using			
	RY(n+2)8, make the auto tuning invalid.			
Position/speed specifying	Select how to give a speed command. (Refer to section 3.6.3.)	Ì	RY(n+2)A	\land
system selection	OFF: Remote input-based speed specifying system	$ \rangle$		$ \rangle$
	Specifying the point table No. with Point table No.			
	selection (RYnA to RYnE) gives a speed command.			$ \rangle$
	ON : Remote register-based speed specifying system			
	Setting the instruction code to the remote register			
	(RWwn+4 to RWwn+6) gives a speed command.			
	Set the parameter No.PC30 (direct specification			
				$ \rangle$
	selection) to " \Box \Box \Box \Box ?".	۱ <u> </u>	N	l



O'reach a serve					Devid	ce No.	
Signal name		D	1 station	2 stations	Remarks		
(Device name)					occupied	occupied	
Speed selection 1	Set the servo r	notor speed,	acceleration	time constant, and		RY(n+2)C	
Speed selection 2	deceleration til	me constant f	for positioning	operation by		RY(n+2)D	
Speed selection 3				0.8 using RY(n+2)C,	Ν	RY(n+2)E	Ν
	RY(n+2)D, and	id RY(n+2)E					$\left \right\rangle$
	(No	te) Remoto i	nput				
	RY(n+2)E	-	RY(n+2)C	Point table No.			
	0	0	0	1			
	0	0	1	2			
	0	1	0	3			
	0	1	1	4			
	1	0	0	5			
	1	0	1	6			
	1	1	0	7			
	1	1	1	8			
	Note. 0: OFF						
	1: ON						
Reset	Keeping RY(n	+1)A or RY(I	n+3)A ON fo	r 50ms or longer	RY(n+1)A	RY(n+3)A	
	allows an alarr	n to be deact	tivated.				$ \rangle$
	Some alarms of	cannot be dea	activated by F	Reset RY(n+1)A or			
	RY(n+3)A. (R						
	If RY(n+1)A o						
	-			t off. When "□□1□"			
	is set in param		U (function se	lection D-1), the base			
			to make a st	op. Do not turn it ON			
	during operation	-	to make a St				



(2) Output signals (Output device)

POINT	
 The output 	devices can be used for both the remote output and the external
output sign	als of CN6 connector.

The signal whose Device No. field has an oblique line cannot be used in CC-Link.

Signal name		Devid	ce No.
(Device name)	Description	1 station	2 stations
()		occupied	occupied
Ready	A ready is assigned to the CN6-14 pin as an external output signal. RXn0	RXn0	RXn0
	turns ON when the driver is ready to operate after servo-on.		
In position	RXn1 turns ON when the droop pulse value is within the preset in-position	RXn1	RXn1
	range.		
	The in-position range can be changed using parameter No.PA10.		
	Increasing the in-position range may result in a continuous conduction		
	status during low-speed rotation.		
	RXn1 turns ON at servo-on.		
Rough match	RXn2 turns ON when the command remaining distance becomes less than	RXn2	RXn2
	the rough match output range set in the parameter.		
	RXn2 turns ON at servo-on.		
Home position return	The home position return completion is assigned to the CN6-16 pin as an	RXn3	RXn3
completion	external output signal. RXn3 turns ON when a home position return is		
	completed. RXn3 turns ON at completion of a home position return.		
	In an absolute position detection system, RXn3 turns ON when operation is		
	ready to start, but turns OFF in any of the following cases.		
	1) Servo-on (RYn0) is turned OFF.		
	2) Forced stop (EMG) is turned OFF.		
	3) Reset $(RY(n+1)A \text{ or } RY(n+3)A)$ is turned ON.		
	4) Alarm occurs.		
	5) Forward rotation stroke end (RYn4) or Reverse rotation stroke end		
	(RYn5) is turned OFF.		
	6) Home position return has not been made after product purchase.		
	7) Home position return has not been made after occurrence of Absolute		
	position erase (A25) or Absolute position counter warning (AE3).		
	8) Home position return has not been made after electronic gear change.		
	9) Home position return has not been made after the absolute position		
	detection system was changed from invalid to valid.		
	10) Parameter No.PA14 (Station No. direction selection) has been		
	changed.		
	11) While a home position return is being made.		
	When any of 1) to 11) has not occurred and a home position return is		
	already completed at least once, Home position return completion (RXn3)		
	turns to the same output status as Ready (RXn0).		
Limiting torque	RXn4 turns ON when the torque is reached at the time of torque	RXn4	RXn4
	generation.		
Electromagnetic brake	RXn6 turns OFF at servo-off or alarm occurrence. At alarm occurrence, it	RXn6	RXn6
interlock	turns OFF independently of the base circuit status.		
Monitoring	Refer to Monitor output execution demand (RYn8).	RXn8	RXn8
Instruction code execution	Refer to Instruction code execution demand (RYn9).	RXn9	RXn9
completion			



Signal name										De	evice	e No.
Signal name (Device name)	Description							1 station occupied		2 stations occupied		
Warning		RXnA turns ON when a warning occurs. When no warning has occurred, RXnA turns OFF within about 1s after power-on.							RXnA		RXnA	
Battery warning	RXnB turn (A9F) occ within abo	urs. Wh	en no ba	attery wa	-	-		-	-	RXnB		RXnB
Movement completion	RXnC tur remaining RXnC tur	g distanc	e is "0".		RXn1) t	urns ON	and the	comma	nd	RXnC		RXnC
Dynamic brake interlock	RXnD turn using the device is not neces	external required	l dynami I. (Refer	c brake to sectio	on the d	river of 1	11kW or	more, th	nis	RXnD		RXnD
Position instruction execution completion	Refer to S	Speed in	structior	n executi	on dema	and (RY)	(n+2)0)				/	RX(n+2)0
Speed instruction execution completion	Refer to F	Position i	instructio	on execu	ition der	nand (R`	Y(n+2)1).				RX(n+2)1
Station output 1	As soon a is output i			t comple	tion (RX	inC) turn	is on, the	e station	number			RX(n+2)2
Station output 2	Station	RX	RX	(No RX	te 1) Re RX	mote ou RX	tput RX	RX	RX			RX(n+2)3
Station output 3	No. (Note 2)	(n+2)9	(n+2)8 0			(n+2)5 0						RX(n+2)4
Station output 4	0	1	1	1	1	1	1	1	1 0			RX(n+2)5
Station output 5	2	1	1	1	1	1	1	0	1			RX(n+2)6
Station output 6		-	-	-	•	-	•	•				RX(n+2)7
Station output 7	-		•	-					•			RX(n+2)8
Station output 8	253 254	0	0	0	0	0	0	1 0	0 1			RX(n+2)9
	At power- within the is output. While ope within the number is While ope the currer servo mo number is	 Note 1. 0: OFF 1: ON 2. All station outputs turn to "0" (OFF) when the current position is out of the in-position range. At power-on, emergency stop or alarm occurrence, if the current position is within the in-position range of each station, corresponding station number										



Circal serve		Device No.		
Signal name (Device name)	Description	1 station occupied	2 stations occupied	
Trouble	A trouble is assigned to the CN6-15 pin as an external output signal. RX(n+1)A or RX(n+3)A turns ON when the protective circuit is activated to shut off the base circuit. When no alarm has occurred, RX(n+1)A or RX(n+3)A turns OFF within about 1.5s after power is switched ON.	RX(n+1)A	RX(n+3)A	
Remote station communication ready	This signal turns ON at power-on and turns off at a trouble occurrence or in the reset $(RY(n+1)A \text{ or } RY(n+3)A)$ ON status.	RX(n+1)B	RX(n+3)B	

(3) Remote registers

The signal whose Remote Register field has an oblique line cannot be used.

(a) Input (PC or PLC...etc \rightarrow driver)

Remote	register			
1 station 2 stations		Signal name	Description	Setting range
occupied	occupied			
RWwn	RWwn	Monitor 1	 Demands the status indication data of the driver. 1) When 1 station is occupied Setting the monitor code of the status indication item to be monitored to RWwn and turning RYn8 to ON sets data to RWrn. RXn8 turns on at the same time. 2) When 2 stations are occupied Setting the monitor code of the status indication item to be monitored to RWwn and turning RYn8 to ON sets data to RWrn. RXn8 turns on at the same time. 2) When 2 stations are occupied Setting the monitor code of the status indication item to be monitored to RWwn and turning RYn8 to ON sets data to RWrn. RXn8 turns on at the same time. When demanding 32-bit data, specifying the lower 16-bit code No. and turning RYn8 to ON sets the lower 16-bit data to RWwn and the upper 16-bit data to RWrn. data is stored in the RXn8. RXn8 turns on at the same time. Refer to section 15.2.3 for the item of the monitor code of the status indication. 	Refer to section 15.2.3.
RWwn+1	RWwn+1	Monitor 2	 Demands the status indication data of the driver. 1) When 1 station is occupied Setting the monitor code of the status indication item to be monitored to RWwn+1 and turning RYn8 to ON sets data to RWrn+1. RXn8 turns on at the same time. 2) When 2 stations are occupied Setting the monitor code of the status indication item to be monitored to RWwn+1 and turning RYn8 to ON sets data to RWrn+5. RXn8 turns on at the same time. When demanding 32-bit data, specifying the lower 16-bit code No. and turning RYn8 to ON sets the lower 16-bit data to RWwn+5 and the upper 16-bit data to RWrn+6. Data is stored in the RXn8. RXn8 turns on at the same time. Refer to section 16.2.3 for the item of the monitor code of the status indication. 	
RWwn+2	RWwn+2	Instruction code	Sets the instruction code used to perform parameter or point table data read and write, alarm reference or the like. Setting the instruction code No. to RWwn+2 and turning RYn9 to ON executes the instruction. RXn9 turns to ON on completion of instruction execution. Refer to section 15.2.4 (1) for instruction code No. definitions.	Refer to section 15.2.4 (1).



Remote	register			
1 station	2 stations	Signal name	Description	Setting range
occupied	occupied			
RWwn+3	RWwn+3	Writing data	Sets the written data used to perform parameter or point	Refer to section
			table data write, alarm history clear or the like.	15.2.4 (2).
			Setting the written data to RWwn+3 and turning RYn9 to ON	
			writes the data to the driver. RXn9 turns to ON on completion	
			of write.	
			Refer to section 15.2.4 (2) for written data definitions.	

(b) Output (Driver \rightarrow PC or PLC...etc)

Note that the data set to RWrn and RWrn+1 depends on whether 1 station or 2 stations are occupied. If you set inappropriate code No. or data to the remote register input, the error code is set to respond code (RWrn+2). Refer to section 3.5.5 for the error code.

When 1 station is occupied

Remote register	Signal name	Description
RWrn	Monitor 1 data	The data of the monitor code set to RWwn is set.
RWrn+1	Monitor 2 data	The data of the monitor code set to RWwn+1 is set.
RWrn+2	Respond code	"0000" is set when the codes set to RWwn to RWwn+3 are executed normally.
RWrn+3	Reading data	Data corresponding to the read code set to RWwn+2 is set.

When 2 stations are occupied

Remote register	Signal name	Description
RWm	Monitor 1 data lower 16bit	The lower 16 bits of the data of the monitor code set to RWwn are set.
RWrn+1	Monitor 1 data upper 16bit	The upper 16 bits of the data of the monitor code set to RWwn are set. A sign is set if there are no data in the upper 16 bits.
RWrn+2	Respond code	"0000" is set when the codes set to RWwn to RWwn+6 are executed normally.
RWrn+3	Reading data	Data corresponding to the read code set to RWwn+2 is set.
RWrn+4		
RWrn+5	Monitor 2 data lower 16bit	The lower 16 bits of the data of the monitor code set to RWwn+1 are set.
RWrn+6	Monitor 2 data upper 16bit	The upper 16 bits of the data of the monitor code set to RWwn+1 are set. <i>I</i> sign is set if there are no data in the upper 16 bits.
RWrn+7		



15.2.3 Monitor codes

To demand 32-bit data when 2 stations are occupied, specify the lower 16-bit code No. Use any of the instruction codes 0101 to 011C to read the decimal point position (multiplying factor) of the status indication. Setting any code No. that is not given in this section will set the error code ($\Box\Box\Box\Box$) to respond code (RWrn+2). At this time, "0000" is set to RWrn, RWrn+1, RWrn+5 and RWrn+6.

Code No.				Answer data (Driver \rightarrow PC or PLCetc)	
1 station	2 stations	Monitored item	Data length	Unit	
occupied	occupied				
0000h	0000h				
0001h	0001h	Not used in indexer positioning operation.		\searrow	
0002h					
0003h	0003h				
0004h					
0005h	0005h				
0006h					
0007h	0007h				
0008h	0008h	Point table No.	16bit	[No.]	
0009h					
000Ah	000Ah	Feedback pulse value lower 16bit	16bit	[pulse]	
000Bh		Feedback pulse value upper 16bit	16bit	[pulse]	
000Ch					
000Dh					
000Eh	000Eh	Droop pulse value lower 16bit	16bit	[pulse]	
000Fh		Droop pulse value upper 16bit	16bit	[pulse]	
0010h	0010h				
0011h	0011h	Regenerative load factor	16bit	[%]	
0012h	0012h	Effective load factor	16bit	[%]	
0013h	0013h	Peak load factor	16bit	[%]	
0014h	0014h	Instantaneously occurring torque	16bit	[%]	
0015h	0015h	ABS counter	16bit	[rev]	
0016h	0016h	Motor speed lower 16bit	16bit	imes0.1[rev/min]	
0017h		Motor speed upper 16bit	16bit	imes0.1[rev/min]	
0018h	0018h	Bus voltage	16bit	[V]	
0019h	0019h	Not used in indexer positioning operation.			
001Ah]			
001Bh	001Bh				
001Ch	001Ch	Within one-revolution position lower 16bit	16bit	[pulse]	
001Dh		Within one-revolution position upper 16bit	16bit	[pulse]	
001Eh	001Eh	Station No.	16bit	[No.]	

15.2.4 Instruction codes (RWwn+2 • RWwn+3)

Refer to section 3.6.2 for the instruction code timing charts.

(1) Read instruction codes

The word data requested to be read with the instruction code 0000h to 0AFFh is read by Read code (RWrn+3).

Set the command code No. corresponding to the item to RWrn+2. The codes and answer data are all 4-digit hexadecimal numbers.

Setting any command code No. that is not given in this section will set the error code $(\Box\Box\Box\Box)$ to respond code (RWrn+2). At this time, "0000" is set to Reading data (RWrn+3).

Code No.	Item/Function	Reading data (RWrn+3) contents (Driver → PC or PLCetc)
0000h	Operation mode	0000: CC-Link operation mode
000011	Reads the current operation mode.	0001: Test operation mode
0002h	Travel multiplying factor	
000211	Reads the multiplying factor of the position	
	data in the point table set in parameter	
	No.PA05.	Travel multiplying factor
		0300: ×1000
		0200: ×100
		0100: ×10
		0000: ×1
0010h	Current alarm (warning) reading	
	Reads the alarm No. or warning No. occurring	0 0
	currently.	
		Cccurring alarm No./warning No.
0020h	Alarm number in alarm history	
	(most recent alarm)	
0021h	Alarm number in alarm history	
	(first recent alarm)	Alarm No. that occurred in past
0022h	Alarm number in alarm history	
	(second recent alarm)	
0023h	Alarm number in alarm history	
	(third recent alarm)	
0024h	Alarm number in alarm history	
	(fourth recent alarm)	
0025h	Alarm number in alarm history	
	(fifth recent alarm)	
0030h	Alarm occurrence time in alarm history	
0031h	(most recent alarm)	
00311	Alarm occurrence time in alarm history (first recent alarm)	Occurrence time of alarm that occurred in past
0032h	Alarm occurrence time in alarm history	
000211	(second recent alarm)	
0033h	Alarm occurrence time in alarm history	
	(third recent alarm)	
0034h	Alarm occurrence time in alarm history	
	(fourth recent alarm)	
0035h	Alarm occurrence time in alarm history	
	(fifth recent alarm)	

Code No.	Item/Function	Reading data (RWrn+3) contents (Driver → PC or PLCetc)
0040h	Input device status 0 Reads the statuses (OFF/ON) of the input devices.	bit 0 to bit F indicate the OFF/ON statuses of the corresponding in devices.
	devices.	bitF bitO
		bit Device bit Device 0 Servo-on 8 Monitor output execution
		1 Start demand
		2 Rotation direction 9 Instruction code execution
		specifying demand
		3 Proximity dog A Next station selection 1
		4 Forward rotation stroke B Next station selection 2
		end C Next station selection 3
		5 Reverse rotation stroke D Next station selection 4
		end E Next station selection 5 6 Operation mode selection 1 F
		7 Operation mode selection 2
0041h	Input device status 1 Reads the statuses (OFF/ON) of the input devices.	bit 0 to bit F indicate the OFF/ON statuses of the corresponding in devices. bitF bit0
		bit Device bit Device
		0 Position instruction 7 Proportion control execution demand 8 Gain changing
		execution demand 8 Gain changing 1 Speed instruction 9
		execution demand A Position/speed specifying
		2 system selection
		3 Next station selection 6 B
		4 Next station selection 7 C Speed selection 1
		5 Next station selection 8 D Speed selection 2
		6 Internal torque limit E Speed selection 3
		selection F For manufacturer setting
0042h	Input device status 2 Reads the statuses (OFF/ON) of the input	bit 0 to bit F indicate the OFF/ON statuses of the corresponding in devices.
	devices.	bitF bit0
		bit Device bit Device
		0 8
		9
		2 A Reset
		5 D
		6 E
		7 F



Code No.	Item/Function	Reading data (RWrn+3) contents (Driver → PC or PLCetc)
0050h	Output device status 0 Reads the statuses (OFF/ON) of the Output devices.	bit 0 to bit F indicate the OFF/ON statuses of the corresponding output devices. bitF bit0 bit Device bit Device 0 Ready 8 Monitoring
		1 In position 9 Instruction code execution completion 2 Rough match A Warning 3 Home position return completion A Warning 4 Limiting torque C Movement completion 5 D Dynamic brake 6 Electromagnetic brake interlock F 7 F
0051h	Output device status 1 Reads the statuses (OFF/ON) of the Output devices.	bit 0 to bit F indicate the OFF/ON statuses of the corresponding output devices. bitF bit0 bit Device bit Device 0 Position instruction execution completion 7 Station output 6 1 Speed instruction execution completion 9 Station output 7 1 Speed instruction execution completion A Station output 9 2 Station output 1 B
0052h	Output device status 2 Reads the statuses (OFF/ON) of the Output devices.	bit 0 to bit F indicate the OFF/ON statuses of the corresponding output devices. bitF bit0 bit Device bit Device 0 9 1 A Trouble 2 A Trouble 3 A Trouble B Remote station communication ready 4 C 5 D 6 E 7 F 8



Code No.	Item/Function	Reading data (RWrn+3) contents (Driver → PC or PLCetc)
0081h	Energization time Reads the energization time from shipment.	Returns the energization time [h].
0082h	Power ON frequency Reads the number of power-on times from shipment.	Returns the number of power-on times.
00A0h	Ratio of load inertia moment Reads the estimated ratio of load inertia moment to servo motor shaft inertia moment.	Return unit [times].
00B0h	Home position within-1-revolution position lower 16bit (CYC0) Reads the lower 16 bits of the cycle counter value of the absolute home position.	Return unit [pulses].
00B1h	Home position within-1-revolution position upper 16bit Reads the upper 16 bits of the cycle counter value of the absolute home position.	Return unit [pulses].
00B2h	Home position Multi-revolution data (ABS0) Multi-revolution counter value of absolute home position reading.	Return unit [rev].
00C0h	Error parameter No./Point data No. reading Reads the parameter No./point table No. in error.	Parameter No. or point table No. Parameter group 0: Basic setting parameters (No.PA) 1: Gain/filter parameters (No.PB) 2: Extension setting parameters (No.PC) 3: I/O setting parameters (No.PD) Type 1: Parameter No. 2: Point table No.
0100h to 011Dh	Monitor multiplying factor Reads the multiplying factor of the data to be read with the monitor code. The instruction codes 0100 to 011D correspond to the monitor codes 0000 to 001D. 0000 applies to the instruction code that does not correspond to the monitor code.	Monitor multiplying factor 0003: ×1000 0002: ×100 0001: ×10 0000: ×1

Code No.	Item/Function	Reading data (RWrn+3) contents
0200h	Parameter group reading Reads the parameter group to be read with code No.8200h to be written.	(Driver → PC or PLCetc)
0201h to 02FFh	Parameter data reading Reads the set value of each No. of the parameter group read with code No.0200h. The decimal value converted from the 2 lower digits of the code No. corresponds to the parameter No. If the instruction code is set outside the range set in parameter No.PA19, an error code is returned and the data cannot be read.	The value set in the parameter No. corresponding to the requested group name is stored.
0301h to 03FFh	Data form of parameter Reads the data format of each No. of the parameter group read with code No.0200h. The decimal value converted from the 2 lower digits of the code No. corresponds to the parameter No. If the instruction code is set outside the range set in parameter No.PA19, an error code is returned and the data cannot be read.	The value set in the parameter No. corresponding to the requested group name is stored. O
0601h to 06FFh	Servo motor speed of point table No.1 to 255 The decimal value converted from the 2 lower digits of the code No. corresponds to the point table No.	The servo motor speed set to the requested point table No. is returned.
0701h to 07FFh	Acceleration time constant of point table No.1 to 255 The decimal value converted from the 2 lower digits of the code No. corresponds to the point table No.	The acceleration time constant set to the requested point table No. is returned.
0801h to 08FFh	Deceleration time constant of point table No.1 to 255 The decimal value converted from the 2 lower digits of the code No. corresponds to the point table No.	The deceleration time constant set to the requested point table No. is returned.



(2) Write instruction codes

Set the data, which was requested to be written with the instruction code 8010h to 91FFh. Set the instruction code No. corresponding to the item to Instruction code (RWwn+2) and the written data to Writing data (RWwn+3). The codes and answer data are all 4-digit hexadecimal numbers. When the instruction code which has not been described in this section is set, the error code ($\Box\Box\Box\Box$) is stored in respond code (RWrn+2).

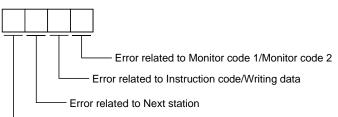
Code No.	Item	Writing data (RWwn+3) contents (PC or PLCetc→ Driver)
8010h	Alarm reset command Deactivates the alarm that occurred.	1EA5
8101h	Feedback pulse value display data is clear Resets the display data of the status indication "feedback pulse value" to 0.	1EA5
8200h	Parameter group write command Writes the group of parameters that are written to with codes No.8201h to 82FFh and 8301h to 83FFh. Writes the group of parameters that are read with codes No.0201h to 02FFh and 0301h to 03FFh.	0 0 0 Parameter group 0: Basic setting parameters (No.PA □) 1: Gain/filter parameters (No.PB □) 2: Extension setting parameters (No.PC □) 3: I/O setting parameters (No.PD □)
8201h to 82FFh	Data RAM instruction of parameter Writes the set value of each No. of the parameter group written by code No.8200h to RAM. These values are cleared when power is switched off. The decimal value converted from the 2 lower digits of the code No. corresponds to the parameter No. An error code is returned if an instruction code outside the range set in parameter No. PA19 or a value outside the setting range of the corresponding parameter is written.	Convert the decimal values into hexadecimal before setting.
8301h to 83FFh	Data EEP-ROM instruction of parameter Writes the set value of each No. of the parameter group written with code No.8200h to EEP-ROM. Written to EEP-ROM, these values are held if power is switched off. The decimal value converted from the 2 lower digits of the code No. corresponds to the parameter No. An error code is returned if an instruction code outside the range set in parameter No.PA19 or a value outside the setting range of the corresponding parameter is written.	Convert the decimal values into hexadecimal before setting.
8601h to 86FFh	Motor speed of point table Writes the motor speeds of point table No.1 to 255 to RAM. These values are cleared when power is switched off. The decimal value converted from the 2 lower digits of the code No. corresponds to the point table No.	Convert the values into hexadecimal before setting.

Code No.	Item	Writing data (RWwn+3) contents (PC or PLCetc → Driver)
8701h to 87FFh	Acceleration time constant data RAM command of point table Writes the acceleration time constants of point table No.1 to 255 to RAM. These values are cleared when power is switched off. The decimal value converted from the 2 lower digits of the code No. corresponds to the point table No.	Convert the values into hexadecimal before setting.
8801h to 88FFh	Deceleration time constant data RAM command of point table Writes the deceleration time constants of point table No.1 to 255 to RAM. These values are cleared when power is switched off. The decimal value converted from the 2 lower digits of the code No. corresponds to the point table No.	Convert the values into hexadecimal before setting.
8D01h to 8DFFh	Servo motor speed data EEP-ROM command of point table Writes the servo motor speeds of point table No.1 to 255 to EEP-ROM. Written to EEP- ROM, these values are held if power is switched off. The decimal value converted from the 2 lower digits of the code No. corresponds to the point table No.	Convert the values into hexadecimal before setting.
8E01h to 8EFFh	Acceleration time constant data EEP-ROM command of point table Writes the acceleration time constants of point table No.1 to 255 to EEP-ROM. Written to EEP-ROM, these values are held if power is switched off. The decimal value converted from the 2 lower digits of the code No. corresponds to the point table No.	
8F01h to 8FFFh	Deceleration time constant data EEP-ROM command of point table Writes the deceleration time constants of point table No.1 to 255 to EEP-ROM. Written to EEP-ROM, these values are held if power is switched off. The decimal value converted from the 2 lower digits of the code No. corresponds to the point table No.	Convert the values into hexadecimal before setting.



15.2.5 Respond codes (RWrn+2)

If any of the monitor codes, instruction codes, Next station, Point table Nos./Speed command data set to the remote register is outside the setting range, the corresponding error code is set to respond code (RWwn+2). "0000" is set if they are normal.



- Error related to point table No./Speed command data

Code No.	Error	Details
0	Normal answer	Instruction was completed normally.
1	Code error	The monitor code not in the specifications was set.Read/write of the point table of No.255 or later was set.
2	Parameter - point table selection error	The parameter No. disabled for reference was set.
3	Write range error	An attempt was made to write the parameter or point table data outside the setting range.



15.3 Signal 15.3.1 Signal (device) e<u>xplanation</u>

POINT	
 In the index 	er positioning operation, devices assigned to the CN6 connector
cannot be c	changed.
	In the index

(1) I/O device

(a) Input device

Device	Symbol	Connector pin No.			Functions/	Applications		
Forced stop	EMG	CN6-1	Turn EMG off (open between commons) to bring the motor to an emergency stop state, in which the base circuit is shut off and the dynamic brake is operated. Turn EMG on (short between commons) in the emergency stop state to reset that state.					
Proximity dog	DOG	CN6-2	When DOG is turned OFF, the proximity dog is detected. The polarity of dog detection can be changed using parameter No.PD16. Parameter No.PD16 Proximity dog (DOG) detection polarity				/ of dog	
				□0□□ (initi	al value)	OF	FF	
						0	N	
Forward rotation stroke end	LSP	CN6-3	When starting operation, turn LSP/LSN to ON. Turning it to OFF causes a					
Reverse rotation stroke end	LSN	CN6-4	sudden stop, resulting in servo lock. A stopping method can be changed in parameter No.PD20. When not using the forward/reverse rotation stroke end, set "Automatic ON" in parameter No.PD01.					-
			(Note) Input signal Operation					
				LSP	LSN	CCW direction	CW direction	
				1	1	0	0	
				0	1		0	
				1	0	0		
				0	0			
			1	Note. 0: OFF 1: ON				

(b) Output device

POINT

• Output devices assigned to the CN6 connector pins can be used with the remote output of the CC-Link communication function.

Device	Symbol	Connector pin No.	Functions/Applications
Ready	RD	CN6-14	RD turns ON when the driver is ready to operate after servo-on.
Trouble	ALM	CN6-15	ALM turns off when power is switched off or the protective circuit is activated to shut off the base circuit. Without alarm occurring, ALM turns on within 1.5s after power-on. The significance of this device is opposite of that of remote output (RX (n+1)A or RX (n+3)A).
Home position return completion	ZP	CN6-16	 ZP turns ON when a home position return is completed. ZP turns ON at completion of a home position return. In an absolute position detection system, RXn3 turns ON when operation is ready to start, but turns OFF in any of the following cases. 1) Servo-on (RYn0) is turned OFF. 2) Forced stop (EMG) is turned OFF. 3) Reset (RY(n+1)A or RY(n+3)A) is turned ON. 4) Alarm occurs. 5) Forward rotation stroke end (LSP) or Reverse rotation stroke end (LSN) is turned OFF. 6) Home position return has not been made after product purchase. 7) Home position return has not been made after occurrence of Absolute position erase (A25) or Absolute position counter warning (AE3). 8) Home position return has not been made after electronic gear change. 9) Home position return has not been made after the absolute position detection system was changed from invalid to valid. 10) Parameter No.PA14 (Station No. direction selection) has been changed. 11) While a home position return is being made. When any of 1) to 11) has not occurred and a home position return is already completed at least once, Home position return completion (ZP) turns to the same output status as Ready (RD).

(2) Input signals

Device	Symbol	Connector pin No.	Functions/Applications
Manual pulse generator	PP	CN6-6	Not used in indexer positioning operation.
	NP	CN6-19	

(3) Output signals

Refer to section 4.8.2 for the output interfaces (symbols in the I/O Division field in the table) of the corresponding connector pins.

Device	Symbol	Connecto r pin No.	Functions/Applications	I/O division
Encoder A-phase pulse (differential line driver)	LA LAR	CN6-11 CN6-24	Outputs pulses per servo motor revolution set in parameter No.PA15 in the differential line driver system. In CCW rotation of the servo motor, the encoder B-phase pulse lags the encoder A-phase pulse by	DO-2
Encoder B-phase pulse (differential line driver)	LB LBR	CN6-12 CN6-25	a phase angle of $\pi/2$. The relationships between rotation direction and phase difference of the A- and B-phase pulses can be changed using parameter No.PC19	
Encoder Z-phase pulse (differential line driver)	LZ LZR	CN6-13 CN6-26	Outputs the zero-point signal of the encoder in the differential line driver system. One pulse is output per servo motor revolution. This signal turns on when the zero-point position is reached. (Negative logic) The minimum pulse width is about 400μ s. For home position return using this pulse, set the creep speed to $100r/min$. or less.	DO-2

(4) Power supply

Signal	Symbol	Connector pin No.	Functions/Applications	I/O division
Digital I/F power supply input	DICOM	CN6-5	Used to input 24VDC (24VDC±10% 150mA) for I/O interface. The power supply capacity changes depending on the number of I/O interface points to be used. Connect the plus of 24VDC terminal external power supply for the sink interface.	
Digital I/F common	DOCOM	CN6-17	Common terminal for input signals such as DOG and EMG. Pins are connected internally. Separated from LG. Connect the plus of 24VDC terminal external power supply for the source interface.	
Control common	LG	CN6-23	Common terminal for the differential line driver of the encoder pulses (LA · LAR · LB · LBR · LZ · LZR).	
Shield	SD	Plate	Connect the external conductor of the shield cable.	

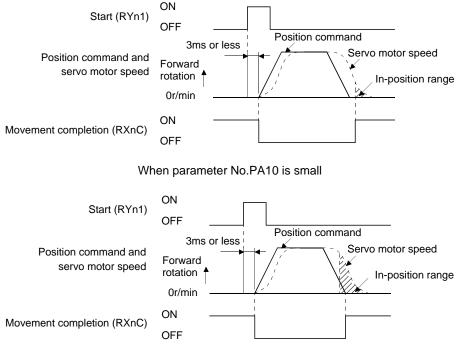


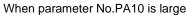
- 15.3.2 Detailed description of signals (devices)
- (1) Forward rotation start reverse rotation start temporary stop/restart
 - (a) A start (RYn1) should make the sequence which can be used after the main circuit has been established. These signals are invalid if it is switched on before the main circuit is established. Normally, it is interlocked with the ready signal (RD).
 - (b) A start in the driver is made when a start (RYn1) changes from OFF to ON. The delay time of the driver's internal processing is max. 3ms. The delay time of other devices is max. 10ms.
 - (c) The ON time of a start (RYn1), should be 6ms or longer to prevent a malfunction.
 - (d) During operation, the start (RYn1) is not accepted. The next operation should always be started after the rough match (RXn2) is output with the rough match output range set to "0" or after the movement completion (RXnC) is output.
- (2) Movement completion rough match in position

 POINT
 If an alarm cause, etc. are removed and servo-on occurs after a stop is made by servo-off, alarm occurrence or Forced stop (EMG) ON during automatic operation, Movement completion (MEND), Rough-match, (CPO) and In position (INP) are turned on. To resume operation, confirm the current position and the selected point table No. for preventing unexpected operation.

(a) Movement completion

The following timing charts show the output timing relationships between the position command generated in the driver and the movement completion (RYnC). This timing can be changed using parameter No.PA10 (in-position range). RYnC turns ON in the servo-on status.

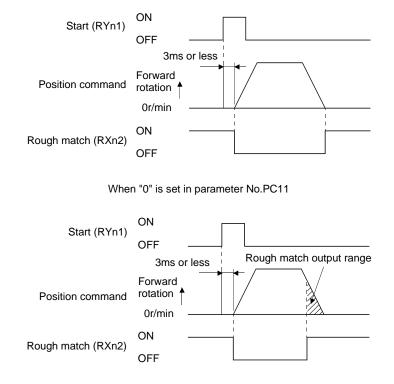






(b) Rough match

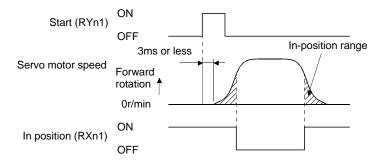
The following timing charts show the relationships between the signal and the position command generated in the driver. This timing can be changed using parameter No.PC11 (rough match output range). RXn2 turns ON in the servo-on status.



When more than "0" is set in parameter No.PC11

(c) In position

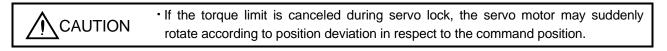
The following timing chart shows the relationship between the signal and the feedback pulse of the servo motor. This timing can be changed using parameter No.PA10 (in-position range). turns on RYn1 in the servo-on status.



When positioning operation is performed once



(3) Torque limit

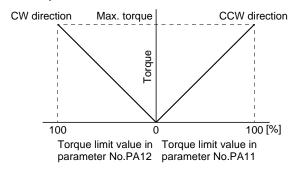


POINT

• In the indexer positioning operation, the torque limit 2 becomes automatically effective depending on the operation status.

(a) Torque limit and torque

By setting parameter No.PA11 (forward rotation torque limit) or parameter No.PA12 (reverse rotation torque limit), torque is always limited to the maximum value during operation. A relationship between the limit value and servo motor torque is shown below.



(b) Torque limit value selection

As shown below, the forward rotation torque limit (parameter No.PA11), reverse rotation torque limit (parameter No.PA12) or internal torque limit 2 (parameter No.PC35) can be chosen using the external torque limit selection (RY(n+2)6).

				Torque limit to be enabled		
(Note) RY(n+2) 6	Limit value status			CCW driving/CW	CW driving/CCW	
				regeneration	regeneration	
0				Parameter No.PA11	Parameter No.PA12	
1	Parameter No.PC35	>	Parameter No.PA11 Parameter No.PA12	Parameter No.PA11	Parameter No.PA12	
1	Parameter No.PC35	<	Parameter No.PA11 Parameter No.PA12	Parameter No.PC35	Parameter No.PC35	
Note 0: OEE						

Note. 0: OFF 1: ON

(c) Limiting torque (RXn4)

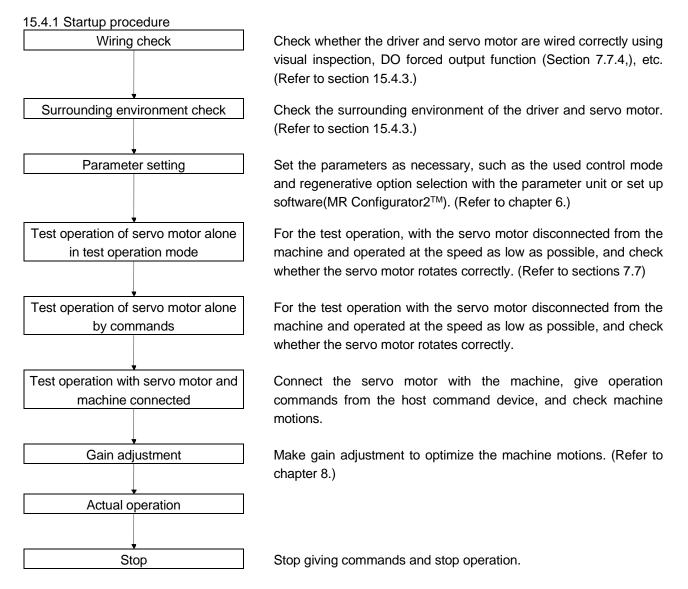
RXn4 turns on when the servo motor torque reaches the torque limited.



15.4 Switching power on for the first time

 Do not operate the switches with wet hands. You may get an electric shock.
 Before starting operation, check the parameters. Some machines may perform unexpected operation.
• Take safety measures, e.g. provide covers, to prevent accidental contact of hands and parts (cables, etc.) with the driver heat sink, regenerative resistor, servo motor, etc. since they may be hot while power is on or for some time after power-off. Their temperatures may be high and you may get burnt or a parts may damaged.
 During operation, never touch the rotating parts of the servo motor. Doing so can cause injury.

When switching power on for the first time, follow this section to make a startup.



15 - 30

- 15.4.2 Wiring check
- (1) Power supply system wiring

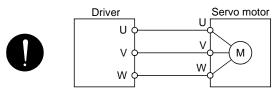
Before switching on the main circuit and control circuit power supplies, check the following items.

(a) Power supply system wiring

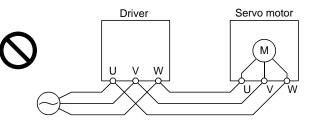
The power supplied to the power input terminals (L_1 , L_2 , L_3 , L_{11} , L_{21}) of the driver should satisfy the defined specifications. (Refer to section 1.2.)

(b) Connection of driver and servo motor

1) The servo motor power supply terminals (U, V, W) of the driver match in phase with the power input terminals (U, V, W) of the servo motor.



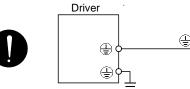
 The power supplied to the driver should not be connected to the servo motor power supply terminals (U, V, W). To do so will fail the connected driver and servo motor.



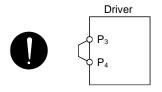
Servo motor

M)

3) The earth terminal of the servo motor is connected to the PE terminal of the driver.



4) P₃-P₄ should be connected.



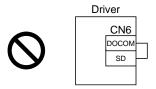
- (c) When option and auxiliary equipment are used
 - 1) When regenerative option is used under 3.5kW for 200V class
 - The lead between P terminal and D terminal of CNP2 connector should not be connected.
 - The generative brake option should be connected to P terminal and C terminal.
 - A twisted cable should be used. (Refer to section 13.2.)



- (2) I/O signal wiring
 - (a) The I/O signals should be connected correctly.

Use DO forced output to forcibly turn on/off the pins of the CN6 connector. This function can be used to perform a wiring check. (Refer to section 7.7.4.) In this case, switch on the control circuit power supply only.

- (b) 24VDC or higher voltage is not applied to the pins of connectors CN6.
- (c) SD and DOCOM of connector CN6 is not shorted.



- 15.4.3 Surrounding environment
- (1) Cable routing
 - (a) The wiring cables are free from excessive force.
 - (b) The encoder cable should not be used in excess of its flex life. (Refer to section 12.4.)
 - (c) The connector part of the servo motor should not be strained.
- (2) Environment

Signal cables and power cables are not shorted by wire offcuts, metallic dust or the like.



15.5 Startup

15.5.1 Power on and off procedures

(1) Power-on

Switch power on in the following procedure. Always follow this procedure at power-on.

- 1) Switch off the servo-on (RYn0).
- 2) Make sure that the start (RYn1) is off.
- 3) Switch on the main circuit power supply and control circuit power supply. When main circuit power/control circuit power is switched on, the driver display shows "b01" (if the driver has the station number of 1).

In the absolute position detection system, first power-on results in the absolute position lost (A25) alarm and the servo system cannot be switched on.

The alarm can be deactivated then switching power off once and on again.

Also in the absolute position detection system, if power is switched on at the servo motor speed of 3000r/min or higher, position mismatch may occur due to external force or the like. Power must therefore be switched on when the servo motor is at a stop.

(2) Power-off

- 1) Make sure that the start (RYn1) is off.
- 2) Switch off the Servo-on (RYn0).
- 3) Switch off the main circuit power supply and control circuit power supply.

15.5.2 Stop

In any of the following statuses, the driver interrupts and stops the operation of the servo motor. Refer to section 4.11 for the servo motor equipped with a lock.

(a) Servo-on (RYn0) OFF

The base circuit is shut off and the servo motor coasts.

(b) Alarm occurrence

When an alarm occurs, the base circuit is shut off and the dynamic brake is operated to bring the servo motor to a sudden stop.

(c) Forced stop (EMG) OFF

The base circuit is shut off and the dynamic brake is operated to bring the servo motor to a sudden stop. The servo forced stop warning (AE6) occurs.

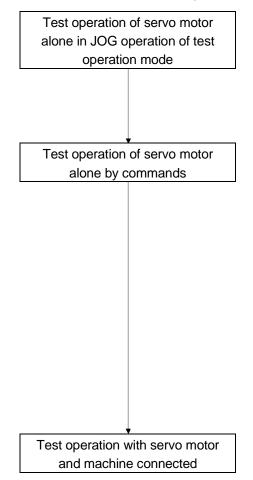
(d) Forward rotation stroke end (LSP), reverse rotation stroke end (LSN) OFF

The droop pulse value is erased and the servo motor is stopped and servo-locked. It can be run in the opposite direction.



15.5.3 Test operation

Before starting actual operation, perform test operation to make sure that the machine operates normally. Refer to section 15.5.1 for the power on and off methods of the driver.



In this step, confirm that the driver and servo motor operate normally.

With the servo motor disconnected from the machine, use the test operation mode and check whether the servo motor correctly rotates at the slowest speed. Refer to section 7.7 or the test operation mode.

In this step, confirm that the servo motor correctly rotates at the slowest speed under the commands from the command device. Make sure that the servo motor rotates in the following procedure.

- Switch on the Forced stop (EMG) and Servo-on (RYn0). When the driver is put in a servo-on status, the Ready (RD) switches on.
- 2) Switch on the Forward rotation stroke end (LSP) or Reverse rotation stroke end (LSN).
- 3) When the point table is designated to switch on the start (RYn1) the servo motor starts rotating. Give a low speed command at first and check the rotation direction, etc. of the servo motor. If the servo motor does not operate in the intended direction, check the input signal.

In this step, connect the servo motor with the machine and confirm that the machine operates normally under the commands from the command device.

Make sure that the servo motor rotates in the following procedure.

- 1) Switch on the Forced stop (EMG) and Servo-on (RYn0). When the driver is put in a servo-on status, the Ready (RD) switches on.
- 2) Switch on the Forward rotation stroke end (LSP) or Reverse rotation stroke end (LSN).
- 3) When the point table is specified from the command device and the start (RYn1) is turned ON, the servo motor starts rotating. Give a low speed command at first and check the operation direction, etc. of the machine. If the machine does not operate in the intended direction, check the input signal. In the status display, check for any problems of the servo motor speed, load ratio, etc.
- 4) Then, check automatic operation with the program of the command device.



15.5.4 Parameter setting

The driver can be used by merely changing the basic setting parameters (No.PA \square) mainly. As necessary, set the gain filter parameters (No.PB \square), extension setting parameters (No.PC \square) and I/O setting parameters (No.PD \square).

Parameter group	Main description
Basic setting parameter	Set the basic setting parameters first. Generally, operation can be performed by merely setting this
(No.PA□□)	parameter group.
	In this parameter group, set the following items.
	Control mode selection (select the position control mode)
	Regenerative option selection
	Absolute position detection system selection
	Setting of command input pulses per revolution
	Electronic gear setting
	Auto tuning selection and adjustment
	In-position range setting
	Torque limit setting
	Command pulse input form selection
	Servo motor rotation direction selection
	Encoder output pulse setting
Gain filter parameter	If satisfactory operation cannot be achieved by the gain adjustment made by auto tuning, execute
(No.PB□□)	in-depth gain adjustment using this parameter group.
	This parameter group must also be set when the gain changing function is used.
Extension setting parameter (No.PC□□)	This parameter group is unique to LECSC2-T driver.
I/O setting parameter (No.PD□□)	Set the stopping method of the stroke end (LSP and LSN), torque limit delay time and others.



15.5.5 Point table setting

Set necessary items to the point table before starting operation. The following table indicates the items that must be set.

Name	Description
Position data	Not used in indexer positioning operation.
Position data	Do not change this value by any means.
Conversion and a	Sets the command rotation speed (Motor rotations/min) when positioning is executed.
Servo motor speed	Please set within allowable speed of each actuator.
	Set the time until the servo motor reaches the rated speed. (3000 r/min)
Acceleration time constant	Please set within allowable acceleration time constant of each actuator.
Deceleration time constant	Set the time until the servo motor slows down to the rated speed. (3000 r/min)
Deceleration time constant	Please set within allowable deceleration time constant of each actuator.
Durall	Not used in indexer positioning operation.
Dwell	Do not change this value by any means.
Auxiliant function	Not used in indexer positioning operation.
Auxiliary function	Do not change this value by any means.

15.5.6 Actual operation

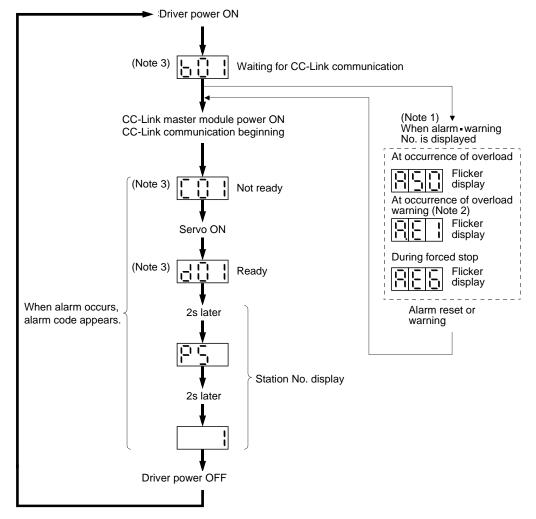
Start actual operation after confirmation of normal operation by test operation and completion of the corresponding parameter settings. Perform a home position return as necessary.



15.6 Driver display

On the driver display (three-digit, seven-segment display), check the status of communication with the CC-Link driver at power-on, check the station number, and diagnose a fault at occurrence of an alarm.

(1) Display sequence



Note 1. Only alarm and warning No. are displayed, but no station No. is displayed.

- 2. If warning other than AE6 occurs during the servo on, flickering the second place of decimal point indicates that it is during the servo on.
- 3. The right-hand segments of b01, c02 and d16 indicate the axis number. (Below example indicates Station No.1)

58 I	5 8 3	··884
Station No.1		Station No.64



15. INDEXER POSITIONING OPERATION

(2) Indication list

Indic	ation	Status	Description
	b##	Waiting for CC-Link communication	 Power of the CC-Link master module was switched on at the condition that the power of CC-Link master module is OFF. The CC-Link master module is faulty.
(Note 1)	d # #	Ready	The servo was switched on after completion of initialization and the driver is ready to operate. (This is indicated for 2 seconds.)
(Note 1)	C # #	Not ready	The driver is being initialized or an alarm has occurred.
(Note 2)	\$\$\$	Ready for operation	Two seconds have passed after the driver is ready to operate by turning ON the servo-on (RYn1).
(Note 3)	A * *	Alarm · Warning	The alarm No./warning No. that occurred is displayed. (Refer to section 15.12.4.)
	888	CPU error	CPU watchdog error has occurred.
(Note 4)	b 0 0.		JOG operation \cdot positioning operation \cdot programmed operation \cdot DO forced output
(Note 1)	d # #. C # #.	(Note 4) Test operation mode	Motor-less operation

Note 1. ## denotes any of numerals 00 to 16 and what it means is listed below.

##	Description					
00	Set to the test operation mode.					
01	Station number 1					
02	Station number 2					
03	Station number 3					
:	:					
:	:					
62	Station number 62					
63	Station number 63					
64	Station number 64					

Note 2. \$\$\$ indicates numbers from 0 to 254, and the number indicates the executing station number.

- 3. ** indicates the warning/alarm No.
- 4. Requires set up software(MR Configurator2[™]).



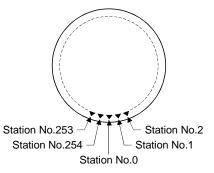
15.7 Automatic operation mode

	_
POINT	
 In the absolute position detection system, the following restriction condition 	
applies for the number of gears on machine-side (parameter No.PA06 CMX)	
and servo motor speed (N).	
• When CMX \leq 2000, N < 3076.7 r/min	
• When CMX $>$ 2000, N $<$ 3276.7–CMX r/min	
 When the servo motor is operated at servo motor speed higher than the limit value, the absolute position counter warning (AE3) occurs. 	
	_

15.7.1 What is automatic operation mode?

(1) Concept of indexer

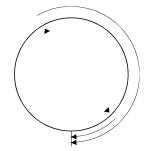
Select the station, which is dividing the circumference (360 degrees) of the machine side into up to 255, using 8-bit device of the next station selection 1 to 8 (RYnA to RYnE, and RY(n+2)3 to RY(n+2)5), and execute positioning.

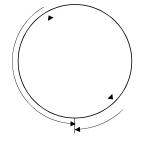


Set the number of stations in the parameter No.PC46.

(2) Rotation direction

There are two types of operation methods: Rotation direction specifying indexer, which is to always rotate in the fixed direction and execute positioning to a station, and Shortest rotating indexer, which is to automatically change the rotation direction for the shortest distance and execute positioning to a station.





Rotation direction specifying indexer

Shortest rotating indexer



15.7.2 Automatic operation mode 1 (Rotation direction specifying indexer) In this operation mode, the servo motor rotates in the fixed direction and executes positioning to a station.

(1) When not using the remote register

Select the station number using 8-bit device of the next station selection 1 to 8 (RYnA to RYnE, and RY(n+2)3 to RY(n+2)5), and execute positioning. For the servo motor speed and acceleration/ deceleration time constant during operation, the value set in the point table is used.

(a) Device/Parameter

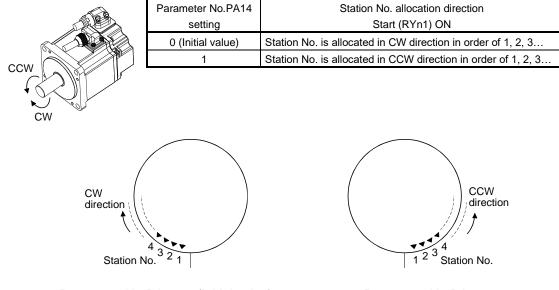
Set the input devices and parameters as indicated below.

Item	Device/Parameter	Setting description
Indexer positioning operation	Parameter No.PA01	1 . Select the indexer positioning
selection		operation.
Automatic operation mode 1	Operation mode selection 1 (RYn6)	Turn off RYn6.
(Rotation direction specifying indexer) selection	Operation mode selection 2 (RYn7)	Turn on RYn7.

(b) Other parameter settings

1) Setting the allocation direction of station numbers

Select the allocation direction of station numbers using the parameter No.PA14 (Station No. direction selection).



Parameter No.PA14: 0 (Initial value)

Parameter No.PA14: 1



2) Setting the number of stations

Set the number of stations in the parameter No.PC46.

	Parameter No.PC46 setting value								
	0000 to 0002	0003	0004		00FF				
Number of stations	2	3	4	• • •	255				
Station No.	No.1	No.2 No.0	No.3 No.3 No.0		No.254 No.0 No.1				

(c) Setting the speed data

Set the servo motor speed, acceleration time constant, and deceleration time constant in the point table number 1 to 8.

Name	Setting range	Unit	Description
Servo motor speed	0 to permissible speed	r/min	Set the command speed of the servo motor for execution of positioning. The setting should be equal to or less than the instantaneous permissible speed of the servo motor.
Acceleration time constant	0 to 20000	ms	Set the time until the rated speed of the servo motor is reached.
Deceleration time constant	0 to 20000	ms	Set the time until the servo motor running at rated speed comes to a stop.

(d) Operation

Select the station number for positioning, using 8-bit device of the next station selection 1 to 8 (RYnA to RYnE, and RY(n+2)3 to RY(n+2)5).

(Note) Device								
2 stations occupied 1 stations occupied								Station No.
RY(n+2)5	RY(n+2)4	RY(n+2)3	RYnE	RYnD	RYnC	RYnB	RYnA	
0	0	0	0	0	0	0	0	0
0	0	0	0	0	0	0	1	1
0	0	0	0	0	0	1	0	2
0	0	0	0	0	1	0	1	3
-	-			-				
•	•	•	•	•		•	•	•
•	-			-				-
1	1	1	1	1	1	0	1	253
1	1	1	1	1	1	1	0	254

Note. 0: OFF 1: ON



Select the point table using the speed selection 1 (RY(n+2)C) to speed selection 3 (RY(n+2)E). Turn on the start (RYn1) to execute positioning with the speed data set in the point table. Rotation direction of the servo motor is the direction set in the rotation direction specifying (RYn2). When one station is occupied, RY(n+2)C, RY(n+2)D, and RY(n+2)E are not available so that the point table number cannot be selected. Use point table No.1 when one station is occupied.

	(Note) Device	•	Point table No.
RY(n+2)E	RY(n+2)D	RY(n+2)C	Point table No.
0	0	0	1
0	0	1	2
0	1	0	3
0	1	1	4
1	0	0	5
1	0	1	6
1	1	0	7
1	1	1	8

Note. 0: OFF 1: ON



(e) Timing chart

POINT
 Always execute a home position return. The home positioning incomplete (A90) occurs when turning on the start (RYn1) without executing a home position return.

The timing chart is shown below.

Operation mode selection 1 (RYn6)	ON OFF								
Operation mode selection 2 (RYn7)	ON — OFF								
Servo-on (RYn0)	ON OFF	Î							
(Note 2) Next station selection 1 to 8 (RYnA to RYnE • RY(n+2)3 to F	RY(n+2)5)		No.1	No.3	Not	e 4)	No.1		
Speed selection 1 to 3 (RY(n+2)C to RY(n+2)E)		1 1 1	Point table Note 1)		s or more	Po	int table No.:	2	
Start (RYn1)	ON OFF		(Note 3)-						
Rotation direction specifying (RYn2)	ON OFF		3ms or less						
(Note 5) Servo motor speed	Forward rotation 0r/min Reverse rotation	1 1	*1		*2		/ *3		
In position (RXn1)	ON OFF	(Note 7)			<u></u>				
Rough match (RXn2)	ON OFF							¦	
Movement completion (RXnC)	ON OFF							<u> </u> [
Station output 1 to 8 (RX(n+2)2 to RX(n+2)9)				No.1	/	No.3	×	\rightarrow	No.1
Torque limit value to be effective	ON — OFF—		Out of in-positi range / (Note 6)		Out of in-pos		Out of in- range	· · ·	n (Note 6)
	Parameter No	o.PC35 /	Parameter		/	meter No.P	1		No.PC35
	Parame	ter No.PA	11. PA12 P	'arameter	No.PA11.	PA12	Parameter N	No.PA1	1, PA12



- Note 1. Configure a sequence that changes the next station selection (RYnA to RYnE and RY(n+2)3 to RY(n+2)5) and speed selection (RY(n+2)C to RY(n+2)E) earlier, considering the delay time of CC-Link communication.
 - 2. When the selected station number exceeds the value that is dividing number set in the parameter No.PC46 minus one, the next station warning (A97) occurs.
 - 3. The start (RYn1) is invalid even if it is turned on during operation. When executing another operation, turn on RYn1 after the movement completion (RXnC) turns on.
 - 4. Change of the servo motor speed and acceleration/deceleration time constant by the speed selection 1 (RY(n+2)C) to speed selection 3 (RY(n+2)E) becomes effective when the start (RYn1) turns on. Even if the speed selection 1 to 3 are changed during servo motor rotation, they do not become effective.
 - 5. The following shows the operation to be executed.

Operation	*1	*2	*3
Station	No.1	No.3	No.1
Servo motor speed Acceleration/deceleration time constant	Point table No.1	Point table No.1	Point table No.2
Positioning			

- 6. Delay time from when RXn1 turns on until the torque limit value changes to the parameter No.PC35 value can be set in the parameter No.PD26.
- 7. After power-on, if the current position is within the in-position range of each station, the in position (RXn1) turns on.

(2) When using the remote register

Select the station number using the next station (RWwn+4) remote register and execute positioning. For the speed data during operation, select the point table number using the point table No./Speed command data (RWwn+6) remote register, or directly set the servo motor speed.

(a) Device/Parameter

Set the input devices and parameters as indicated below.

Item	Device/Parameter	Setting description
Indexer positioning operation selection	Parameter No.PA01	1□□□: Select the indexer positioning operation.
Speed data setting method selection	Parameter No.PC30	Select the setting method for speed data.
Automatic operation mode 1 (Rotation direction specifying indexer)	Operation mode selection 1 (RYn6)	Turn off RYn6.
selection	Operation mode selection 2 (RYn7)	Turn on RYn7.
Position/speed specifying system selection	Position/speed specifying system selection (RY(n+2)A)	Turn on RY(n+2)A.



- (b) Other parameter settings
 - Setting the servo motor rotation direction and allocation direction of station numbers Select the allocation direction of station numbers using the parameter No.PA14 (Station No. direction selection). Setting is the same as that for when not using the remote register. Refer to (1) (b) 1) in this section.
 - 2) Setting the number of stations

Set the number of stations in the parameter No.PC46. Setting is the same as that for when not using the remote register. Refer to (1) (b) 2) in this section.

(c) Setting the speed data

1) When using the speed data of point table

Set the servo motor speed, acceleration time constant, and deceleration time constant in the point table number 1 to 8.

Name	Setting range	Unit	Description
Servo motor speed	0 to permissible speed	r/min	Set the command speed of the servo motor for execution of positioning. The setting should be equal to or less than the instantaneous permissible speed of the servo motor.
Acceleration time constant	0 to 20000	ms Set the time until the rated speed of the servo motor is reached.	
Deceleration time constant	0 to 20000	ms	Set the time until the servo motor running at rated speed comes to a stop.

(2) When directly setting the servo motor speed (only when two stations are occupied) Set the followings because the acceleration time constant and deceleration time constant of the point table No.1 are used.

Name	Setting range	Unit	Description
Servo motor speed	0 to permissible speed	r/min	Setting is not required.
Acceleration time constant	0 to 20000	ms	Set the time until the rated speed of the servo motor is reached.
Deceleration time constant	0 to 20000	ms	Set the time until the servo motor running at rated speed comes to a stop.

(d) Operation

1) When using the speed data of point table

Set the station number for positioning by using the next station (RWwn+4) remote register. Set the point table number in the point table No./Speed command data (RWwn+6) remote register. Turn on the start (RYn1) to execute positioning with the speed data set in the point table.

2) When directly setting the servo motor speed (only when two stations are occupied)

Set the station number for positioning by using the next station (RWwn+4) remote register. Set the servo motor speed in the point table No./Speed command data (RWwn+6) remote register. Turn on the start (RYn1) to execute positioning with the servo motor speed set in RWwn+6 and the acceleration time constant and deceleration time constant set in the point table No.1.

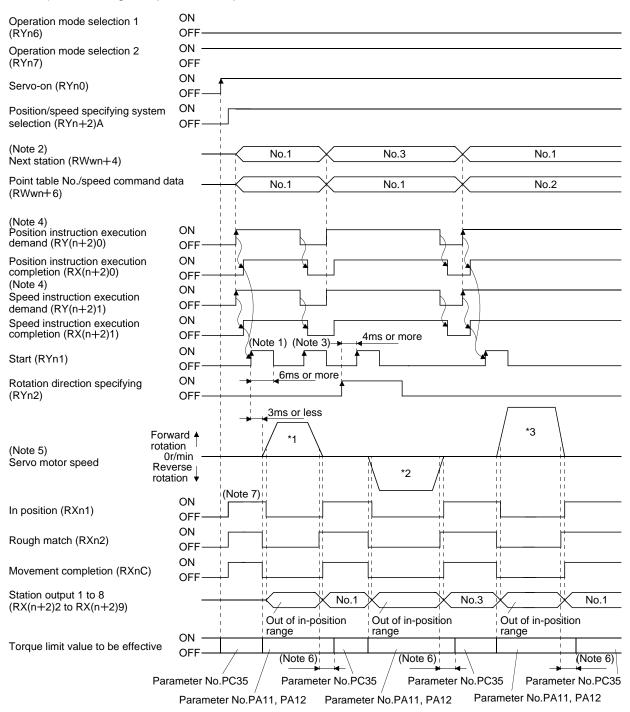


(e) Timing chart

POINT
 Always execute a home position return. The home positioning incomplete (A90) occurs when turning on the start (RYn1) without executing a home position return.

The timing chart is shown below.

1) When using the speed data of point table





- Note 1. Configure a sequence that changes RWwn+4 and RWwn+6 earlier, considering the delay time of CC-Link communication.
 - 2. When the selected station number exceeds the value that is dividing number set in the parameter No.PC46 minus one, the next station warning (A97) occurs
 - 3. The start (RYn1) is invalid even if it is turned on during operation. When executing another operation, turn on RYn1 after the movement completion (RXnC) turns on.
 - 4. For details of the operation timing of RY(n+2)0 and RY(N+2)1, refer to the section 3.6.2 (3).
 - 5. The following shows the operation to be executed.

Operation	*1	*2	*3
Station	No.1	No.2	No.3
Servo motor speed Acceleration/deceleration time constant	Point table No.1	Point table No.1	Point table No.2
Positioning			

- 6. Delay time from when RXn1 turns on until the torque limit value changes to the parameter No.PC35 value can be set in the parameter No.PD26.
- 7. After power-on, if the current position is with the in-position range of each station, the in position (RXn1) turns on.



Operation mode selection 1 (RYn6)	ON OFF—	
Operation mode selection 2 (RYn7)	ON — OFF	
Servo-on (RYn0)	ON OFF—	
Position/speed specifying syst selection (RYn+2)A	tem ON OFF—	
(Note 2) Next station (RWwn+4)		No.1 No.3 No.1
Point table No./Speed comma (RWwn+6)	nd data	I Speed 1 I Speed 2 I Speed 3
(Note 4) Position instruction execution demand (RY(n+2)0)	ON	
Position instruction execution completion (RX(n+2)0) (Note 4)	OFF ON OFF—	
Speed instruction execution demand (RY(n+2)1)	ON OFF—	
Speed instruction execution completion $(RX(n+2)1)$	ON OFF—	4ms or more
Start (RYn1)	ON	(Note 1) (Note 3)
Rotation direction specifying (RYn2)	OFF ON OFF—	6ms or more
	Forward rotation 0r/min Reverse	3ms or less *1 *3
	rotation •	(Note 7)
In position (RXn1)	ON OFF—	
Rough match (RXn2)	ON OFF	
Movement completion (RXnC)	ON OFF—	
Station output 1 to 8 (RX(n+2)2 to RX(n+2)9)		No.1 No.3 No.1 No.1
Torque limit value to be effecti	ON — ^{ive} OFF—	Out of in-position range Out of in-position range (Note 6) (Note 6)
	Parameter N	
	Parame	eter No.PA11, PA12 Parameter No.PA11, PA12 Parameter No.PA11, PA12

2) When directly setting the servo motor speed



- Note 1. Configure a sequence that changes RWwn+4 and RWwn+6 earlier, considering the delay time of CC-Link communication.
 - 2. When the selected station number exceeds the value that is dividing number set in the parameter No.PC46 minus one, the next station warning (A97) occurs.
 - 3. The start (RYn1) is invalid even if it is turned on during operation. When executing another operation, turn on RYn1 after the movement completion (RXnC) turns on.
 - 4. For details of the operation timing of RY(n+2)0 and RY(N+2)1, refer to the section 3.6.2 (3).
 - 5. The following shows the operation to be executed.

Operation	*1	*2	*3
Station	No.1	No.3	No.1
Servo motor speed	Speed 1	Speed 2	Speed 3
Acceleration/deceleration time constant	Point table No.1	Point table No.1	Point table No.1
Positioning			

- 6. Delay time from when RXn1 turns on until the torque limit value changes to the parameter No.PC35 value can be set in the parameter No.PD26.
- 7. After power-on, if the current position is with the in-position range of each station, the in position (RXn1) turns on.



15.7.3 Automatic operation mode 2 (Shortest rotating indexer)

In this operation mode, the servo motor automatically changes the direction for the shortest distance and executes positioning.

(1) When not using the remote register

Select the station number using 8-bit device of the next station selection 1 to 8 (RYnA to RYnE, and RY(n+2)3 to RY(n+2)5), and execute positioning. For the servo motor speed and acceleration/ deceleration time constant during operation, the value set in the point table is used.

(a) Device/Parameter

Set the input devices and parameters as indicated below.

Item	Device/Parameter	Setting description
Indexer positioning operation	Parameter No.PA01	1□□□: Select the indexer positioning
selection		operation.
Automatic operation mode 2	Operation mode selection 1 (RYn6)	Turn on MD0.
(Rotation direction specifying indexer) selection	Operation mode selection 2 (RYn7)	Turn on MD1.

(b) Other parameter settings (Setting the number of stations)

Set the number of stations in the parameter No.PC46. Setting is the same as that for the automatic operation mode 1. Refer to (1) (b) 2) in section 15.7.2.

In the automatic operation mode 2, the station No. direction selection (parameter No.PA14) is not used.

(c) Setting the speed data

Set the servo motor speed, acceleration time constant, and deceleration time constant in the point table number 1 to 8. Setting is the same as that for the automatic operation mode 1. Refer to (1) (c) in section 15.7.2.

(d) Operation

Select the station number for positioning, using 8-bit device of the next station selection 1 to 8 (RYnA to RYnE, and RY(n+2)3 to RY(n+2)5).

(Note) Device								
2 stations occupied 1 stations occupied						Station No.		
RY(n+2)5	RY(n+2)4	RY(n+2)3	RYnE	RYnD	RYnC	RYnB	RYnA	
0	0	0	0	0	0	0	0	0
0	0	0	0	0	0	0	1	1
0	0	0	0	0	0	1	0	2
0	0	0	0	0	1	0	1	3
	•		•	•	•	• • •	• • •	-
1	1	1	1	1	1	1	0	253 254

Note. 0: OFF

1: ON



Select the point table using the speed selection 1 (RY(n+2)C) to speed selection 3 (RY(n+2)E). Turn on the start (RYn1) to execute positioning with the speed data set in the point table. When one station is occupied, RY(n+2)C, RY(n+2)D, and RY(n+2)E are not available so that the point table number cannot be selected. Use the point table No.1 when one station is occupied.

	(Note) Device		Pint table No.
RY(n+2)E	RY(n+2)D	RY(n+2)C	Pint table No.
0	0	0	1
0	0	1	2
0	1	0	3
0	1	1	4
1	0	0	5
1	0	1	6
1	1	0	7
1	1	1	8

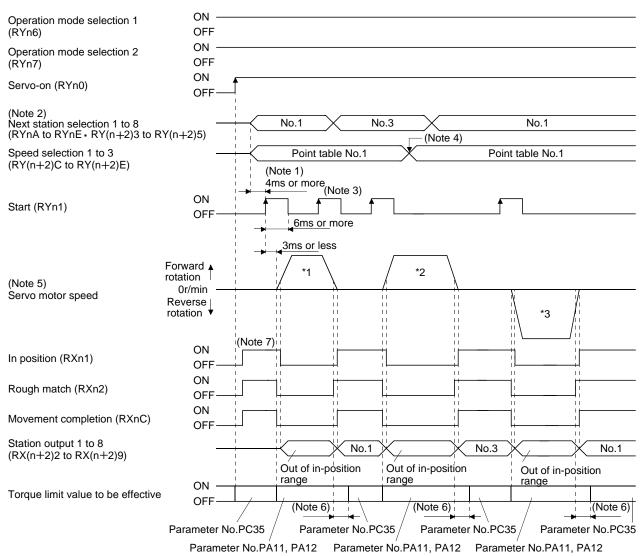
Note. 0: OFF 1: ON



(e) Timing chart

POINT				
 Always exe 	ecute a home position return. The home positioning incomplete			
(A90) occu	(A90) occurs when turning on the start (RYn1) without executing a home			
position ret	urn.			

The timing chart is shown below.





- Note 1. Configure a sequence that changes the next station selection (RYnA to RYnE and RY(n+2)3 to RY(n+2)5) and speed selection (RY(n+2)C to RY(n+2)E) earlier, considering the delay time of CC-Link communication.
 - 2. When the selected station number exceeds the value that is dividing number set in the parameter No.PC46 minus one, the next station warning (A97) occurs.
 - 3. The start (RYn1) is invalid even if it is turned on during operation. When executing another operation, turn on RYn1 after the movement completion (RXnC) turns on.
 - 4. Change of the servo motor speed and acceleration/deceleration time constant by the speed selection 1 (RY(n+2)C) to speed selection 3 (RY(n+2)E) becomes effective when the start (RYn1) turns on. Even if the speed selection 1 to 3 are changed during servo motor rotation, they do not become effective.
 - 5. The following shows the operation to be executed.

Operation	*1	*2	*3
Station	No.1	No.3	No.1
Servo motor speed Acceleration/deceleration time constant	Point table No.1	Point table No.1	Point table No.2
Positioning			

- 6. Delay time from when RXn1 turns on until the torque limit value changes to the parameter No.PC35 value can be set in the parameter No.PD26.
- 7. After power-on, if the current position is with the in-position range of each station, the in position (RXn1) turns on.

(2) When using the remote register

Select the station number using the next station (RWwn+4) remote register and execute positioning. For the speed data during operation, select the point table number using the point table No./Speed command data (RWwn+6) remote register, or directly set the servo motor speed.

(a) Device/Parameter

Set the input devices and parameters as indicated below.

Item	Device/Parameter	Setting description
Indexer positioning operation selection	Parameter No.PA01	1 .: Select the indexer positioning operation.
Speed data setting method selection	Parameter No.PC30	Select the setting method for speed data. Select the setting method for speed data. Select the setting value. Select the servo motor speed setting value for the point table No./Speed command data (RWwn+6) remote register. In the case, always set the acceleration/deceleration time constant in the point table No.1. (Refer to (2) (c) in this section.)
Automatic operation mode 2 (Rotation direction specifying indexer)	Operation mode selection 1 (RYn6)	Turn on RYn6.
selection	Operation mode selection 2 (RYn7)	Turn on RYn7.
Position/speed specifying system selection	Position/speed specifying system selection (RY(n+2)A)	Turn on RY(n+2)A.



(b) Other parameter settings (Setting the number of stations)

Set the number of stations in the parameter No.PC46. Setting is the same as that for the automatic operation mode 1. Refer to (1) (b) 2) in section 15.7.2.

In the automatic operation mode 2, the station No. direction selection (parameter No.PA14) is not used.

- (c) Setting the speed data
 - 1) When using the speed data of point table

Set the servo motor speed, acceleration time constant, and deceleration time constant in the point table number 1 to 7. Setting is the same as that for the automatic operation mode 1. Refer to (2) (c) 1) in section 15.7.2.

2) When directly setting the servo motor speed (only when two stations are occupied)

Set the followings because the acceleration time constant and deceleration time constant of the point table No.1 are used. Setting is the same as that for the automatic operation mode 1. Refer to (2) (c) 2) in section 15.7.2.

- (d) Operation
 - 1) When using the speed data of point table

Set the station number for positioning by using the next station (RWwn+4) remote register. Set the point table number in the point table No./Speed command data (RWwn+6) remote register. Turn on the start (RYn1) to execute positioning with the speed data set in the point table.

2) When directly setting the servo motor speed (only when two stations are occupied)

Set the station number for positioning by using the next station (RWwn+4) remote register. Set the servo motor speed in the point table No./Speed command data (RWwn+6) remote register. Turn on the start (RYn1) to execute positioning with the servo motor speed set in RWwn+6 and the acceleration time constant and deceleration time constant set in the point table No.1.



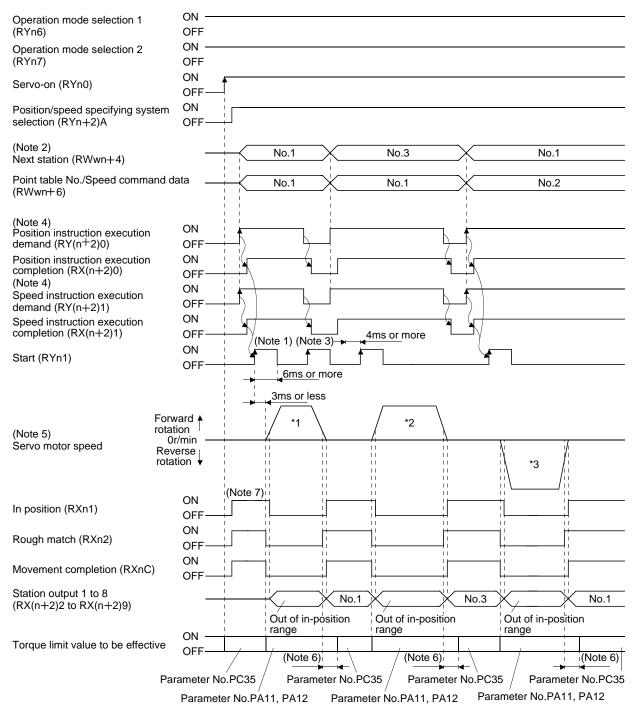
(e) Timing chart

POINT

 Always execute a home position return. The home positioning incomplete (A90) occurs when turning on the start (RYn1) without executing a home position return.

The timing chart is shown below.

1) When using the speed data of point table



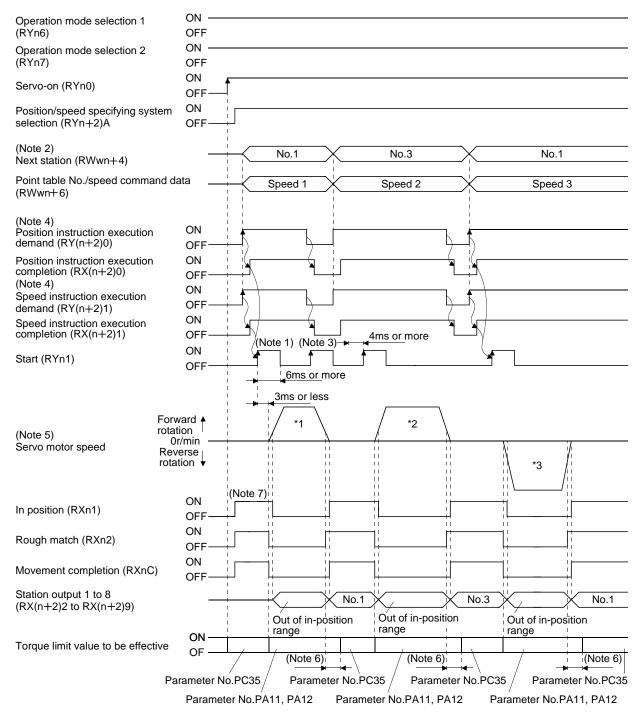


- Note 1. Configure a sequence that changes RWwn+4 and RWwn+6 earlier, considering the delay time of CC-Link communication.
 - 2. When the selected station number exceeds the value that is dividing number set in the parameter No.PC46 minus one, the next station warning (A97) occurs.
 - 3. The start (RYn1) is invalid even if it is turned on during operation. When executing another operation, turn on RYn1 after the movement completion (RXnC) turns on.
 - 4. For details of the operation timing of RY(n+2)0 and RY(N+2)1, refer to the section 3.6.2 (3).
 - 5. The following shows the operation to be executed.

Operation	*1	*2	*3
Station	No.1	No.3	No.1
Servo motor speed Acceleration/deceleration time constant	Point table No.1	Point table No.1	Point table No.2
Positioning			

- 6. Delay time from when RXn1 turns on until the torque limit value changes to the parameter No.PC35 value can be set in the parameter No.PD26.
- 7. After power-on, if the current position is with the in-position range of each station, the in position (RXn1) turns on.





2) When directly setting the servo motor speed (only when 2 stations are occupied)



- Note 1. Configure a sequence that changes RWwn+4 and RWwn+6 earlier, considering the delay time of CC-Link communication.
 - 2. When the selected station number exceeds the value that is dividing number set in the parameter No.PC46 minus one, the next station warning (A97) occurs.
 - 3. The start (RYn1) is invalid even if it is turned on during operation. When executing another operation, turn on RYn1 after the movement completion (RXnC) turns on.
 - 4. For details of the operation timing of RY(n+2)0 and RY(N+2)1, refer to the section 3.6.2 (3).
 - 5. The following shows the operation to be executed.

Operation	*1	*2	*3
Station	No.1	No.3	No.1
Servo motor speed	Speed 1	Speed 2	Speed 3
Acceleration/deceleration time constant	Point table No.1	Point table No.1	Point table No.1
Positioning			

- 6. Delay time from when RXn1 turns on until the torque limit value changes to the parameter No.PC35 value can be set in the parameter No.PD26.
- 7. After power-on, if the current position is with the in-position range of each station, the in position (RXn1) turns on.



15.8 Manual operation mode

For adjusting the machine or home position, JOG operation or indexer JOG operation can be used to move the position to any position.

15.8.1 Indexer JOG operation

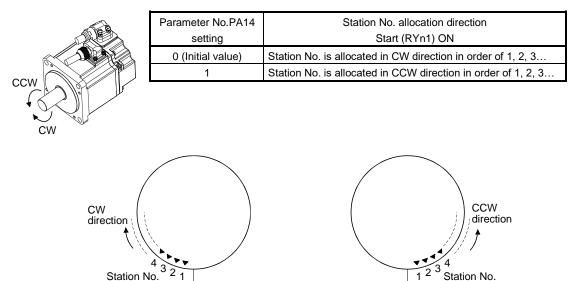
(1) Setting

Set the devices and parameters as indicated below according to the purpose of use. In this case, the next station selection 1 to 8 (RYnA to RYnE and RY(n+2)3 to RY(n+2)5) and the speed selection 1 to 3 (RY(n+2)C to RY(n+2)E) are invalid.

Item	Device/Parameter	Setting description
Indexer positioning operation selection	Parameter No.PA01	1 . Select the indexer positioning operation.
Manual operation mode selection	Operation mode selection 1 (RYn6)	Turn on RYn6.
	Operation mode selection 2 (RYn7)	Turn off RYn7.
Indexer JOG operation selection	Parameter No.PC45	Set it to "□□□0 (Initial value)"
Station No. direction	Parameter No.PA14	Refer to (2) in this section.
JOG speed	Point table No.1	Use the servo motor speed in the point table No.1.
Acceleration/deceleration time constant	Point table No.1	Use the acceleration/deceleration time constant in the point table No.1.

(2) Setting the allocation direction of station numbers

Select the allocation direction of station numbers using the parameter No.PA14 (Station No. direction selection).



Parameter No.PA14: 0 (Initial value)



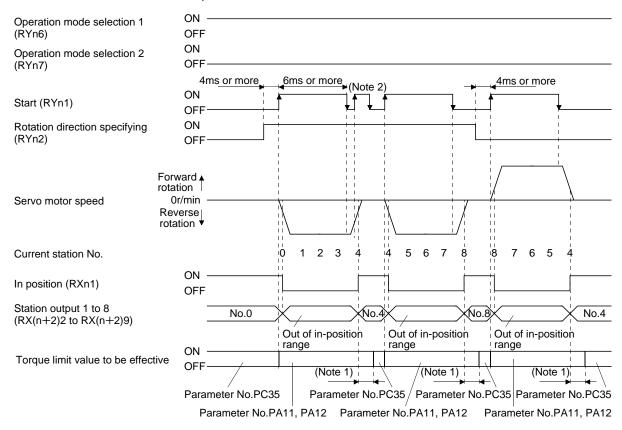


(3) Operation

Turn on the start (RYn1) to operate the servo motor with the servo motor speed, acceleration time constant, and deceleration time constant set in the point table No.1. Turning off RYn1 makes the servo motor execute positioning to the station where the servo motor can decelerate to stop. For the rotation direction, refer to (2) in this section.

(4) Timing chart

The following timing chart shows an example when executing the indexer JOG operation from the status where the servo motor is at a stop on the station No.0 when the servo-on is turned on.



Note 1. Torque limit delay time can be set in the parameter No.PD26.

2. The start (RYn1) is invalid even if it is turned on during operation. When executing another operation, turn on RYn1 after the movement completion (RXnC) turns on.



15.8.2 JOG operation

(1) Setting

Set the devices and parameters as indicated below for the purpose of use. In this case, the next station selection 1 to 8 (RYnA to RYnE and RY(n+2)3 to RY(n+2)5) and the speed selection 1 to 3 (RY(n+2)C to RY(n+2)E) are invalid.

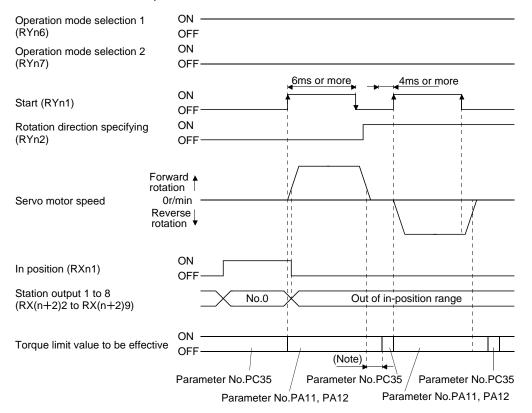
Item	Device/Parameter	Setting description
Indexer positioning operation selection	Parameter No.PA01	1□□□: Select the indexer positioning operation.
Manual operation mode coloction	Operation mode selection 1 (RYn6)	Turn on RYn6
Manual operation mode selection	Operation mode selection 2 (RYn7)	Turn off RYn7
JOG operation selection	Parameter No.PC45	Set it to "
Station No. direction	Parameter No.PA14	Refer to (2) in this section.
JOG speed	Point table No.1	The setting is the same as for the indexer JOG operation. Refer to (2) in section 15.8.1.
Acceleration/deceleration time constant	Point table No.1	Use the acceleration/deceleration time constant in the point table No.1.

(2) Operation

Turn on the start (RYn1) to operate the servo motor with the servo motor speed, acceleration time constant, and deceleration time constant set in the point table No.1. Turning off RYn1 makes the servo motor decelerate to stop regardless of stations. For the rotation direction, refer to (2) in section 15.8.1.

(3) Timing chart

The following timing chart shows an example when executing the indexer JOG operation from the status where the servo motor is at a stop on the station No.0 when the servo-on is turned on.



Note. Torque limit delay time can be set in the parameter No.PD26.



15.9 Home position return mode

15.9.1 Outline of home position return

Home position return is performed to match the command coordinates with the machine coordinates. In the incremental system, home position return is required every time input power is switched on. In the absolute position detection system, once home position return is done at the time of installation, the current position is retained if power is switched off. Hence, home position return is not required when power is switched on again. This driver has the home position return methods given in this section. Choose the most appropriate method for your machine structure and application.

This driver has the home position return automatic return function which executes home position return by making an automatic return to a proper position if the machine has stopped beyond or at the proximity dog. Manual motion by jog operation or the like is not required.

(1) Home position return types

Choose the optimum home position return according to the machine type, etc.

Туре	Home position return method	Features
Torque limit changing dog type home position return	With deceleration started at the front end of a proximity dog, the position where the first Z-phase signal is given past the rear end of the dog or a motion has been made over the home position shift distance starting from the Z-phase signal is defined as a home position.	 General home position return method using a proximity dog. Repeatability of home position return is excellent. The machine is less burdened. Used when the width of the proximity dog can be set greater than the deceleration distance of the servo motor. Torque limit value by the parameter No.PC35 (Internal torque limit 2) becomes effective while the servo motor at stop.
Torque limit changing data setting type home position return	An arbitrary position is defined as a home position.	 No proximity dog required. Torque limit value turns to "0" in the home position return mode.



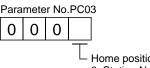
(2) Home position return parameter

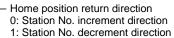
When performing home position return, set each parameter as follows.

(a) Choose the home position return method with parameter No.PC02 (Home position return type).

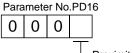
Para	mete	er No	.PC02
0	0	0	
			Home position return method 0: 1: 2: 3: 4: 5: Not used in indexer postioning operation. 6: 7: 8: 9: A: C: Torque limit changing dog type D: Torque limit changing data setting type

(b) Choose the starting direction of home position return with parameter No.PC03 (Home position return direction). Set "0" to start home position return in the direction in which the station No. is incremented from the current position, or "1" to start home position return in the direction in which the address is decremented.





(c) Choose the polarity at which the proximity dog is detected with parameter No.PD16 (Input polarity setting). Set "0" to detect the dog when the proximity dog device (DOG) is OFF, or "1" to detect the dog when the device is ON.



- Proximity dog input polarity0: OFF indicates detection of the dog1: ON indicates detection of the dog
- (3) Instructions
 - 1) Before starting home position return, always make sure that the limit switch operates.
 - 2) Confirm the home position return direction. Incorrect setting will cause the machine to run reversely.
 - 3) Confirm the proximity dog input polarity. Not doing so may cause unexpected operation.



15.9.2 Torque limit changing dog type home position return

A home position return method using a proximity dog. With deceleration started at the front end of the proximity dog, the position where the first Z-phase signal is given past the rear end of the dog or a motion has been made over the home position shift distance starting from the Z-phase signal is defined as a home position. A limit can be put on the servo motor torque at home position return execution and at stop separately.

(1) Devices, parameters

Set the input devices and parameters as follows.

Item	Device/Parameter used	Description
Home position return mode	Operation mode selection 1 (RYn6)	Turn off RYn6.
selection	Operation mode selection 2 (RYn7)	Turn off RYn7.
Torque limit changing dog type home position return	Parameter No.PC02	□□□C: Torque limit changing dog type home position return is selected.
Home position return direction	Parameter No.PC03	Refer to section 15.9.1 (2) and choose home position return direction.
Dog input polarity	Parameter No.PD16	Refer to section 15.9.1 (2) and choose dog input polarity.
Home position return speed	Parameter No.PC04	Set speed until detection of dog.
Creep speed	Parameter No.PC05	Set speed after detection of dog.
Home position shift distance	Parameter No.PC06	Set when shifting the home position starting at the first Z-phase signal after passage of proximity dog rear end.
Home position return acceleration/deceleration time constants	Point table No.1	Use the acceleration/deceleration time constants of point table No.1.
Torque limit value at home position	Point table No.PA11	Set the torque limit value for the forward rotation direction at home position return execution.
return execution	Point table No.PA12	Set the torque limit value for the reverse rotation direction at home position return execution.
Torque limit value at stop	Point table No.PC35	Set the torque limit value at stop.

(2) Length of proximity dog

Adjust the length of proximity dog or home position return speed so that the servo motor speed reaches to the creep speed while detecting the proximity dog (DOG).

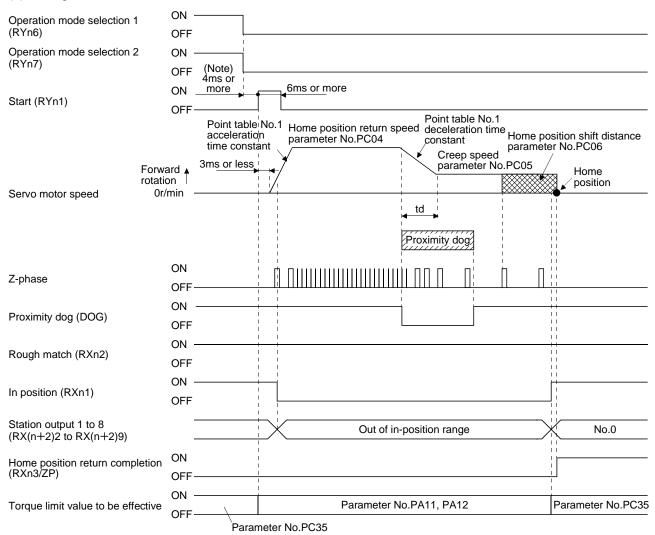
$$L_1 \geq \frac{V}{60} \cdot \frac{td}{2} \times \frac{CDV}{CMX} \times 360$$

L1 : Angle that proximity dog holds on the circumference of machine side [degree]

- V : Home position return speed of motor side [r/min]
- td : Deceleration time of motor side [s]



15. INDEXER POSITIONING OPERATION



(3) Timing chart

Note. Configure a sequence that changes the operation mode earlier, considering the delay time of CC-Link communication.



15.9.3 Torque limit changing data setting type home position return

POINT

Torque limit becomes effective after completing the torque limit changing data setting type home position return, so that when the servo motor is rotated by the external force, a difference occurs in between the command position and the current position. In the home position return mode, even if a difference occurs in between the command position and the current position, the error excessive alarm (A52) does not occur. Therefore, when the mode is changed from home position return to automatic operation, depending on the size of difference between the command position and the current position, the error excessive alarm (A52) occurs. Note that if the error excessive alarm (A52) does not occur, the servo motor rotates to eliminate the difference.

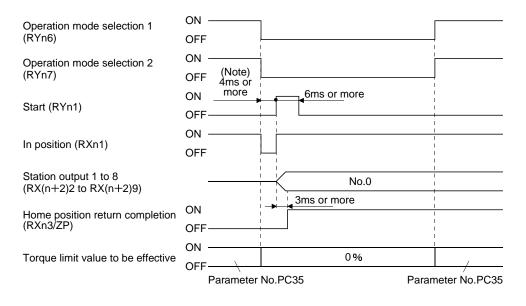
Use the torque limit changing data setting type home position return to set the home position in any place. JOG operation can be used for moving a position. For this home position return, torque generation is stopped at the same time when the mode is changed to the home position return mode. Home position can be set for any position by rotating the axis with external force.

The proximity dog (DOG) cannot be used. The proximity dog (DOG) is disabled even if it is turned off.

(1) Device/Parameter

Set the input devices and parameters as indicated below.

Item	Device/Parameter	Setting description
	Operation mode selection 1 (RYn6)	Turn off RYn6.
Home position return mode selection	Operation mode selection 2 (RYn7)	Turn off RYn7.
Position/speed specifying system by remote register (only when 2 stations are occupied)	Position/speed specifying system selection (RY(n+2)A)	Turn off RY(n+2)A.
Torque limit changing data setting type home position return	Parameter No.PC02	□□□D: Select the torque limit changing data setting type.



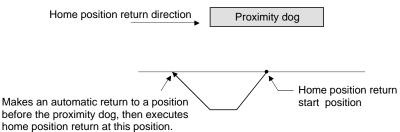
Note. Configure a sequence that changes the operation mode earlier, considering the delay time of CC-Link communication.



15.9.4 Home position return automatic return function

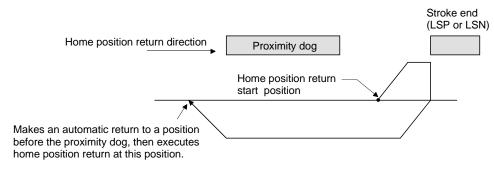
If the current position is at or beyond the proximity dog in the home position return using the proximity dog, this function starts home position return after making a return to the position where the home position return can be made.

- (1) When the current position is at the proximity dog
 - When the current position is at the proximity dog, an automatic return is made before home position return.



(2) When the current position is beyond the proximity dog

At a start, a motion is made in the home position return direction and an automatic return is made on detection of the stroke end (LSP or LSN). The motion stops past the front end of the proximity dog, and home position return is resumed at that position. If the proximity dog cannot be detected, the motion stops on detection of the LSP or LSN switch and A90 occurs.



Software limit cannot be used with these functions.



15. INDEXER POSITIONING OPERATION

15.10 Absolute position detection system

- If an absolute position erase alarm (A25) or an absolute position counter warning
(AE3) has occurred, always perform home position setting again. Not doing so
 may cause unexpected operation.

POINT

- If the encoder cable is disconnected, absolute position data will be lost in the following servo motor series. LE-□-□. After disconnecting the encoder cable, always execute home position setting and then positioning operation.
- When the following parameters are changed, the home position is lost when turning on the power after the change. Execute the home position return again when turning on the power.
 - Parameter No.PA06 (Number of gears on machine-side)
 - · Parameter No.PA07 (Number of gears on servo motor-side)
 - Parameter No.PA14 (Station No. direction selection)
 - Parameter No.PC07 (Home position return position data)

This driver contains a single-axis driver. Also, all servo motor encoders are compatible with an absolute position detection system. Hence, an absolute position detection system can be configured up by merely loading an absolute position data back-up battery and setting parameter values.

(1) Restrictions

In the absolute position detection system, the following restriction condition applies for the number of gears on machine-side (parameter No.PA06 CMX) and servo motor speed (N).

- When CMX \leq 2000, N < 3076.7 r/min
- When CMX > 2000, N < 3276.7 CMX r/min

When the servo motor is operated at servo motor speed higher than the limited value, the absolute position counter warning (AE3) occurs.

(2) Specifications

Item	Description
System	Electronic battery backup system.
Battery	1 piece of lithium battery (primary battery, nominal+3.6V) Type: LEC-MR-J3BAT.
Maximum revolution range	Home position+32767 rev.
(Note 1) Maximum speed at power failure	3000r/min
(Note 2) Battery backup time	Approx. 10,000 hours (battery life with power off)
Battery storage period	5 years from date of manufacture.

Note 1. Maximum speed available when the shaft is rotated by external force at the time of power failure or the like.

2. Time to hold data by a battery with power off. It is recommended to replace the battery in three years independently of whether power is kept on or off.



(3) Structure

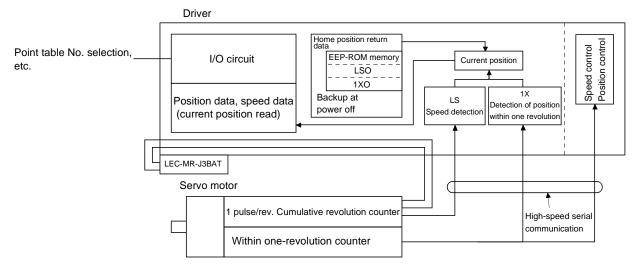
Component	Description	
Driver	Use standard models.	
Servo motor		
Battery	LEC-MR-J3BAT	
Encoder cable	Use a standard model. (Refer to section 13.1.)	

(4) Outline of absolute position detection data communication

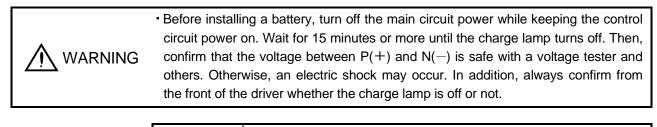
For normal operation, as shown below, the encoder consists of a detector designed to detect a position within one revolution and a cumulative revolution counter designed to detect the number of revolutions.

The absolute position detection system always detects the absolute position of the machine and keeps it battery-backed, independently of whether the general-purpose PC or PLC...etc power is on or off. Therefore, once the home position is defined at the time of machine installation, home position return is not needed when power is switched on thereafter.

If a power failure or a fault occurs, restoration is easy.



(5) Battery installation procedure



POINT

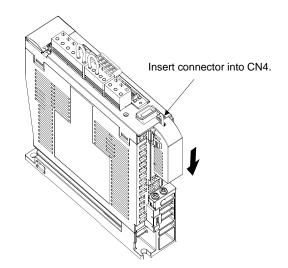
- The internal circuits of the driver may be damaged by static electricity. Always take the following precautions.
 - Ground human body and work bench.
 - Do not touch the conductive areas, such as connector pins and electrical parts, directly by hand.
- Before starting battery changing procedure, make sure that the main circuit power is switched OFF with the control circuit power ON. When battery is changed with the control power OFF, the absolute position data is lost.



(a) For LECSC2−T□

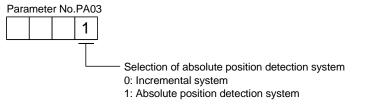
POINT

• For the driver with a battery holder on the bottom, it is not possible to wire for the earth with the battery installed. Insert the battery after executing the earth wiring of the driver.



(b) Parameter setting

Set parameter No.PA03 (Absolute position detection system) as indicated below to make the absolute position detection system valid.





15. INDEXER POSITIONING OPERATION

15.11 Parameters

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• Never adjust or change the parameter values extremely as it will make operation instable.

POINT

• For any parameter whose symbol is preceded by *, set the parameter value and switch power off once, then switch it on again to make that parameter setting valid.

In this driver, the parameters are classified into the following groups on a function basis.

Parameter group	Main description	
Basic setting parameters (No.PA□□)	Make basic setting with these parameters. Generally, the operation is possible only with these parameter settings.	
Gain/filter parameters (No.PB□□)	Use these parameters when making gain adjustment manually.	
Extension setting parameters (No.PC□□)	These parameters are inherent to the LECSC2-T□ driver.	
I/O setting parameters (No.PD□□)	Use these parameters when changing the I/O devices of the driver.	

Mainly setting the basic setting parameters (No.PA \Box \Box) allows the setting of the basic parameters at the time of introduction.

15.11.1 Basic setting parameters (No.PA

(1) Parameter list

No.	Symbol	Name	Initial value	Unit
PA01	*STY	Control mode		
PA02	*REG	G Regenerative option		
PA03	*ABS	Absolute position detection system		
PA04	\searrow	Not used in indexer positioning operation.	0000h	
PA05		Do not change the parameter.	0000h	
PA06	*CMX	Number of gears on machine-side	1	
PA07	*CDV	Number of gears on servo motor-side	1	
PA08	ATU	Auto tuning mode	0001h	
PA09	RSP	Auto tuning response	12	
PA10	INP	In-position range	100	pulse
PA11	TLP	Forward rotation torque limit	100.0	%
PA12	TLN	Reverse rotation torque limit	100.0	%
PA13	/	For manufacturer setting	0002h	
PA14	*POL	Rotation direction selection	0	
PA15	*ENR	Encoder output pulses	4000	pulse/rev
PA16		For manufacturer setting	0000h	
PA17		Do not change this valve by any means.	0000h	
PA18			0000h	
PA19	*BLK	Parameter write inhibit	000Ch	

(2) Parameter write inhibit

	Parameter			Unit	Cotting rongo
No.	Symbol	Name	value	Unit	Setting range
PA19	*BLK	Parameter write inhibit	000Ch		Refer to the text.

POINT

 This parameter is made valid when power is switched off, then on after setting.

In the factory setting, this driver allows changes to the basic setting parameter, gain/filter parameter and extension setting parameter settings. With the setting of parameter No.PA19, write can be disabled to prevent accidental changes.

The following table indicates the parameters which are enabled for reference and write by the setting of parameter No.PA19. Operation can be performed for the parameters marked \bigcirc .

Parameter No.PA19 setting	Setting operation	Basic setting parameters No.PA□□	Gain/Filter parameters No.PB□□	Extension setting parameters No.PC□□	I/O setting parameters No.PD□ □
0000h	Reference	0			
0000h	Write	0			
000Dh	Reference	0	0	0	
000Bh	Write	0	0	0	
000Ch	Reference	0	0	0	0
(initial value)	Write	0	0	0	0
	Reference	0			
100Bh	Write	Parameter No. PA19 only			
	Reference	0	0	0	0
100Ch	Write	Parameter No. PA19 only			

(3) Selection of command system

	Parameter				
No.	Symbol	Name	value	Unit	Setting range
PA01	*STY	Control mode	0000h	/	Refer to the text.

POINT
This parameter is made valid when power is switched off, then on after setting.

Select the command system.



Operation method
 0: Point table positioning operation
 1: Indexer positioning operation



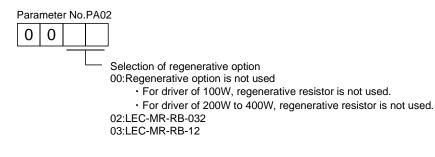
(4) Selection of regenerative option

	Parameter			Linit	Cotting rongo
No.	Symbol	Name	value	Unit	Setting range
PA02	*REG	Regenerative option	0000h		Refer to the text.

POINT

- This parameter is made valid when power is switched off, then on after setting.
- Wrong setting may cause the regenerative option to burn.
- If the regenerative option selected is not for use with the driver, parameter error (A37) occurs.

Set this parameter when using the regenerative option, brake unit, power regeneration converter, or power regeneration common converter.

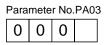


(5) Using absolute position detection system

	Parameter			L la it	
No.	Symbol	Name	value	Unit	Setting range
PA03	*ABS	Absolute position detection system	0000h	/	Refer to the text.

	POINT						
ſ	• This parameter is made valid when power is switched off, then on after						
	setting.						

Set this parameter when using the absolute position detection system.



└─ Selection of absolute position detection system (refer to section 16.10)

0: Used in incremental system

1: Used in absolute position detection system



(6) Electronic gear

	Parameter			Linit	Cotting rongs
No.	Symbol	Name	value	Unit	Setting range
PA06	*CMX	Number of gears on machine-side	1	/	1 to 16384
PA07	*CDV	Number of gears on servo motor-side	1		1 to 16384

· False setting will result in unexpected fast rotation, causing injury.

POINT

- This parameter is made valid when power is switched off, then on after setting.
- Set the electronic gear within the following condition range.
- (1) 1/9999≦CMX/CDV≦9999
- (2) CDV × STN≦32767
- (3) CMX × CDV≦100000

When a value out of the condition range is set, the parameter error (A37) occurs. If the setting of electronic gear ratio is small, the servo motor may not operate with the set servo motor speed.

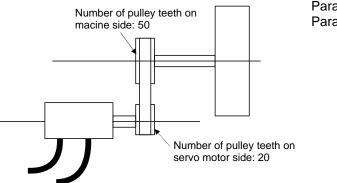
 Setting range of the parameters No.PA06 and PA07 for the indexer positioning operation is 1 to 16384. It is different from the setting range for the point table positioning operation.

Use the parameters No. PA06 and PA07 to adjust the rotation amount "m" on the servo motor shaft that is necessary to rotate the machine side "n" times. A setting example for electronic gear is shown next.



(a) Example 1

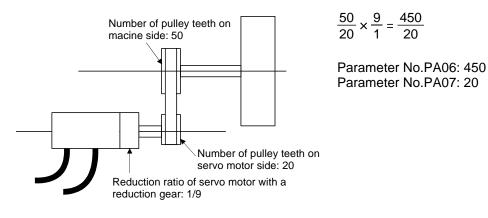
When the number of pulley teeth on the machine-side is 50, and the number of pulley teeth on the servo motor side is 20.



Parameter No.PA06: 50 Parameter No.PA07: 20

(b) Example 2

When the number of pulley teeth on the machine-side is 50, the number of pulley teeth on the servo motor side is 20, and using the servo motor with 1/9 reduction gear.





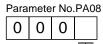
(7) Auto tuning

	Parameter			Unit	Cotting range
No.	Symbol	Name	Name value		Setting range
PA08	ATU	Auto tuning mode	0001h	/	Refer to the text.
PA09	RSP	Auto tuning response	12		1 to 32

Make gain adjustment using auto tuning. Refer to section 8.2 for details.

(a) Auto tuning mode (parameter No.PA08) Select the gain adjustment mode.

Select the gain adjustment mode.



Gain adjustment mode setting

Setting	Gain adjustment mode	Automatically set parameter No. (Note)
0	Interpolation mode	PB06· PB08· PB09· PB10
1	Auto tuning mode 1	PB06· PB07· PB08· PB09· PB10
2	Auto tuning mode 2	PB07· PB08· PB09· PB10
3	Manual mode	

Note. The parameters have the following names.

Parameter No.	Name
PB06	Ratio of load inertia moment to servo motor inertia moment
PB07	Model loop gain
PB08	Position loop gain
PB09	Speed loop gain
PB10	Speed integral compensation

(b) Auto tuning response (parameter No.PA09)

If the machine hunts or generates large gear sound, decrease the set value. To improve performance, e.g. shorten the settling time, increase the set value.

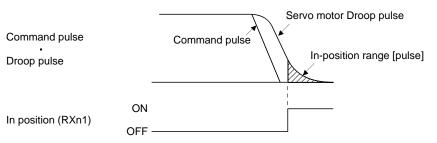
Setting	Response	Guideline for machine resonance frequency [Hz]	Setting	Response	Guideline for machine resonance frequency [Hz]
1	Low response	10.0	17	Low response	67.1
2	↑	11.3	18	↑	75.6
3		12.7	19		85.2
4		14.3	20		95.9
5		16.1	21		108.0
6		18.1	22		121.7
7		20.4	23		137.1
8		23.0	24		154.4
9		25.9	25		173.9
10		29.2	26		195.9
11		32.9	27		220.6
12		37.0	28		248.5
13		41.7	29		279.9
14		47.0	30		315.3
15	↓ ↓	52.9	31	↓ ↓	355.1
16	Middle response	59.6	32	Middle response	400.0



(8) In-position range

	Parameter			ا ا ما ا	
No.	Symbol	Name	value	Unit	Setting range
PA10	INP	In-position range	100	pulse	0 to 10000

Set the range for outputting the movement completion (RXnC) and the in position (RXn1) in command pulse unit.



(9) Torque limit

		Parameter	Initial	11	0
No.	Symbol	Name	value	Unit	Setting range
PA11	TLP	Forward rotation torque limit	100.0	%	0 to 100.0
PA12	TLN	Reverse rotation torque limit	100.0	%	0 to 100.0

The torque generated by the servo motor can be limited.

(a) Forward rotation torque limit (parameter No.PA11)

Set this parameter on the assumption that the maximum torque is 100[%]. Set this parameter when limiting the torque of the servo motor in the CCW driving mode or CW regeneration mode. Set this parameter to "0.0" to generate no torque.

(b) Reverse rotation torque limit (parameter No.PA12)

Set this parameter on the assumption that the maximum torque is 100[%]. Set this parameter when limiting the torque of the servo motor in the CW driving mode or CCW regeneration mode. Set this parameter to "0.0" to generate no torque.

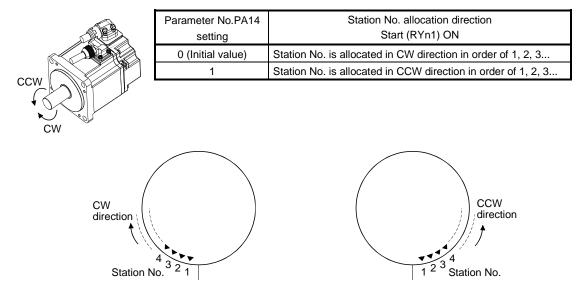


(10)Station No. direction selection

		Parameter	Initial	Linit	
No.	Symbol	Name	value	Unit	Setting range
PA14	*POL	Station No. direction selection	0		0 • 1

POINT
 This parameter is made valid when power is switched off, then on after setting.

Select the allocation direction of station numbers using the parameter No.PA14 (Station No. direction selection).



Parameter No.PA14: 0 (Initial value)

Parameter No.PA14: 1



(11)Encoder output pulse

		Parameter	Initial	L lus it	
No.	Symbol	Name	value	Unit	Setting range
PA15	*ENR	Encoder output pulse	4000	pulse/ rev	1 to 65535

POINT

 This parameter is made valid when power is switched off, then on after setting.

Used to set the encoder pulses (A-phase, B-phase) output by the driver.

Set the value 4 times greater than the A-phase or B-phase pulses.

You can use parameter No.PC19 to choose the output pulse setting or output division ratio setting. The number of A/B-phase pulses actually output is 1/4 times greater than the preset number of pulses. The maximum output frequency is 4.6Mpps (after multiplication by 4). Use this parameter within this range.

(a) For output pulse designation

Set "□□0□" (initial value) in parameter No.PC19.

Set the number of pulses per servo motor revolution.

Output pulse = set value [pulses/rev]

For instance, set "5600" to Parameter No.PA15, the actually output A/B-phase pulses are as indicated below.

A·B-phase output pulses = $\frac{5600}{4}$ =1400[pulse]

(b) For output division ratio setting

Set " \Box \Box 1 \Box " in parameter No.PC19.

The number of pulses per servo motor revolution is divided by the set value.

Output pulse = Resolution per servo motor revolution [pulses/rev]

For instance, set "8" to Parameter No.PA15, the actually output A/B-phase pulses are as indicated below.

A·B-phase output pulses = $\frac{262144}{8} \cdot \frac{1}{4} = 8192$ [pulse]



15.11.2 Gain/filter parameters (No.PB□□) (1) Parameter list

No.	Symbol	Name	Initial value	Unit
PB01	FILT	Adaptive tuning mode (Adaptive filter II)	0000h	
		Vibration suppression control tuning mode		
PB02	VRFT	(Advanced vibration suppression control)	0000h	
PB03		For manufacturer setting	0000h	\sim
PB04	FFC	Feed forward gain	0	%
PB05		For manufacturer setting	500	
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment	7.0	Multiplier
				(×1)
PB07	PG1	Model loop gain	24	rad/s
PB08	PG2	Position loop gain	37	rad/s
PB09	VG2	Speed loop gain	823	rad/s
PB10	VIC	Speed integral compensation	33.7	ms
PB11	VDC	Speed differential compensation	980	
PB12		For manufacturer setting	0	\sim
PB13	NH1	Machine resonance suppression filter 1	4500	Hz
PB13	NHQ1	Notch shape selection 1	0000h	112
РВ14 PB15	NHQ1 NH2	Machine resonance suppression filter 2	4500	Hz
PB16		Notch shape selection 2		
	NHQ2		0000h	
PB17		Automatic setting parameter	04.44	
PB18		Low-pass filter	3141	rad/s
PB19	VRF1	Vibration suppression control vibration frequency setting	100.0	Hz
PB20	VRF2	Vibration suppression control resonance frequency setting	100.0	Hz
PB21		For manufacturer setting	0.00	
PB22	VEDE	Law and Changes last an	0.00	$\langle \rangle$
PB23	VFBF	Low-pass filter selection	0000h	
PB24	*MVS	Slight vibration suppression control selection	0000h	
PB25		For manufacturer setting	0000h	
PB26	*CDP	Gain changing selection	0000h	
PB27	CDL	Gain changing condition	10	
PB28	CDT	Gain changing time constant	1	ms
PB29	GD2B	Gain changing ratio of load inertia moment to servo motor inertia moment	7.0	Multiplier
				(×1)
PB30	PG2B	Gain changing position loop gain	37	rad/s
PB31	VG2B	Gain changing speed loop gain	823	rad/s
PB32	VICB	Gain changing speed integral compensation	33.7	ms
PB33	VRF1B	Gain changing vibration suppression control vibration frequency setting	100.0	Hz
PB34	VRF2B	Gain changing vibration suppression control resonance frequency setting	100.0	Hz
PB35	\setminus	For manufacturer setting	0.00	_\
PB36	\backslash		0.00] /
PB37			100	
PB38			0	
PB39	\setminus		0	
PB40	\		0	1 \
PB41			1125	1 \
PB42			1125	1 \
	\		0004h	+
PB43	\			- \
PB44	\		0000h	- \
PB45			0000h	۱

(2) Detail list

No.	Symbol	Name and function	Initial value	Unit	Setting range
PB01	FILT	Adaptive tuning mode (Adaptive filter II) Select the setting method for filter tuning. Setting this parameter to "□□□1" (filter tuning mode 1) automatically changes the machine resonance suppression filter 1 (parameter No.PB13) and notch shape selection (parameter No.PB14).	0000h		
		Response of mechanical system The chanical system Frequency			
		Store Frequency Notch frequency			
		0 0 Filter tuning mode selection			
		Setting Filter adjustment mode Automatically set parameter			
		0 Filter OFF (Note)			
		1 Filter tuning mode Parameter No.PB13 Parameter No.PB14 Parameter No.PB14			
		2 Manual mode			
		Note. Parameter No.PB13 and PB14 are fixed to the initial values.			
		When this parameter is set to " 1", the tuning is completed after positioning is done the predetermined number or times for the predetermined			
		period of time, and the setting changes to " $\Box\Box\Box$ 2". When the filter tuning is			
		not necessary, the setting changes to " $\Box\Box\Box\Box$ ". When this parameter is set to			
		" $\Box\Box\Box$ ", the initial values are set to the machine resonance suppression filter			
		1 and notch shape selection. However, this does not occur when the servo off.			



No.	Symbol		Name and f	unction	Initial value	Unit	Setting range
PB02	VRFT	control) The vibration su setting is "	ppression is valid when the l2" or "□□□3". When PA g method for vibration suppress anges the vibration suppress PB19) and vibration suppress PB20) after positioning is de ulse lise lise lise 0 0	ession control vibration frequency ession control resonance frequency one the predetermined number of Droop pulse	0000h		
		Setting	Vibration suppression control tuning mode	Automatically set parameter			
		0	Vibration suppression control OFF Vibration suppression	(Note)			
		1	control tuning mode (Advanced vibration suppression control)	Parameter No.PB19 Parameter No.PB20			
		2	Manual mode				
				20 are fixed to the initial values.			
				e tuning is completed after ber or times for the predetermined			
		-		$\Box\Box\Box\Box$. When the vibration			
				y, the setting changes to " $\Box\Box\Box$.			
			•	ine initial values are set to the vibration			
		•		Ind vibration suppression control -			
				not occur when the servo off.			
PB03		For manufacture			0000h		
		Do not change t	his value by any means.				
PB04	FFC	Feed forward ga	in		0	%	0
		Set the feed forv	vard gain. When the setting	g is 100%, the droop pulses during			to
		operation at con	stant speed are nearly zer	o. However, sudden			100
		acceleration/dec	eleration will increase the	overshoot. As a guideline, when the			
		feed forward gai	n setting is 100%, set 1s o	r more as the			
		acceleration/dec	eleration time constant up	to the rated speed.			

No.	Symbol	Name and function	Initial value	Unit	Setting range
PB05		For manufacturer setting Do not change this value by any means.	500		
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment Used to set the ratio of the load inertia moment to the servo motor shaft inertia moment. When auto tuning mode 1 and interpolation mode is selected, the result of auto tuning is automatically used. (Refer to section 8.1.1) In this case, it varies between 0 and 100.0.	7.0	Multiplier (×1)	0 to 300.0
PB07	PG1	Model loop gain Set the response gain up to the target position. Increase the gain to improve track ability in response to the command. When auto turning mode 1,2 is selected, the result of auto turning is automatically used.	24	rad/s	1 to 2000
PB08	PG2	Position loop gain Used to set the gain of the position loop. Set this parameter to increase the position response to level load disturbance. Higher setting increases the response level but is liable to generate vibration and/or noise. When auto tuning mode 1,2 and interpolation mode is selected, the result of auto tuning is automatically used.	37	rad/s	1 to 1000
PB09	VG2	Speed loop gain Set this parameter when vibration occurs on machines of low rigidity or large backlash. Higher setting increases the response level but is liable to generate vibration and/or noise. When auto tuning mode 1,2 manual mode and interpolation mode is selected, the result of auto tuning is automatically used.	823	rad/s	20 to 50000
PB10	VIC	Speed integral compensation Used to set the integral time constant of the speed loop. Lower setting increases the response level but is liable to generate vibration and/or noise. When auto tuning mode 1,2 and interpolation mode is selected, the result of auto tuning is automatically used.	33.7	ms	0.1 to 1000.0
PB11	VDC	Speed differential compensation Used to set the differential compensation. Made valid when the proportion control (RY(n+2)7) is switched on.	980		0 to 1000
PB12		For manufacturer setting Do not change this value by any means.	0		
PB13	NH1	Machine resonance suppression filter 1 Set the notch frequency of the machine resonance suppression filter 1. Setting parameter No.PB01 (filter tuning mode 1) to "□□□1" automatically changes this parameter. When the parameter No.PB01 setting is "□□□0", the setting of this parameter is ignored.	4500	Hz	100 to 4500



No.	Symbol	Name and function	Initial value	Unit	Setting range
PB14	NHQ1	Notch shape selection 1 Used to selection the machine resonance suppression filter 1. 0 0 Notch depth selection Setting value Depth 0 0 1 to -14dB 2 -4dB 3 Shallow -4dB 0 Standard 2 0 1 to -3 Width 0 Standard 2 0 4 3 3 Wide 5 5	0000h		Refer to name and function column.
PB15	NH2	Setting parameter No.PB01 (filter tuning mode 1) to "□□□1" automatically changes this parameter. When the parameter No.PB01 setting is "□□□0", the setting of this parameter is ignored. Machine resonance suppression filter 2 Set the notch frequency of the machine resonance suppression filter 2. Set parameter No.PB16 (notch shape selection 2) to "□□□1" to make this	4500	Hz	100 to 4500
PB16	NHQ2	parameter valid. Notch shape selection 2 Select the shape of the machine resonance suppression filter 2. 0 Machine resonance suppression filter 2 selection 0: Invalid 1: Valid Notch depth selection Setting value 0 1 2 1 2 1 2 1 2 1 2 3 2	0000h		Refer to name and function column.
PB17		Automatic setting parameter The value of this parameter is set according to a set value of parameter No.PB06 (Ratio of load inertia moment to servo motor inertia moment).			



No.	Symbol	Name and function	Initial value	Unit	Setting range
PB18	LPF	Low-pass filter Set the low-pass filter. Setting parameter No.PB23 (low-pass filter selection) to "□□0□" automatically changes this parameter. When parameter No.PB23 is set to "□□1□", this parameter can be set manually.	3141	rad/s	100 to 18000
PB19	VRF1	Vibration suppression control vibration frequency setting Set the vibration frequency for vibration suppression control to suppress low- frequency machine vibration, such as enclosure vibration. Setting parameter No.PB02 (vibration suppression control tuning mode) to "□□□1" automatically changes this parameter. When parameter No.PB02 is set to "□□□2", this parameter can be set manually.	100.0	Hz	0.1 to 100.0
PB20	VRF2	Vibration suppression control resonance frequency setting Set the resonance frequency for vibration suppression control to suppress low- frequency machine vibration, such as enclosure vibration. Setting parameter No.PB02 (vibration suppression control tuning mode) to "DD1" automatically changes this parameter. When parameter No.PB02 is set to "DD2", this parameter can be set manually.	100.0	Hz	0.1 to 100.0
PB21		For manufacturer setting	0.00		
PB22		Do not change this value by any means.	0.00		
PB23	VFBF	Low-pass filter selection Select the low-pass filter.	0000h		Refer to name and function column.
PB24	*MVS	Slight vibration suppression control selection Select the slight vibration suppression control. When parameter No.PA08 (auto tuning mode) is set to "□□□3", this parameter is made valid. 0 0 0	0000h		Refer to name and function column.



No.	Symbol	Name and function	Initial value	Unit	Setting range
PB25		For manufacturer setting Do not change this value by any means.	0000h		
PB26	*CDP	Gain changing selection Select the gain changing condition. (Refer to section 9.6.) Gain changing selection Under any of the following conditions, the gains change on the basis of the parameter No.PB29 to PB32 settings. 0: Invalid 1: Gain changing (RX(n+2)8) is ON 2: Command frequency (Parameter No.PB27 setting) 3: Droop pulse value (Parameter No.PB27 setting) 4: Servo motor speed (Parameter No.PB27 setting) Gain changing condition 0: Valid at more than condition (Valid when gain changing (RX(n+2)8) is ON) 1: Valid at less than condition (Valid when gain changing (RX(n+2)8) is OFF)	0000h		Refer to name and function column.
PB27	CDL	Gain changing condition Used to set the value of gain changing condition (command frequency, droop pulses, servo motor speed) selected in parameter No.PB26. The set value unit changes with the changing condition item. (Refer to section 9.6.)	10	kpps pulse r/min	0 to 9999
PB28	CDT	Gain changing time constant Used to set the time constant at which the gains will change in response to the conditions set in parameters No.PB26 and PB27. (Refer to section 9.6.)	1	ms	0 to 100
PB29	GD2B	Gain changing ratio of load inertia moment to servo motor inertia moment Used to set the ratio of load inertia moment to servo motor inertia moment when gain changing is valid. This parameter is made valid when the auto tuning is invalid (parameter No. PA08: □□□3).	7.0	Multiplier (×1)	0 to 300.0
PB30	PG2B	Gain changing position loop gain Set the position loop gain when the gain changing is valid. This parameter is made valid when the auto tuning is invalid (parameter No. PA08: □□□3).	37	rad/s	1 to 2000
PB31	VG2B	Gain changing speed loop gain Set the speed loop gain when the gain changing is valid. This parameter is made valid when the auto tuning is invalid (parameter No. PA08: □□□3). Note. The setting range of 50000 applies to the driver whose software version is A3 or later. The setting range of the driver whose software version is older than A3 is 20 to 20000. When the software version of set up software(MR Configurator2 TM) is A3 or earlier, 20001 or more cannot be set. Use the display/operation section of the driver to set 20001 or more.	823	rad/s	20 to 20000
PB32	VICB	Gain changing speed integral compensation Set the speed integral compensation when the gain changing is valid. This parameter is made valid when the auto tuning is invalid (parameter No. PA08: □□□3).	33.7	ms	0.1 to 5000.0

No.	Symbol	Name and function	Initial value	Unit	Setting range
PB33	VRF1B	Gain changing vibration suppression control vibration frequency setting Set the vibration frequency for vibration suppression control when the gain changing is valid. This parameter is made valid when the parameter No.PB02 setting is "DD2" and the parameter No.PB26 setting is "DD1". When using the vibration suppression control gain changing, always execute the changing after the servo motor has stopped.	100.0	Hz	0.1 to 100.0
PB34	VRF2B	Gain changing vibration suppression control resonance frequency setting Set the resonance frequency for vibration suppression control when the gain changing is valid. This parameter is made valid when the parameter No.PB02 setting is "DD2" and the parameter No.PB26 setting is "DD1". When using the vibration suppression control gain changing, always execute the changing after the servo motor has stopped.	100.0	Hz	0.1 to 100.0
PB35 PB36 PB37 PB38 PB39 PB40 PB41 PB42 PB42 PB43 PB44 PB45		For manufacturer setting Do not change this value by any means.	0.00 0.00 100 0 0 1125 1125 0004h 0000h		



15.11.3 Extension setting parameters (No.PC D)

(1) Parameter list

No.	Symbol	Name	Initial value	Unit
PC01	/	For manufacturer setting	0000h	
PC02	*ZTY	Home position return type	0000h	
PC03	*ZDIR	Home position return direction	0001h	
PC04	ZRF	Home position return speed	500	r/min
PC05	CRF	Creep speed	10	r/min
PC06	ZST	Home position shift distance	0	μm
PC07	\setminus	Not used in indexer positioning operation.	0	
PC08	\backslash		1000	
PC09	\backslash		100	
PC10	\setminus		15.0	
PC11	CRP	Rough match output range	0	pulse
PC12	JOG	Jog speed	100	r/min
PC13	/	Not used in indexer positioning operation.	0	
PC14	*BKC	Backlash compensation	0	pulse
PC15		For manufacturer setting	0000h	
PC16	MBR	Electromagnetic brake sequence output	100	ms
PC17		Not used in indexer positioning operation.	50	
PC18	*BPS	Alarm history clear	0000h	
PC19	*ENRS	Encoder output pulse selection	0000h	
PC20	*SNO	Station number setting	0	station
PC21	*SOP	RS-422 communication function selection	0000h	
PC22	*COP1	Function selection C-1	0000h	
PC23	\sim	For manufacturer setting	0000h	
PC24	\backslash	Not used in indexer positioning operation.	0000h	
PC25	\backslash	For manufacturer setting	0000h	
PC26	*COP5	Function selection C-5	0000h	
PC27		For manufacturer setting	0000h	
PC28		Not used in indexer positioning operation.	0000h	
PC29	\backslash	For manufacturer setting	0000h	
PC30	*DSS	Remote register-based position/speed specifying system selection	0000h	
PC31	$\overline{)}$	Not used in indexer positioning operation.	0	
PC32	\backslash		Ū	
PC33	\backslash		0	
PC34	\setminus		0	
PC35	TL2	Internal torque limit 2	100.0	%
PC36		For manufacturer setting	0000h	70
PC30		Not used in indexer positioning operation.	000011	
PC37	\backslash	not used in indexer positioning operation.	U	
PC30			0	
PC39 PC40			0	
PC40 PC41		For manufacturer setting	0000h	
	\backslash	For manufacturer setting		
PC42			0000h	
PC43			0000h	
PC44	*00.00		0000h	
PC45	*COP9	Function selection C-9	0000h	
PC46	*STN	Indexer positioning operation number of stations/rotation	0000h	
PC47	PSST	Indexer positioning operation station home position shift distance	0000h	pulse
PC48		For manufacturer setting	0000h	



No.	Symbol	Name and function	Initial value	Unit
PC49	$\overline{\ }$	For manufacturer setting	0000h	
PC50			0000h	

(2) Detail list

No.	Symbol	Name and function	Initial value	Unit	Setting range
PC01		For manufacturer setting	0000h		
		Do not change this value by any means.			
PC02	*ZTY	Home position return type	0000h	Ν	Refer to
		Used to set the home position return system. (Refer to section 5.6.)			name and
		Parameter No.PC02			function
					column.
		Home position return method			
		0: 1:			
		2:			
		3:			
		4: 5: → Not used in indexer postioning operation.			
		6:			
		7: 8:			
		9:			
		A:			
		D: Torque limit changing dog type			
PC03	*ZDIR	Home position return direction	0001h	\	Refer to
		Used to set the home position return direction.		$\left \right\rangle$	name and
		Parameter No.PC03			function
					column.
		Home position return direction			
		0: Station No. increment direction			
		1: Station No. decrement direction			
PC04	ZRF	Home position return speed	500	r/min	0 to
1 004	2111	Used to set the servo motor speed for home position return.	500	1/11111	permissible
		(Refer to section 15.9.)			speed
PC05	CRF	Creep speed	10	r/min	0 to
	••••	Used to set the creep speed after proximity dog detection.		.,	permissible
		(Refer to section 15.9.)			speed
PC06	ZST	Home position shift distance	0	μ m	0
		Used to set the shift distance starting at the Z-phase pulse detection position			to
		inside the encoder. (Refer to section 15.9.)			65535
PC07	\backslash	Not used in indexer positioning operation.	0	\mathbf{N}	\backslash
PC08		Do not change the parameter.	1000		\backslash
PC09			100		
PC10			15.0		
PC11	CRP	Rough match output range	0	$ imes$ 10 ^{STM} μ m	0
		Used to set the command remaining distance range where the rough match			to
		(RXn2) is output.			65535
PC12	JOG	Jog speed	100	r/min	0
		Used to set the jog speed command.			to permissible
					speed



No.	Symbol	Name and function	Initial value	Unit	Setting range
PC13		Not used in indexer positioning operation.	0		
		Do not change the parameter.			
PC14	*BKC	Backlash compensation	0	pulse	0
		Used to set the backlash compensation made when the command			to
		direction is reversed.			32000
		This function compensates for the number of backlash pulses in the			
		opposite direction to the home position return direction.			
		For the home position ignorance (servo-on position as home position), this			
		function compensates for the number of backlash pulses in the opposite			
		direction to the first rotating direction after establishing the home position by switching ON the servo-on (RYn0).			
		In the absolute position detection system, this function compensates for			
		the backlash pulse count in the direction opposite to the operating direction			
		at power-on.			
PC15		For manufacturer setting	0000h		
		Do not change this value by any means.			
PC16	MBR	Electromagnetic brake sequence output	100	ms	0
		Used to set the delay time (Tb) between when the electromagnetic brake			to
		interlock (MBR) switches off and when the base circuit is shut off.			1000
PC17		Not used in indexer positioning operation.	50		
		Do not change the parameter.			
PC18	*BPS	Alarm history clear	0000h	Ν	Refer to
		Used to clear the alarm history.		\backslash	name and
		0 0 0			function
					column.
		Alarm history clear			
		0: Invalid			
		1: Valid When alarm history clear is made valid,			
		the alarm history is cleared at next power-on.			
		After the alarm history is cleared, the setting			
		is automatically made invalid (reset to 0).			
				\	
PC19	*ENRS	Encoder output pulse selection	0000h		Refer to
		Use to select the, encoder output pulse direction and encoder output pulse			name and
		setting.			function
					column.
		Encoder output pulse phase changing			
		Changes the phases of A, B-phase encoder pulses output .			
		Servo motor rotation direction			
		Set value CCW CW			
			1		
		0 B-phase B-phase B-phase A-phase A-phase A-phase			
		0 B-phase B-phase A-phase A-phase			
		0 B-phase B-phase B-phase 1 A-phase A-phase			
		0 B-phase B-phase 1 A-phase A-phase B-phase B-phase Encoder output pulse setting selection (refer to parameter No.PA15).			
		0 B-phase B-phase 1 A-phase A-phase B-phase B-phase Encoder output pulse setting selection (refer to parameter No.PA15). 0: Output pulse designation			
		0 B-phase B-phase 1 A-phase A-phase B-phase B-phase Encoder output pulse setting selection (refer to parameter No.PA15).			



No.	Symbol	Name and function	Initial value	Unit	Setting range
PC20	*SNO	Station number setting	0	station	
1 020	0110	Used to specify the station number for RS-422 serial communication and	Ŭ	Station	to
		USB communication.			31
		Always set one station to one axis of driver. If one station number is set to			01
		two or more stations, normal communication cannot be made.			
PC21	*SOP	RS-422 communication function selection	0000h		Refer to
1021	001	Select the communication I/F and select the RS-422 communication	000011	\backslash	name and
		conditions.			function
					column.
		0 0			
		RS-422 communication baud rate selection			
		0: 9600 [bps]			
		1: 19200 [bps]			
		2: 38400 [bps] 3: 57600 [bps]			
		4: 115200[bps]			
		RS-422 communication response delay time			
		0: Invalid			
		1: Valid, reply sent after delay time of 800 μs or more			
				\\	
PC22	*COP1	Function selection C-1	0000h	\land	Refer to the
		Select the encoder cable communication system selection.			name and
					function field.
		Encoder cable communication system selection			
		0: Two-wire type 1: Four-wire type			
		The following cables are of 2-wire type.			
		LE-CSE-□2□ LE-CSE-□5□			
		LE-CSE-□A□			
		Incorrect settinf will result in an encoder alarm1(A16) or encoder alarm2(A20)			
PC23		For manufacturer setting	0000h		
		Do not change this value by any means.			
PC24	$\overline{}$	Not used in indexer positioning operation.	0000h	\searrow	
		Do not change the parameter.			
PC25		For manufacturer setting	0000h	\searrow	
		Do not change this value by any means.		\mid	
PC26	*COP5	Function selection C-5	0000h	\backslash	Refer to
		Select the stroke limit warning (A99).			name and
					function
					column.
		Stroke limit warning (A99) selection			
		0: Valid			
		1: Invalid When this parameter is set to "1", A99 will not			
		occur if the forward rotation stroke end (LSP) or			
		reverse rotation stroke end (LSN) turns OFF.			
PC27		For manufacturer setting	0000h	\sim	
		Do not change this value by any means.			
PC28		Not used in indexer positioning operation.	0000h	\searrow	
		Do not change the parameter.	1		



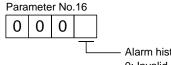
No.	Symbol	Name and function	Initial value	Unit	Setting range
PC29		For manufacturer setting	0000h		
		Do not change this value by any means.			
PC30	*DSS	Remote register-based position/speed specifying system selection This parameter is made valid when Position/speed specification selection (RY(n+2)A) is turned ON with 2 stations occupied. Select how to receive the position command and speed command. When 1 station is occupied, selection of "0001" or "0002" will result in a parameter error. 0 0 Set value Position command Set value Position command Specify the servo point table No. Specify the servo motor speed. (Note)	0000h		Refer to name and function column.
		Note. In the case, always set the acceleration/deceleration time constant in the point table No.1.			
PC31	\backslash	Not used in indexer positioning operation.	0	\backslash	
PC32		Do not change the parameter.			
PC33			0		
PC34 PC35	TL2	Internal torque limit 2	100.0	%	0
FC35	I LZ	Set this parameter to limit servo motor torque on the assumption that the	100.0	70	to
		maximum torque is 100[%].			100.0
		When 0 is set, torque is not produced.			
PC36		For manufacturer setting	0000h		
		Do not change this value by any means.			
PC37		Not used in indexer positioning operation.	0		
PC38		Do not change the parameter.			
PC39			0		
PC40					
PC41		For manufacturer setting	0000h		\backslash
PC42		Do not change this value by any means.	0000h		
PC43			0000h		
PC44			0000h		
PC45	*COP9	Function selection C-9	0000h	\backslash	0000h
		Select the manual operation mode.		$\langle \rangle$	to
					0001h
		Manual operation for indexer positioning operation selection (Refer to section 16.7.3) 0: Indexer JOG operation 1: JOG operation			

No.	Symbol		Name and	I function		Initial value	Unit	Setting range
PC46	*STN	STNIndexer positioning operation number of stations/rotationSet the number of stations (dividing number) per machine rotation. When the setting value is 2 or lower, the number of stations is set to 2.		0000h	Number of stations	0000h to 00FFh		
			Setting value	Number of stations]			
			0000	2]			
			0001	2				
			0002	2				
			0003	3				
			0004	4				
			•	•				
			-	•				
			•	•	-			
			00FF	255	J			
PC47	PSST	This parameter is Set the distance for position in number This shift distance position setting. It When the sift dista (RXn1) does not to	dexer positioning operation station home position shift distance his parameter is available only in the absolute position detection system. et the distance for shifting the home position toward the set home his shift distance does not become valid immediately after the home his shift distance does not become valid immediately after the home his shift distance does not become valid after turning off and then on the power. hen the sift distance is larger than the in-position range, the in position Xn1) does not turn on at power-on. et the number of pulses to be shifted after converting it into hexadecimal.		0000h	pulse	Refer to name and function column	
PC48		For manufacturer		-		0000h		
PC49		Do not change this	o not change this value by any means.					
PC50						0000h		

(3) Alarm history clear

The alarm history can be confirmed by using the set up software(MR Configurator2TM). The driver stores one current alarm and five past alarms from when its power is switched on first. To control alarms which will occur during operation, clear the alarm history using parameter No.PC18 (alarm history clear) before starting operation. Clearing the alarm history automatically returns to "DDD0".

This parameter is made valid by switching power off, then on after setting.

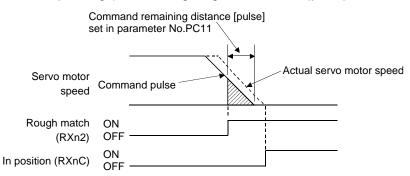


Alarm history clear 0: Invalid (not cleared) 1: Valid (cleared)



(4) Rough match output

Rough match (RXn2) is output when the command remaining distance reaches the value set in parameter No.PC11 (rough match output range). The setting range is 0 to 65535 [pulse].



15.11.4 I/O setting parameters (No.PDDD)

(1) Parameter list

No.	Symbol	Name	Initial value	Unit
PD01	*DIA1	Input signal automatic ON selection 1	0000h	
PD02		For manufacturer setting	0000h	
PD03		Not used in indexer positioning operation.	0000h	
PD04			0000h	
PD05		For manufacturer setting	0000h	
PD06	\setminus	Not used in indexer positioning operation.	002Bh	Ν
PD07	\setminus		000Ah	
PD08	\setminus		000Bh	
PD09	\setminus		0002h	
PD10			0003h	
PD11	\setminus		0024h	
PD12			0C00h	
PD13		For manufacturer setting	0000h	
PD14		Not used in indexer positioning operation.	0800h	
PD15		For manufacturer setting	0000h	
PD16	*DIAB	Input polarity selection	0000h	
PD17		For manufacturer setting	0000h	
PD18			0000h	
PD19	*DIF	Response level setting	0002h	
PD20	*DOP1	Function selection D-1	0010h	
PD21	\sim	For manufacturer setting	0000h	
PD22	\sim	Not used in indexer positioning operation.	0000h	
PD23		For manufacturer setting	0000h	
PD24	*DOP5	Function selection D-5	0000h	
PD25		For manufacturer setting	0000h	
PD26	TLT	Indexer positioning operation torque limit delay time	0064h	
PD27	\backslash	For manufacturer setting	0000h	\square
PD28	\backslash		0000h	
PD29	\backslash		0000h	
PD30	\backslash		0000h	



(2) Detail list

No.	Symbol	Name and function	Initial value	Unit	Setting range
PD01	*DIA1	Input signal automatic ON selection 1 Select the input devices to be automatically turned ON. part is for manufacturer setting. Do not set the value by any means. Image: Device name Initial value Image: Device name Initial value Image: Device name Initial value Image: Device name Image: Device name Image: Device name Image	0000h		Refer to name and function column.
PD02		For example, to turn ON SON, the setting is "□□□4". For manufacturer setting	0000h		
		Do not change this value by any means.			
PD03	$\left \right\rangle$	Not used in indexer positioning operation.	0000h		\sim
PD04		Do not change the parameter.	0000h		
PD05	$>$ $ $	For manufacturer setting	0000h		
DDOG	$ \rightarrow $	Do not change this value by any means.	00006	$ \longrightarrow $	$ \longrightarrow $
PD06 PD07	$\langle \rangle$	Not used in indexer positioning operation. Do not change the parameter.	002Bh 000Ah	$\langle \rangle$	\backslash
PD07 PD08	$\langle \rangle$	Do not change the parameter.	-		\backslash
			000Bh 0002h		
PD09					
PD10 PD11			0003h		
			0024h	\	
PD12			0C00h		
PD13	\mathbf{i}	For manufacturer setting	0000h		
		Do not change this value by any means.	00006	$ \rightarrow $	
PD14	\mathbf{i}	Not used in indexer positioning operation.	0800h		
		Do not change the parameter. For manufacturer setting	0000h		$ \longrightarrow$
PD15					

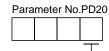


PD20 'DOP1 For manufacturer setting 0000h name and function column. PD11 For manufacturer setting 0000h 0000h Refer to setting the detection of the dog PD13 'DIF Response level setting 0000h 0000h Refer to namufacturer setting PD13 'DIF Response level setting 0000h 0000h Refer to namufacturer setting PD13 'DIF Response level setting 0000h 0000h name and function column. Imput filter If external input signal causes chattering due to noise, etc., input filter is used to suppress it. 0000h column. Imput filter If external input signal causes chattering due to noise, etc., input filter is used to suppress it. 0010h name and function column. PD20 'DDP1 Function selection D-1 Select the stop processing at forward rotation stroke end (LSN)/reverse rotation stroke end (LSN)/reverse rotation stroke end (LSN) OFF and the base circuit status at reset (RY(N+1)A or RY(n+3)A) ON. 0010h name and function column. Imput filter Stopping method used when forward rotation stroke end (LSN) device or software limit is valid 0.5 Moden stop (home position retreate) 0010h Imput filter Stopping nethod used when forward rotation stroke end (LSN) de	No.	Symbol	Name and function	Initial value	Unit	Setting range
PD18 Do not change this value by any means. 0000h PD19 *DIF Response level setting Used to select the input. 0002h Refer to name and function column. Imput filter If external input signal causes chattering due to noise, etc., input filter is used to suppress it. 0002h Refer to name and function column. PD20 *DOP1 Function selection D-1 Select the stop processing at forward rotation stroke end (LSN)/reverse rotation stroke end (LSN) OFF and the base circuit status at reset (RY(N+1)A or RY(n+3)A) ON. 0010h Refer to name and function column. Imput filter imit is value (CSN) certain stroke end (LSN)/reverse rotation stroke end (LSN) OFF and the base circuit status at reset (RY(N+1)A or RY(n+3)A) ON. 0010h Refer to name and function column. Imput filter imit is value (CSN) certain stroke end (LSN)/deverse rotation stroke end (LSN) of theme position erased) 0010h Refer to name and function column. Imput filter imit is value (CSN) certain stroke end (LSN)/deverse rotation stroke end (LSN) device or software imit is value (CSN) certain stroke end (LSN) device or software imit is value (CSN) certain is the same as for "1".) 3: Sudden stop (fetting contents is the same as for "1".) 3: Sudden stop (fetting contents is the same as for "1".) 3: Sudden stop (CSN carbotic position erased) Stopicing method used when forward rotation position restrom. How were, in the absolute position restrom. How were, in the absolute position restrom. How were, in the absolute position restrom. In the case, executing anothetection system (Gearame	PD16	*DIAB	Used to set the proximity dog input polarity. (Refer to section 5.6.)	0000h		name and function
PD19 *DIF Response level setting Used to select the input. 0002h Refer to name and function oolumn. 0 0 0 0 0 0 1 Input filter If external input signal causes chattering due to noise, etc., input filter is used to suppress it. 0: None 1: 0.88[ms] 2: 1.77[ms] 3: 2.66[ms] 5: 4.44[ms] 0010h Refer to name and function stroke end (LSN) OFF and the base circuit status at reset (RY(N+1)A or RY(n+3)A) ON. 0010h Refer to name and function column. 0 0	PD17		For manufacturer setting	0000h		
Used to select the input. name and function column. Image: Input filter Input filter If external input signal causes chattering due to noise, etc., input filter is used to suppress it. 0.000 Image: Imag	PD18		Do not change this value by any means.	0000h		
Select the stop processing at forward rotation stroke end (LSN)/reverse rotation stroke end (LSN) OFF and the base circuit status at reset (RY(N+1)A or RY(n+3)A) ON. name and function column. O O	PD19	*DIF	Used to select the input. OOOO Input filter If external input signal causes chattering due to noise, etc., input filter is used to suppress it. O: None 1: 0.88[ms] 2: 1.77[ms] 3: 2.66[ms] 4: 3.55[ms]	0002h		name and function
Do not change this value by any means. PD22 Not used in indexer positioning operation. Do not change the parameter.	PD20	*DOP1	Select the stop processing at forward rotation stroke end (LSN)/reverse rotation stroke end (LSN) OFF and the base circuit status at reset (RY(N+1)A or RY(n+3)A) ON.	0010h		name and function
Do not change the parameter.	PD21		0	0000h		
	PD22		Not used in indexer positioning operation.	0000h		
	PD23			0000h	$\overline{)}$	

No.	Symbol	Name and function	Initial value	Unit	Setting range
PD24	*DOP5	Function selection D-5 Select the output status of the warning (RXnA). 0 0 0 Select the output device at warning occurrence Select the warning (RXnA) and trouble (RX(n+1)A or RX(n+3)A) output status at warning occurrence. Setting (Note) Device status Remote output RX(n+1)A or RX(n+3)A 1 0 Output device RX(n+1)A or RX(n+3)A 1 0 Output device ALM ON OFF 1 Output device RXnA 1 RX(n+3)A 0 OFF 1 Output device ALM ON OFF Warning occurred. Note. 0: OFF 1: QN OFF Warning occurred.	0000h		
PD25		For manufacturer setting Do not change this value by any means.	0000h		
PD26	TLT	Indexer positioning operation torque limit delay time Set the delay time from when the in position (RXn1) turns on until the internal torque limit 2 (parameter No.PC35) becomes effective. Set the delay time after converting it into hexadecimal. The setting range is from 0 to 1000 ms.	0064h	ms	Refer to name and function column.
PD27 PD28 PD29 PD30		For manufacturer setting Do not change this value by any means.	0000h 0000h 0000h 0000h		



(3) Stopping method when the forward stroke end (LSP) or reverse stroke end (LSN) is valid The setting of the first digit of parameter No.PD20 enables to select a stopping method of the servo motor when the forward rotation stroke end (LSP) or reverse rotation stroke end (LSN) turns off.



Stopping method when the forward rotation stroke end (LSP) or reverse rotation stroke end (LSN) is valid

- 0: Sudden stop (home position erased)
- 1: Slow stop (home position erased)
- 2: Slow stop (Setting contents is the same as for "1".)
- 3: Sudden stop (Setting contents is the same as for "0".)

Setting value of	Operati	on status	Remarks
parameter No.PD20	When rotating at constant speed	When decelerating to stop	Remarks
□□□0 (Initial value) □□□3	Without S-pattern acceleration/deceleration With S-pattern acceleration/deceleration Servo motor speed 0r/min	Without S-pattern acceleration/deceleration With S-pattern acceleration/deceleration speed	Clears droop pulses and stops. Erases the home position. A difference occurs between the command position and the current
	LSP ON or LSN OFF	LSP or ON LSN OFF	position. Execute a home position return again.
	Servo motor speed Or/min OFF	Servo motor speed Or/min Servo motor Servo mo	Moves for the amount of droop pulse and stops. Erases the home position. A difference occurs between the command position and the current position. Execute a home position return again.

15.12 TROUBLESHOOTING

15.12.1 Trouble at start-up



• Excessive adjustment or change of parameter setting must not be made as it will make operation instable.

POINT

• Using the set up software(MR Configurator2[™]), you can refer to unrotated servo motor reasons, etc.

The following faults may occur at start-up. If any of such faults occurs, take the corresponding action.

No.	Start-up sequence	Fault	Investigation	Possible cause	Reference
1	Power on	 LED is not lit. LED flickers. 	Not improved if connectors CN2, CN3 and CN6 are disconnected.	 Power supply voltage fault Driver is faulty. 	
			Improved when connectors CN6 is disconnected.	Power supply of CN6 cabling is shorted.	
			Improved when connector CN2 is disconnected.	 Power supply of encoder cabling is shorted. Encoder is faulty. 	
			Improved when connector CN3 is disconnected.	Power supply of CN3 cabling is shorted.	
		Alarm occurs.	Refer to section 15.12.4 and re	emove cause.	Section 15.12.4
2	Switch on servo-on (RYn0) signal.	Alarm occurs.	Refer to section 15.12.4 and re	emove cause.	Section 15.12.4
		Servo motor shaft is not servo-locked (is free).	1. Check the external I/O signal indication to see if the servo-on (RYn0) signal is ON.	 Servo-on (RYn0) is not input. (Wiring mistake) 24VDC power is not supplied to DICOM. 	
3	Gain adjustment	Rotation ripples (speed fluctuations) are large at low speed.	 Make gain adjustment in the following procedure. 1. Increase the auto tuning response level. 2. Repeat acceleration and deceleration several times to complete auto tuning. 	Gain adjustment fault	Chapter 8
		Large load inertia moment causes the servo motor shaft to oscillate side to side.	If the servo motor may be run with safety, repeat acceleration and deceleration several times to complete auto tuning.	Gain adjustment fault	Chapter 8
4	Cyclic operation	Position shift occurs	Confirm the cumulative command pulses, cumulative feedback pulses and actual servo motor position.	Pulse counting error, etc. due to noise.	



15.12.2 Operation at error occurrence

An error occurring during operation will result in any of the statuses indicated in the following table.

Error location	Description	Operati	Operation mode		
Error location	Description	Test operation	CC-Link operation		
Servo side alarm	Servo operation	Stop	Stop		
occurrence	CC-Link data communication	Continued	Continued		
Option unit	Servo operation	Stop	Stop		
communication error	CC-Link data communication	Stop	Stop		
CC-Link	Servo operation	Stop	Stop		
communication error	CC-Link data communication	Stop	Stop		
PC or PLCetc	Servo operation	Continued	Stop		
error/STOP	CC-Link data communication	Stop	Stop		
Servo side warning	ervo side warning Servo operation		Continued		
occurrence	CC-Link data communication	Continued	Continued		

15.12.3 CC-Link communication error

This section gives the definitions of the indications given in the communication alarm display section. The driver has four LED indications.

L.RUN : Lit at normal receive of refresh data. Extinguished when data is not received for a given period of time.

- SD : Lit when send data is "0".
- RD : Lit when the carrier of receive data is detected.

L.ERR : Lit when the data addressed to the host is in CRC or abort error.

(Note) Cor	nmunicatio	on alarm di	splay LED	Occuritien	
L.RUN	SD	RD	L.ERR	Operation	
0	\odot	0	0	Normal communication is made, but a CRC error sometimes occurs due to noise.	
0	0	0		Normal communication	
0	\odot		0	Hardware fault	
0	\odot		•	Hardware fault	
0		0	0	Receive data results in CRC error, disabling a response.	
0		0		Data does not reach the host.	
0			0	Hardware fault	
0	•	•		Hardware fault	
	\odot	0		Hardware fault	
	0	0	0	Polling response is made, but refresh receive is in CRC error.	
	0	0		Hardware fault	
	0	•	0	Hardware fault	
\bullet	0			Hardware fault	
	•	0	0	Data addressed to the host resulted in CRC error.	
		0		Data does not reach the host, or the data addressed to the host cannot be received due to	
-	•	e	•	noise.	
		•	0	Hardware fault	
			0	Baud rate setting illegal	
		0	0	Station number setting illegal	
	0	0	0	Baud rate or station number setting changed midway (ERROR flickers for about 4s)	
	•	•		Data cannot be received due to power-off, power supply failure, open cable, etc.	
-	-	-	-	WDT error occurrence (hardware fault)	

Note. \bigcirc : Lit \bullet : Extinguished \bigcirc : Flicker



15.12.4 When alarm or warning has occurred

POINT		
 Configure 	up	а

• Configure up a circuit which will detect the trouble (ALM) signal and turn off the servo-on (RYn0) at occurrence of an alarm.

(1) Alarms and warning list

When a fault occurs during operation, the corresponding alarm or warning is displayed. If any alarm or warning has occurred, refer to (2), (3) in this section and take the appropriate action. When an alarm occurs, ALM turns off.

After its cause has been removed, the alarm can be deactivated in any of the methods marked \bigcirc in the alarm deactivation column.

\setminus			Ala	rm deactivatio	on	\geq	Display	Name	
$\left \right $	Dianlass	Norre	Davier	(Note 3)	(Note 2)		A90	Home positioning incomplete warning	
	Display	Name	Power OFF→ON	MR	Alarm reset		A92	Open battery cable warning	
				0	(RES)		A96	Home position setting error	
				parameter unit	(110)		A97	Next station warning	
	A10	Undervoltage	0	0	0		A99	Stroke limit warning	
	A12	Memory error 1 (RAM)	0				A9D	CC-Link warning 1	
	A13	Clock error	0			S	A9E	CC-Link warning 2	
	A15	Memory error 2	0		$ \ \ \ \ \ \ \ \ \ \ \ \ \ $	nin	A9F	Battery warning	
	ЛIJ	(EEP-ROM)				Warnings	AE0	Excessive regeneration warning	
	A16	Encoder error 1	0	\sim	\searrow		AE1	Overload warning 1	
		(At power on)					AE3	Absolute position counter warning	
	A17	Board error	0				AE6	Servo forced stop warning	
	A19	Memory error 3 (Flash-ROM)	0		\searrow		AE8	Cooling fan speed reduction warning	
	A1A	Motor combination error	0				AE9	Main circuit off warning	
	A20	Encoder error 2	0				AEC	Overload warning 2	
	A24	Main circuit error	0	0	0		AED	Output watt excess warning	
	A25	Absolute position erase	0						
	A30	Regenerative error	(Note 1)	(Note 1)	(Note 1)				
6	A31	Overspeed	0	0	0				
Alarms	A32	Overcurrent	0	/					
Ala	A33	Overvoltage	0	0	0				
	A37	Parameter error	0						
	A45	Main circuit device overheat	(Note 1)	(Note 1)	(Note 1)				
	A46	Servo motor overheat	(Note 1)	(Note 1)	(Note 1)				
	A47	Cooling fan alarm	0						
	A50	Overload 1	(Note 1)	(Note 1) 〇	(Note 1)				
	A51	Overload 2	(Note 1)	(Note 1)	(Note 1)				
	A52	Error excessive	0	0	0				
	A61	Operation alarm	0	0	0				
	A8A	Serial communication time-out error	0	0	0				
	A8D	CC-Link alarm	0	0	0				
	A8E	Serial communication error	0	0	0				
	888	Watchdog	0	\sim	\sim				

Note 1. Deactivate the alarm about 30 minutes of cooling time after removing the cause of occurrence.

2. Turns on RY(n+1)A or RY(n+3)A.

3. Clicking the "Alarm reset" button on the "Alarm display" screen of set up software(MR Configurator2[™]) allows an alarm to be deactivated. Pressing the "STOP RESET" key of the parameter unit allows an alarm to be deactivated.



(2) Remedies for alarms

	 When any alarm has occurred, eliminate its cause, ensure safety, then reset the alarm, and restart operation. Otherwise, injury may occur. 		
	 If an absolute position erase (A25) occurred, always make home position setting again. Not doing so may cause unexpected operation. 		
	 As soon as an alarm occurs, turn off Servo-on (RYn0) and power off. 		
	POINT		

• When any of the following alarms has occurred, do not deactivate the alarm
and resume operation repeatedly. To do so will cause the driver/servo motor
to fail. Remove the cause of occurrence, and leave a cooling time of more
than 30 minutes before resuming operation.

- Regenerative error (A30)
- Overload 1 (A50)
- Overload 2 (A51)
- For the alarm deactivation method, refer to (1) in this section.

When an alarm occurs, the trouble (ALM) switches off and the dynamic brake is operated to stop the servo motor. At this time, the display indicates the alarm No.

The servo motor comes to a stop. Remove the cause of the alarm in accordance with this section. Use the set up software(MR Configurator) to refer to a factor of alarm occurrence.

Display	Name	Definition	Cause	Action
A10	Undervoltage	Power supply voltage dropped.	 Power supply voltage is low. There was an instantaneous control power failure of 60ms or longer. 	Check the power supply.
		160VAC or less	 Shortage of power supply capacity caused the power supply voltage to drop at start, etc. 	
			 The bus voltage dropped to the following value or less. LECSC2-T	
			5. Faulty parts in the driver. Checking method Alarm (A10) occurs if power is switched on after disconnection of all cables but the control circuit power supply cables.	Change the driver.
A12	Memory error 1 (RAM)	RAM, memory fault	Faulty parts in the driver. Checking method	Change the driver.
A13	Clock error	Printed board fault	Alarm (any of A12 and A13) occurs if power is switched on after disconnection of all cables but the control circuit power supply cables.	



Display	Name	Definition	Cause	Action
A15	Memory error 2 (EEP-ROM)	EEP-ROM fault	 Faulty parts in the driver Checking method Alarm (A15) occurs if power is switched on after disconnection of all cables but the control circuit power supply cables. The number of write times to EEP-ROM exceeded 100,000. 	Change the driver.
			3. The multi-revolution data, which is saved as a home position, read from EEP-ROM is abnormal.	Execute a home position setting.
A16	Encoder error 1 (At power on)	Communication error occurred	1. Encoder connector (CN2) disconnected.	Connect correctly.
		between encoder and driver.	 2. Encoder fault 3. Encoder cable faulty (Wire breakage or shorted) 4. Encoder cable type (2-wire, 4-wire) 	Change the servo motor. Repair or change the cable. Correct the setting in the fourth digit of
			selection was wrong in parameter setting.	parameter No.PC22.
A17 A19	Board error Memory error 3 (Flash ROM)	CPU/parts fault ROM memory fault	Faulty parts in the driver Checking method Alarm (A17 or A19) occurs if power is switched on after disconnection of all cables but the control circuit power supply cable.	Change the driver.
A1A	Motor combination error	Wrong combination of driver and servo motor.	Wrong combination of driver and servo motor connected.	Use correct combination.
A20	Encoder error 2	Communication error occurred between encoder and driver.	 Encoder connector (CN2) disconnected. Encoder cable faulty (Wire breakage or shorted) Encoder fault 	Connect correctly. Repair or change the cable. Change the servo motor.
A24	Main circuit error	Ground fault occurred at the servo motor power (U,V and W phases) of the driver.	 Power input wires and servo motor power wires are in contact. Sheathes of servo motor power cables deteriorated, resulting in ground fault. Main circuit of driver failed. Checking method Alarm (A24) occurs if the servo is switched on after disconnecting 	Connect correctly. Change the cable. Change the driver.
			the U, V, W power cables from the driver.	



Display	Name	Definition	Cause	Action
A25	Absolute position erase	Absolute position data in error	1. Voltage drop in encoder (Battery disconnected.)	After leaving the alarm occurring for a few minutes, switch power off, then on again. Always make home position setting again.
			2. Battery voltage low	Change the battery.
			3. Battery cable or battery is faulty.	Always make home position setting again.
		Power was switched on for the first time in the absolute position detection system.	4. Home position not set.	After leaving the alarm occurring for a few minutes, switch power off, then on again. Always make home position setting again.
A30	Regenerative	Permissible	1. Wrong setting of parameter No.	Set correctly.
	error	regenerative power	PA02	
		of the built-in	2. Built-in regenerative resistor or	Connect correctly
		regenerative resistor or regenerative	regenerative option is not connected.	
		option is exceeded.	3. High-duty operation or continuous regenerative operation caused the permissible regenerative power of the regenerative option to be exceeded. Checking method Call the status display and check the regenerative load ratio.	 Reduce the frequency of positioning. Use the regenerative option of larger capacity. Reduce the load.
			 Power supply voltage is abnormal. LECSC2-T□:260VAC or more 	Check the power supply
			 Built-in regenerative resistor or regenerative option faulty. 	Change the driver or regenerative option.
		Regenerative transistor fault	 6. Regenerative transistor faulty. Checking method 1) The regenerative option has overheated abnormally. 2) The alarm occurs even after removal of the built-in regenerative resistor or regenerative option. 	Change the driver.
A31	Overspeed	Speed has exceeded the instantaneous	 Input command pulse frequency exceeded the permissible instantaneous speed frequency. 	Set command pulses correctly.
		permissible speed.	2. Small acceleration/deceleration time constant caused overshoot to be large.	Increase acceleration/deceleration time constant.
			 Servo system is instable to cause overshoot. 	 Re-set servo gain to proper value. If servo gain cannot be set to proper value. Reduce load inertia moment ratio; or Reexamine acceleration/ deceleration time constant.
			4. Electronic gear ratio is large (parameters No.PA06, PA07)	Set correctly.
			5. Encoder faulty.	Change the servo motor.



Display	Name	Definition	Cause	Action
A32	Overcurrent	Current that flew is higher than the	1. Short occurred in servo motor power (U, V, W).	Correct the wiring.
	pe of al aç O	permissible current of the driver. (If the alarm (A32) occurs again when turning ON the servo after resetting the alarm	2. Transistor (IPM, IGBT) of the driver faulty. Checking method Alarm (A32) occurs if power is switched on after U,V and W are disconnected.	Change the driver.
		by turning OFF/ON the power when the	3. Ground fault occurred in servo motor power (U, V, W).	Correct the wiring.
		alarm (A32) first occurred, the transistor (IPM, IGBT) of the driver may be at fault. In the case, do not repeat to turn OFF/ON the power. Check the transistor with the checking method of "Cause 2".)	 External noise caused the overcurrent detection circuit to misoperate. 	Take noise suppression measures.
A33	Overvoltage	The following shows	1. Regenerative option is not used.	Use the regenerative option.
		the input value of converter bus voltage.	 Though the regenerative option is used, the parameter No.PA02 setting is "	Set correctly.
		LECSC2-T :	3. Lead of built-in regenerative resistor	1. Change the lead.
		400VDC or more	or regenerative option is open or disconnected.	2. Connect correctly.
			4. Regenerative transistor faulty.	Change the driver
			5. Wire breakage of built-in regenerative resistor or regenerative option.	 For wire breakage of built-in regenerative resistor, change the driver. For wire breakage of regenerative option, change the regenerative option.
			 Capacity of built-in regenerative resistor or regenerative option is insufficient. 	Add regenerative option or increase capacity.
			7. Power supply voltage high.	Check the power supply.
			8. Ground fault occurred in servo motor power (U, V, W).	Correct the wiring.



Display	Name	Definition	Cause	Action
A37	Parameter error	r Parameter setting is wrong.	 Driver fault caused the parameter setting to be rewritten. 	Change the driver.
			 Regenerative option not used with driver was selected in parameter No.PA02. 	Set parameter No.PA02 correctly.
			 Value outside setting range has been set in electronic gear. 	Set parameters No.PA06, PA07 correctly.
			4. The number of write times to EEP- ROM exceeded 100,000 due to parameter write, etc.	Change the driver.
			5. The MR-J3-D01 (Mitsubishi Electric Corporation) is connected to the driver for the indexer positioning operation.	The MR-J3-D01 (Mitsubishi Electric Corporation) cannot be used for the indexer positioning operation.
		Point table setting is wrong.	6. Setting value is out of the setting range.	Set it correctly.
A45	Main circuit device overheat	Main circuit device overheat.	1. Driver faulty.	Change the driver.
			2. The power supply was turned on and off continuously by overloaded status.	The drive method is reviewed.
			3. Ambient temperature of servo motor is over 55°C (131°F).	Check environment so that ambient temperature is 0 to 55°C (32 to 131°F).
			 Used beyond the specifications of close mounting. 	Use within the range of specifications.
A46	Servo motor overheat	Servo motor temperature rise	1. Ambient temperature of servo motor is over 40°C (104°F).	Check environment so that ambient temperature is 0 to 40°C (32 to 104°F).
		actuated the thermal sensor.	2. Servo motor is overloaded.	 Reduce load. Check operation pattern. Use servo motor that provides larger output.
			3. Thermal sensor in encoder is faulty.	Change the servo motor.
A47	Cooling fan alarm	The cooling fan of the driver stopped,	Cooling fan life expiration (Refer to section 2.5.)	Change the cooling fan of the driver.
		or its speed decreased to or	Foreign matter caught in the cooling fan stopped rotation.	Remove the foreign matter.
		below the alarm level.	The power supply of the cooling fan failed.	Change the driver.



Display	Name	Definition	Cause	Action
A50	Overload 1	Load exceeded overload protection characteristic of driver.	 Driver is used in excess of its continuous output current. 	 Reduce load. Check operation pattern. Use servo motor that provides larger output.
			2. Servo system is instable and hunting.	 Repeat acceleration/deceleration to execute auto tuning. Change auto tuning response setting. Set auto tuning to OFF and make gain adjustment manually.
			3. Machine struck something.	 Check operation pattern. Install limit switches.
			 Wrong connection of servo motor. Driver's output terminals U, V, W do not match servo motor's input terminals U, V, W. 	Connect correctly.
			5. Encoder faulty. Checking method When the servo motor shaft is rotated with the servo off, the cumulative feedback pulses do not vary in proportion to the rotary angle of the shaft but the indication skips or returns midway.	Change the servo motor.
			 After Overload 2 (A51) occurred, turn OFF/ON the power supply to clear the alarm. Then the overload operation is repeated. 	 Reduce load. Check operation pattern. Use servo motor that provides larger output.
A51	Overload 2	Machine collision or the like caused max. For the time of the alarm occurrence, refer to the section 12.1.	 Machine struck something. Wrong connection of servo motor. Driver's output terminals U, V, W do not match servo motor's input terminals U, V, W. 	 Check operation pattern. Install limit switches. Connect correctly.
			 Servo system is instable and hunting. 	 Repeat acceleration/deceleration to execute auto tuning. Change auto tuning response setting. Set auto tuning to OFF and make gain adjustment manually.
			4. Encoder faulty. Checking method When the servo motor shaft is rotated with the servo off, the cumulative feedback pulses do not vary in proportion to the rotary angle of the shaft but the indication skips or returns midway.	Change the servo motor.



15. INDEXER POSITIONING OPERATION

Display	Name	Definition	Cause	Action
A52	Error excessive The difference between the model		1. Acceleration/deceleration time constant is too small.	Increase the acceleration/deceleration time constant.
		position and the actual servo motor position exceeds three rotations.	2. Forward rotation torque limit (parameter No.PA11) or reverse rotation torque limit (parameter	Increase the torque limit value.
		(Refer to the function block diagram in section	No.PA12) are too small.3. Motor cannot be started due to torque shortage caused by power supply voltage drop.	 Check the power supply capacity. Use servo motor which provides larger output.
		1.1.2.)	 Position loop gain (parameter No.PB08) value is small. 	Increase set value and adjust to ensure proper operation.
			5. Servo motor shaft was rotated by external force.	 When torque is limited, increase the limit value. Reduce load. Use servo motor that provides larger
			6. Machine struck something.	output. 1. Check operation pattern. 2. Install limit switches.
			 7. Encoder faulty. 8. Wrong connection of servo motor. Driver's output terminals U, V, W do not match servo motor's input terminals U, V, W. 	Change the servo motor. Connect correctly.
A61	Operation alarm	Setting mistake of auxiliary function.	"1" or "3" is set for the auxiliary function of point table No.255.	Set "0" or "2" for the value of auxiliary function.
A8A	Serial communication	Communication stopped for longer	1. Communication cable breakage.	Repair or change the communication cable.
	time-out error	than the specified time.	2. Communication cycle longer than regulated time.	Shorten the communication cycle.
			3. Wrong protocol.	Correct protocol.
A8D	CC-Link alarm	Normal communication with the master station	 The station number switch (STATION NO.) setting is 0 or not less than 65. 	Set the station number to within the range 1 to 64, and switch power on.
		cannot be made.	2. The baud rate switch (MODE) setting is outside the range 0 to 4.	Set the baud rate switch (MODE) to within the range 0 to 4.
			 The transmission status is abnormal. CC-Link twisted cable wiring incorrect. CC-Link twisted cable faulty. The CC-Link connector has come 	Reexamine the wiring.1. Repair or change the CC-Link twisted cable.2. Connect the cable or connector correctly.
			off. 7. The terminating resistor is not connected. 8. Noise entered the CC-Link twisted cable.	Connect the terminating resistor correctly.
			9. The CC-Link master unit was reset.	
			 10. The manufacturer setting switch (SW 2) was changed from the shipping state (left side). (Refer to section 3.2.5.) 	Please change the manufacturer setting switch (SW 2) to the shipping state (left side)



15. INDEXER POSITIONING OPERATION

Display	Name	Definition	Cause	Action
A8E			 Communication cable fault (Open cable or short circuit). 	Repair or change the cable.
			2. Communication device (e.g. personal computer) faulty.	Change the communication device (e.g. personal computer).
(Note) 888	, ,		Fault of parts in driver. Checking method Alarm (888) occurs if power is switched on after disconnection of all cables but the control circuit power supply cable.	Change the driver.

Note. At power-on, "888" appears instantaneously, but it is not an error.

(3) Remedies for warnings

• If an absolute position counter warning (AE3) occurred, always make home position setting again. Not doing so may cause unexpected operation.

POINT

- When any of the following alarms has occurred, do not resume operation by switching power of the driver OFF/ON repeatedly. The driver and servo motor may become faulty. If the power of the driver is switched OFF/ON during the alarms, allow more than 30 minutes for cooling before resuming operation.
 - Excessive regenerative warning (AE0)
 - Overload warning 1 (AE1)
- Always execute a home position return when the forward rotation stroke end (LSP) or the reverse rotation stroke end (LSN) turns off.



If AE6 occur, the servo off status is established. If any other warning occurs, operation can be continued but an alarm may take place or proper operation may not be performed.

Remove the cause of warning according to this section. Use the set up software(MR Configurator) to refer to a factor of warning occurrence.

Display	Name		Definition	Cause	Action
A90	Home position return incomplete		Positioning operation was performed without home position return.	 Positioning operation was performed without home position return. 	Perform home position return.
		In incremental system	Home position return ended abnormally.	 Home position return speed could not be decreased to creep speed. The stroke end (LSP or LSN) was actuated during home position return starting at other than position beyond dog. 	Check home position return speed/creep speed/moving distance after proximity dog.
		In incren	Home position return is incomplete.	 4. Indexer JOG operation (in automatic/ manual operation) was executed without home position return. 5. The operation method (parameter No.PA01), electronic gear (parameter No.PA06 and PA07), station No. direction selection (parameter No.PA14), or number of stations/rotation (parameter No.PC46) is changed. 	Perform home position return. This warning is automatically cleared after executing a home position return.
			Positioning operation was performed without home position setting.	1. Positioning operation was performed without home position setting.	Perform home position setting.
		system	Home position setting ended abnormally.	 Home position setting speed could not be decreased to creep speed. The stroke end (LSP or LSN) was actuated during home position setting starting at other than position beyond dog. 	Check home position setting speed/creep speed/moving distance after proximity dog.
		sition detection system	Operation was performed without making home position setting	4. Voltage drop in encoder (Battery disconnected.)	After leaving the alarm occurring for a few minutes, switch power off, then on again. Always make home position setting again.
		In absolute pos	while an absolute position erase (A25) is being occurred.	 5. Battery voltage low 6. Battery cable or battery is faulty. 	Change the battery. Always make home position setting again.
		L	Home position setting is incomplete.	 Indexer JOG operation (in automatic/ manual operation) was executed without home position setting. The operation method (parameter No.PA01), electronic gear (parameter No.PA06 and PA07), station No. direction selection (parameter No.PA14), or number of stations/rotation (parameter No.PC46) is changed. 	Perform home position setting. This warning is automatically cleared after executing a home position setting.



15. INDEXER POSITIONING OPERATION

Display	Name	Definition	Cause	Action
A92	Open battery	Absolute position	1. Battery cable is open.	Repair cable or changed.
	cable warning	detection system battery voltage is low.	 Battery voltage supplied from the driver to the encoder fell to about 3V or less. (Detected with the encoder) 	Change the battery.
A96	Home position setting error	Home position setting could not be made.	1. Droop pulses remaining are greater than the in-position range setting.	Remove the cause of droop pulse occurrence
			2. Command pulse entered after clearing of droop pulses.	Do not enter command pulse after clearing of droop pulses.
A97	Next station warning	Automatic operation is executed with invalid next station setting.	 Creep speed high. Automatic operation has been started when station number that exceeded the setting value of parameter No.PC46 (number of stations/rotation) is specified. Automatic operation has been started when the next station selection 1 to 8 (RYnA to RYnE, and RY(n+2)3 to RY(n+2)5) are all set to on. 	Reduce creep speed. Specify the station number up to the maximum number of stations set in the parameter No.PC46 (indexer positioning operation number of stations/rotation).
A99	Stroke limit warning	The limit switch become valid.	The stroke end (LSP or LSN) of the direction which gave instructions was turned off.	Reexamine the operation pattern to turn LSP/LSN ON.
A9D	CC-Link warning 1	The station number switch or baud rate switch position was changed from the setting at power-on.	 The station number switch position was changed from the setting at power-on. The baud rate switch position was changed from the setting at power-on. The occupied station count switch position was changed from the setting at power-on. 	Return to the setting at power- on.
A9E	CC-Link warning 2	Communication error of cable.	 The transmission status is abnormal. CC-Link twisted cable wiring incorrect. CC-Link twisted cable faulty. The CC-Link connector has come off. 	 Take measures against noise. Change the CC-Link twisted cable. Connect the cable or connector correctly.
			5. The terminating resistor is not connected.6. Noise entered the CC-Link twisted cable.	Connect the terminating resistor correctly.
A9F	Battery warning	Voltage of battery for absolute position detection system reduced.	Battery voltage fell to 3.2V or less. (Detected with the driver)	Change the battery.
AE0	Excessive regenerative warning	There is a possibility that regenerative power may exceed permissible regenerative power of built-in regenerative resistor or regenerative option.	Regenerative power increased to 85% or more of permissible regenerative power of built-in regenerative resistor or regenerative option. Checking method Call the status display and check regenerative load ratio.	 Reduce frequency of positioning. Change the regenerative option for the one with larger capacity. Reduce load.
AE1	Overload warning 1	There is a possibility that overload alarm 1 or 2 may occur.	Load increased to 85% or more of overload alarm 1 or 2 occurrence level. Cause, checking method Refer to A50, A51.	Refer to A50, A51.



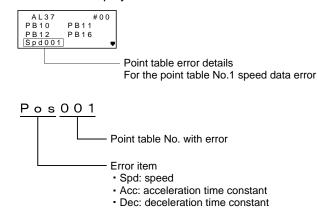
15. INDEXER POSITIONING OPERATION

Display	Name	Definition	Cause	Action
AE3	Absolute position counter warning	Absolute position encoder pulses faulty.	1. Noise entered the encoder.	Take noise suppression measures.
			2. Encoder faulty.	Change the servo motor.
		The multi-revolution counter value of the absolute position encoder exceeded the maximum revolution range.	 The movement amount from the home position exceeded a 32767 rotation or 37268 rotation in succession. 	Make home position setting again.
		The update cycle for writing the multi- revolution counter value of the absolute position encoder to EEPROM is short.	Refer to POINT in section 15.7.	Refer to POINT in section 15.7.
AE6	Servo forced stop warning	EMG is off.	External forced stop was made valid. (EMG was turned off.)	Ensure safety and deactivate forced stop.
AE8	Cooling fan speed reduction warning	The speed of the driver decreased to or below the warning level.	Cooling fan life expiration (Refer to section 2.5.)	Change the cooling fan of the driver.
			The power supply of the cooling fan is broken.	Change the driver.
AE9	Main circuit off warning	Servo-on (SON) was switched on with main circuit power off.		Switch on main circuit power.
AEC	Overload warning 2	Operation, in which a current exceeding the rating flew intensively in any of the U, V and W phases of the servo motor, was repeated.	During a stop, the status in which a current flew intensively in any of the U, V and W phases of the servo motor occurred repeatedly, exceeding the warning level.	 Reduce the positioning frequency at the specific positioning address. Reduce the load. Replace the driver/ servo motor with the one of larger capacity.
AED	Output watt excess warning	The status, in which the output wattage (speed \times torque) of the servo motor exceeded the rated output, continued steadily.	Continuous operation was performed with the output wattage (speed \times torque) of the servo motor exceeding 150% of the rated output.	 Reduce the servo motor speed. Reduce the load.



15.12.5 Point table error

When a point table error occurs, the parameter error (A37) occurs. After the parameter No. of parameter error (A37), the point table error details are displayed.





16. SERVO MOTOR	2
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16.2 Protection from oil and water	
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16.5 Mounting connectors	6
16.2 Protection from oil and water	5 5



16. SERVO MOTOR

16.1 Servo motor with a lock

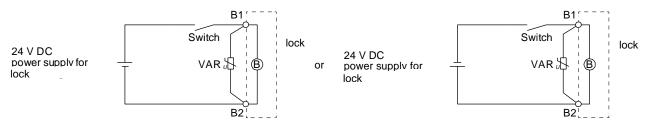
16.1.1 Features

≜ CAUTION	 The lock is provided to prevent a drop at a power failure or servo alarm occurrence during vertical drive or to hold a shaft at a stop. Do not use it for normal braking (including braking at servo-lock). The lock has a time lag. Use the lock so that servo motor control starts after the lock has completely opened. Be sure to check the time lag of the locking with a real machine. Configure a lock circuit so that it is activated also by an external EMG stop switch. While the lock is opened, the motor may be raised to high temperature regardless of driving. The life will be shorten under sudden acceleration/deceleration conditions.
------------------	---

The servo motor with a lock can be used to prevent a drop in vertical lift applications or to ensure double safety at an emergency stop, for example. When operating the servo motor, supply power to the lock to release the lock. Switching power off enables the lock.

(1) Lock power supply

Prepare the following power supply for use with the lock only. The lock terminals (B1 and B2) have no polarity.



The surge absorber (VAR) must be installed between B1 and B2. When you use a diode for a surge absorber, the locking time will be longer.

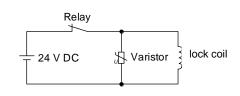
(2) Sound generation

Though the brake lining may rattle during operation, it poses no functional problem. If braking sounds, it may be improved by setting the machine resonance suppression filter in the driver parameters.

(3) Selection of surge absorbers for lock circuit

The following shows an example how to select a varistor with a surge absorber. (a) Selection conditions

Item	Condition
Lock specification	R [Ω]: Resistance (Note) L [H]: Inductance (Note) Vb [V]: Power supply voltage
Desired suppression voltage	Vs [V] or less
Durable surge application time	N times



Note. Refer to section 16.1.2



- (b) Tentative selection and verification of surge absorber
 - 1) Maximum allowable circuit voltage of varistor

Tentatively select a varistor whose maximum allowable voltage is larger than Vb [V].

2) Lock current (lb)

$$Ib = \frac{Vb}{R} [A]$$

3) Energy (E) generated by lock coil

$$\mathsf{E} = \frac{\mathsf{L} \times \mathsf{lb}^2}{2} \, [\mathsf{J}]$$

4) Varistor limit voltage (Vi)

From the energy (E) generated in the lock coil and the varister characteristic diagram, calculate the varistor limit voltage (Vi) when the lock current (Ib) flows into the tentatively selected varistor during opening of the circuit. Please refer to the varistor characteristic diagram to the varistor manufacturer.

The desired suppressed voltage (Vs) is the sum of the 24 VDC \pm 10% used and the other devices (relays etc.) used by the user.

Please confirm the specification of the equipment to be used.

Vi is favorable when the varistor limit voltage (Vi) [V] is smaller than the desired suppressed voltage (Vs) [V].

If Vi is not smaller than Vs, reselect a varistor or improve the withstand voltage of devices. Regarding the characteristics characteristic diagram, specification, selection of the varistor, it is necessary to check with the varistor manufacturer.

5) Surge current width (T)

Given that the varistor absorbs all energies, the surge current width (T) will be as follows.

$$T = \frac{E}{Vi \times Ib} [S]$$

6) Examining surge life of varister

From the varistor characteristic diagram, the guaranteed current value (Ip) in which the number of the surge application life is N at the surge current width (τ). Calculate the guaranteed current value (Ip) ratio to lock current (Ib).

If an enough margin is ensured for Ip/Ib, the number of the surge application life N [time] can be considered as favorable.

(4) Others

A leakage magnetic flux will occur at the shaft end of the servo motor equipped with a lock. Note that chips, screws, etc. are attracted.



16.1.2 Characteristics of servo motor with a lock

 The lock is provided to prevent a drop at a power failure or servo alarm occurrence during vertical drive or to hold a shaft at a stop. Do not use it for normal braking (including braking at servo-lock). Before performing the operation, be sure to confirm that the lock operates properly.
The operation time of the lock differs depending on the power supply circuit you use. Be sure to check the operation delay time with a real machine.

The characteristics (reference value) of the lock provided for the servo motor with a lock are indicated below.

	Serv	o motor		LE-	B	
Item			T6	T7	Т8	Т9
			(100W)	(200W)	(400W)	(750W)
Type (Note 1)			Sp	oring actuated	type safety lo	ck
Rated voltage (Note 4)				24 V E	DC -10%	
Power consumption	[W] :	at 20 °C	6.3	7	.9	10
Coil resistance (Note 6)		[Ω]	91.0	73	3.0	57.0
Inductance (Note 6)		[H]	0.15	0.	18	0.13
Lock static friction torque		[N•m]	0.32	1	.3	2.4
Release delay time (Note 2)		[s]	0.03	0.	03	0.04
Locking delay time (Note 2) [s]	DC off		0.01	0.	02	0.02
Permissible locking work	Per locking	[J]	5.6	2	2	64
T ermissible locking work	Per hour	[J]	56	22	20	640
Lock looseness at servo motor shaft (N	ote 5) [degree	es]	2.5	1	.2	0.9
Lock life (Note 3)	Number of lockings [times]			200	000	
	Work per locking	[J]	5.6	2	2	64
Selection example of surge absorbers to be used	For the suppressed voltage 145 V		TND20V-680KB (135[V])			
(Note 7, 8)	For the suppressed vo 370 V	ltage		TND10V-22	IKB (360[V])	

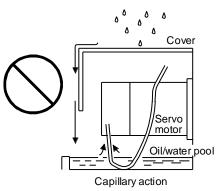
Note 1. There is no manual release mechanism. When it is necessary to hand-turn the servo motor shaft for machine centering, etc., use a separate 24 V DC power supply to release the lock electrically.

- 2. The value for initial on gap at 20 $^{\circ}\text{C}.$
- 3. The lock gap will increase as the brake lining wears, but the gap is not adjustable.
 - The lock life indicated is the number of locking cycles after which adjustment will be required.
- 4. Always prepare a power supply exclusively used for the lock.
- 5. These are design values. These are not guaranteed values.
- 6. These are measured values. These are not guaranteed values.
- 7. Select the lock control relay properly, considering the characteristics of the lock and surge absorber. When you use a diode for a surge absorber, the locking time will be longer.
- 8. Manufactured by Nippon Chemi-Con Corporation.



16.2 Protection from oil and water

(1) Do not use the servo motor with its cable soaked in oil or water.



(2) If oil such as cutting oil drops on the servo motor, the sealant, packing, cable and others may be affected depending on the oil type.

16.3 Cable

The standard motor and encoder cables routed from the servo motor should be fixed to the servo motor to keep them unmovable. Otherwise, the cable may disconnect. In addition, do not modify the connectors, terminals and others at the ends of the cables.

16.4 Rated speed of servo motor

The rated speed of servo motor (LE-T6-□, LE-T7-□, LE-T8-□, LE-T9-□) is 3000[r/min].

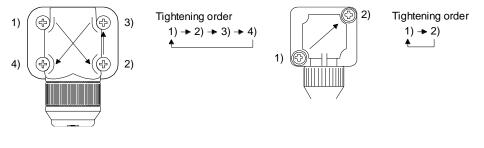


16.5 Mounting connectors

If the connector is not fixed securely, it may come off or may not produce a splash-proof effect during operation.

To achieve the IP rating IP65, pay attention to the following points and install the connectors.

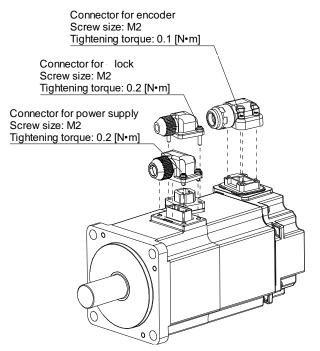
(1) When screwing the connector, hold the connector still and gradually tighten the screws in a crisscross pattern.



Connector for power supply, connector for encoder

Connector for lock

(2) Tighten the screws evenly. Tightening torques are as indicated below.



(3) The servo motor fitting part of each connector is provided with a splash-proof seal (O ring). When mounting a connector, use care to prevent the seal (O ring) from dropping and being pinched. If the seal (O ring) has dropped or is pinched, a splash-proof effect is not produced.



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App. 1 Parameter list

POINT

• For any parameter whose symbol is preceded by *, set the parameter value and switch power off once, then switch it on again to make that parameter setting valid.

Basic setting parameters (PA □ □)No.SymbolNamePA01*STYControl modePA02*REGRegenerative optionPA03*ABSAbsolute position detection systemPA04*AOP1Function selection A-1PA05*FTYFeeding function selectionPA06*CMXElectronic gear numeratorPA07*CDVElectronic gear denominatorPA08ATUAuto tuningPA09RSPAuto tuning responsePA10INPIn-position rangePA11TLPForward rotation torque limitPA12TLNReverse rotation torque limitPA13For manufacturer settingPA14*POLRotation direction selectionPA15*ENREncoder output pulsesPA16For manufacturer settingPA18*BLKParameter write inhibit					
PA01*STYControl modePA02*REGRegenerative optionPA03*ABSAbsolute position detection systemPA04*AOP1Function selection A-1PA05*FTYFeeding function selectionPA06*CMXElectronic gear numeratorPA07*CDVElectronic gear denominatorPA08ATUAuto tuningPA09RSPAuto tuning responsePA10INPIn-position rangePA11TLPForward rotation torque limitPA12TLNReverse rotation torque limitPA13For manufacturer settingPA14*POLRotation direction selectionPA15*ENREncoder output pulsesPA16toFor manufacturer settingPA18For manufacturer setting	Basic setting parameters (PA \Box \Box)				
PA02*REGRegenerative optionPA03*ABSAbsolute position detection systemPA04*AOP1Function selection A-1PA05*FTYFeeding function selectionPA06*CMXElectronic gear numeratorPA07*CDVElectronic gear denominatorPA08ATUAuto tuningPA09RSPAuto tuning responsePA10INPIn-position rangePA11TLPForward rotation torque limitPA12TLNReverse rotation torque limitPA13For manufacturer settingPA14*POLRotation direction selectionPA15*ENREncoder output pulsesPA16For manufacturer settingPA18For manufacturer setting	No.	Symbol	Name		
PA03*ABSAbsolute position detection systemPA04*AOP1Function selection A-1PA05*FTYFeeding function selectionPA06*CMXElectronic gear numeratorPA07*CDVElectronic gear denominatorPA08ATUAuto tuningPA09RSPAuto tuning responsePA10INPIn-position rangePA11TLPForward rotation torque limitPA12TLNReverse rotation torque limitPA13For manufacturer settingPA14*POLRotation direction selectionPA15*ENREncoder output pulsesPA16For manufacturer settingPA18For manufacturer setting	PA01	*STY	Control mode		
PA04*AOP1Function selection A-1PA05*FTYFeeding function selectionPA06*CMXElectronic gear numeratorPA07*CDVElectronic gear denominatorPA08ATUAuto tuningPA09RSPAuto tuning responsePA10INPIn-position rangePA11TLPForward rotation torque limitPA12TLNReverse rotation torque limitPA13For manufacturer settingPA14*POLRotation direction selectionPA15*ENREncoder output pulsesPA16toFor manufacturer settingPA18PA18For manufacturer setting	PA02	*REG	Regenerative option		
PA05*FTYFeeding function selectionPA06*CMXElectronic gear numeratorPA07*CDVElectronic gear denominatorPA08ATUAuto tuningPA09RSPAuto tuning responsePA10INPIn-position rangePA11TLPForward rotation torque limitPA12TLNReverse rotation torque limitPA13For manufacturer settingPA14*POLRotation direction selectionPA15*ENREncoder output pulsesPA16toFor manufacturer settingPA18For manufacturer setting	PA03	*ABS	Absolute position detection system		
PA06 *CMX Electronic gear numerator PA07 *CDV Electronic gear denominator PA08 ATU Auto tuning PA09 RSP Auto tuning response PA10 INP In-position range PA11 TLP Forward rotation torque limit PA12 TLN Reverse rotation torque limit PA13 For manufacturer setting PA14 *POL Rotation direction selection PA16 to For manufacturer setting PA18 For manufacturer setting	PA04	*AOP1	Function selection A-1		
PA07*CDVElectronic gear denominatorPA08ATUAuto tuningPA09RSPAuto tuning responsePA10INPIn-position rangePA11TLPForward rotation torque limitPA12TLNReverse rotation torque limitPA13For manufacturer settingPA14*POLRotation direction selectionPA15*ENREncoder output pulsesPA16toFor manufacturer settingPA18For manufacturer setting	PA05	*FTY	Feeding function selection		
PA08ATUAuto tuningPA09RSPAuto tuning responsePA10INPIn-position rangePA11TLPForward rotation torque limitPA12TLNReverse rotation torque limitPA13For manufacturer settingPA14*POLRotation direction selectionPA15*ENREncoder output pulsesPA16For manufacturer settingPA18For manufacturer setting	PA06	*CMX	Electronic gear numerator		
PA09 RSP Auto tuning response PA10 INP In-position range PA11 TLP Forward rotation torque limit PA12 TLN Reverse rotation torque limit PA13 For manufacturer setting PA14 *POL Rotation direction selection PA15 *ENR Encoder output pulses PA16 to For manufacturer setting PA18 For manufacturer setting	PA07	*CDV	Electronic gear denominator		
PA10 INP In-position range PA11 TLP Forward rotation torque limit PA12 TLN Reverse rotation torque limit PA13 For manufacturer setting PA14 *POL Rotation direction selection PA15 *ENR Encoder output pulses PA16 to For manufacturer setting PA18 For manufacturer setting	PA08	ATU	Auto tuning		
PA11 TLP Forward rotation torque limit PA12 TLN Reverse rotation torque limit PA13 For manufacturer setting PA14 *POL Rotation direction selection PA15 *ENR Encoder output pulses PA16 to For manufacturer setting PA18 For manufacturer setting	PA09	RSP	Auto tuning response		
PA12 TLN Reverse rotation torque limit PA13 For manufacturer setting PA14 *POL Rotation direction selection PA15 *ENR Encoder output pulses PA16 to For manufacturer setting PA18 For manufacturer setting	PA10	INP	In-position range		
PA13 For manufacturer setting PA14 *POL Rotation direction selection PA15 *ENR Encoder output pulses PA16 to For manufacturer setting PA18 For manufacturer setting	PA11	TLP	Forward rotation torque limit		
PA14 *POL Rotation direction selection PA15 *ENR Encoder output pulses PA16 to For manufacturer setting PA18 For manufacturer setting	PA12	TLN	Reverse rotation torque limit		
PA15 *ENR Encoder output pulses PA16 to For manufacturer setting PA18	PA13	/	For manufacturer setting		
PA16 to PA18 For manufacturer setting	PA14	*POL	Rotation direction selection		
to For manufacturer setting PA18	PA15	*ENR	Encoder output pulses		
PA18	PA16				
	to		For manufacturer setting		
PA19 *BLK Parameter write inhibit	PA18				
	PA19	*BLK	Parameter write inhibit		

	(Gain/filter parameters (PB □ □)						
No.	Symbol	Name						
PB01	FILT	Adaptive tuning mode (Adaptive filter II)						
PB02	VRFT	Vibration suppression control tuning mode (Advanced vibration suppression control)						
PB03		For manufacturer setting						
PB04	FFC	Feed forward gain						
PB05	<u> </u>	For manufacturer setting						
		Ratio of load inertia moment to servo motor						
PB06	GD2	inertia moment						
PB07	PG1	Model loop gain						
PB08	PG2	Position loop gain						
PB09	VG2	Speed loop gain						
PB10	VIC	Speed integral compensation						
PB11	VDC	Speed differential compensation						
PB12		For manufacturer setting						
PB13	NH1	Machine resonance suppression filter 1						
PB14	NHQ1	Notch form selection 1						
PB15	NH2	Machine resonance suppression filter 2						
PB16	NHQ2 Notch form selection 2							
PB17		Automatic setting parameter						
PB18	LPF	Low-pass filter						
PB19	VRF1	Vibration suppression control vibration frequency setting						
PB20	VRF2	Vibration suppression control resonance frequency setting						
PB21	$\overline{}$							
PB22	\sim	For manufacturer setting						
PB23	VFBF Low-pass filter selection							
PB24	*MVS Slight vibration suppression control selection							
PB25		For manufacturer setting						
PB26	*CDP	Gain changing selection						
PB27	CDL	Gain changing condition						
PB28	CDT	Gain changing time constant						
PB29	GD2B	Gain changing ratio of load inertia moment to servo motor inertia moment						
PB30	PG2B	Gain changing position loop gain						
PB31	VG2B	Gain changing speed loop gain						
PB32	VICB	Gain changing speed integral compensation						
PB33	VRF1B	Gain changing vibration suppression control vibration frequency setting						
PB34	VRF2B	Gain changing vibration suppression control resonance frequency setting						
PB35								
to		For manufacturer setting						
PB45		,						

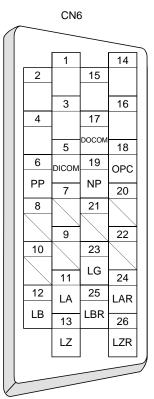


	Extensio	n setting parameters (PC □ □)			
No. Symbol Name					
PC01	Symbol				
	*71	For manufacturer setting			
PC02	*ZTY	Home position return type			
PC03	*ZDIR	Home position return direction			
PC04	ZRF	Home position return speed			
PC05	CRF	Creep speed			
PC06	ZST	Home position shift distance			
PC07	*ZPS	Home position return position data			
PC08	DCT	Moving distance after proximity dog			
PC09	ZTM	Stopper type home position return stopper time			
PC10	ZTT	Stopper type home position return torque limit value			
PC11	CRP	Rough match output range			
PC12	JOG	Jog speed			
PC13	*STC	S-pattern acceleration/deceleration			
PCIS	510	time constant			
PC14	*BKC	Backlash compensation			
PC15	/	For manufacturer setting			
PC16	MBR	Electromagnetic brake sequence			
PC17	ZSP	Zero speed			
PC18	*BPS	Alarm history clear			
PC19	*ENRS	Encoder output pulse selection			
PC20	*SNO	Station number setting			
PC21	*SOP	RS-422 communication function selection			
PC22	*COP1	Function selection C-1			
PC23	/	For manufacturer setting			
PC24	*COP3	Function selection C-3			
PC25		For manufacturer setting			
PC26	*COP5	Function selection C-5			
PC27	\sim	For manufacturer setting			
PC28	*COP7	Function selection C-7			
PC29	<u> </u>	For manufacturer setting			
		Remote register-based position/speed			
PC30	*DSS	specifying system selection			
PC31	LMPL				
PC32	LMPH	Software limit +			
PC33	LMNL				
PC34	LMNH	Software limit -			
PC35	TL2	Internal torque limit 2			
PC36	\sim	For manufacturer setting			
PC37	*LPPL				
PC38	*LPPH	Position range output address +			
PC39	*LNPL				
PC40	*LNPH	Position range output address —			
PC41					
to		For manufacturer setting			
PC50		For manufacturer setting			
FU3U					

	I	/O setting parameters (PD □ □)						
No.	Symbol	Name						
PD01	*DIA1	Input signal automatic ON selection 1						
PD02	/	For manufacturer setting						
PD03	*DIA3	Input signal automatic ON selection 3						
PD04	*DIA4	Input signal automatic ON selection 4						
PD05	/	For manufacturer setting						
PD06	*DI2	Input signal device selection 2 (CN6-2)						
PD07	*DI3	Input signal device selection 3 (CN6-3)						
PD08	*DI4	Input signal device selection 4 (CN6-4)						
PD09	*DO1	Input signal device selection 1 (CN6-14)						
PD10	*DO2	Input signal device selection 2 (CN6-15)						
PD11	*DO3	Input signal device selection 3 (CN6-16)						
PD12	DIN1	External DI function selection 1						
PD13		For manufacturer setting						
PD14	DIN3	External DI function selection 3						
PD15	/	For manufacturer setting						
PD16	*DIAB	Input polarity selection						
PD17		For manufacturer setting						
PD18		Tor manufacturer setting						
PD19	*DIF	Response level setting						
PD20	*DOP1	Function selection D-1						
PD21	/	For manufacturer setting						
PD22	*DOP3	Function selection D-2						
PD23	/	For manufacturer setting						
PD24	*DOP5	Function selection D-5						
PD25								
to		For manufacturer setting						
PD30								



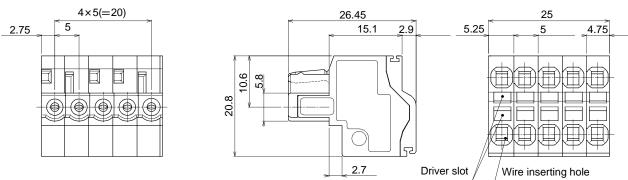
App. 2 Signal layout recording paper





App. 3 Twin type connector: outline drawing for 721-2105/026-000(WAGO)

[Unit: mm]





App. 4 Parameter list

POINT

• For any parameter whose symbol is preceded by *, set the parameter value and switch power off once, then switch it on again to make that parameter setting valid.

Basic setting parameters (PA □ □)							
No.	Symbol	Name					
PA01	*STY	Control mode					
PA02	*REG	Regenerative option					
PA03	*ABS	Absolute position detection system					
PA04		Not used in indexer positioning operation.					
PA05							
PA06	*CMX	Number of gears on machine-side					
PA07	*CDV	Number of gears on servo motor-side					
PA08	ATU	Auto tuning					
PA09	RSP	Auto tuning response					
PA10	INP	In-position range					
PA11	TLP	Forward rotation torque limit					
PA12	TLN	Reverse rotation torque limit					
PA13	/	For manufacturer setting					
PA14	*POL	Rotation direction selection					
PA15	*ENR	Encoder output pulses					
PA16		For manufacturer setting					
to							
PA18							
PA19	*BLK	Parameter write inhibit					

		Gain/filter parameters (PB □ □)						
No.	Symbol	Name						
PB01	FILT	Adaptive tuning mode (Adaptive filter II)						
		Vibration suppression control tuning mode						
PB02	VRFT	(Advanced vibration suppression control)						
PB03	/	For manufacturer setting						
PB04	FFC	Feed forward gain						
PB05	/	For manufacturer setting						
0000	0.00	Ratio of load inertia moment to servo motor						
PB06	GD2	inertia moment						
PB07	PG1	Model loop gain						
PB08	PG2	Position loop gain						
PB09	VG2	Speed loop gain						
PB10	VIC	Speed integral compensation						
PB11	VDC	Speed differential compensation						
PB12	/	For manufacturer setting						
PB13	NH1	Machine resonance suppression filter 1						
PB14	NHQ1	Notch form selection 1						
PB15	NH2	Machine resonance suppression filter 2						
PB16	NHQ2	Notch form selection 2						
PB17	/	Automatic setting parameter						
PB18	LPF	Low-pass filter						
PB19	VRF1	Vibration suppression control vibration						
1 013		frequency setting						
PB20	VRF2	Vibration suppression control resonance						
-		frequency setting						
PB21		For manufacturer setting						
PB22		Law and Chan a last an						
PB23	VFBF	Low-pass filter selection						
PB24	*MVS	Slight vibration suppression control selection						
PB25		For manufacturer setting						
PB26	*CDP	Gain changing selection						
PB27	CDL	Gain changing condition						
PB28	CDT	Gain changing time constant						
PB29	GD2B	Gain changing ratio of load inertia moment to						
DDaa	DOOD	servo motor inertia moment						
PB30	PG2B VG2B	Gain changing position loop gain						
PB31		Gain changing speed loop gain						
PB32	VICB	Gain changing speed integral compensation Gain changing vibration suppression control						
PB33	VRF1B	vibration frequency setting						
		Gain changing vibration suppression control						
PB34	VRF2B	resonance frequency setting						
PB35	\searrow	For manufacturer setting						
to								
PB45								



	Eutonoio	
N1.		n setting parameters (PC)
No.	Symbol	Name
PC01		For manufacturer setting
PC02	*ZTY	Home position return type
PC03	*ZDIR	Home position return direction
PC04	ZRF	Home position return speed
PC05	CRF	Creep speed
PC06	ZST	Home position shift distance
PC07		Not used in indexer positioning
PC08		operation.
PC09		
PC10		
PC11	CRP	Rough match output range
PC12	JOG	Jog speed
PC13		Not used in indexer positioning
		operation.
PC14	*BKC	Backlash compensation
PC15		For manufacturer setting
PC16	MBR	Electromagnetic brake sequence
FUID	IVIDR	output
D017		Not used in indexer positioning
PC17		operation.
PC18	*BPS	Alarm history clear
PC19	*ENRS	Encoder output pulse selection
PC20	*SNO	Station number setting
F 620	3110	RS-422 communication function
PC21	*SOP	
		selection
PC22	*COP1	Function selection C-1
PC23		For manufacturer setting
PC24	\searrow	Not used in indexer positioning
1 024		operation.
PC25		For manufacturer setting
PC26	*COP5	Function selection C-5
PC27	\backslash	For manufacturer setting
PC28	*COP7	Function selection C-7
PC29	<u> </u>	For manufacturer setting
1 023		Remote register-based position/speed
PC30	*DSS	
DC24		specifying system selection
PC31		Not used in indexer positioning
PC32		operation.
PC33		
PC34		
PC35	TL2	Internal torque limit 2
PC36		For manufacturer setting
PC37		Not used in indexer positioning
PC38		operation.
PC39		
PC40		
PC41	$ \land $	For manufacturer setting
		. c. manaratation ootting
to		
PC44		
PC45	*COP9	Function selection C-9
PC46	*STN	Indexer positioning operation number
. 0.40	0.114	of stations/rotation
PC47	PSST	Indexer positioning operation station
1 047	1 001	home position shift distance
PC48	\sim	For manufacturer setting
to		
PC50		
	,	

		/O setting parameters (PD □ □)
No.	Symbol	Name
PD01	*DIA1	Input signal automatic ON selection 1
PD02		For manufacturer setting
PD03		Not used in indexer positioning operation.
PD04		
PD05		For manufacturer setting
PD06	\backslash	Not used in indexer positioning operation.
PD07	\backslash	
PD08	\backslash	
PD09		
PD10	\setminus	
PD11	\setminus	
PD12	\setminus	
PD13	/	For manufacturer setting
PD14	/	Not used in indexer positioning operation.
PD15	/	For manufacturer setting
PD16	*DIAB	Input polarity selection
PD17		For monufacturar actting
PD18		For manufacturer setting
PD19	*DIF	Response level setting
PD20	*DOP1	Function selection D-1
PD21	/	For manufacturer setting
PD22	/	Not used in indexer positioning operation.
PD23	/	For manufacturer setting
PD24	*DOP5	Function selection D-5
PD25		For manufacturer setting
PD26	TLT	Indexer positioning operation torque limit delay
		time
PD27	\backslash	For manufacturer setting
to		
PD30		



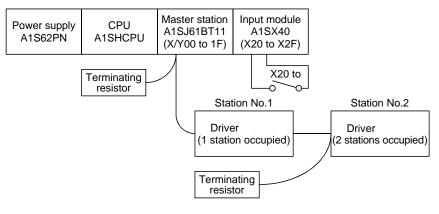
App. 5 Program example with programmable PLC (A series) (point table positioning operation)

App. 5.1 Function-by-function programming examples

This section explains specific programming examples for servo operation, monitor, parameter read and write, and others on the basis of the equipment makeup shown in appendix 5.1.1.

App. 5.1.1 System configuration example

As shown below, the CC-Link system master - local unit is loaded to run two drivers (1 station occupied / 2 stations occupied).



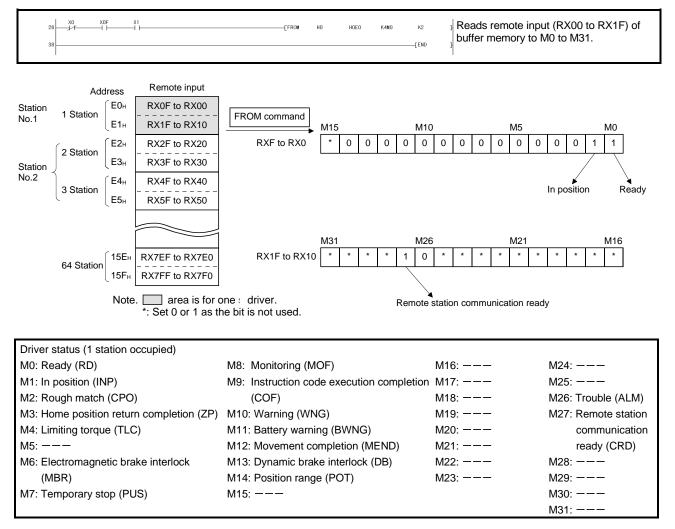
Programmable PLC (A series)



App. 5.1.2 Reading the driver status

Read the driver status from the master station buffer memory. The driver status is always stored in the remote input RX (addresses E0H to 15FH) Read the driver status of station 1 to M0 to M31.

Specific programming examples are explained based on the equipment configuration shown in appendix 5.1.1.



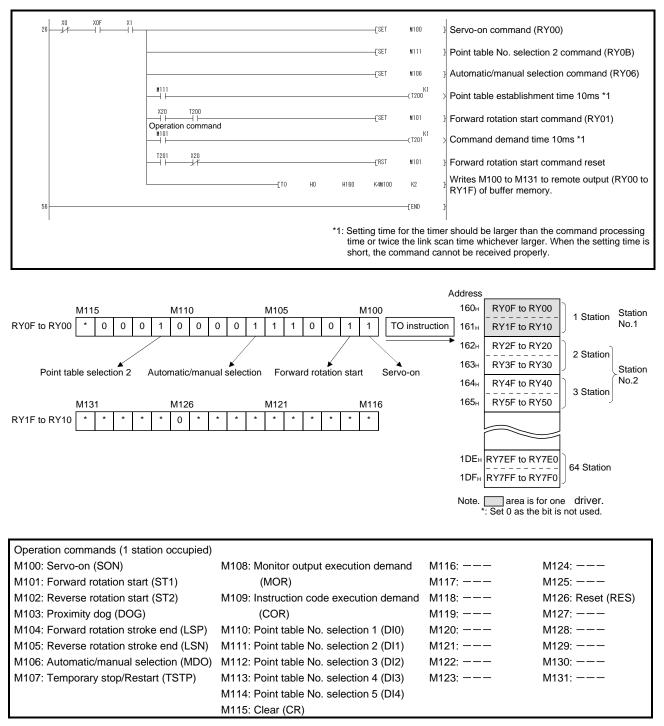


App. 5.1.3 Writing the operation commands

To operate the driver, write the operation commands to the remote output RY (addresses 160_H to 1DF_H). Perform positioning operation of point table No.2 for the driver of station 2.

Start the operation by turning on X20.

Specific programming examples are explained based on the equipment configuration shown in appendix 5.1.1.



App. 5.1.4 Reading the data

Read various data of the driver.

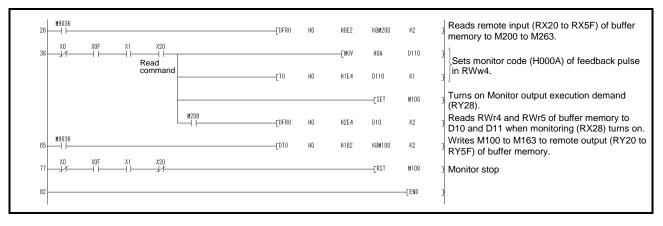
Specific programming examples are explained based on the equipment configuration shown in appendix 5.1.1.

(1) Reading the monitor value

Read the (feedback pulse value) of the driver of station 2 to D1.

Data No.	Description				
H000A	Cumulative feedback pulse data (hexadecimal)				

Read the cumulative feedback pulse monitor by turning on X20.





(2) Reading the parameter

Read parameter No.PA04 "Function selection A-1" of the driver of station 2 to D1.

Data No.	Description			
H8200	Parameter group selection			
H2024	Parameter No.PA04 setting (hexadecimal)			

Read the parameter No.PA04 by turning on X20.

The respond code at instruction code execution is set to D9.

16 17 19 19 19 19 19 19 19 19 19 19 19 19 19	XOF X1	Read command	[10	НО	——Емол	—_[PLS [SET H8200 Н0	M302 M303 D110	
13	1109 ₩201 ↓/t ↓t	9	£10	НО		H8200		
15 - 1 1 - 3	1109 W201 17 17	9	[10	НО			D110	
			[10	но	EWOA	110		
			[10	HO		HU	D111	Writes parameter group No. write (H8200) to RWw6 and parameter group PA (H0000) to RWw7.
					H1E6	D110	K1	3
						[SET	W109	[]] Turns on instruction code execution demand (RY29).
						[RST	M303	3
						[SET	M304	3
	1109 M201 ⊣ ⊨−−−−− ↓ ⊨					ERST	W109	Turns off instruction code execution demand (RY29) when instruction code execution completion (RX29) turns on.
	1109 M201 1/1 1/1				Ewon	H204	D110	³ Writes parameter No.PA04 read (H0204) to
			[10	HO	H1E6	D110	K1	RWw6.
						[SET	M109	¹ Turns on instruction code execution demand (RY29).
						[RST	M304	3
						[SET	N305	3
	1109 M20! ⊣ ├────┤ ├		[FROM	HO	H2E7	D1	K1	Reads RWr7 and RWr6 of buffer memory to D1 and D9 when instruction code execution
			FROM	HO	H2E6	D9	K1	} ∫ completion (RX29) turns on.
						[RST	W109	Turns off instruction code execution demand (RY29).
						[RST	M305	Writes M100 to M163 to remote output (RY20 to RY5F) of buffer memory.
8 M9036			[DTO	HO	H162	K8M100	K2	ŀ
0							-END	<u>э</u>

(3) Reading the alarm definition

Read the alarm definition of the driver of station 2 to D1.

Data No.	Description				
H0010	Occurring alarm/warning No. (hexadecimal)				

Read current alarms by turning on X20.

The respond code at instruction code execution is set to D9.

26	M9036				(DFRO	HO	H0E2	K8M200	K2 _	Reads remote input (RX20 to RX5F) of buffer memory to M200 to M263.
36	/r	XOF 		ad command					[PLS	M302	
43	M302								[SET	M303	ł
45	M303	₩109 ↓/	M209					Ewon	H10	D110	
					[TO	HO	H1E6	D110	К1	Writes current alarm read (H0010) to RWw6.
									[RST	M303	
									[SET	N109	Turns on instruction code execution demand (RY29).
									CSET	M304	
65 -	M304	M109 -	M209		(FROM	HO	H2E7	D1	K1	Reads RWr7 and RWr6 of buffer memory to
					[FROM	HO	H2E6	D9	K1	completion (RX29) turns on.
									-ERST	M109	Turns off instruction code execution demand (RY29).
									-ERST	N304	
88	M9036				[DTO	HO	H162	K8M100	K2	Writes M100 to M163 to remote output (RY20 to RY5F) of buffer memory.
100										-[END	



App. 5.1.5 Writing the data

This section explains the programs for writing various data to the driver. Specific programming examples are explained based on the equipment configuration shown in appendix 5.1.1.

(1) Writing the servo motor speed data of point table

Change the servo motor speed data in the point table No.1 of the driver of station 2 to "100".

The following shows a program example for writing data to the driver when two stations are occupied. Writing is disabled for the driver when one station is occupied.

Code No.	Description
H8D01	Write of servo motor speed data of point table No.1 (hexadecimal)

Set data	Description
K100	Servo motor speed data of point table No.1
K I UU	(decimal)

Write the data to the servo motor speed data of point table No.1 by turning on X20. The respond code at instruction code execution is set to D2.

26	M9036					[DFRO	HO	H0E2	K8M200	K2	Reads remote input (RX20 to RX5F) of buffer memory to M200 to M263.
36	X0 ↓∕f	XOF	×1 — I —	X20					[PLS	M302	3
44-	M302			Write comman	In position d				[SET	M303	3
46	M303	W109	₩209 //*					EMOA	H8D01	D110	
								EWOA	K100	D111	Writes speed data (H8D01) of point table No.1 to RWw6, and speed data (K100) to RWw7.
						[10	HO	H1E6	D110	K2	₽]
									ESET	M109	Turns on instruction code execution demand (RY29).
									[RST	M303	3
									ESET	M304	3
71	M304	M109	₩209			[FROM	HO	H2E6	D2	К1	Reads respond code (RWr6) to D2 when instruction code execution completion (RX29) turns on.
									ERST	M109	Turns off instruction code execution demand (RY29).
									ERST	M304	3
85 -	M9036					EDTO	HO	H162	K8M100	K2	Writes M100 to M163 to remote output (RY20 to RY5F) of buffer memory.
97 -										-END]

(2) Writing the parameter

The following shows a program example when two stations are occupied. Change parameter No.PC12 (JOG speed) of the driver of station 2 to "100". The parameter group PC is specified as follows.

Code No.	Description				
8200h	Parameter group selection				

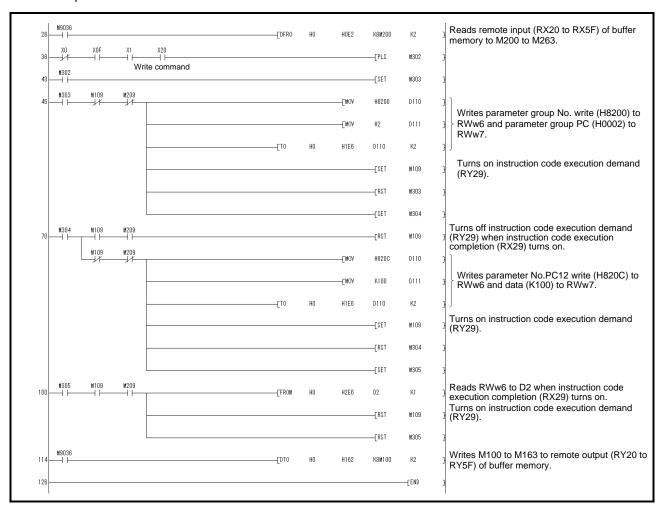
Set data	Description
H0002	Set data (hexadecimal)

The parameter No.12 is changed to "100" as follows.

Code No.	Description
H820C	Parameter No.PC12 write (hexadecimal)

Set data	Description
K100	Set data (decimal)

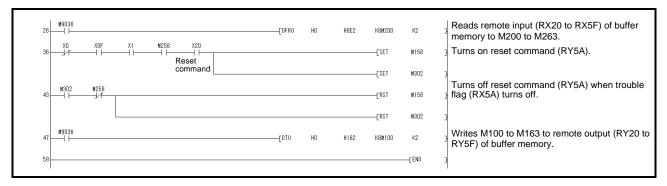
Write the data to the parameter No.PC12 by turning on X20. The respond code at instruction code execution is set to D2.





(3) Driver alarm resetting program examples

(a) Deactivate the alarm of the driver of station 2 by issuing a command from the programmable PLC. Reset the driver on the occurrence of a servo alarm by turning on X20.



(b) Deactivate the alarm of the driver of station 2 using the instruction code.

Code No.	Description
H8010	Alarm reset command (hexadecimal)

Set data	Description
H1EA5	Execution data (hexadecimal)

Reset the driver by turning on X20.

The respond code at instruction code execution is set to D2.

26	M9036				[DFRO	HO	HOE2	K8M200	K2	Reads remote input (RX20 to RX5F) of buffer memory to M200 to M263.
36	X0	XOF	 Res	x20 et command				[PLS	M302	3
43 -	M302							ESET	M303	3
45	M303	M109	₩209 ↓/				ENOA	H8010	D110	۲ ۲
							ENOA	H1EA5	D111	Writes alarm reset command (H8010) to RWw6 and execution data (H1EA5) to RWw7.
					[T0	HO	H1E6	D110	K2	۶) (ا
								[SET	M109	Turns on instruction code execution demand (RY29).
								ERST	M303	3
								ESET	M304	3
70 -	M304	M109	₩209 ——↓		ELECT	HO	H2E6	D2	К1	Reads respond code (RWr6) to D2 when instruction code execution completion (RX29) turns on.
								ERST	M109	Turns off instruction code execution demand (RY29).
								ERST	M304	3
84-	M9036				EDTO	HO	H162	K8W100	K2	Writes M100 to M163 to remote output (RY20 to RY5F) of buffer memory.
96 -									-END	3
1										I



App. 5.1.6 Operation

This section explains the operation programs of the driver.

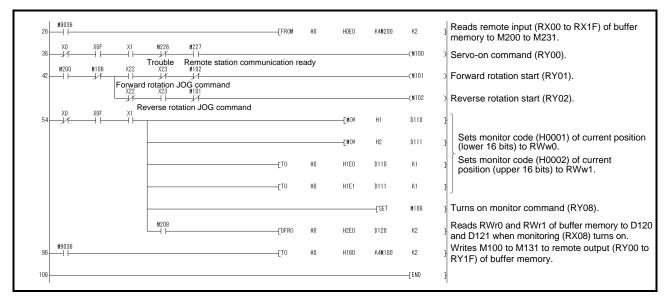
Specific programming examples are explained based on the equipment configuration shown in appendix 5.1.1.

(1) JOG operation

Perform JOG operation of the driver of station 1 and read the "current position" data.

Code No.	Description
H0001	Lower 16-bit data of current position (hexadecimal)
H0002	Upper 16-bit data of current position (hexadecimal)

Start the forward rotation JOG operation by turning on X22. Start the reverse rotation JOG operation by turning on X23.





(2) Remote register-based position data/speed data setting

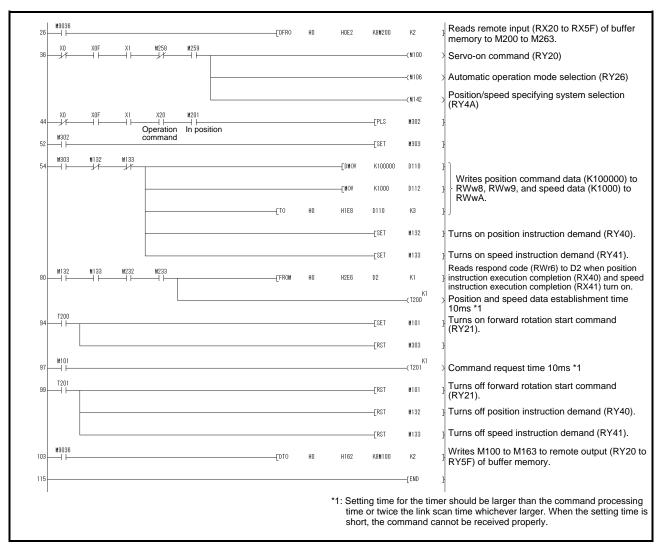
The following program example is only applicable when two stations are occupied.

Operate the driver of station 2 after specifying the position data as "100000" and the speed data as "1000" in the direct specification mode.

Preset "DDD2" in parameter No.PC30.

Set data	Description
K100000	Position command data (decimal)
K1000	Speed command data (decimal)

Execute positioning operation with position and speed settings specified in the remote register by turning on X20.





(3) Remote register-based point table No. setting (incremental value command system)

The following program example is only applicable when two stations are occupied.

Operate the driver of station 2 with incremental values after specifying the point table No.5 in the direct specification mode.

Preset "DDD" in parameter No.PA01 and "DDD" in parameter No.PC30.

Set data	Description
K5	Point table No. (decimal)

Execute positioning operation to the point table No.5 by turning on X20.

26 M9036			[DFR0	НО	HOE2	K8M200	K2	Reads remote input (RX20 to RX5F) of buffer memory to M200 to M263.
	X1 M258	M259					(M100)	Servo-on command (RY20)
							—(M106)	Automatic operation mode selection (RY26)
							——(M142)	Position/speed specifying system selection (RY4A)
							(M143)	Incremental value selection (RY4B)
		^{₩201} ⊣				[PLS	M302	J
53 N302	command					[SET	M303	3
55 N303 N132					-E NOA	K5	D110	J
			E10	HO	H1E8	D110	К1	Writes point table No.5 (K5) to RWw8.
						[SET	M132	Turns on position instruction demand (RY40).
72 M132 M232			EFROM	HO	H2E6	D2	K1	Reads respond code (RWr6) to D2 when position instruction execution completion (RX40) turns on.
							(T200 ^{K1})	Point table establishment time 10ms *1
84 T200						ESE1	W101	Turns on forward rotation start command (RY21).
						ERST	M303	3
87 M101							(T201 K1	Command request time 10ms *1
89 T201						[RST	H 101	Turns off forward rotation start command (RY21).
						ERST	₩132	Turns off position instruction demand (RY40).
92 M9036			-EDIO	HO	H162	K8M100	K2	Writes M100 to M163 to remote output (RY20 to RY5F) of buffer memory.
104							END	3
1				,	time	or twice	the link sc	er should be larger than the command processing an time whichever larger. When the setting time is nnot be received properly.

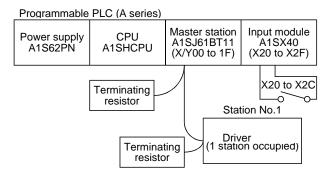


App. 5.2 Continuous operation program example

This section shows a program example which includes a series of communication operations from a servo start. The program will be described on the basis of the equipment makeup shown in appendix 5.2.1, appendix 5.2.3.

App. 5.2.1 System configuration example when 1 station is occupied

As shown below, the CC-Link system master • local unit is loaded to run one driver (1 station occupied).



Input signal assignment

Input signal	Signal name	General operation when the input is on
X20	Reset command	Resets the driver on an occurrence of a servo alarm.
X21	Servo-on command	Turns on the servo motor. (Servo-on status)
X22	Forward rotation JOG command	Executes a forward JOG operation in the manual operation mode.
X23	Reverse rotation JOG command	Executes a reverse JOG operation in the manual operation mode.
X24	Automatic/manual selection	OFF: Manual operation mode ON: Automatic operation mode
X25	Home position return command	Executes a dog type home position return when home position return is incomplete in the automatic operation mode.
X26	Proximity dog command	OFF: Proximity dog is on. (Note) ON: Proximity dog is off.
X27	Positioning start command	Executes a positioning operation to the point table number specified by X28 to X2C when home position return is incomplete in the automatic operation mode.
X28	No. selection 1	Specifies the position for the point table No. selection 1
X29	No. selection 2	Specifies the position for the point table No. selection 2
X2A	No. selection 3	Specifies the position for the point table No. selection 3
X2B	No. selection 4	Specifies the position for the point table No. selection 4
X2C	No. selection 5	Specifies the position for the point table No. selection 5

Note. This is when the parameter No.PD16 is set to "DD0 (initial value)" (detects the dog at off).



App. 5.2.2 Program example when 1 station is occupied

POINT
 To execute a dog type home position return with the CC-Link communication functions, set "□0□□" in parameter No.PD14 and use Proximity dog (DOG) with the remote input (RY03) in this example.

1

Operate the driver of station 1 in the positioning mode and read the "current position" data.

Specific programming examples are explained based on the equipment configuration shown in appendix 5.2.1.

Operation: Alarm reset, dog type home position return, JOG operation, automatic operation under point table command

Code No.	Description
H0001	Lower 16-bit data of current position (hexadecimal)
H0002	Upper 16-bit data of current position (hexadecimal)

			—Емс	NO	MO]	Check the status of CC-Link.
NO T MO						
34 H9036	[FROM	HO	HOEO	K4M200	K2]	Reads remote input (RX00 to RX1F) of buffer memory to M200 to M231.
44 1 1 1 1 1 1 1 1 1 1 1 1 1 1 1 1 1 1			-E NOA	H10	D10]	Writes current alarm read (H0010) to RWw2 at
-	60	HO	H1E2	D10	кі]	trouble (RX1A) occurrence.
-				[SET	M109]	Turns on instruction code execution demand (RY09).
				[SET	M301]	
63 M301 M109 M209	EROM	HO	H2E3	D11	К1]	Reads RWr3 and RWr2 of buffer memory to
-	[FROM	HO	H2E2	D12	K1]	D11 and D12 when instruction code execution completion (RX09) turns on.
-				CRST	M109]	Turns off instruction code execution demand (RY09).
				-ERST	M301]	
86 K226 X20 Reset command					—(M126)	Alarm reset command (RY1A)
89 Kerver on command					-(M100)	Servo-on command (RY00)
93 X24 M201 M202				[SET	M106]	Automatic operation mode selection (RY06)
Automatic/manual selection X24 W201 W202 97				[RST	M106]	Manual operation mode selection (RY06)
Automatic/manual selection				[PLS	M302]	Home position return request
Home position return Home	e position return completion				M303 T	
M303					-(T200)	Point table establishment time 10ms *1
				[SET	M5]	Forward rotation start request
				[RST	M303]	· · · · · · · · · · · · · · · · · · ·
M5					-(T201)	Command request time 10ms *1
T201				[RST	M5]	Forward rotation start request reset
X26					-(M103)	Proximity dog command (RY03)
Proximity dog command					,	

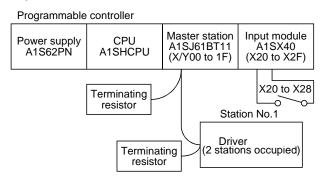


						1
20 106 X22 X23 N4 Forward rotation JOG comma	nd				—(M3	Forward rotation start request
Positioning start command Reverse rotation JC					—(M4	Reverse rotation start request
32 X27 M106 M201 M202 M203				[PLS	M304	Positioning start command
In Rough Home pos M304 position match return com	ipletion			[SET	M305	3
M305					K1 (T203	Point table establishment time 10ms *1
1203					M6	Forward rotation start request
					M305	· · · · · · · · · · · · · · · · · · ·
MG				[N01	K1	Command request time 10ms *1
T202					(T202	
X28 M303				[RST	M6	Forward rotation start request reset
No. selection 1					-(M110	Point table No. selection 1 (RY0A)
No. selection 2					(M111	Point table No. selection 2 (RY0B)
No. selection 3					—(M112	Point table No. selection 3 (RY0C)
X2B #303 No. selection 4					—(M113	Point table No. selection 4 (RY0D)
X2C H303					(M114	Point table No. selection 5 (RY0E)
					(M101	Forward rotation start (RY01)
M5						
M6						
M4					(M102	Poweree retation start (PV02)
N227						Reverse rotation start (RY02)
			——Emoa	H1	D110	Sets monitor code (H0001) of current position
			ENOA	H2	D111	(lower 16 bits) in RWw0.
	[T0	HO	H1EO	D110	K1	Sets monitor code (H0002) of current position (upper 16 bits) in RWw1.
	[10	HO	HIEI	D111	K1	ا ٦
				[SET	M108	Turns on monitor output execution demand (RY08).
M208	[FROM	HO	H2E0	D120	K2	Reads RWr0 and RWr1 of buffer memory to D120 and D121 when monitoring (RX08) turns on.
M9036	ET0	HO	H160	K4M100	K2	Writes M100 to M131 to remote output (RY00 to
				[MCR	NO	RY2F) of buffer memory.
5						1
					[
						er should be larger than the command processing an time whichever larger. When the setting time is
						nnot be received properly.



App. 5.2.3 System configuration example when 2 stations are occupied

As shown below, the CC-Link system master · local unit is loaded to run one drivers (2 station occupied).



Input signal assignment

Input signal	Signal name	General operation when the input is on
X20	Reset command	Resets the driver on an occurrence of a servo alarm.
X21	Servo-on command	Turns on the servo motor. (Servo-on status)
X22	Forward rotation JOG command	Executes a forward JOG operation in the manual operation mode.
X23	Reverse rotation JOG command	Executes a reverse JOG operation in the manual operation mode.
X24	Automatic/manual selection	OFF: Manual operation mode ON: Automatic operation mode
X25	Home position return command	Executes a dog type home position return when home position return is incomplete in the automatic operation mode.
X26	Proximity dog command	OFF: Proximity dog is on. (Note) ON: Proximity dog is off.
X27	Positioning start command	Executes a positioning operation with position and speed settings specified in the remote register when home position return is completed in the automatic operation mode.
X28	Position/speed setting system changing command	Changes to position/speed specification by the remote register.

Note. This is when the parameter No.PD16 is set to "DD0 (initial value)" (detects the dog at off).



App. 5.2.4 Program example when 2 stations are occupied

POINT
 To execute a dog type home position return with the CC-Link communication functions, set "□0□□" in parameter No.PD14 and use Proximity dog (DOG) with the remote input (RY03) in this example.

Operate the driver of station 1 in the positioning mode and read the "motor speed" data.

Preset the parameter No.PC30 to " \Box \Box \Box 2".

Specific programming examples are explained based on the equipment configuration shown in appendix 5.2.3. Operation: Alarm reset, dog type home position return, JOG operation, automatic operation under point table

commanu		
Code No.	Description	
H0016	32-bit data of motor speed (hexadecimal)	

Code No.	Description
K50000	Position command data (decimal)
K100	Speed command data (decimal)

			——Емс	NO	NO	[]] Check the status of CC-Link.
	[DFRO	HO	HOEO	K8M200	K2	Reads remote input (RX00 to RX3F) of buffe memory to M200 to M263.
44 109 M209			[MOV	H10	D10	³ Writes current alarm read (H0010) to RWw
	[10	HO	H1E2	D10	K1	trouble (RX3A) occurrence.
				[SET	M109	¹ Turns on instruction code execution demand (RY09).
				[SET	M301	Ъ
63 M301 M109 M209	[FROM	HO	H2E3	D11	К1	Reads RWr3 and RWr2 of buffer memory to D11 and D12 when instruction code execution
	ELEV	HO	H2E2	D12	K1	completion (RX09) turns on.
				[RST	W109	¹ Turns off instruction code execution demand (RY09).
				[RST	M301	Э
86 Keset command					—(M158	> Alarm reset command (RY3A)
X21 M259 M258					(M100	> Servo-on command (RY00)
Servo-on command X24 W201 M202				FSET	M106	Automatic operation mode selection (RY06)
					MIUO	
97 Automatic/manual selection				ERST	M106	Manual operation mode selection (RY06)
101 X25 M106 M203 Home position return Home position r				[PLS	M302	Home position return request
107 King command				ESET	M303	3
109 M303					(T200 K1	> Point table establishment time 10ms *1
				[SET	M5	Forward rotation start request
				[RST	M303	3
N5					K1	> Command request time 10ms *1
				ERST	N5	Forward rotation start request reset
X26						



120		/ř			JOG command					Forward rot	ation start request
			X22		M3					Reverse rot	ation start request
132	X28	<i>.</i> .									eed specifying system selection
134	X27	/speed s	etting syste	M202	ging command M203					(RY4A)	
	₩ 304		In position	Rough match	Home position return completion				-	-	
142			•						[SET	M305]	
144	M305	₩132 ↓/	M133					EDMOA	K50000	D130 J	
								EMOA	K100	0132 } RWw4, RV	ition command data (K50000) to Vw5, and speed data (K100) to
						[T0	НО	H1E4	D130	кз т) RWw6.	
						L					
									[SET	^{#132}] Turns on po	osition instruction demand (RY20
									ESET		peed instruction demand (RY21) ond code (RWr2) to D2 when
170	M132	₩133	M232	M233		EFROM	HO	H2E2	D2	position inst	truction execution completion (R
										_{K1} (RX21) turn	on. I speed data establishment time
	T203								-057	10ms *1	
184									ESET	Positioning	start command
									ERST	мзо5 }	
187	₩6 —									T202 ^{K1} > Command r	equest time 10ms *1
189	T202								ERST	Positioning	start command reset
										_	sition instruction demand (RY2
									-		·
	M3								[RST		beed instruction demand (RY21)
193-										Forward rot	ation start (RY01)
+	₩5 — —	-									
	M6 ── ──]									
197	M4									(M102) Reverse rot	ation start (D)(02)
	M259										ation start (RY02)
199								ENOA	H16		or code (H0016) of motor speed
						E10	HO	H1EO	D110	кі _}] RWw0.	
		L							[SET	¹¹⁰⁸ ^{Turns on m (RY08).}	onitor output execution demand
		M208				FROM	НО	H2E0	D120	Reads RWr	0 and RWr1 of buffer memory to
	M9036			_		-				on.	0121 when monitoring (RX08) tu
225						[DT0	HO	H160	K8M100		0 to M163 to remote output (RY
237									EMCR		uffer memory.
240										END }	
								*1: Setti	na time f	the timer should be la	arger than the command proces



App. 6 Handling of AC driver batteries for the United Nations Recommendations on the Transport of Dangerous Goods

To transport lithium batteries, take actions to comply with the instructions and regulations such as the United Nations (UN), the International Civil Aviation Organization (ICAO), and the International Maritime Organization (IMO).

The battery (LEC-MR-J3BAT) is an electric cell (lithium metal battery ER6).

The IATA Dangerous Goods Regulations are revised, and the requirements are changed annually.

When transporting lithium batteries, the responsibility for the cargo lies with the customer.

Thus, be sure to check the latest version of the IATA Dangerous Goods Regulations.

When contracting transportation to a carrier, follow the carrier's instructions.

Battery (Cell) : LEC-MR-J3BAT Lithium content : 0.65(g)



App. 7 Recommended parameter values for each actuator

Please change the parameter values according to the customer application. Refer to "LECSC2-T
Operation Manual", chapter 6 for details.

Recommended Para	meter Va	alues [LEF	-/LEKE	Sj							
			LEFS	25/LEKF	-S25	LEF	S32/LEK	FS32	LEF	S40/LEKF	-S40
Series	Lead	symbol	Н	А	В	Н	Α	В	Н	А	В
	Le	ead	20	12	6	24	16	8	30	20	10
Parameter *1,*2	Para. No.	Initial value				Rec	commend	ed value			
Electronic gear numerator *3	PA06	1		32768							2
Electronic gear denominator *3	PA07	1	2500	1500	750	3000	2000	1000	3750	2500	1250
Feel length multiplication (STM) (Multiplier)	PA05	0000	0000(Less than stroke 1000)/ 0001(Stroke 1000 or more)								
Home position return type	PC02	0000					3 (Stopp	oer type)		
Home position return direction	PC03	0001		□□□1 (Motor side)							
Home position return Speed (rpm)	PC04	500	90	150	300	75	113	225	60	90	180
Home position return position data (µm)	PC07	0	-2000(Less than stroke 1000) / -200(Stroke 1000 or more)						I		
Stopper type home position return stopper time (msec)	PC09	100					200				
Stopper type home position return torque limit value (%)	PC10	15					24				
Regenerative option	PA02	0000			00	00(Non)	/ 0002(LI	EC-MR-R	B-032)		
Rotation direction selection *4	PA14	0				1(+:C	ounter m	notors sid	de)		
Adaptive tuning mode	PB01	0000					0000)			
Load to motor inertia moment ratio	PB06	7	7								
Machine resonance suppression filter 1	PB13	4500	4500								
Notch shape selection 1	PB14	0000	0000								
selection 1		0000							n the init	ial value	

Recommended Parameter Values [LEF/LEKFS]

*1 Parameter is the recommended value. Please change the parameter to the appropriate value for the operating method.

*2 A mechanical resonance may occur depending on the configuration or the mounting orientation of the transferred object. Please change the parameter in the initial setting.

*3 The minimum unit of the travel distance of the actuator should be 1 [µm].

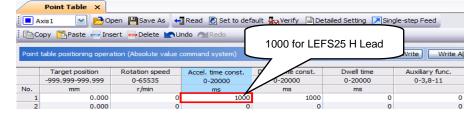
*4. When the motor mounting position is right side parallel (LEFS*R /LEKFS*R) or left side parallel (LEFS*L /LEKFS*L), the rotation direction PA14 selection is 0(+: Counter motors side).



Recommended Value of acceleration time constant of Point table No.1 [LEF]

			LEFS25/LEKFS25			LEFS32/LEKFS32			LEFS40/LEKFS40		
Series	Lead symbol	Н	А	В	Н	А	В	Н	А	В	
	Lead	20	12	6	24	16	8	30	20	10	
Point table No.1	Initial value	Recommended Value									
Home position return acceleration time constant (msec) *5	0	1000	600	300	1200	800	400	1500	1000	500	
Different from the initial value.											





*5. Use the acceleration time constant of Point table No.1 as the acceleration time constant (msec) of Home position return. Set the recommended value in the above figure. Refer to "LECSC2-T Operation Manual ", section 5.4.2 for how to set the Point table.



			LEFB25	LEFB25U	LEFB32	LEFB32U	LEFB40	LEFB40U	
Series	Lead	symbol				6	-		
		ead			5	4			
Parameter *1,*2	Para. No.	Initial value			Recomme	nded value			
Electronic gear numerator *3	PA06	1			327	768			
Electronic gear denominator *3	PA07	1	6750						
Feel length multiplication (STM) (Multiplier)	PA05	0000	0000(Less than stroke 1000)/ 0001(Stroke 1000 or more)						
Home position return type	PC02	0000		l	□□□3(Stop	per type)			
Home position return direction	PC03	0001			0001 (Ma	otor side)			
Home position return Speed (rpm)	PC04	500	33						
Home position return position data (µm)	PC07	0	-3000(Less than stroke 1000) / -300(Stroke 1000 or more)						
Stopper type home position return stopper time (msec)	PC09	100			20	00			
Stopper type home position return torque limit value (%)	PC10	15			2	4			
Regenerative option	PA02	0000		-	Non) / 0002((LEC-MR-RE	3-032)		
Rotation direction selection	PA14	0	1(+ : Counter motors side)	0(+ : Counter motors side)	1(+ : Counter motors side)	0(+ : Counter motors side)	1(+ : Counter motors side)	0(+ : Counter motors side)	
★ Adaptive tuning mode	PB01	0000	00	02		00	00		
★ Load to motor inertia moment ratio	PB06	7	50						
★Machine resonance suppression filter 1	PB13	4500	400 4500						
★ Notch shape selection 1	PB14	0000	o 0030 0000						
						arameter sl fferent from		-	

*1 Parameter is the recommended value. Please change the parameter to the appropriate value for the operating method.

*2 A mechanical resonance may occur depending on the configuration or the mounting orientation of the transferred object. Please change the parameter in the initial setting.

*3 The minimum unit of the travel distance of the actuator should be 1 [μ m].



Recommended Value of acceleration time constant of Point table No.1 [LEF]

		LEFB25	LEFB25U	LEFB32	LEFB32U	LEFB40	LEFB40U					
Series	Lead symbol		S									
	Lead		54									
Point table No.1	Point table No.1 Initial value			Recommended value								
Home position return acceleration time constant (msec) *4			2	700								

Different from the initial value.

Point Table ×												
📔 Axis1 🕑 🖻 Open 💾 Save As ┥ Read 👸 Set to default 👷 Verify 📄 Detailed Setting 💌 Single-step Feed												
Copy Paste - Insert - Delete Undo Redo												
Point table positioning operation (Absolute value command system)												
	Target position	Rotation speed	Accel. time const.	Decel Ist.	Dwell time	Auxiliary func.						
	-999.999-999.999	0-65535	0-20000	0000	0-20000	0-3,8-11						
No.	mm	r/min	ms	ms	ms							
1	0.000	0	2700	2700	0	0						
2	0.000	0	0	0	0	0						

*4. Use the acceleration time constant of Point table No.1 as the acceleration time constant (msec) of Home position return. Set the recommended value in the above figure. Refer to "LECSC2-T□ Operation Manual", section 5.4.2 for how to set the Point table.



Recommended Parameter Values [LEJ]

Recommended i ala	meter v	alues [L	_J]							
				LEJS40			LEJS63		LEJB40	LEJB63
Series	Lead s	symbol	Н	А	В	Н	А	В	-	Г
	Le	ad	24	16	8	30	20	10	27	42
D (1110	Para.	Initial					•		•	-
Parameter *1,*2	No.	value				Recom	mended	value		
Electronic gear numerator *3	PA06	1					32768			
Electronic gear denominator *3	PA07	1	3000	3000 2000 1000 3750 2500 1250						5250
Feel length multiplication (STM) (Multiplier)	PA05	0000		0000(Less than stroke 1000) / 0001(Stroke 1000 or more)						
Home position return type	PC02	0000		□□□3 (Stopper type)						
Home position return direction	PC03	0001		□□□1 (Motor side)						
Home position return Speed (rpm)	PC04	500	75	113	225	60	90	180	133	86
Home position return position data (µm)	PC07	0	-2000(Less than stroke 1000) / -200(Stroke 1000 or more)							
Stopper type home position return stopper time (msec)	PC09	100					200			
Stopper type home position return torque limit value (%)	PC10	15					24			
Regenerative option	PA02	0000		0000(No	n) / 0002	(LEC-MF	R-RB-032	2) / 0003(LEC-MR-RB	-12)
Rotation direction selection	PA14	0			, Counter	1			() ter motors
★Adaptive tuning mode	PB01	0000			00	00			0002	0000
★Load to motor inertia moment ratio	PB06	7	7 50						0	
★Machine resonance suppression filter 1	PB13	4500	4500 400 45				4500			
★Notch shape selection 1	PB14	0000			0000 0030 0					0000

 \star Parameter should be changed.

Different from the initial value.

- *1 Parameter is the recommended value. Please change the parameter to the appropriate value for the operating method.
- *2 A mechanical resonance may occur depending on the configuration or the mounting orientation of the transferred object. Please change the parameter in the initial setting.

*3 The minimum unit of the travel distance of the actuator should be 1 [μ m].

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Recommended Value of acceleration time constant of Point table No.1 [LEJ]

	_	LEJS40			LEJS63			LEJB40	LEJB63
Series	Lead symbol	н	А	В	н	А	В	-	г
	Lead	24	16	8	30	20	10	27	42
Point table No.1	Initial value				Recomn	nended val	ue		
Home position return acceleration time constant (msec) *4	0	1200	800	400	1500	1000	500	1350	2100

Different from the initial value.

Point Table ×												
🔲 Axis 1 🛛 🕑 Open 💾 Save As 🛛 🔄 Read 🐻 Set to default 🦕 Verify 📄 Detailed Setting 🖉 Single-step Feed												
: Poc	Copy Paste = Insert = Delete Cundo MRedo											
Point	Point table positioning operation (Absolute value command system 1200 for LEJS40 H Lead											
	Target position	Rotation speed	Accel. time const.	ne const.	Dwell time	Auxiliary func.						
	-999.999-999.999	0-65535	0-20000	0-20000	0-20000	0-3,8-11						
No.	No. mm r/min ms ms ms											
1	0.000	0	1200	1200	0	0						
2	0.000	0	0	0	0	0						

*4. Use the acceleration time constant of Point table No.1 as the acceleration time constant (msec) of Home position return. Set the recommended value in the above figure. Refer to "LECSC2-T
 Operation Manual ", section 5.4.2 for how to set the Point table.



				LEJS100			
Series	Leads	symbol	Н	А	В		
	Le	ad	50	25	10		
Parameter *1,*2	Para.	Initial		Recommended value			
Electronic secs	No.	value					
Electronic gear numerator *3	PA06	1		32768			
Electronic gear denominator *3	PA07	1	6250 3125 1250				
Feel length multiplication (STM) (Multiplier)	PA05	0000	0000(Less than stroke 1000) / 0001(Stroke 1000 or mor				
Home position return type	PC02	0000		IIII 3 (Stopper type)			
Home position return direction	PC03	0001		□□□1 (Motor side)			
Home position return Speed (rpm)	PC04	500	36	72	180		
Home position return position data (µm)	PC07	0	-7000(Less than	ke 1000 or more)			
Stopper type home position return stopper time (msec)	PC09	100		200			
Stopper type home position return torque limit value (%)	PC10	15		24			
Regenerative option	PA02	0000	0000(Non) / 0002	(LEC-MR-RB-032) / 0003	3(LEC-MR-RB-12)		
Rotation direction selection	PA14	0	1	(+ : Counter motors sid	le)		
Adaptive tuning mode *4	PB01	0000		0000			
Load to motor inertia moment ratio	PB06	7		7			
Machine resonance suppression filter 1 *4	PB13	4500	4500				
Notch shape selection 1 *4	PB14	0000	0000				
Low-pass filter *4	PB18	3141	3141 3141				
Low-pass filter selection *4	PB23	0000	0000				

Dfferent from the initial value.

*1 Parameter is the recommended value. Please change the parameter to the appropriate value for the operating method.

- *2 A mechanical resonance may occur depending on the configuration or the mounting orientation of the transferred object. Please change the parameter in the initial setting.
- *3 The minimum unit of the travel distance of the actuator should be 1 [μ m].
- *4 If noise or vibration occurs due to the load or mounting posture, change the parameter values and make appropriate adjustments. Refer to "LECSC2-T Operation Manual section 9" for the adjustment method.



Recommended Value of acceleration time constant of Point table No.1 [LEJ]

			LEJS100			
Series	Lead symbol	н	А	В		
	Lead	50	25	10		
Point table No.1	Initial value	Rec	Recommended value			
Home position return acceleration time constant (msec) *5	0	2500	1250	500		

Different from the initial value.

Point Table X													
	Axis1 Copy Paste - Insert - Delete Undo Redo												
Point	Point table positioning operation (Absolute value command system) Selected Items Write A												
	Target position	Rotation speed	Accel. time const.	D ame const.	Dwell time	Auxiliary func.							
	-999.999-999.999	0-65535	0-20000	0-20000	0-20000	0-3,8-11							
No.	No. mm r/min ms ms ms												
1	0.000	0	2500	2500	0	0							
2	0.000	0	0	0	0	0							

*5. Use the acceleration time constant of Point table No.1 as the acceleration time constant (msec) of Home position return. Set the recommended value in the above figure. Refer to "LECSC2-T□ Operation Manual ", section 5.4.2 for how to set the Point table.



Recommended Parameter Values [LEY]

neter val		1						1					
		LEY	25/LEY	′G25		-		LEY	′32/LEY	G32			
Lead	symbol	Α	В	С	А	В	С	А	В	С	А	В	С
Le	ead	12	6	3	12	6	3	20	10	5	16	8	4
Para. No	Initial value					Rec	omme	nded v	alue				
PA06	1						327	768					
PA07	1	1500	750	375	1500	750	375	2500	1250	625	2000	1000	500
PA05	0000		0000) (Less	s than	stroke	e 1000)	/ 000′	1 (Stro	ke 100	0 or m	nore)	
PC02	0000					<u> </u>	(Stop	oper	type)				
PC03	0001						⊐⊐1 (M	otor si	de)				
PC04	500	150	300	600	150	300	600	90	180	360	112	225	450
PC07	0		-200)0(Les	s than	strok	e 1000) / -20	0(Strol	ke 100	0 or m	ore)	
PC09	100	200											
PC10	15						2	4					
PA02	0000				000) (Non)/ 0002	2 (LEC	-MR-R	B-032)			
PA14	0							· ·					
PB01	0000						00	00					
PB06	7	7											
PB13	4500						45	00					
		0000											
	Lead Para. No PA06 PA07 PA05 PC02 PC03 PC04 PC04 PC07 PC09 PC09 PC10 PC09 PC10 PA02 PA14 PB01 PB06	Lead symbol Lead Para. No Initial value PA06 1 PA07 1 PA05 0000 PC02 0000 PC03 0001 PC04 500 PC07 0 PC09 100 PC10 15 PA02 0000 PA14 0 PB01 0000	Lead symbol A Lead 12 Para. No Initial value 12 PA06 1 12 PA06 1 1500 PA07 1 1500 PA05 0000 1 PC02 0000 1 PC03 0001 1 PC04 500 150 PC07 0 1 PC09 100 1 PC10 15 2 PA02 0000 1 PA14 0 (+ PB01 00000 1	Lead symbol A B Lead 12 6 Para. No Initial value 12 6 PA06 1 12 6 PA07 1 1500 750 PA05 0000 750 0000 PC02 0000 0000 0000 PC03 0001 0 0000 PC04 500 150 300 PC07 0 -200 0000 PC09 100 150 300 PC10 15 0000 0 PA02 0000 0 0 PA14 0 (+ : Cour motors si PB01 0000 15 0	Lead symbol A B C Lead 12 6 3 Para. No Initial value	LEY25/LEYG25 I Lead symbol A B C A Lead 12 6 3 12 Para. No Initial value	LEY25/LEYG25 LEY25/LEYG25	Levisitian Levisitan Levisitan <thlevisitan< th=""> <thlevisitan< th=""> <t< td=""><td>LEY25/LEYG25 LEY25/LEYG25 LEY25/LEYG25 LEY25/LEYG25 LEY25/LEYG25 LEY Lead symbol A B C A B C A Lead 12 6 3 12 6 3 20 Para. No Initial value Initial value Recommended value Recommended value PA06 1 1500 750 375 1500 750 375 2500 PA07 1 1500 750 375 1500 750 375 2500 PA05 0000 O000 (Less than stroke 1000) / 0007 PC02 0000 Image: Strong test test test test test test test tes</td><td>LEY25/LEYG25 LEY25/LEYG25 LEY32/LEY Lead symbol A B C A B C A B Lead 12 6 3 12 6 3 20 10 Para. No Initial value Initial value Recommended value Recommended value PA06 1 State State</td><td>LEY25/LEYG25 LEY25/LEYG25 LEY32/LEYG32 Lead symbol A B C D D D D<!--</td--><td>$\begin{tabular}{ c c c c c c c c c c c c c c c c c c c$</td><td>LEY25/LEYG25 LEY25D/LEYG25 LEY32/LEYG32 LEY32/LEYG3</td></td></t<></thlevisitan<></thlevisitan<>	LEY25/LEYG25 LEY25/LEYG25 LEY25/LEYG25 LEY25/LEYG25 LEY25/LEYG25 LEY Lead symbol A B C A B C A Lead 12 6 3 12 6 3 20 Para. No Initial value Initial value Recommended value Recommended value PA06 1 1500 750 375 1500 750 375 2500 PA07 1 1500 750 375 1500 750 375 2500 PA05 0000 O000 (Less than stroke 1000) / 0007 PC02 0000 Image: Strong test test test test test test test tes	LEY25/LEYG25 LEY25/LEYG25 LEY32/LEY Lead symbol A B C A B C A B Lead 12 6 3 12 6 3 20 10 Para. No Initial value Initial value Recommended value Recommended value PA06 1 State State	LEY25/LEYG25 LEY25/LEYG25 LEY32/LEYG32 Lead symbol A B C D D D D </td <td>$\begin{tabular}{ c c c c c c c c c c c c c c c c c c c$</td> <td>LEY25/LEYG25 LEY25D/LEYG25 LEY32/LEYG32 LEY32/LEYG3</td>	$\begin{tabular}{ c c c c c c c c c c c c c c c c c c c$	LEY25/LEYG25 LEY25D/LEYG25 LEY32/LEYG32 LEY32/LEYG3

*1 Parameter is the recommended value. Please change the parameter to the appropriate value for the operating method.

*2 A mechanical resonance may occur depending on the configuration or the mounting orientation of the transferred object. Please change the parameter in the initial setting.

*3 The minimum unit of the travel distance of the actuator should be 1 [μ m].

*4 When the motor mounting position is right side parallel (LEY*R) or left side parallel (LEY*L), the rotation direction selection is 0(+: Counter motors side).



Recommended Value of acceleration time constant of Point table No.1 [LEY]

		LE	(25/LEY	G25	LEY2	25D/LEY	G25D	LE	Y32/LEYG	32	LEY3	2D/LEY	G32D
Series	Lead symbol	А	В	С	А	В	С	А	В	С	А	В	С
	Lead	12	6	3	12	6	3	20	10	5	16	8	4
Point table No.1	Initial value	Recommended value											
Home position return acceleration time constant (msec) *5	0	600	300	150	600	300	150	1000	500	250	800	400	200

Different from the initial value.

	Point Table X										
📔 Axis1 💌 🖻 Open 💾 Save As 📲 Read 🕃 Set to default 🥵 Verify 📄 Detailed Setting 📝 Single-step Feed											
: Do	📴 Copy 🖺 Paste 🚽 Insert 🖶 Delete 📉 Undo 🐋 Redo										
Point	table positioning opera	ation (Absolute value o	command syster	600 for LE	Y25 A Lead	Write A					
	Target position	Rotation speed	Accel. time con-			miary func.					
	-999.999-999.999	0-65535	0-20000		0-20000	0-3,8-11					
No.	mm	r/min	ms	ms	ms						
1	0.000	0	6	600	0	0					
2	0.000	0	0	0	0	0					

*5. Use the acceleration time constant of Point table No.1 as the acceleration time constant (msec) of Home position return. Set the recommended value in the above figure. Refer to "LECSC2-T
 Operation Manual ", section 5.4.2 for how to set the Point table.



				LE`	Y63			LEY63D			
	Lead	symbol	А	В	с	L	А	В	С		
Series	(Includi	ead ng pulley tio)	20	10	5	5(2.86) (Pulley ratio 4/7)	20	10	5		
Parameter *1,*2	Para. No	Initial value			Rec	ommended	value				
Electronic gear numerator *3	PA06	1		32768		57344		32768			
Electronic gear denominator *3	PA07	1	2500	1250	625	625	2500	1250	625		
Feel length multiplication (STM) (Multiplier)	PA05	0000	0000 (Less than stroke 1000) / 0001 (Stroke 1000 or more						re)		
Home position return type	PC02	0000			3	(Stopper	type)				
Home position return direction	PC03	0001	□□□1 (Motor side)					2)			
Home position return speed (rpm)	PC04	500	90	180	360	629	90	180	360		
Home position return position data (µm)	PC07	0	-4000 (Less than stroke 1000) / -400(Stroke 1000 or mo						re)		
Stopper type home position return stopper time (msec)	PC09	100				200					
Stopper type home position return torque limit value (%)	PC10	15				24					
Regenerative option	PA02	0000	0	000 (Non)/	0002 (LEC	-MR-RB-03	2)/ 0003 (L	EC-MR-RB	-12)		
Rotation direction selection *4	PA14	0	(-	(+ : Counter	0 motors sid	le)	(+ : Coi	1 unter moto	rs side)		
Adaptive tuning mode	PB01	0000				0000					
Load to motor inertia moment ratio	PB06	7	7								
Machine resonance suppression filter 1	PB13	4500	4500								
Notch shape selection 1	PB14	0000				0000					

Different from the initial value.

*1 Parameter is the recommended value. Please change the parameter to the appropriate value for the operating method.

*2 A mechanical resonance may occur depending on the configuration or the mounting orientation of the transferred object. Please change the parameter in the initial setting.

*3 The minimum unit of the travel distance of the actuator should be 1 [μ m].

*4 When the motor mounting position is right side parallel (LEY*R) or left side parallel (LEY*L), the rotation direction selection is 0(+: Counter motors side).



Recommended Value of acceleration time constant of Point table No.1 [LEY]

			LE`	Y63			LEY63D	
	Lead symbol	А	В	С	L	А	В	С
Series	Lead (Including pulley ratio)	20	10	5	5(2.86) (Pulley ratio 4/7)	20	10	5
Point table No.1	Initial value	Recommended value						
Home position return acceleration time constant (msec) *5	0	1000	500	250	143	1000	500	250

Different from the initial value.

/	Point Table X							
: 🔳 A	xis1 🕑 🔁 O	pen 💾 Save As 🗧	Read 👩 Set to def	ault 🌄 Verify	Detailed	Setting 🗾 Single	e-step Feed	
: Do	opy 💾 Paste 📥 Ins	ert 👄 Delete 📉 U	Indo Marado					
Point	table positioning opera	ation (Absolute value)	command system)	100	0 for l	EY63 A L	ead	A
	Target position	Rotation speed	Accel. time const.	100			cau	
	-999.999-999.999	0-65535	0-20000					-
No.	mm	r/min	ms			ms		
1	0.000	0	1000		1000	0		0
2	0.000	0	0		0	0		0

*5. Use the acceleration time constant of Point table No.1 as the acceleration time constant (msec) of Home position return. Set the recommended value in the above figure. Refer to "LECSC2-TD Operation Manual", section 5.4.2 for how to set the Point table.



				LEY100D				
	Lead s	symbol	В	D	L			
Series		ad uding ratio)	10	10(3.3) [Pulley ratio 1/3]	10(2) [Pulley ratio 1/5]			
Parameter *1,*2	Para. No.	Initial value		Recommended value				
Electronic gear numerator *3	PA06	1		49152				
Electronic gear denominator *3	PA07	1	1875	625	375			
Feel length multiplication (STM) (Multiplier)	PA05	0000	0000 (Less than stroke 1000) / 0001 (Stroke 1000 or mor					
Home position return type	PC02	0000		Gamma Stopper type				
Home position return direction	PC03	0001		□□□1 (Motor side)				
Home position return Speed (rpm)	PC04	500	180	545	900			
Home position return position data (µm)	PC07	0	-5000 (Less than stroke 1000) / -500(Stroke 1000 or n					
Stopper type home position return stopper time (msec)	PC09	100		200				
Stopper type home position return torque limit value (%)	PC10	15		24				
Regenerative option	PA02	0000	0000 (Non)/ 000	02 (LEC-MR-RB-032)/ 000	03 (LEC-MR-RB-12)			
Rotation direction selection	PA14	0	1	(+ : Counter motors sid	le)			
Adaptive tuning mode *4	PB01	0000		0000				
Load to motor inertia moment ratio	PB06	7		7				
Machine resonance suppression filter 1 *4	PB13	4500		4500				
Notch shape selection 1 *4	PB14	0000		0000				
Low-pass filter *4	PB18	3141	41 3141					
Low-pass filter selection *4	PB23	0000		0000				

*1 Parameter is the recommended value. Please change the parameter to the appropriate value for the operating method.

*2 A mechanical resonance may occur depending on the configuration or the mounting orientation of the transferred object. Please change the parameter in the initial setting.

*3 The minimum unit of the travel distance of the actuator should be 1 [μ m].

*4 If noise or vibration occurs due to the load or mounting posture, change the parameter values and make appropriate adjustments. Refer to "LECSC2-T Operation Manual section 9" for the adjustment method.



Recommended Value of acceleration time constant of Point table No.1 [LEY]

			LEY100D				
Series	Lead symbol	В	D	L			
Selles	Lead (Including pulley ratio)	10	10(3.3)	10(2)			
Point table No.1	Initial value	Rec	commended v	alue			
Home position return							
acceleration time constant	0	500	166	100			
(msec) *5							
Point Table	×				: Di	ifferent from th	ne initial value.
📕 Axis 1 🛛 💌	🔁 Open 💾 Save As 🖣 R	Read [🛃 Set to c	lefault 🌄 Verif	y 🖹 Detailed	Setting 🔀 Sing	gle-step Feed	
	g operation (Absolute value cor		500 for	r LEY100 B	Lead	ns Write Write Al	
Target posit		Accel. time const			Dwell time	Auxiliary func.	
-999.999-999		0-20000	0-2000	00	0-20000	0-3,8-11	
No. mm	r/min 0.000 0	ms	ms	500	ms 0	0	
2	0.000 0	500	0	0	0	0	

*5 Use the acceleration time constant of Point table No.1 as the acceleration time constant (msec) of Home position return. Set the recommended value in the above figure. Refer to "LECSC2-T□ Operation Manual", section 5.4.2 for how to set the Point table.



Recommended Parameter Values [LESYH]

	ielei vait		1							
			LES	YH16	LESY	Ή16D	LES	YH25	LESY	H25D
	Lead	symbol	А	В	А	В	А	В	А	В
Series	(Includi	ead ing pulley atio)	10	6	10	6	16(20) (Pulley ratio 5/4)	8(10) (Pulley ratio 5/4)	16	8
Parameter *1,*2	Para. No.	Initial value			F	Recomme	nded valu	e		
Electronic gear numerator *3	PA06	1				32	768			
Electronic gear denominator *3	PA07	1	1250	750	1250	750	2500	1250	2000	1000
Feel length multiplication (STM) (Multiplier)	PT03	0000	0000 (Less than stroke 1000) / 0001 (Stroke 1000 or more)						e)	
Home position return type	PT04	0010				⊐3 (Stop	oper typ	e)		
Home position return direction	PT04	0010	□□□1 (Motor side)							
Home position return Speed (rpm)	PT05	100	180	300	180	300	90	180	112	225
Home position return position data (µm)	PT08	0	-2000 (Less than stroke 1000) / -200(Stroke 1000 or more						e)	
Stopper type home position return stopper time (msec)	PT10	100	200							
Stopper type home position return torque limit value (%)	PT11	15				2	4			
Regenerative option	PA02	0000	0	000 (Non)	/ 0002 (LI	EC-MR-R	B-032)/ 00	003 (LEC-	MR-RB-1	2)
Rotation direction selection *4	PA14	0	(+ : C	0 ounter s side)	•	1 ounter s side)	`) ounter s side)	(+ : Co motors	ounter
Adaptive tuning mode	PB01	0000				00	000			
Load to motor inertia moment ratio	PB06	7	7							
Machine resonance suppression filter 1	PB13	4500	4500							
Notch shape selection 1	PB14	0000				00	00			

Different from the initial value.

*1 Parameter is the recommended value. Please change the parameter to the appropriate value for the operating method.

*2 A mechanical resonance may occur depending on the configuration or the mounting orientation of the transferred object. Please change the parameter in the initial setting.

*3 The minimum unit of the travel distance of the actuator should be 1 [μ m].

*4. When the motor mounting position is right side parallel (LESYH*R) or left side parallel (LESYH*L), the rotation direction selection is 0(+: Counter motors side).



		LES	YH16	LESY	′H16D	LESYH	25R/LN	LESY	H25D
	Lead symbol	Α	В	Α	В	А	В	А	В
Series	Lead (Including pulley ratio)	10	6	10	6	16(20)	8(10)	16	8
Point table No.1	Initial value	Recommended value							
Home position return acceleration time constant (msec) *5	0	500	300	500	300	1000	500	800	400

Recommended Value of acceleration time constant of Point table No.1 [LESYH]

/	Point Table ×										
📄 Axis 1 🕑 🎦 Open 💾 Save As 🗧 Read 👸 Set to default 🌄 Verify 📄 Detailed Setting 🔎 Single-step Feed											
Copy Paste - Insert Delete Undo Redo 500 for LESYH16 A Lead											
Point table positioning operation (Absolute value command system) Selected Items Write Write A											
	Target position	Rotation speed	Accel. time const.	el. time const.	Dwell time	Auxiliary func.					
	-999.999-999.999	0-65535	0-20000	0-20000	0-20000	0-3,8-11					
No. mm r/min ms ms ms											
1	0.000	0	500	500	0	0					
	0.000			0							

*5. Use the acceleration time constant of Point table No.1 as the acceleration time constant (msec) of Home position return. Set the recommended value in the above figure. Refer to "LECSC2-T□ Operation Manual", section 5.4.2 for how to set the Point table.



Revision history

No.JXC*-OMW0028 Jun/2019 1th printing No.LEC*-OMY0116 Sep/2021 [App.7 Recommended parameter values for each actuator] add No.LEC*-OMY0116-A Jan/2022 Add LEKFS parameter recommended values to App.7 No.LEC*-OMY0116-B Apr/2023 Add note to chapter1.2 and 1.7

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