Preface

This user manual is applicable to Wecon VD3E series bus servo drives.

In order to use this series of servo drives correctly, please read this manual carefully in advance and save it for later use.

During use, if you have any doubt about the function and performance of this equipment, please contact our technicians for relevant assistance to use this equipment smoothly.

The company's products are constantly being improved and upgraded, and the contents of this manual are subject to change without notice.

This manual is suitable for introductory and use reference books for elementary and intermediate readers. At the same time, all interpretation rights of this manual belong to our company.

⚠ Dangerous
The danger caused by failure to operate as required may result in serious injuries or even death.

⚠ Notice
The danger caused by failure to operate as required may result in moderate or minor injuries, and equipment damage.

User Manual Change Record

Date	Changed version	Changed content	Applicable models
October 2022	V1.0	First edition	★ VD3E-0☐☐SA1G model
August 2023	V2.0	**Chapter 7:** Add the supplementary explanation of touch probe function and DI touch probe function; Add homing mode 35, and add 60E6 to set absolute coordinates and relative coordinate modes; **Chapter 8:** Add 60E0, 60C5h and 60C6h object dictionaries; Delete 6071, 6074, 607D: 01 object dictionaries; Modify the data range and default value of some object dictionaries; U0-57 is added to support 64-bit absolute position display; Add U0-48 servo power-on counting description, U0-52 encoder bit monitoring value; Update the object dictionary table and add 6000 groups of data format standard device sub-protocol areas; Add 2001-17, 2000-18, 2000-1F and other object dictionaries; Add JOG acceleration time 2001-25 and JOG deceleration time 2001-26; Add 2004-12 speed feedback filter time; Add 200A-05 motor model and 200A-07 manual motor code; Speed feedforward filtering time P2-10 default value and range unit changed; Torque limit source P1-14 added: EtherCAT control; **Chapter 10:** Add Er.43 drive overload fault and A-80 power limit alarm; Er.27 [Encoder disconnected] changed to be unclearable. Modify the fault logic and troubleshooting method of A-91; Add temporary solutions to A-93; **Chapter 11:** Add the hardware requirements of European EMC certification standard;	★VD3E-0☐☐SA1G model

Date	Changed version	Changed content	Applicable models
		Add EMC input noise filter recommendation; Add cable and wiring requirements, etc.	
July 2024	V2.1	**Chapter 4** Add the main circuit terminal description of VD3E type B drive (380V); Add the main circuit terminals schematic diagram of VD3E type B drive (380V); Add three-phase 380V main circuit wiring of VD3E type B drive; Add the example of encoder line connection between power wiring servo drive and servo motor; **Chapter 5** Add description of VD3E quick stop status panel display; **Chapter 6** Add description of the PDO maximum added quantity; **Chapter 7** Add Cyclic Synchronous Velocity mode (CSV); Add Cyclic Synchronous Torque mode (CST); Add profile torque mode (PT); **Chapter 8** Add 2000-20, 2001-09, 2001-11, 2001-12 and other object dictionaries; Add 2002-07, 2002-08, 2002-10, 2002-14, 2002-15, 2002-16, 2002-17, 2002-18 and 2002-19 and other object dictionaries; Add 200A-04, 200A-0B and other object dictionaries; Add 6065, 6071, 60B2, 60F4, 60FD and other object dictionaries； **Chapter 9** Add model tracking control function; Add gain switching function; **Chapter 10** Add drive stalled and over-temperature protection fault;	★ VD3E-0☐☐TA1G model
October 2024	V3.1	**Chapter 1** Add 1.7 Leakage protection description and circuit-breaker recommendation **Chapter 2** 2.1.3 (2) Basic specifications **Chapter 3**	★ VD3E-0☐☐SA1G model ★ VD3E-0☐☐TA1G model

Date	Changed version	Changed content	Applicable models
		3.1.3 Installation environment 3.2.3 Installation environment **Chapter 8** Add object dictionaries such as 605B, 605C, 605E, 60FF, and 6502; Add historical maximum values of bus voltage 201E-41 and 201E-42 average historical maximum values of power; Modify 6040 and 605A object ordinary Modify 2002-01 default value **Chapter 10** 10.2 Add Er.19 Software overcurrent	
April 2025	V3.2	**Chapter 7** Delete Section 7.8.3 "Related Function Settings". Delete the object dictionary entry for position calculation method at [60E6]. **Chapter 8** Add the following object dictionary entries: [P01-20], [P06-34], [P05-23], [P05-24], [P05-25], [P05-26], and [60FE]. Add the following monitoring variables: [U2-12], [U2-13], [U2-14], [U2-15], and [U2-16]. Modify the range of [P10-06].	★ VD3E-0☐☐SA1G model ★ VD3E-0☐☐TA1G model

Content

Chapter 1 Safety

1.1 Safety Precautions

This section describes the important items that users must observe, such as product confirmation, storage, transportation, installation, wiring, operation, inspection, and disposal. Please follow the steps required by this manual for trial operation.

Dangerous

◆After the power is turned off for more than 5 minutes and the power indicator is off, use a multimeter to confirm that the voltage across the high-voltage capacitor has dropped to a safe voltage, and then proceed with the disassembly and assembly of the drive, otherwise the residual voltage may cause electric shock.

◆Please never touch the inside of the servo drive, otherwise it may cause electric shock.

◆Please insulate the connection part of the power terminal, otherwise it may cause electric shock.

◆The grounding terminal of the servo drive must be grounded, otherwise it may cause electric shock.

◆Please install the servo drive, servo motor, and external braking resistor on non-combustible materials, otherwise it may cause a fire.

◆Be sure to connect an electromagnetic contactor and a non-fuse circuit breaker between the power supply and the main circuit power supply of the servo drive. Otherwise, when the equipment fails, it may cause fire because it cannot cut off the large current.

◆In the servo drive and servo motor, please do not mix with oil, grease and other flammable foreign objects and screws, metal pieces and other conductive foreign objects, otherwise it may cause a fire.

◆When the servo motor is connected to the machine, in case of any error in operation, it will not only cause damage to the machine, but also sometimes cause personal safety accidents.

◆Do not damage or pull the cable forcefully, do not impose excessive force on the cable, or place heavy objects underneath, otherwise electric shock may occur, causing the product to stop operating or burn out.

◆Do not use the brake of the brake motor for normal braking, otherwise it may cause a malfunction.

◆Except for the designated operator, please do not set up, disassemble and repair the equipment, otherwise it may cause electric shock or injury.

◆Do not remove the cover, cables, connectors and optional accessories while the power is on, otherwise it may cause electric shock.

◆Please install a stop device on the machine side to ensure safety.

◆Please take measures to ensure that your personal safety will not be endangered when restarting, otherwise it may cause injury.

◆Do not modify this product, otherwise it may cause personal injury or mechanical damage.

1.2 Precautions for Storage and Transportation

Notice

Please keep and install the product in the following environment:
◆Places without direct sunlight;
◆Places where the ambient temperature does not exceed product specifications;
◆Places where the relative humidity does not exceed product specifications;
◆Places where condensation will not occur due to rapid changes in temperature;
◆Places free of corrosive gas and flammable gas;
◆Places without combustible materials nearby;
◆Places with less dust, salt and metal powder;
◆Places where there is no splash of water, oil, medicine, etc.;
◆Places where vibration or shock will not affect the product (places that exceed product specifications);
◆Places that will not be exposed to radiation;

Storage or installation in environments other than the above may cause product failure or damage:
◆Please use the correct method for handling according to the weight of the product;
◆Do not hold the motor cable or motor shaft for transportation;
◆When operating the servo unit and servo motor, please pay attention to sharp parts such as the corners of the device.

1.3 Precautions During Installation

Notice

◆Do not install this product in a p2lace free from water splashed or in an environment prone to corrosion;
◆Please be sure to comply with the device installation direction, otherwise it may cause device failure;
◆When installing, please make sure to keep the specified distance between the servo drive and the inner surface of the electric cabinet and other machines, otherwise it may cause fire or device failure;
◆Do not apply excessive impact, otherwise it may cause equipment failure;
◆Do not sit on the product or place heavy objects on it, otherwise it may cause personal injury;
◆Do not use this product near flammable gases and combustibles, otherwise there may be a risk of electric shock or fire;
◆Do not block the suction and exhaust ports, and do not allow foreign objects to enter the product, otherwise it may cause device failure or fire due to the aging of internal components.

1.4 Precautions During Wiring

⚠ Notice
◆Do not connect the three-phase power supply to the output terminals U, V, W of the servo drive, otherwise it may damage the device or cause a fire; ◆Please connect the output U, V, W of the servo drive and the U, V, W of the servo motor directly. Do not use the electromagnetic contactor during the connection, otherwise it may cause abnormal operation or malfunction of the device; ◆When the DO output terminals are connected to the relay, please pay attention to the polarity of the freewheeling diode, otherwise the drive may be damaged and the signal can not be output normally; ◆Please fix the power terminal and the motor terminal firmly, otherwise it may cause a fire hazard; ◆Do not connect the 220V servo unit directly to the 380V power supply; ◆Do not pass the power line and signal line through the same pipe or bundle them together. When wiring, the power line and signal line should be placed at an interval of more than 30cm; ◆Use twisted-pair shielded cables for signal cables and encoder cables, and the shielding layer should be grounded at both ends; ◆The wiring length of the signal input line is recommended to be within 3M, and the wiring length of the encoder is recommended to be within 15M; ◆When using in the following places, please take adequate shielding measures. ■ When interference occurs due to static electricity. ■ Places where strong electric or magnetic fields are generated; ■ Places where there may be radiation; ◆When checking the status, please make sure that the CHARGE indicator is off.

1.5 Precautions During Operation

Notice
◆During trial operation, in order to prevent accidents, please run the servo motor without load (not connected to the drive shaft), otherwise it may cause injury. ◆When the servo motor is running, do not touch its rotating parts, otherwise it may cause injury. ◆Be sure to set the correct rotational inertia ratio, otherwise it may cause vibration. ◆When it is installed on the supporting machine and starts to run, please set the user parameters in accordance with the machine in advance. If the operation is started without parameter setting, the machine may lose control or fail. ◆When installing on the supporting machinery and starting to run, please put the servo motor in a state where it can be stopped in an emergency at any time, otherwise you may get injured. ◆When using a servo motor on a vertical axis, please install a safety device to prevent the workpiece from falling under states such as alarm and overrun. In addition, please perform servo lock stop setting when overrun occurs, otherwise the workpiece may fall in overrun status. ◆Since extreme user parameter adjustments and setting changes will cause the servo system to become unstable, please never make settings, otherwise it may cause injury. ◆When an alarm occurs, reset the alarm after removing the cause and ensuring safety, and restart the operation, otherwise it may cause injury. ◆Except for special purposes, do not change the maximum speed threshold (P01-10). If user change it carelessly, it may damage the machine or cause injury. ◆When the power is turned on and within a period of time after the power is cut off, the cooling fin of the servo drive, the external braking resistor, the servo motor, etc. may be exposed to high temperature. Please do not touch it, otherwise it may cause burns. ◆If the power supply is restored after an instantaneous power failure occurs during operation, the machine may restart suddenly, so please do not stay close to the machine, and press the stop button when the power is off, and operate after the power supply is stable.

1.6 Precautions During Maintenance and Inspection

Notice
◆The power on and off operations should be carried out by professional operators. ◆When testing the insulation resistance of the drive, please cut off all the connections with the drive first, otherwise it may cause the drive to malfunction. ◆Do not use gasoline, alcohol, acid and alkaline detergents to avoid discoloration or damage to the casing. ◆When replacing the servo drive, please transfer the user parameters of the servo drive to be replaced to the new servo drive before restarting operation, otherwise the machine may be damaged. ◆Do not change the wiring when the power is on, otherwise it may cause electric shock or injury. ◆Do not disassemble the servo motor, otherwise it may cause electric shock or injury.

1.7 Leakage protection and circuit breaker recommendations

Servo Drive			Recommended circuit breaker		
Voltage level	Drive model	Rated input current IN(A)	Manufacturer	Current (A)	Model
VD3E-0xxSA1G					
Single-phase 220V	VD3E-003SA1G	0.9	Schneider	2	OSMC32N2D2
	VD3E-010SA1G	3.61		6	OSMC32N2D6
	VD3E-014SA1G	6.76		16	OSMC32N2D16
	VD3E-016SA1G	16.23		25	OSMC32N2D25
	VD3E-021SA1G	19.84		32	OSMC32N2D32
Three-phase 220V	VD3E-016SA1G	9.37		16	OSMC32N3D16
	VD3E-021SA1G	11.46		20	OSMC32N3D20
	VD3E-025SA1G	13.54		25	OSMC32N3D25
	VD3E-030SA1G	15.62		25	OSMC32N3D25
VD3E-0xxTA1G					
Three-phase 380V	VD3E-016TA1G	9.04	Schneider	16	OSMC32N3D16
	VD3E-019TA1G		Schneider	19	OSMC32N3D16
	VD3E-021TA1G		Schneider	21	OSMC32N3D16
	VD3E-030TA1G		Schneider	30	OSMC32N3D16
	VD3E-040TA1G		Schneider	40	OSMC32N3D16
	VD3E-050TA1G		Schneider	50	OSMC32N3D16

Notice

If a residual current operated protective device(RCD) is to be used for device, please conform the following conditions for selection:

Drive device can generate DC leakage current in protective conductors, be sure to use B type Residual Current Action Protection Device(RCD);

When the driver is running, a certain high-frequency leakage current will be generated. In order to avoid RCD malfunctioning, select not less than100mA of operating current RCD for each drive;

When multiple drives are connected in parallel sharing oneRCD, the operating current should be selected not less than300mAofRCD;

Please do not change the wiring when the power is on, otherwise it may lead to electric shock or injury;

Recommend Chint and Schneider RCD.

Chapter 2 Product Information

2.1 Servo Drives

2.1.1 Servo Drive Model Naming

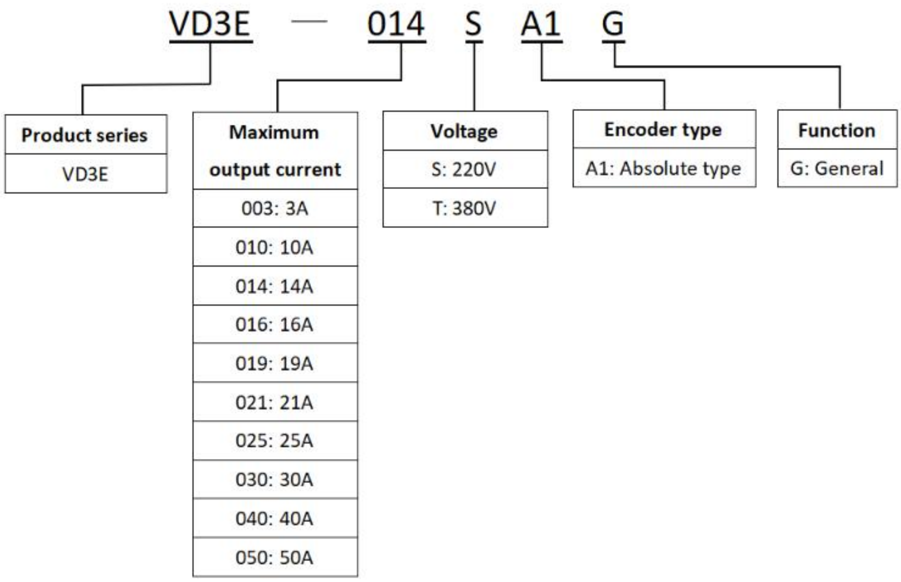


Figure 2-1 Servo drive model

Wecon VD3E series bus servo drive nameplate and appearance are shown in Figure 2-2 and Figure 2-3

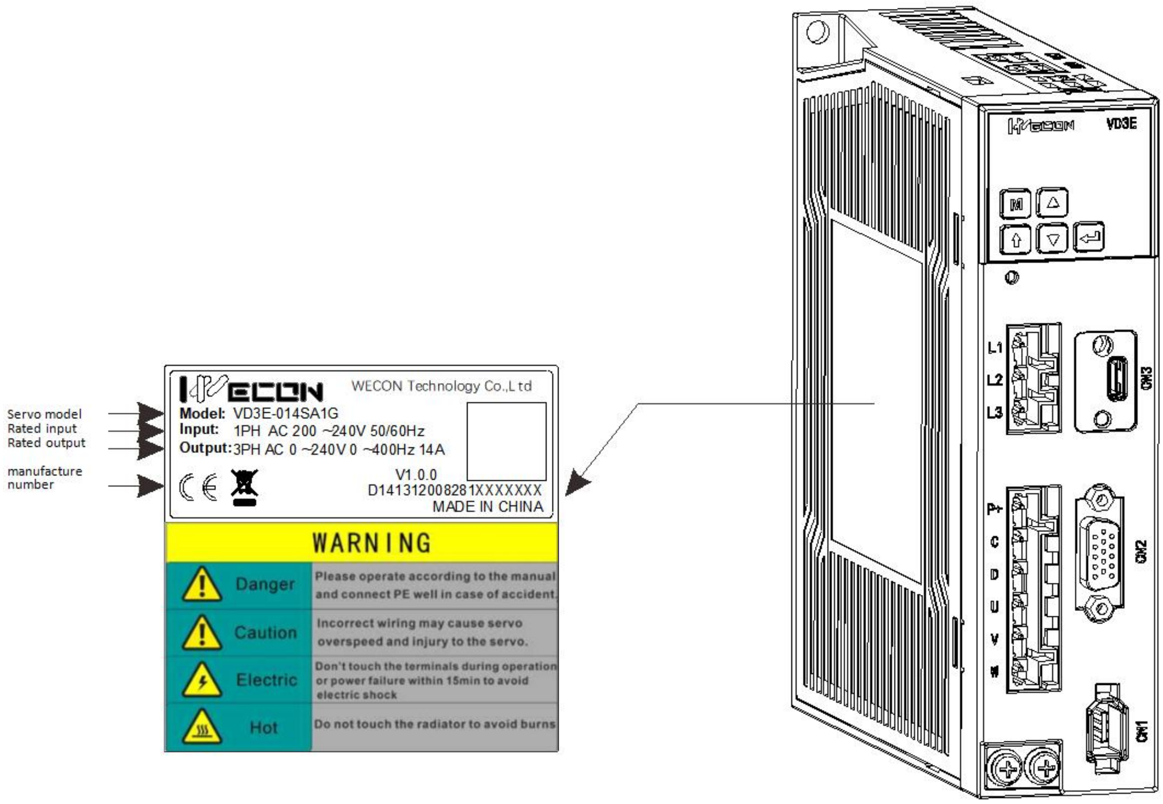


Figure 2-2 Type A servo drive nameplate and appearance

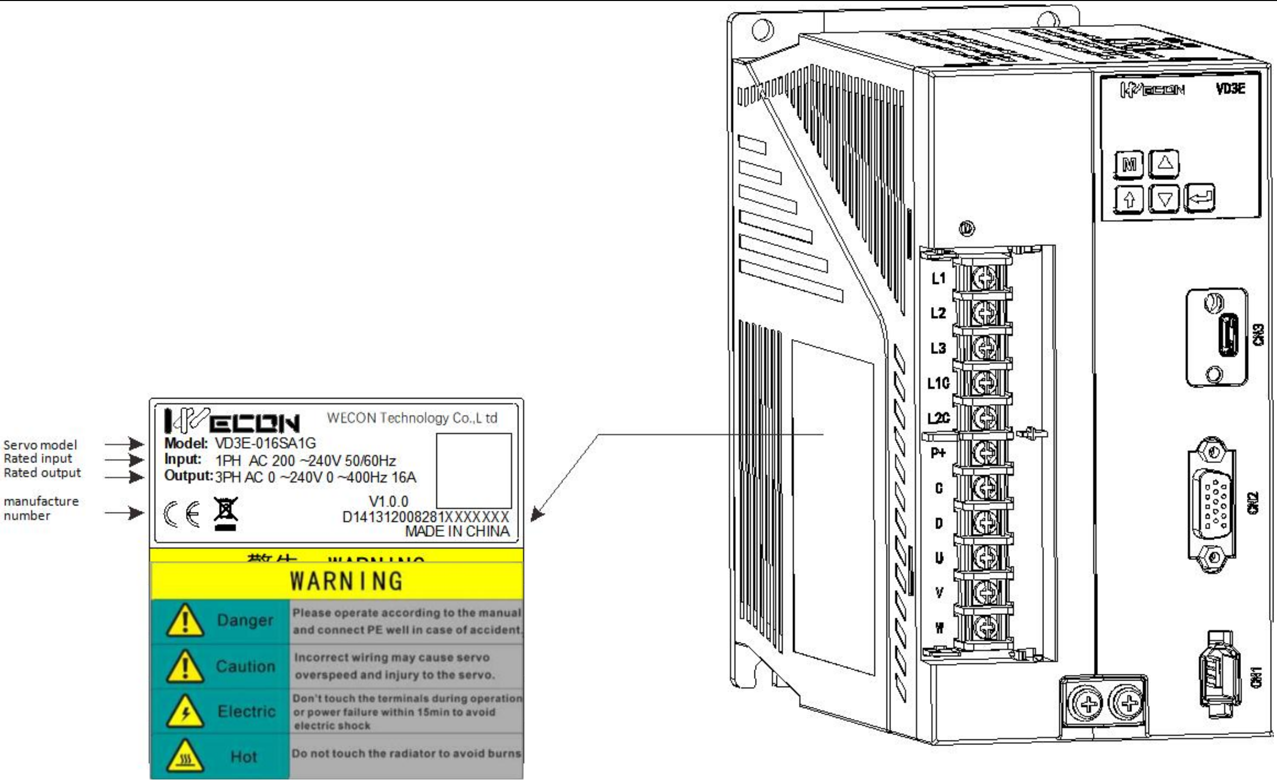


Figure 2- 3Type B servo drive nameplate and appearance

The 220V power supply specification and the 380V power supply specification of the VD3E B-type driver are identical in appearance. For the composition diagram of the VD3E driver, please refer to Figures 2-5 and 2-6.

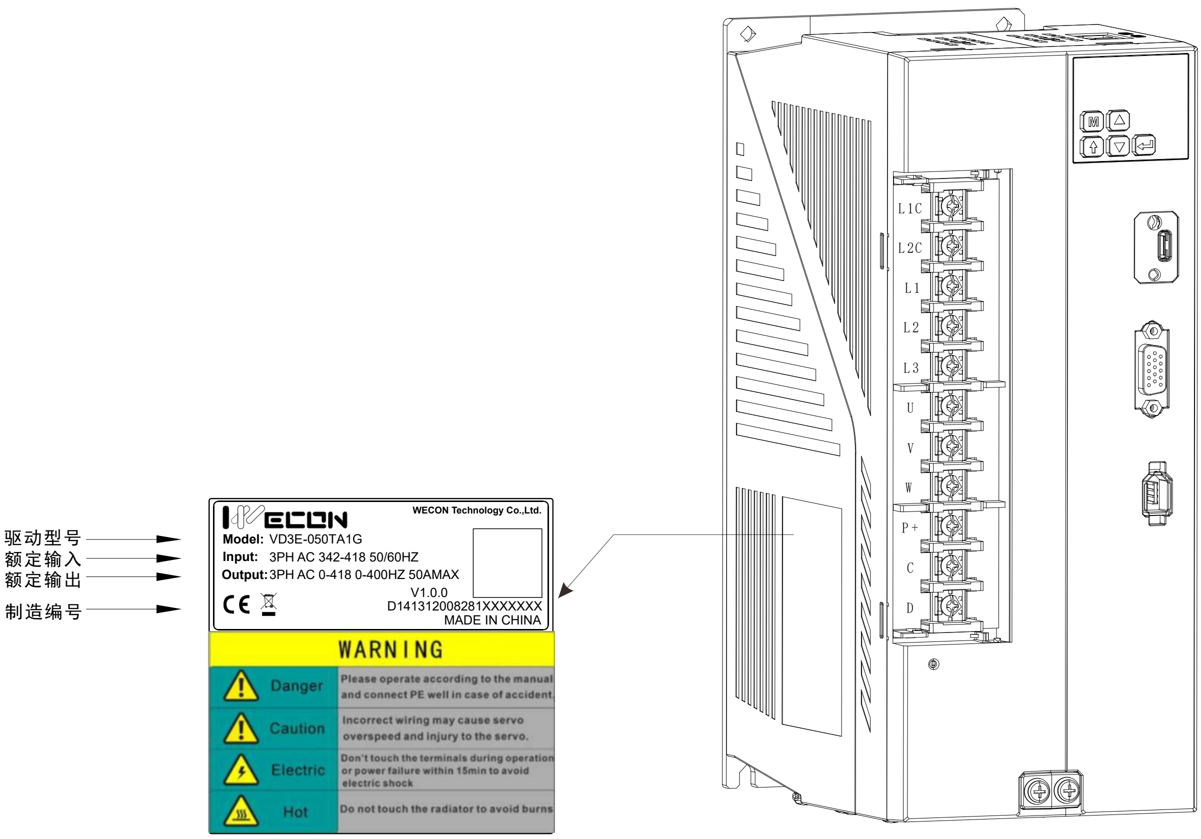


Figure 2- 4 Type C servo drive nameplate and appearance

2.1.2 The composition of servo Drive

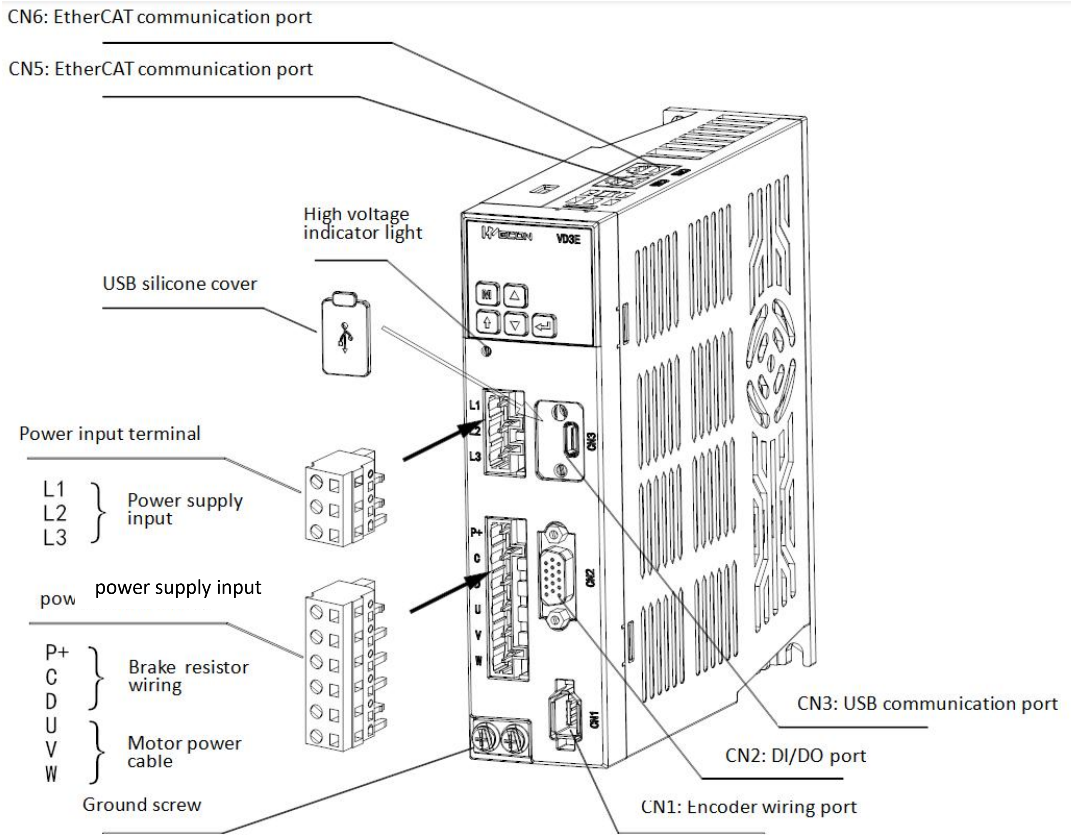


Figure 2-5 Composition of VD3E type A servo drive

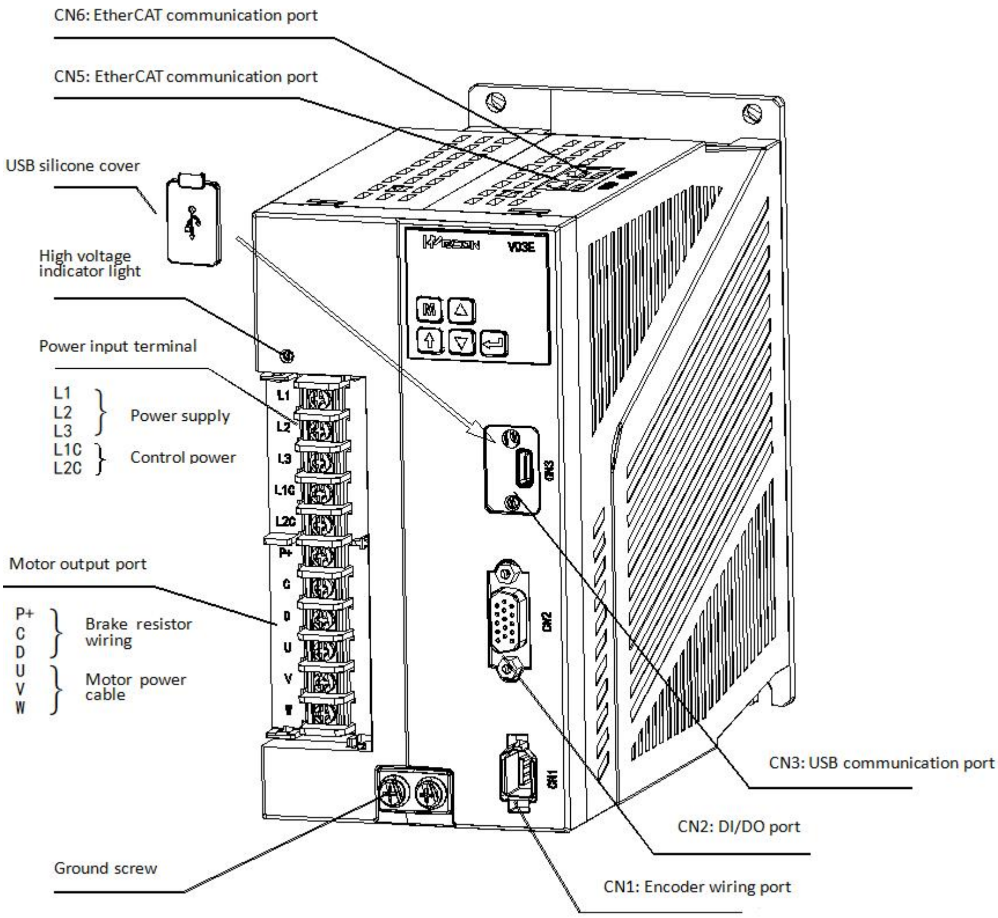


Figure 2-6 Composition of VD3E type B servo drive

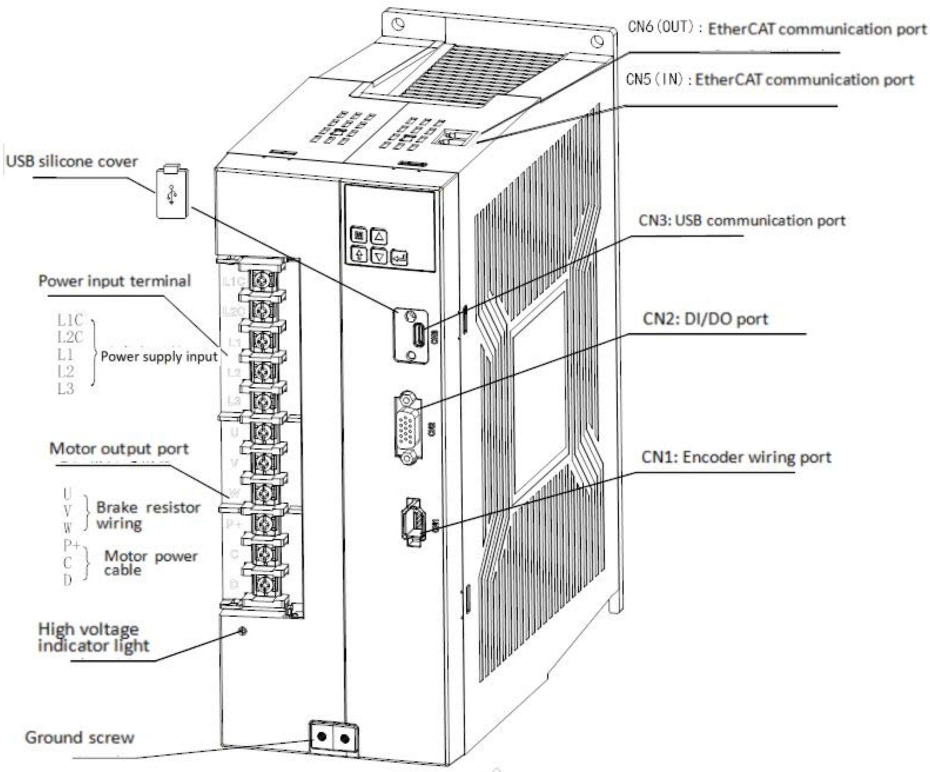


Figure 2-7 Composition of VD3E type C servo

Remarks: When using external braking resistor or internal braking resistor, special short-circuit treatment is required, which is shown in Figure 2-6.

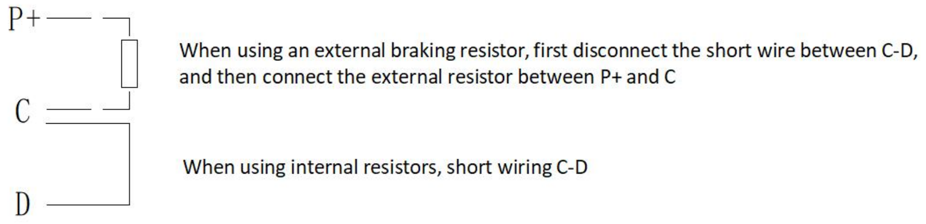


Figure 2-8 Short circuit schematic diagram of braking resistance

2.1.3 Specification of servo Drive

(1) Electrical specification

Table 2-1 Electrical specification for single-phase 220V class servo drives

Item	VD3E Type A			VD3E Type B	
Model	VD3E-003SA1G	VD3E-010SA1G	VD3E-014SA1G	VD3E-016SA1G	VD3E-019SA1G
Maximum output current	3A	10A	14A	16A	19A
Control power supply	-			Single-phase AC 200V ~ 240V 50/60 Hz	
Power supply	Single-phase AC 200V to 240V 50/60 Hz				
Braking resistor	Support external		Support built-in and external	Support built-in and external	

Table 2-2 Electrical specification for type B servo drives

Item	VD3E Type B		
Model	VD3E-021SA1G	VD3E-025SA1G	VD3E-030SA1G
Maximum output current	21A	25A	30A
Control power supply	Single phaseAC198-242V, 50/60 Hz		
Power supply	Three phaseAC198-242V, 50/60 Hz		
Braking resistor	Support built-in and external connection		

Table 2-3 Electrical Specifications of Three-phase 380V Servo Drive

Project	VD3E Type T		
Model	VD3E-016TA1G	VD3E-019TA1G	VD3E-021TA1G
Maximum output current	16A	19A	21A
Control power supply	Single-phase AC 342 to 440V, 50/60Hz		
Power supply	Three-phase AC 342V to 440V, 50/60Hz		
Braking resistor	Support built-in and external connection		

Table 2-4 Electrical specification for type T servo drives

Project	VD3E Type T		
Model	VD3E-030TA1G	VD3E-040TA1G	VD3E-050TA1G
Maximum output current	30A	40A	50A
Control power supply	Single-phase AC 342V to 440V, 50/60 Hz		
Power supply	Three-phase AC 342V to 440V, 50/60 Hz		
Braking resistor	Support built-in and external connection		

(2) Basic specifications

Project			Description
Environment	Usage	Temperature	0℃ to 40℃
		Humidity	20% to 90%, no condensation
		Shock	3M4, 3mm [2~9Hz], Class 1 area
		Vibration	3M4, 1G [9~200Hz], Class 1 area
	Storage	Temperature	-20℃ to 65℃
		Humidity	20% to 90%, no condensation
		Vibration	2M2, 3.5 mm [2~9Hz]
	Protection level		IP20
	Contamination level		II
	Overvoltage level		III
	Altitude		The highest elevation reaches 2000m. ● No derating is required for use at 1000m and below; ● Each rise above 1000m 100m derating 1%; ● Please contact the manufacturer for over 2000m.
Basic information	Control method		IGBT PWM control, sine wave current drive mode
	Drive model		VD3E-0xxSA1G
	Encoder feedback		17bit absolute value encoder 23bit absolute value encoder
	Operating temperature		0~45℃
	Operating humidity		Below 90% RH (no condensation)
Basic Performance of	Communication protocol		EtherCAT protocol

Project		Description
EtherCAT Slave Station	Support services	CoE
	Synchronization mode	DC
	Physical layer	100BASE-TX
	Baud rate	100Mbit/s
	Duplex mode	Full duplex
	Topological structure	Ring, linear
	Slave station quantity	It is recommended that the actual networking use be lower than 128 units.
	Synchronous jitters	1 µs
EtherCAT Configuration Unit	FMMU unit	8
	Storage synchronization snap-in	8
	Process data RAM	8KB
	Distributed clock	64-bit
	EEPROM capacity	32Kbit
Input and output	Digital input (DI) signal	6-channel DI
	Digital output signal	3-channel DO

(3) Support function

Project		Description
Input and output	Digital input (DI) signal	Servo enable (S-ON), fault and warning clear (A-CLR), forward drive disable (POT), reverse driveMovement prohibition (NOT), deviation counter cleared (CL), emergency shutdown (E-STOP), origin signal (HOMEORG)
	Digital output signal	Servo Ready (RDY), Fault Signal (ALM), Speed Limit (V-LIMIT), Brake Output (BRK-OFF),Warning signal (WARN warning signal), servo on status output (SRV-ST), rotation detection (TGON),CorrespondenceVDO1 output (COM_VDO1), communicationVDO2 output (COM_VDO2), communicationVDO3Output (COM_VDO3), ZSP (zero speed signal), positioning complete (P-COIN), speed approaching (V-NEAR),Torque arrival (T-COIN).
Built-in function	Electronic gear ratio	The range is [0.001×Encoder Resolution/10000, 4000×Encoder Resolution/10000].

Project		Description
	Protective function	Overcurrent protection, overvoltage protection, undervoltage protection, overload protection, main circuit phase loss protection, overtemperature protection, parameter abnormality protection, encoder protection, others.
	LED display function	Panel 5-bit LED
	Others	Gain adjustment, fault and alarm recording, inching operation

2.2 Servo Motors

2.2.1 Servo Motor Model Naming

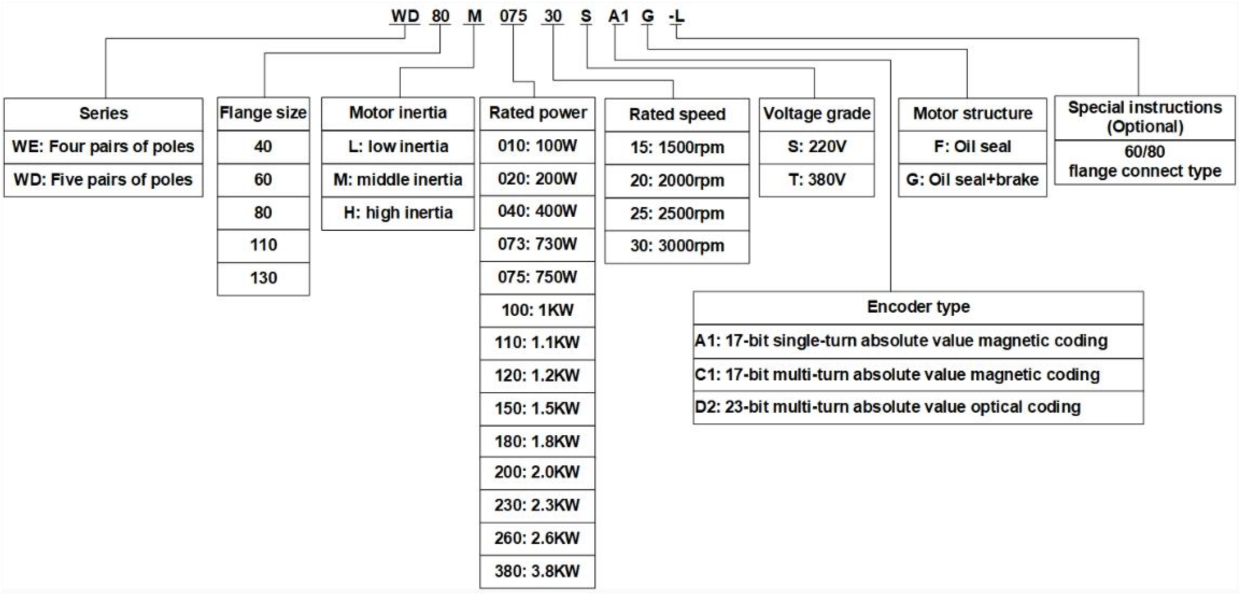


Figure 2-9 Naming of servo motor

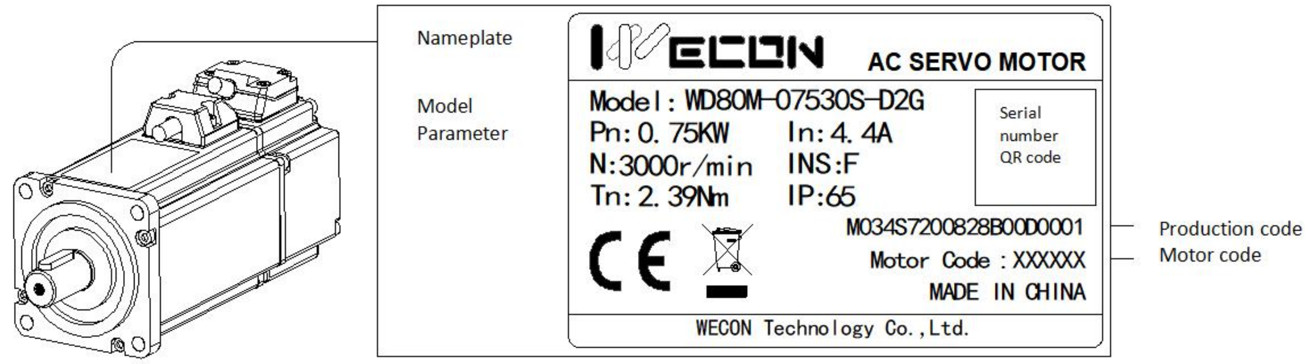


Figure 2-10 Servo motor nameplate

2.2.2 Composition of Servo Motor

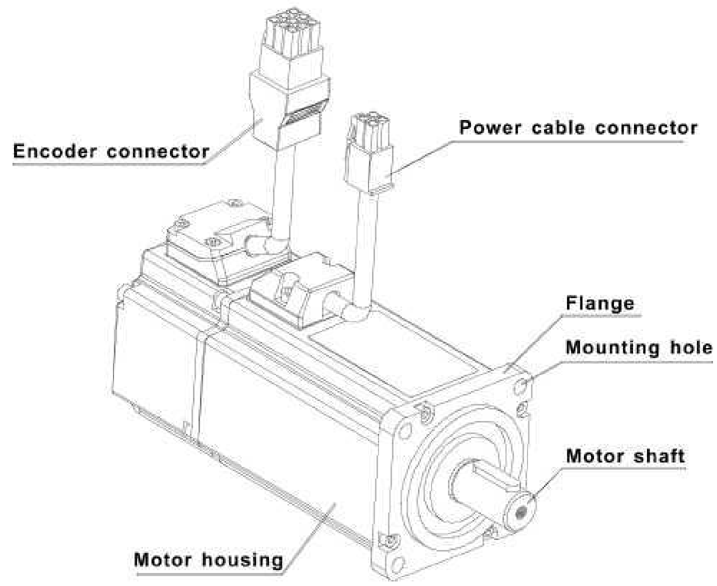


Figure 2-11 Composition of 40/60/80 flange motor

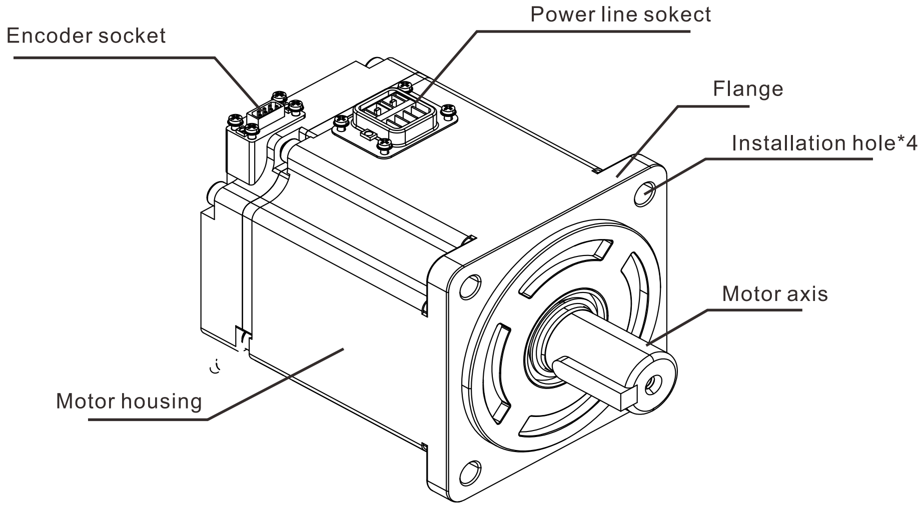


Figure 2-12 Composition of 40/60/80 flange motor

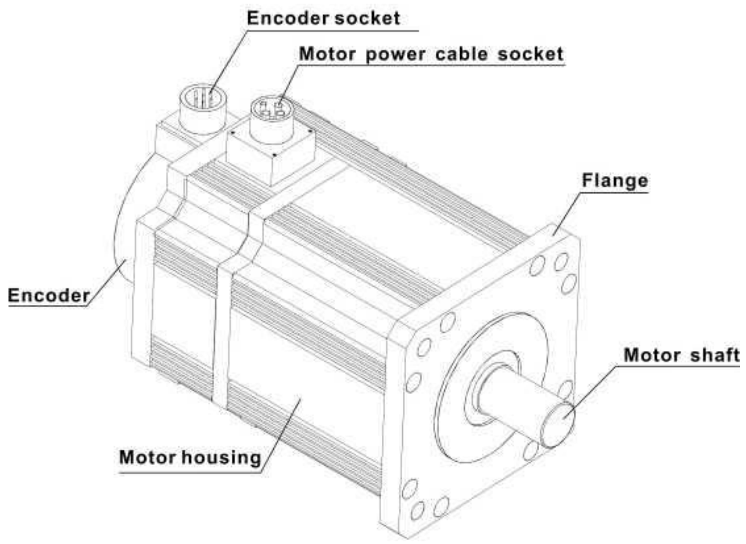


Figure 2-13 Composition of 110/130 flange motor

2.2.3 Specification of servo Motor

Table 2-4 Wecon motor specifications

Wecon motor model	Motor Code	Flange size	Rated power (kW)	Rated torque (N.m)	Voltage (V)	Rated speed (rpm)	Encoder type	Brake function
WE130M-10025S-A1F	A091	130	1.0	4.0	220	2500	17-bit single turn absolute magnetic	Not supported
WE130M-15025S-A1G	A111	130	1.5	6.0	220	2500	17-bit single turn absolute magnetic	Supported
WE130M-26025S-C1F	C191	130	2.6	10	220	2500	17-bit multi turn absolute magnetic	Not supported
WE80M-12030S-C1G	C231	80	1.2	4.0	220	3000	17-bit multi turn absolute magnetic	Supported
WE110M-18030S-D2G	D131	110	1.8	6.0	220	3000	23-bit multi turn absolute optical	Supported
WE130M-23015S-D2F	D161	130	2.3	15.0	220	1500	23-bit multi turn absolute optical	Not supported

✎**Note:** Only part of the motor models is displayed, please refer to [Model Selection Manual] for details.

2.3 Servo System Wiring Diagram

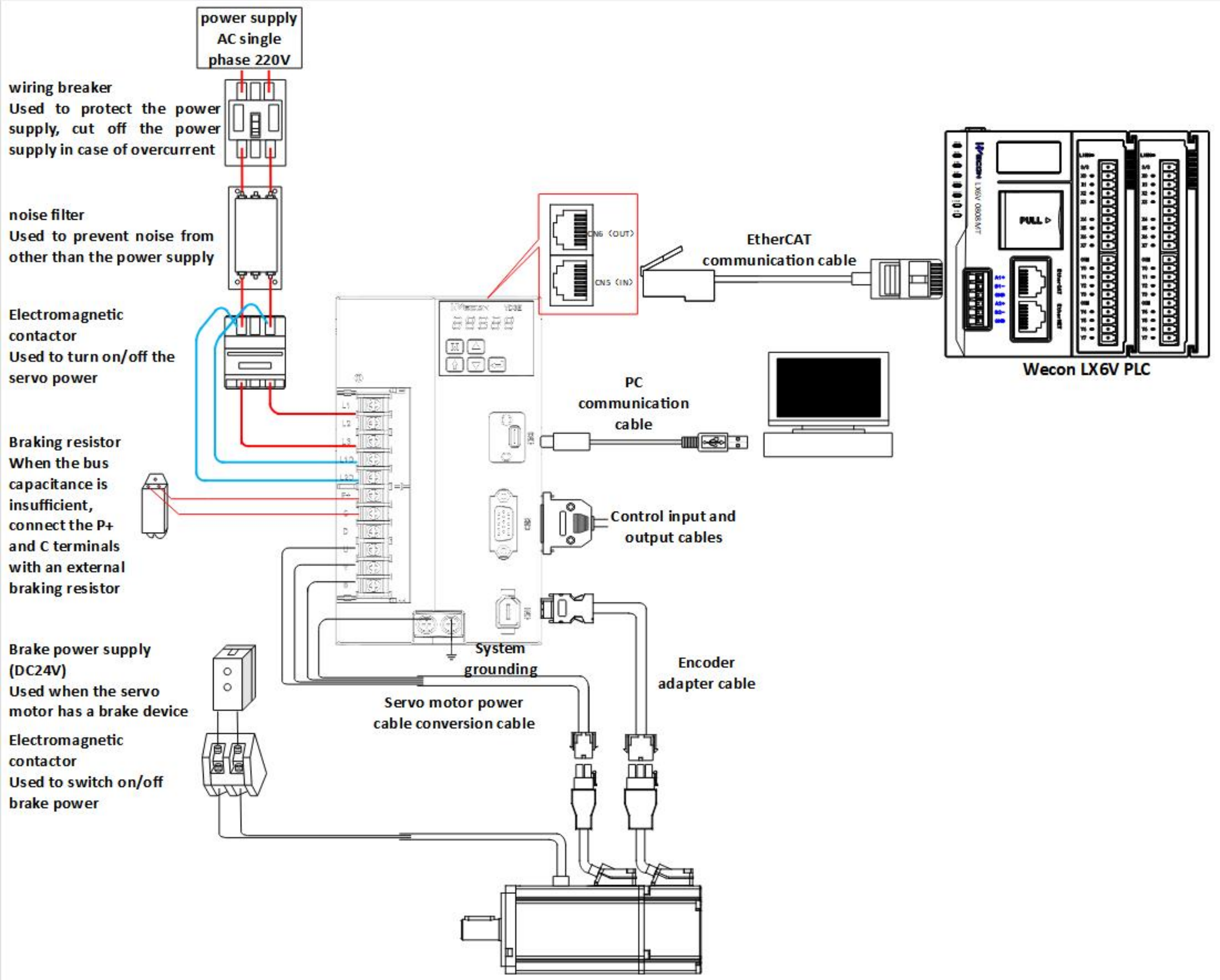


Figure 2-14 Wiring diagram of single-phase 220V servo drive system

Notice
① When using external brake, need to remove the shorting cap or short wiring between terminal C and D of servo drive before operating! ② Pay attention to the power capacity of the brake power supply. When powering multiple brake devices at the same time, if the power supply capacity is insufficient, the brake will fail! ③ It is strictly forbidden to use electromagnetic brake for motor operation and stop operation! Otherwise, the instantaneous high voltage generated by the motor may break down the contactor! ④ In order to prevent cross-shock accidents in the servo system, please use a fuse or a circuit breaker for wiring on the input power supply!

Chapter 3 Installation of Servo Drive and Motor

3.1 Installation of Servo Drive

3.1.1 Dimensions (Unit: mm)

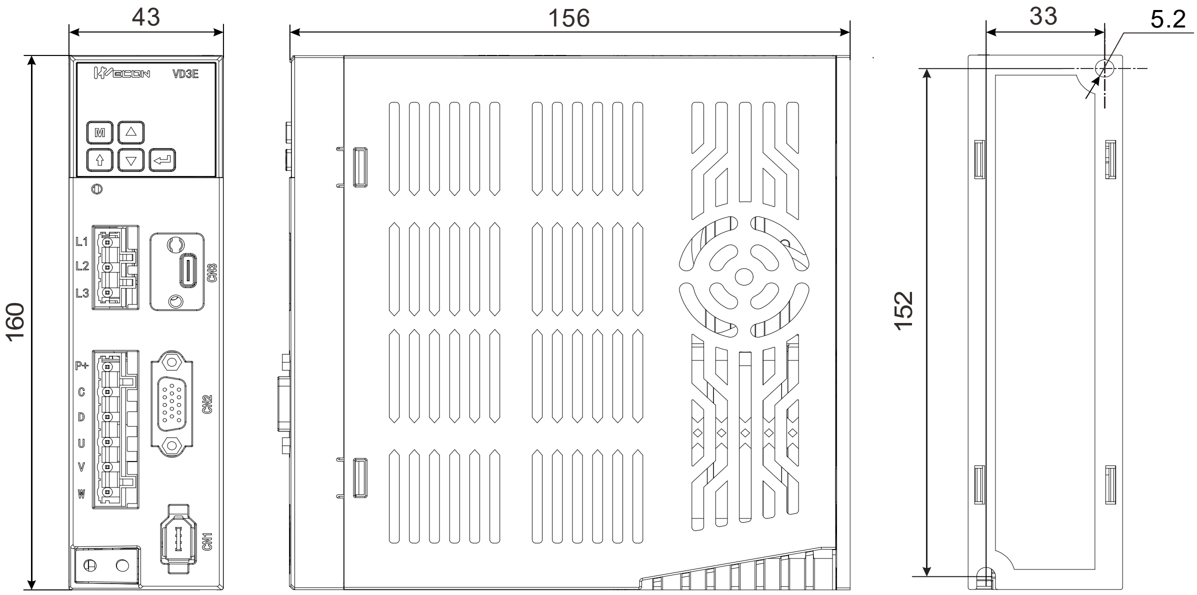


Figure 3-1 Installation Dimensions of VD3E Type A Servo Drive

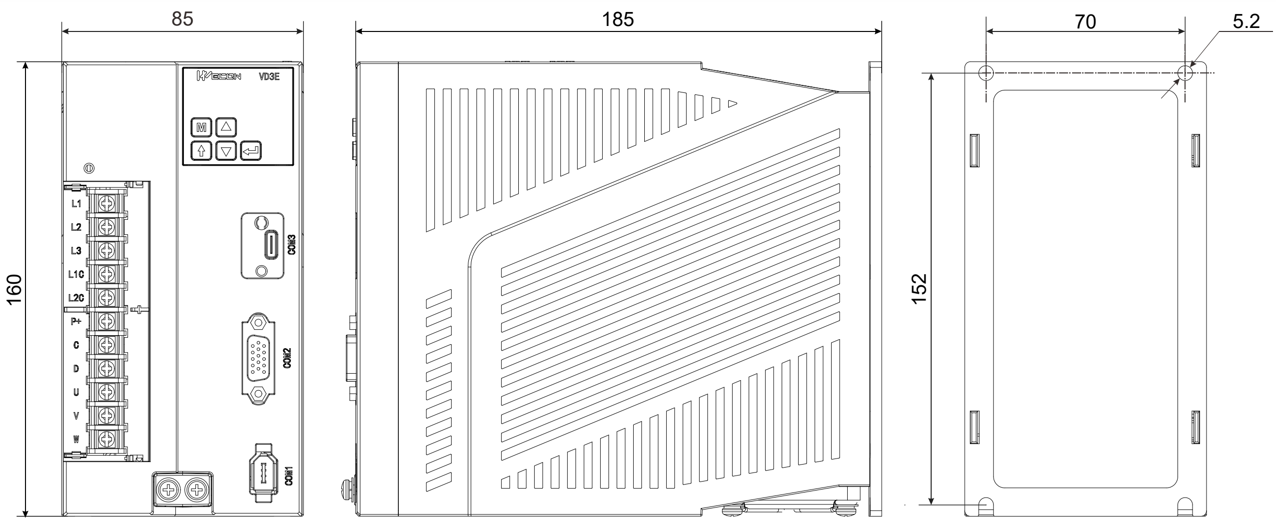


Figure 3-2 Installation Dimensions of VD3E Type B Servo drive

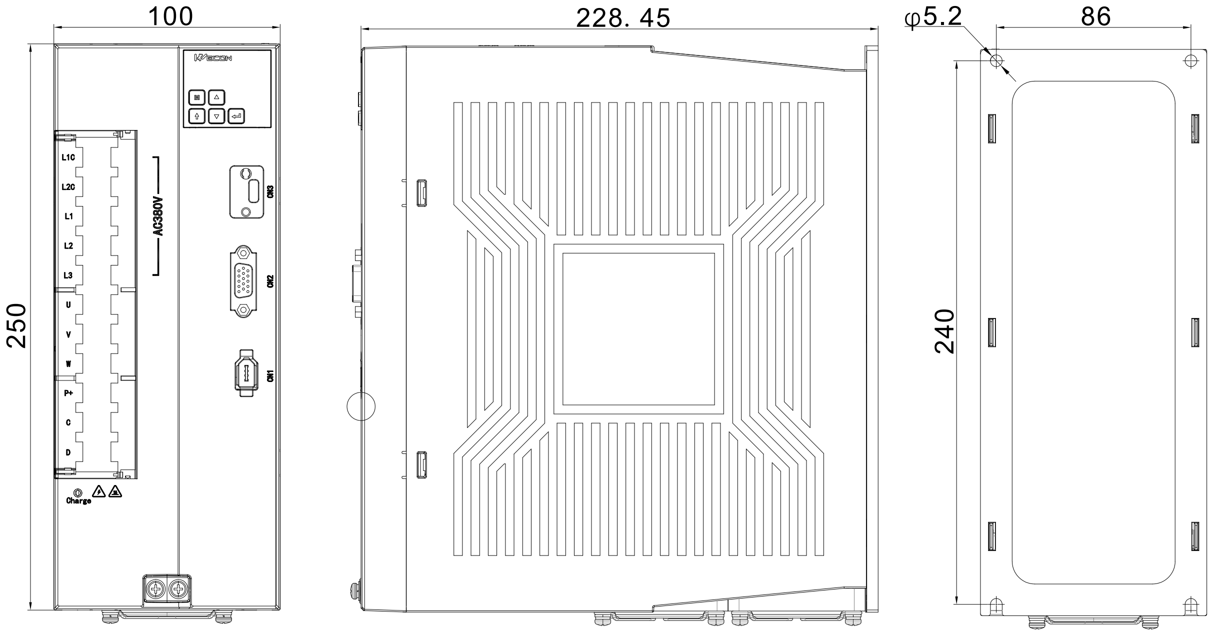


Figure 3-3 Installation Dimensions of VD3E Type C Servo Drive

3.1.2 Installation site

①Please install the device in an installation cabinet free from sunlight and rain;
②In a place without vibration;
③Please do not install in the environment exposed to high temperature, humidity, dust and metal dust;
④Do not use this product near corrosive and flammable gases such as hydrogen sulfide, chlorine, ammonia, sulfur, chlorinated gas, acid, alkali, salt or combustible materials.

3.1.3 Installation Environment

The installation environment of the servo drive has a direct impact on the normal function of it and its service life. Therefore, the installation environment of servo drive must meet the following conditions:

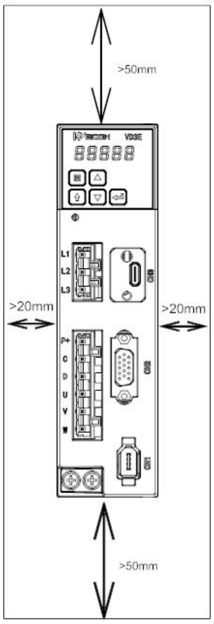
Project	Specifications
Ambient temperature	0℃~40℃ (not freezing)
Ambient humidity	20%-90% RH (No condensation)
Storage temperature	-20℃-65℃
Storage humidity	20%-90% RH (No condensation)
Protection level	IP20
Contamination level	II
Overvoltage level	III
Altitude	The highest elevation reaches 2000m. ● No derating is required for use at 1000m and below; ● Each rise above 1000m100m derating1%; ● Please contact the manufacturer for over 2000m.
Vibration	Less than 0.5G (4.9m/s2), 10-60Hz (discontinuous operation)
Power Systems	TN system*

✎**Note:** The neutral point of the power system is directly connected to the ground, and the exposed metal objects are connected to the ground via protective ground conductors.

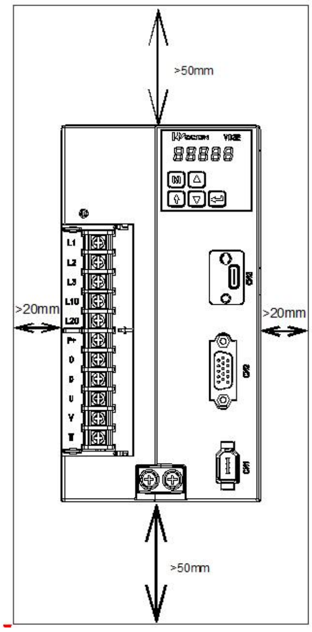
3.1.4 Installation Precautions

(1) Installation specifications

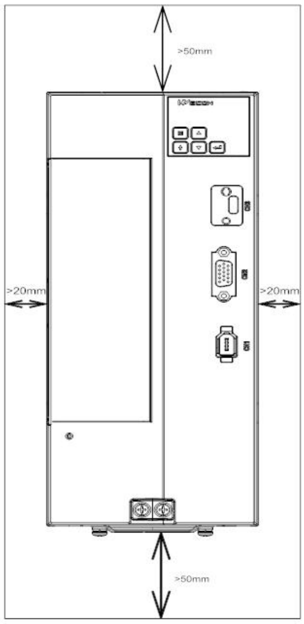
In order to achieve a good cooling cycle effect, ensure that there is enough ventilation space around it when installing the servo drive, and be sure to comply with the installation standards in the control cabinet shown in the figure below, otherwise it may cause the drive to malfunction. See Figure for typical minimum installation dimensions3-4.



(a)VD3E Type A driver



(b) VD3E Type B driver



(c) VD3E Type C driver

Figure 3-4 Minimum installation dimensions

(2) Parallel installation

When multiple units are installed in parallel, the minimum distance between each other should be 20mm, and the distance between each other in vertical dimension should be at least 100mm. Please refer to Figure 3-5 and Figure 3-6 for details. To prevent temperature rise, a cooling fan can be placed on the upper part. For smaller spacing installation, please consult Wecon.

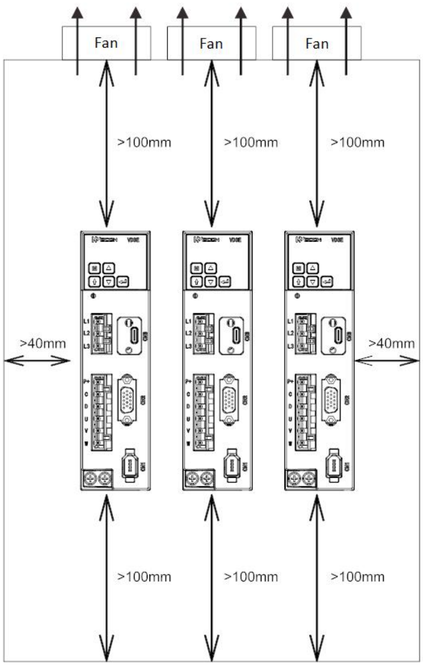


Figure 3-5 Parallel installation dimensions of multiple type A drives

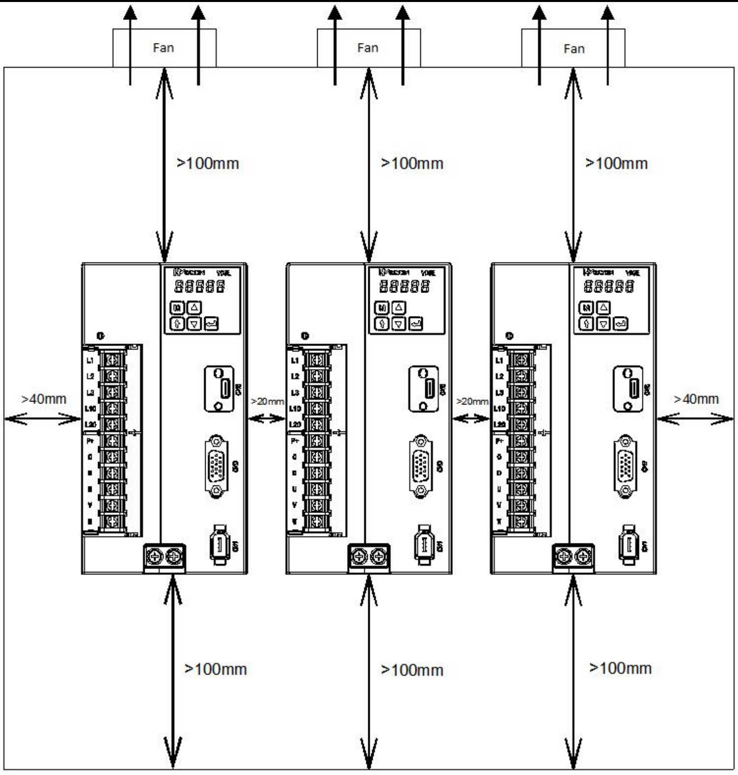


Figure 3-6 Parallel installation dimensions of multiple type B drives

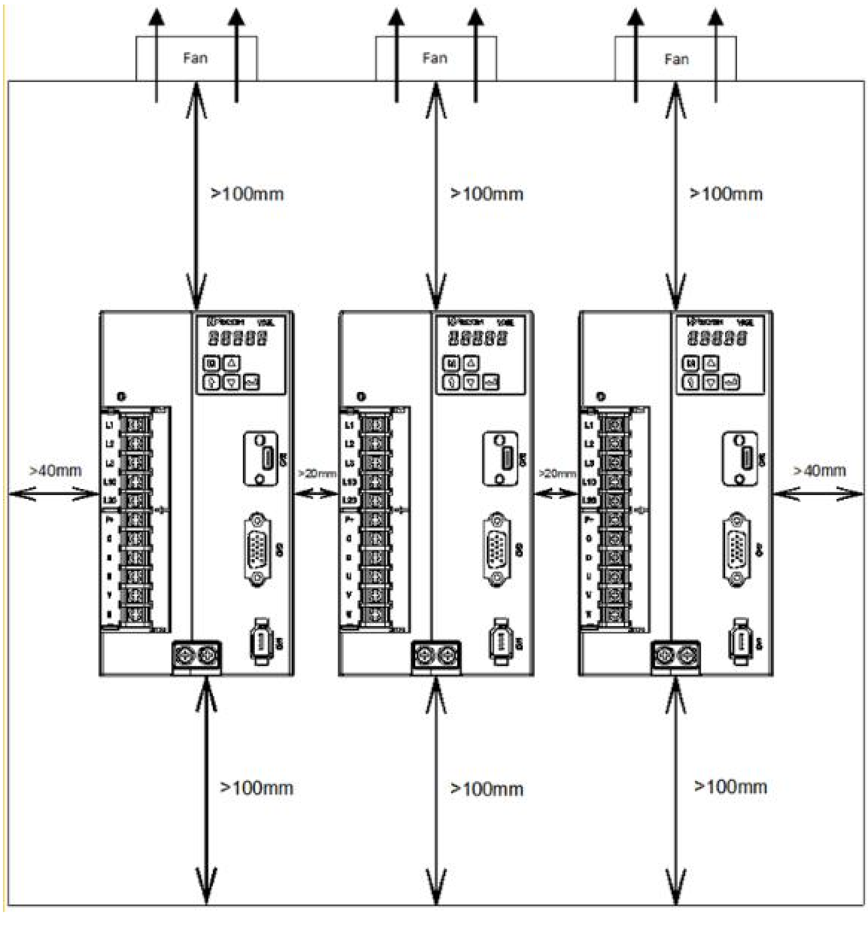


Figure 3-7 Parallel installation dimensions of multiple type B drives

(3) Installation direction

When installing the servo drive, face the front (panel interface) of the servo drive to the operator so that the servo drive is perpendicular to the wall.

3.2 Installation of Servo Motor

3.2.1 Dimensions (unit: mm)

(1) Installation dimensions of WD series 40 flange servo motor

Specification	WD series 40 flange motor
Rated torque (N.m)	0.318
LA without brake (mm)	74.8
LA with brake (mm)	108

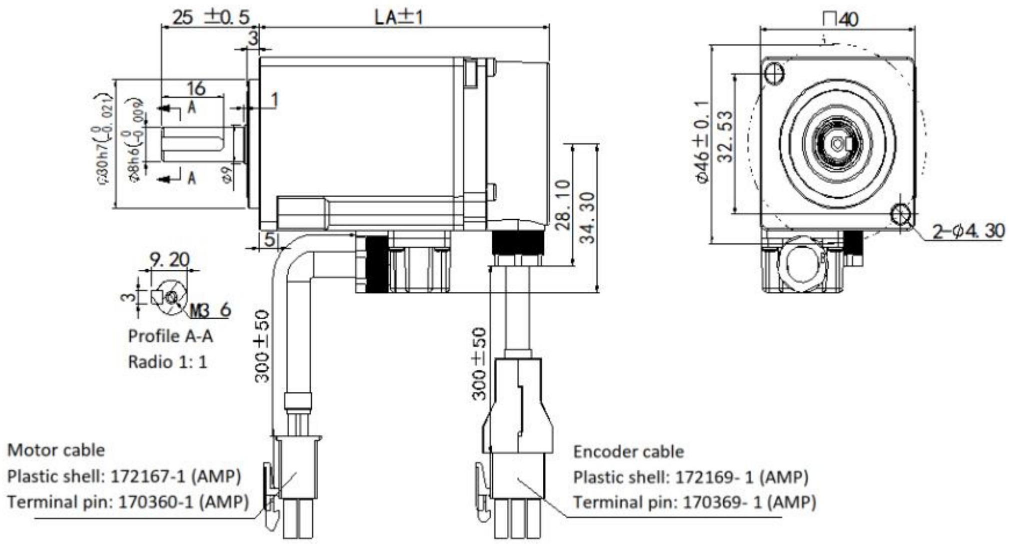


Figure 3-8 WD series 40 flange servo motor installation dimension drawing

(2) Installation dimensions of 60 flange servo motor

Specification	WD series 60 flange motor	
Rated torque (N.m)	0.64	1.27
LA without brake (mm)	75	92
LA with brake (mm)	104.5	121.5

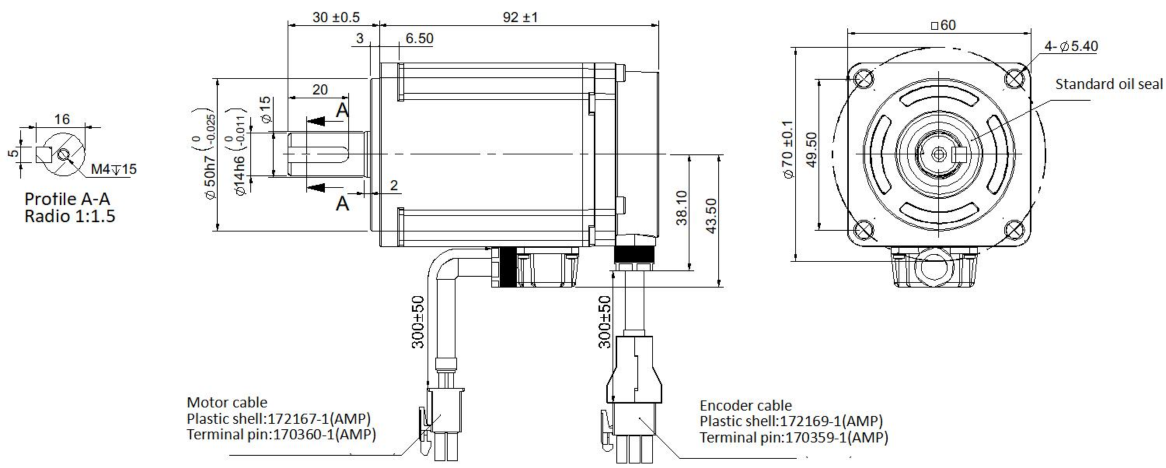


Figure 3-9 Installation dimension drawing of WD series 60 flange servo motor

(3) Installation dimensions of 80 flange servo motor

①WD series motor

Specification	WE series 80 flange motor
Rated torque (N.m)	2.39
LA without brake (mm)	98.5
LA with brake (mm)	132.5

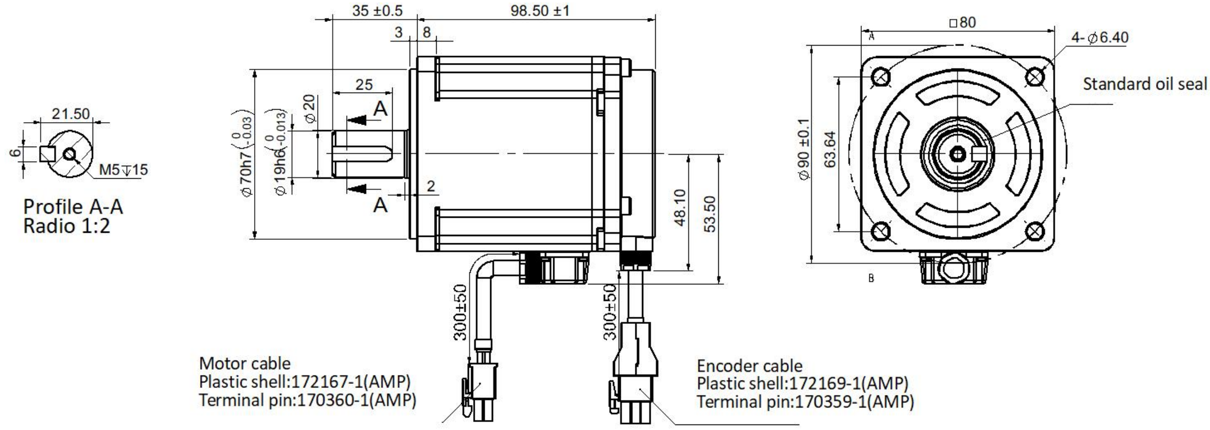


Figure 3-10 Installation dimension drawing of WD series 80 flange servo motor

②WE series motor

Specification	WE series 80 flange motor	
Rated torque (N.m)	3.5	4.0
LA without brake (mm)	179	191
LA with brake (mm)	221	233

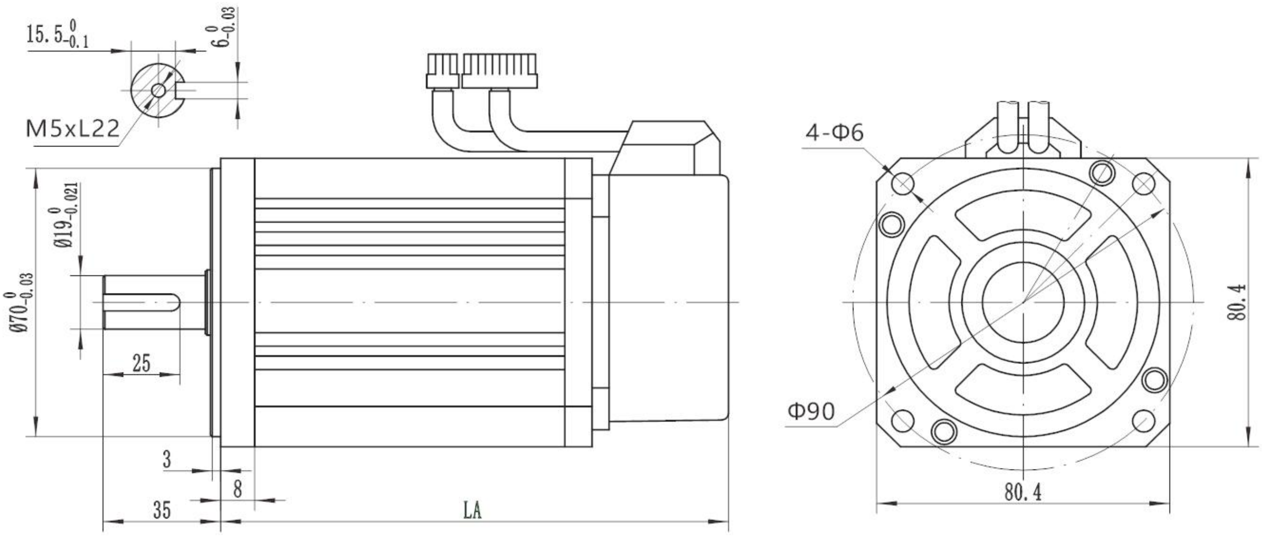


Figure 3-11 Installation dimension drawing of WE series 80 flange servo motor

(4) Installation dimensions of WE series 110 flange servo motor

Specification	WE series 110 flange motor		
Rated torque (N.m)	4	5	6
LA without brake (mm)	189	204	219
LA with brake (mm)	254	269	284

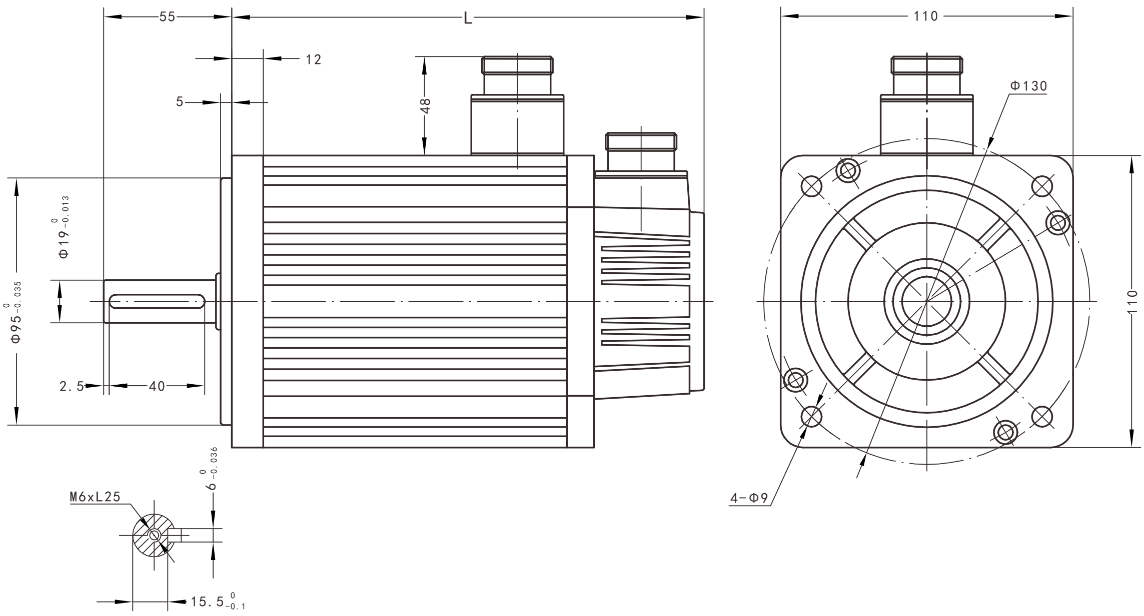


Figure 3-12 Installation dimensions of WE series 110 flange servo motor

(5) Installation dimensions of WE series 130 flange servo motor

Specification	WE series 130 flange motor							
Rated torque (N.m)	4	5	6	7.7	10		15	
					1500rpm	2500rpm	1500rpm	2500rpm
LA without brake (mm)	166	171	179	192	213	209	241	231
LA with brake (mm)	226	231	239	252	276	276	304	294

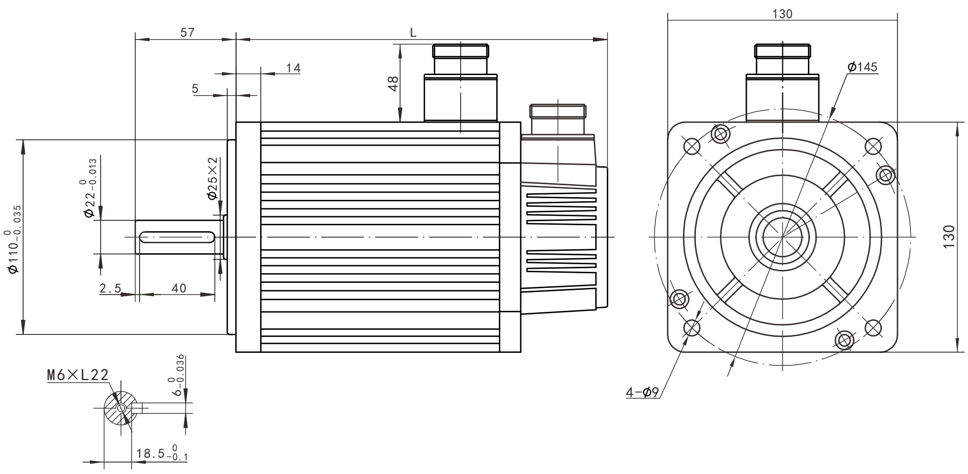


Figure 3-13 Installation dimension drawing of WE series 130 flange servo motor

(6) Installation dimensions of WE series 180 flange servo motor

Specification	WE series 180 flange motor					
Rated torque (N.m)	17	19	21.5	27	35	48
LA without brake (mm)	226	232	243	262	292	346
LA with brake (mm)	298	304	315	334	364	418

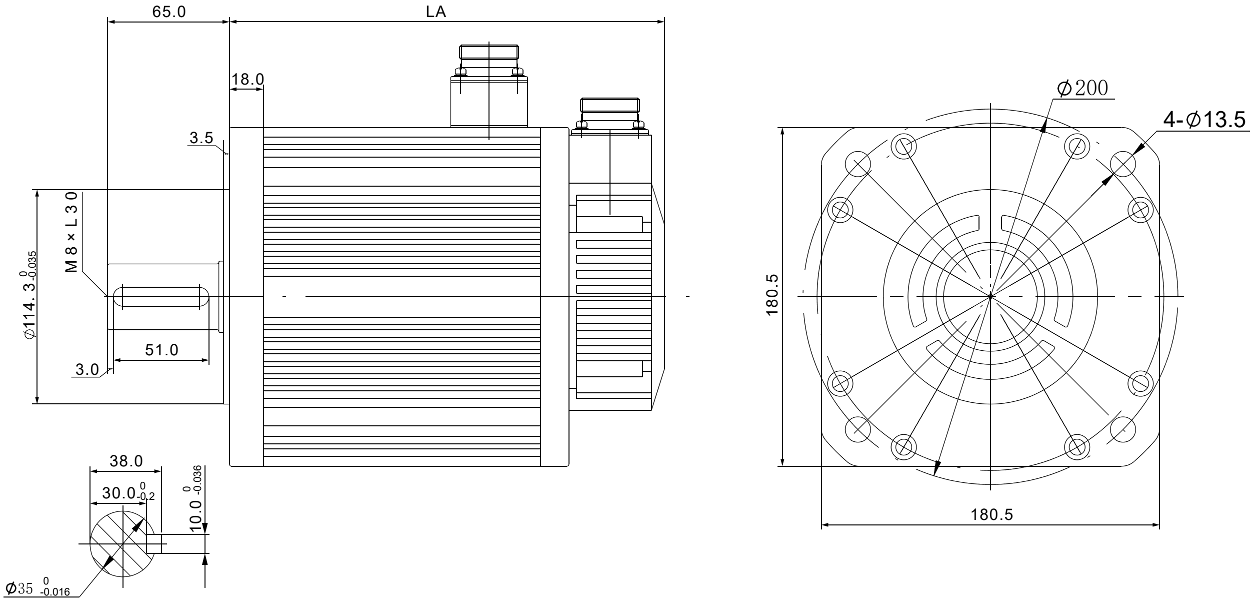


Figure 3-14 Installation dimension drawing of WE series 180 flange servo motor

3.2.2 Installation site

1. Do not use the motor near corrosive, flammable gas environment, combustible materials such as hydrogen sulfide, chlorine, ammonia, sulfur, chlorinated gas, acid, base, salt, etc.
2. Do not remove the oil seal in places where there is grinding fluid, oil mist, iron powder, cutting, etc.
3. Do not use the motor in a closed environment. Closed environment will cause high temperature of the motor and shorten the service life.
4. A place far away from heat sources such as stoves.

3.2.3 Installation Environment

The installation environment of the servo motor has a direct impact on the normal function of it and its service life. Therefore, the installation environment of the servo motor must meet the following conditions:

Project	Specification
Ambient temperature	-10℃ to 40℃ (no freezing)
Ambient humidity	-20% to 90%RH (no condensation)
Storage temperature	-20℃ to 60℃
Storage humidity	-20%~90%RH (no condensation)
Protection level	IP65
Vibration	Less than 0.5G (4.9m/s2), 10~60Hz (non-continuous operation)

3.2.4 Installation precautions

Project	Specification
Rust inhibitor	Before installation, please wipe clean the "anti-rust agent" on the shaft extension end of the servo motor, and then do the relevant anti-rust treatment.
Encoder notice	✎When installing a pulley on a servo motor shaft with a keyway, use a screw hole at the shaft end. In order to install the pulley, first insert the double-headed nail into the screw hole of the shaft, use a washer on the surface of the coupling end, and gradually lock the pulley into the pulley with a nut; ✎For the servo motor shaft with keyway, use the screw hole on the shaft end to install; ✎For shafts without keyway, adopt friction coupling or similar methods ✎When removing the pulley, use a pulley remover to prevent the bearing from being strongly impacted by the load; ✎To ensure safety, install a protective cover or similar device in the rotating area, such as a pulley installed on the shaft.
Centering	When linking with the machine, please use the coupling, and keep the axis of the servo motor and the axis of the machine in a straight line.
Installation direction	The servo motor can be installed horizontally or vertically.
Oil and water countermeasures	When using in a place with dripping water, please use it after confirming the protection level of the servo motor. When using it in a place where oil drips on the shaft penetration part, do not remove the oil seal of the servo motor. The use conditions of the servo motor with oil seal: ✎When using, please make sure the oil level is lower than the lip of the oil seal; ✎The oil seal can be used in a state with a good degree of splashing of oil foam; ✎When the servo motor is installed vertically upwards, please be careful not to accumulate oil on the oil seal lip.
Stress condition of the cable	Do not "bend" the wire or apply "tension" to it, especially the signal wire whose core diameter is 0.2mm or 0.3mm. During the wiring process, please do not make it too tight.
Processing of the connector part	Regarding the connector part, please note the following matters: ✎When connecting the connector, please make sure that there is no foreign matter such as garbage or metal pieces in the connector; ✎When connecting the connector to the servo motor, be sure to connect it from the side of the main circuit cable of the servo motor first, and the grounding of the main line cable must be reliably connected. If you connect one side of the encoder cable first, the encoder may malfunction due to the potential difference between PEs; ✎When connecting, please make sure that the pin arrangement is correct; ✎The connector is made of resin, please do not apply impact to avoid damage to the connector; ✎Do not apply stress to the connector part during handling while the cable is connected. If stress is applied to the connector part, the connector may be damaged.

Chapter 4 Wiring

4.1 Main Circuit Wiring

4.1.1 Main circuit Terminals

(1) Main circuit terminal distribution of VD3E type A servo drive

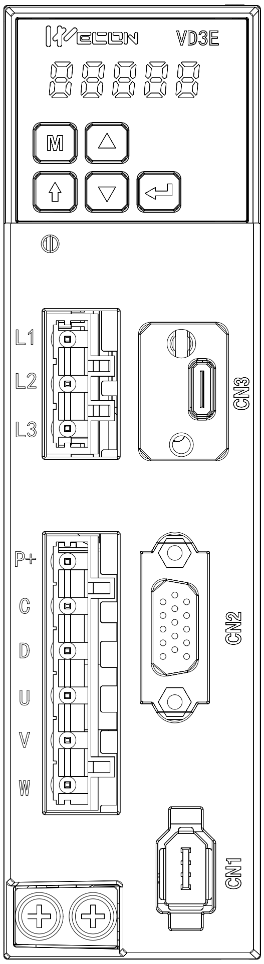


Figure 4-1 VD3E Type A Servo Drive Main Circuit Terminal Schematic

Table 4-1 Name and function of main circuit terminal of VD3E type A servo drive

Terminal number	Terminal name	Terminal function
L1	Power input terminal	Single-phase 220V AC input is connected to L1 and L3.
L2		
L3		
P+	Braking resistor terminal	Use internal braking resistor: short-circuited C-D. Use an external braking resistor: please disconnect the short wire between C-D, and then connect the external braking resistor between P+ and C;
C		
D		
U	Motor power line terminal	Connect with the U, V, W of the motor to supply power to the motor.
V		
W		
Ground terminal	Ground terminal	Grounding of the servo drive.

(2) Main circuit terminal distribution of VD3E type B servo drive (220V)

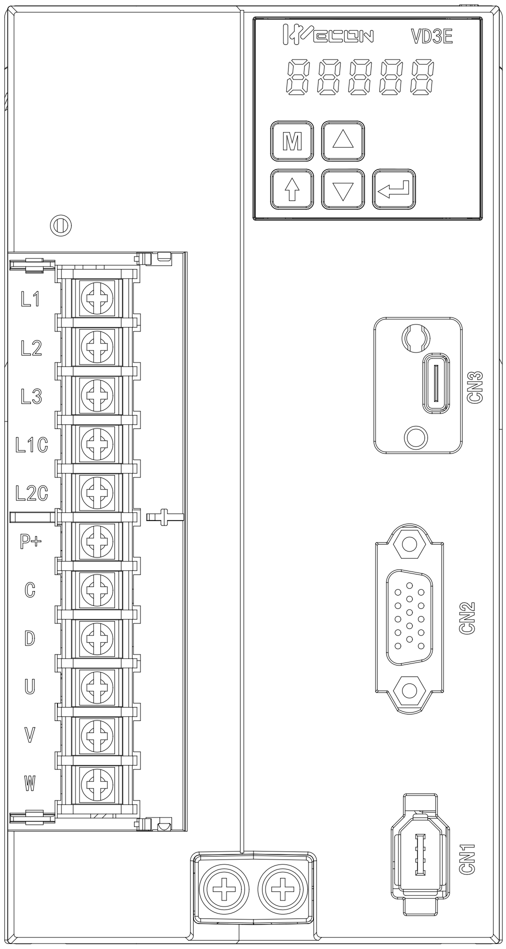


Figure 4-2 Schematic Diagram of VD3E Type B Servo Drive Main Circuit Terminal

Table 4-2 Name and function of main circuit terminal of VD3E type B servo drive

Terminal number	Terminal name	Terminal function
L1	Power input terminal	Single-phase 220V AC input is connected to L1 and L3. Three-phase 220V AC input is connected to L1, L2, L3;
L2		
L3		
L1C	Control power input terminal	Single-phase 220V AC input connected to L1C and L2C
L1C		
P+	Braking resistor terminal	Use internal braking resistor: short connected C-D. Use an external braking resistor: please disconnect the short wire between C-D, and then connect the external braking resistor between P+ and C;
C		
D		
U	Motor power line terminal	Connect with the U, V, W of the motor to supply power to the motor.
V		
W		
Ground terminal	Ground terminal	Grounding of the servo drive.

(3) Main circuit terminal distribution of VD3E type B servo drive (380V)

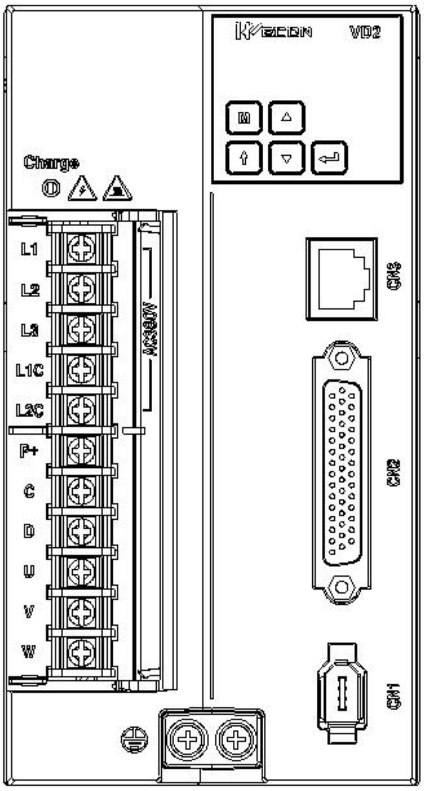


Figure 4-3 Schematic diagram of main circuit terminals of VD3E Type B servo drive (380V)

Table 4-3 Names and Functions of Main Circuit Terminals of VD3E Type B Servo Drive (380V)

Terminal number	Terminal name	Terminal function
L1	Power input terminal	Three-phase AC 380V input connect to L1, L2, L3
L2		
L3		
L1C	Control power input terminal	Single-phase AC 380V input connected to L1C, L2C
L1C		
P+	Braking resistor terminal	Use internal brake resistors: Short circuit C-D. Use external brake resistors: Please disconnect C-D short circuit wiring first, and then connect the external brake resistor between P+ and C.
C		
D		
U	Motor power line terminal	Connect with the U, V, W of the motor to supply power to the motor.
V		
W		
Ground terminal	Ground terminal	Grounding treatment of the servo drive

(4)Main circuit terminal distribution of VD3E type C servo drive (380V)

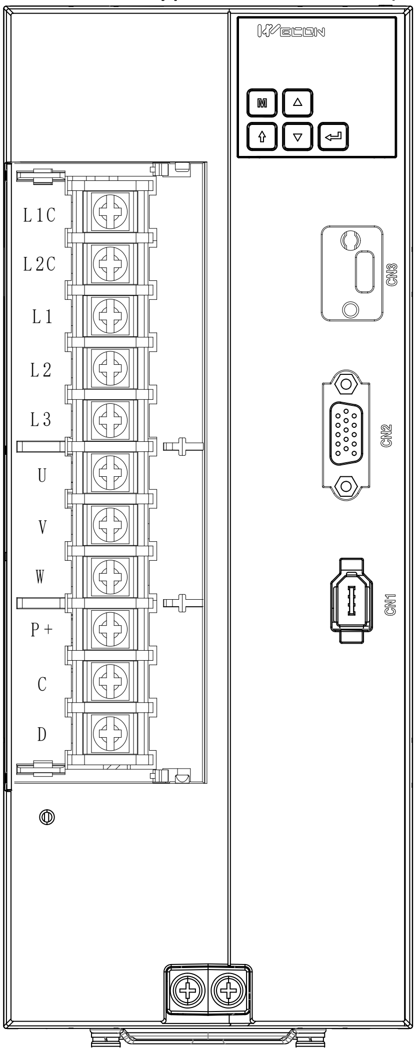


Figure 4-4 Schematic diagram of main circuit terminals of VD3E Type C servo drive (380V)

Terminal number	Terminal name	Terminal function
L1	Power input terminal	Three-phase AC 380V input connect to L1, L2, L3
L2		
L3		
L1C	Control power input terminal	Single-phase AC 380V input connected to L1C, L2C
L1C		
P+	Braking resistor terminal	Use internal brake resistors: Short circuit C-D. Use external brake resistors: Please disconnect C-D short circuit wiring first, and then connect the external brake resistor between P+ and C.
C		
D		
U	Motor power line terminal	Connect with the U, V, W of the motor to supply power to the motor.
V		
W		
Ground terminal	Ground terminal	Grounding treatment of the servo drive

4.1.2 Power wiring Example

(1) VD3E Type A Drive Single-phase 220V Main Circuit Wiring

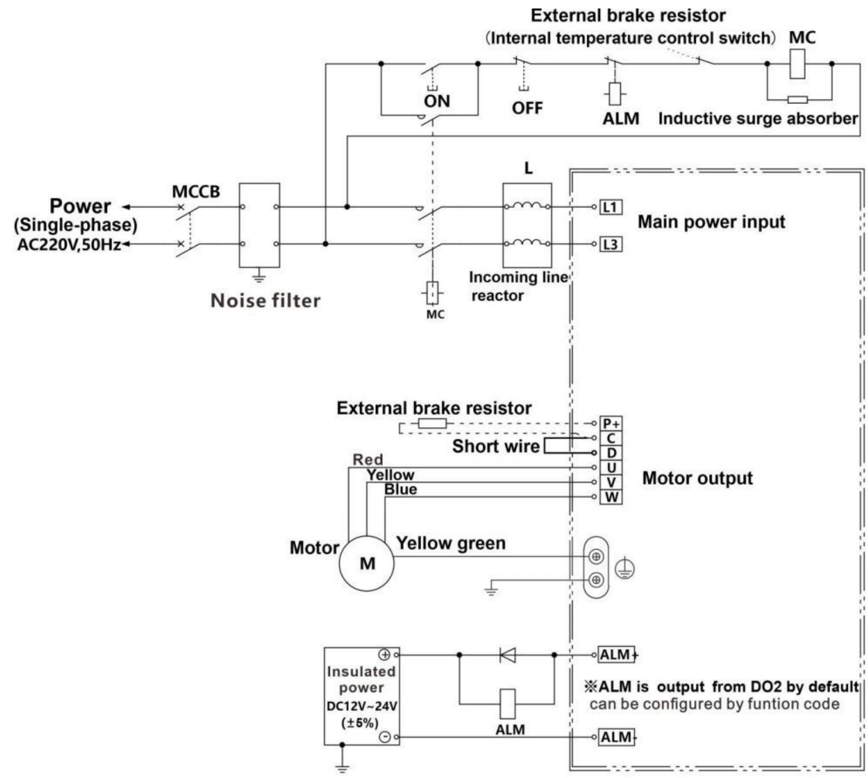


Figure 4-5 VD3E Type A Drive Single-phase 220V Main Circuit Wiring

(2) VD3E Type B Drive Single-phase 220V Main Circuit Wiring

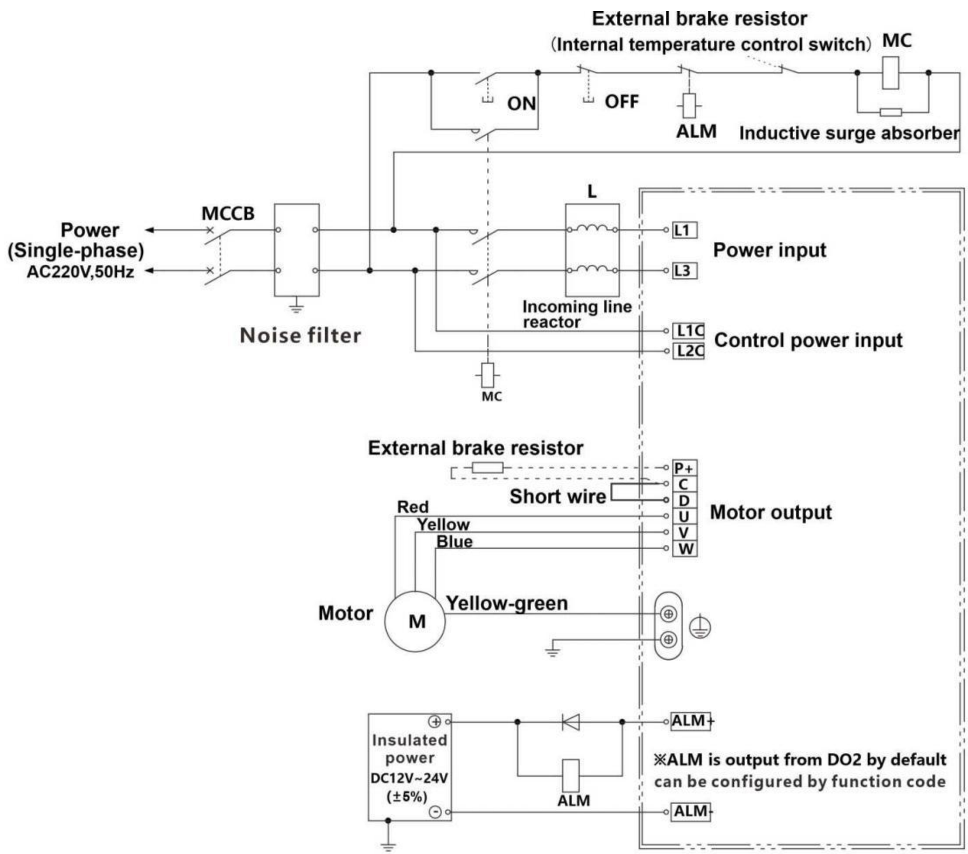


Figure 4-6 VD3E Type B Drive Single-phase 220V Main Circuit Wiring

(3) VD3E Type B Drive Three-phase 220V Main Circuit Wiring

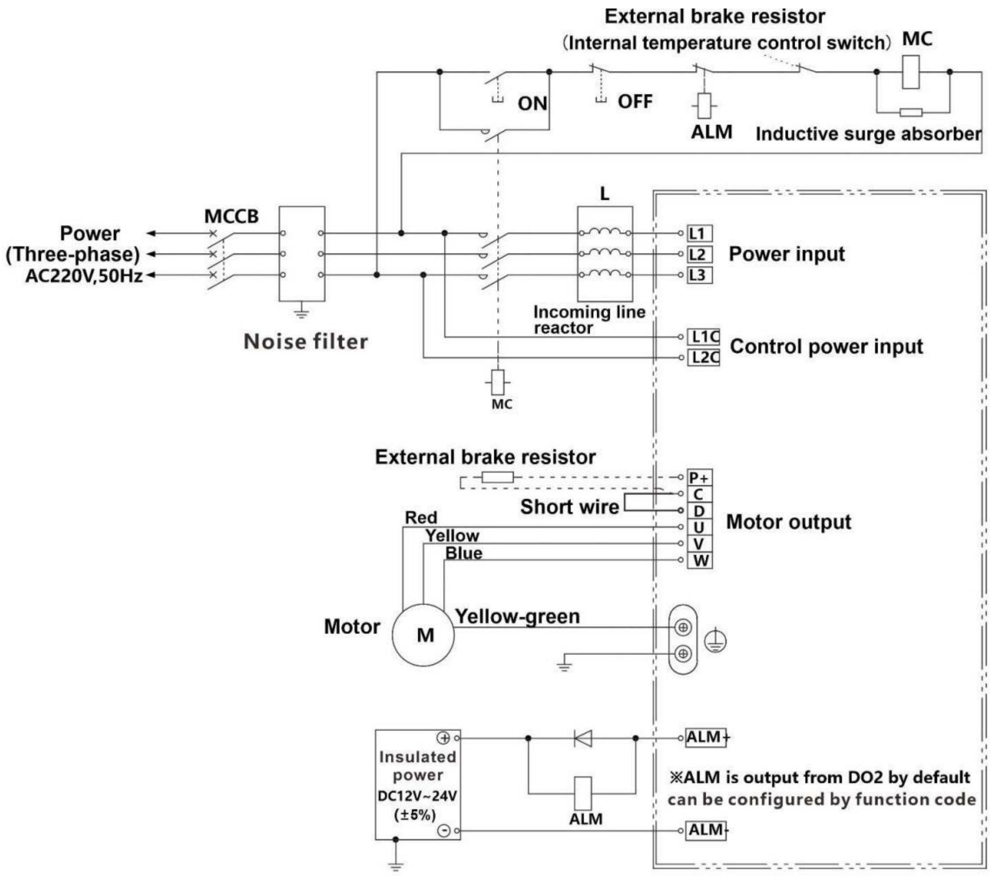


Figure 4-7 VD3E Type B Drive Three-phase 220V Main Circuit Wiring

(4) VD3E Type B Drive Three-phase 380V Main Circuit Wiring

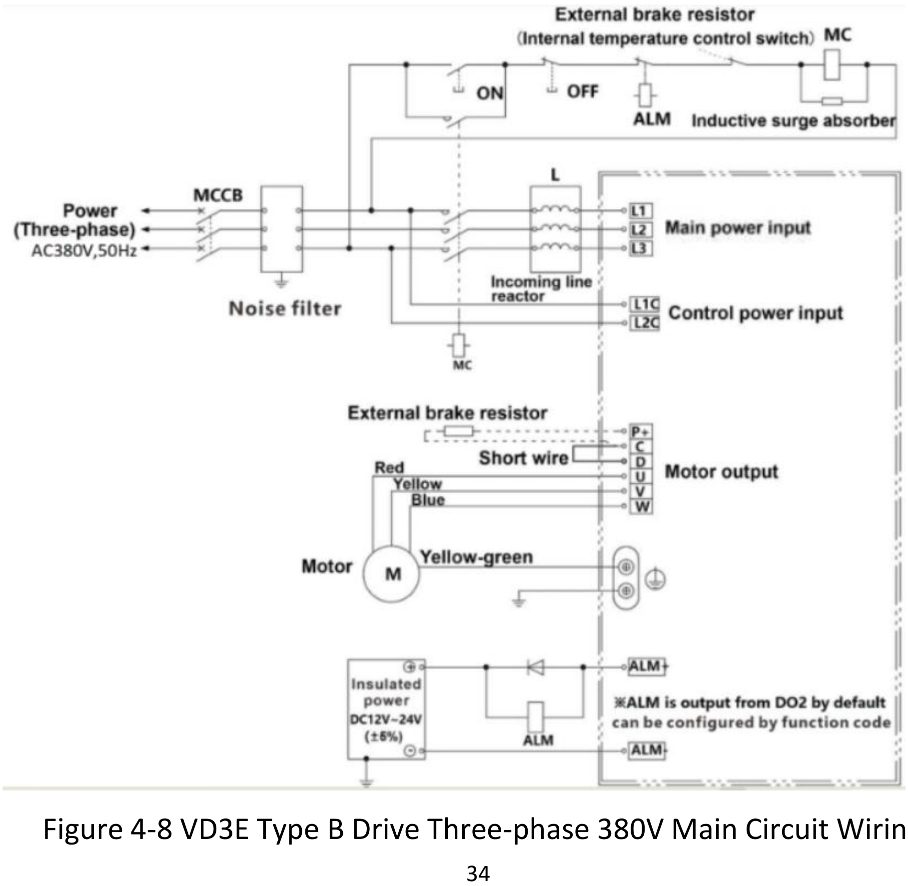


Figure 4-8 VD3E Type B Drive Three-phase 380V Main Circuit Wiring

(5) VD3E Type C Drive Three-phase 380V Main Circuit Wiring

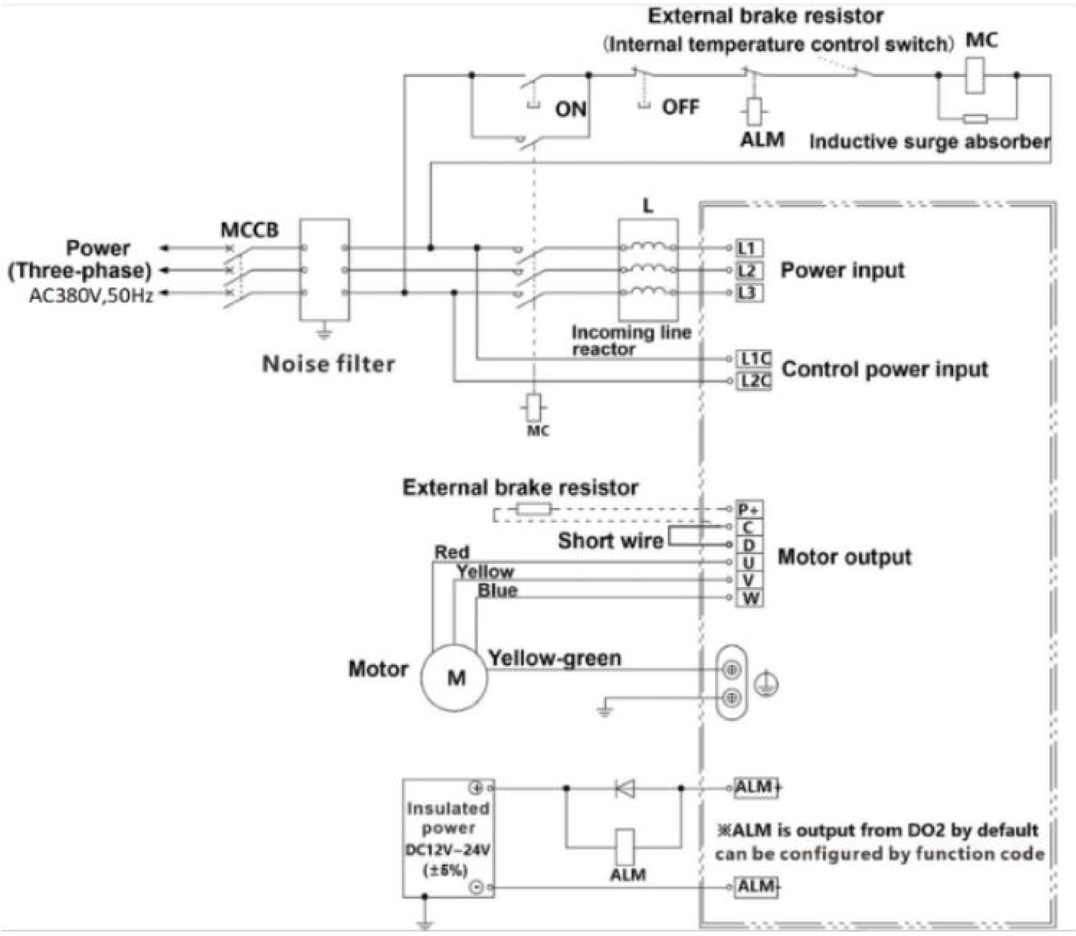


Figure 4-9 VD3E Type C Drive Three-phase 380V Main Circuit Wiring

4.1.3 Precautions for Main circuit wiring

① The input power line cannot be connected to the output terminals U, V and W, otherwise the servo drive will be damaged. When using the built-in braking resistor, C and D must be connected (factory default connection).

② When the cables are bundled and used in pipes, etc., due to the deterioration of heat dissipation conditions, please consider the allowable current reduction rate.

③ When the temperature in the cabinet is higher than the cable temperature limit, please choose a cable with a larger cable temperature limit, and it is recommended that the cable wire use Teflon wire. Please pay attention to the warmth of the cable in the low temperature environment. Generally, the surface of the cable is prone to hardening and breakage under the low temperature environment.

④ The bending radius of the cable should be more than 10 times the outer diameter of the cable itself to prevent the core of the cable from breaking due to long-term bending.

4.2 Power Line Connection of Servo Drive and Servo Motor

4.2.1 Power Cable

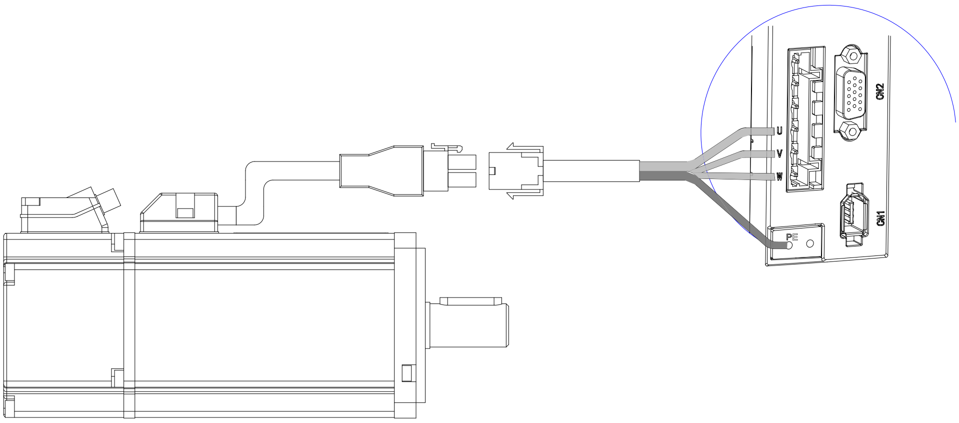
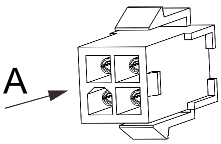
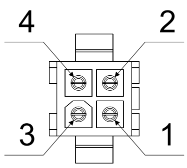
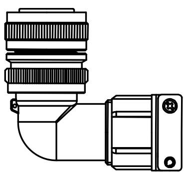
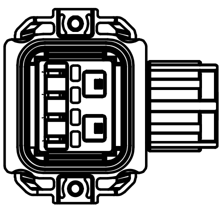
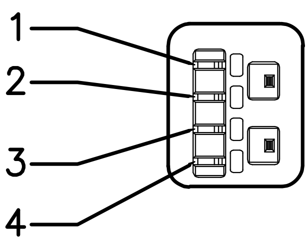


Figure 4-10 Connection schematic diagram of servo drive and servo motor

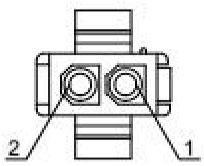
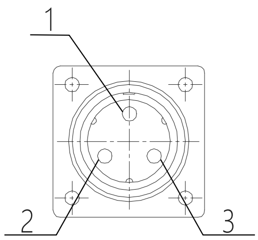
Wecon VD3E series servo drives have 3 kinds of interface power cables: rectangular plug, aviation plug and in-line type.

Table 4-5 Power cable servo motor side connector

<table>
<tr><th>Connector exterior</th><th>Terminal pin distribution</th><th>Pin description</th><th>Adaptation Motor flange</th></tr>
<tr><td></td><td></td><td>Rectangular plug<table><tr><th>Pin number</th><th>Signal name</th><th>Color</th></tr><tr><td>1</td><td>U</td><td>Red</td></tr><tr><td>2</td><td>V</td><td>White</td></tr><tr><td>3</td><td>W</td><td>Black</td></tr><tr><td>4</td><td>PE</td><td>Yellow-green</td></tr></table></td><td>40
60
80</td></tr>
<tr><td></td><td></td><td>Aviation plug<table><tr><th>Pin number</th><th>Signal name</th><th>Color</th></tr><tr><td>2</td><td>U</td><td>Red</td></tr><tr><td>4</td><td>V</td><td>Yellow</td></tr><tr><td>3</td><td>W</td><td>Blue</td></tr><tr><td>1</td><td>PE</td><td>Yellow-green</td></tr></table></td><td>110
130</td></tr>
<tr><td></td><td></td><td>In-line type plug<table><tr><th>Pin number</th><th>Signal name</th><th>Color</th></tr><tr><td>3</td><td>U</td><td>Red</td></tr><tr><td>1</td><td>V</td><td>White</td></tr><tr><td>2</td><td>W</td><td>Black</td></tr><tr><td>4</td><td>PE</td><td>Yellow-green</td></tr></table></td><td>60
80</td></tr>
</table>

✎**Note:** The color of the lines is subject to the actual product. The lines described in this manual are all lines of Wecon.

4.2.2 Brake Device cable

<table>
<tr><th colspan="2">Connector shape and terminal pin distribution</th><th>Pin description</th><th>Adaptable motor flange</th></tr>
<tr><td>WD Series</td><td>
</td><td>
<table>
<tr><th>Pin number</th><th>Signal name</th></tr>
<tr><td>1</td><td>BR+</td></tr>
<tr><td>2</td><td>BR-</td></tr>
</table>
</td><td>60
80</td></tr>
<tr><td>WE Series</td><td>
</td><td>
<table>
<tr><th>Pin number</th><th>Signal name</th></tr>
<tr><td>1</td><td>DC 24V</td></tr>
<tr><td>2</td><td>GND</td></tr>
<tr><td>3</td><td>-</td></tr>
</table>
</td><td>80
110
130</td></tr>
</table>

4.3 Encoder Cable Connection of Servo Drive and Servo Motor

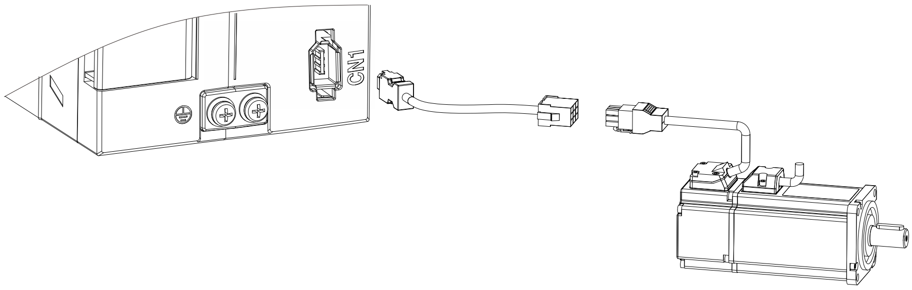


Figure 4-11 Encoder cable connection schema

Table 4-6 Encoder cable servo drive side connector

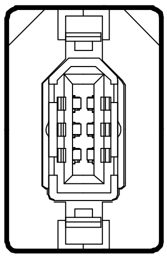
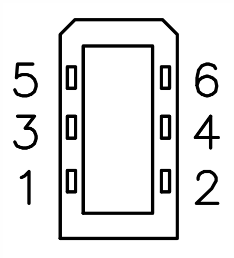
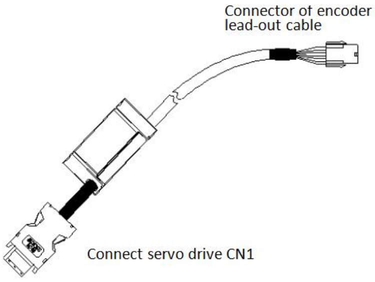
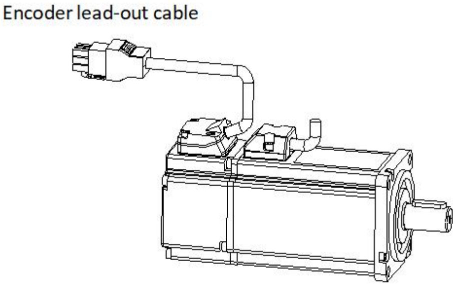
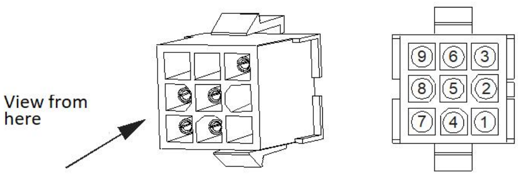
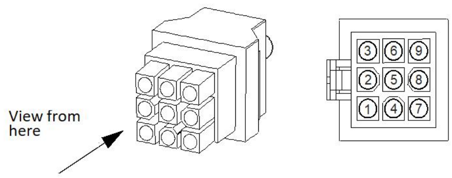
<table>
<tr><th>Connector exterior</th><th>Terminal pin distribution</th><th>Pin description</th></tr>
<tr><td></td><td>
</td><td>
<table>
<tr><th>Pin number</th><th>Signal name</th></tr>
<tr><td>1</td><td>5V</td></tr>
<tr><td>2</td><td>GND</td></tr>
<tr><td>3</td><td>-</td></tr>
<tr><td>4</td><td>-</td></tr>
<tr><td>5</td><td>SD+</td></tr>
<tr><td>6</td><td>SD-</td></tr>
</table>
</td></tr>
</table>

Table 4-7 Absolute encoder cable connector (rectangular plug)

<table>
<tr><th colspan="2">Connector shape and terminal pin distribution</th><th>Adapted motor Flange</th></tr>
<tr><td>
</td><td>
</td><td rowspan="2">60
80</td></tr>
<tr><td>
</td><td>
</td></tr>
</table>

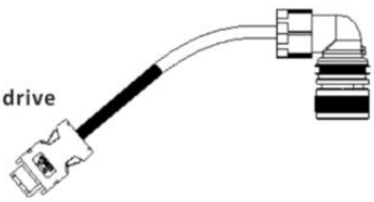
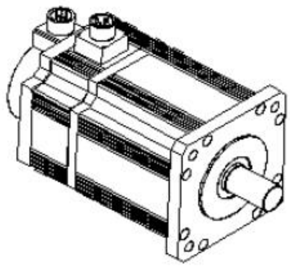
<table>
<tr><th>Connector shape and terminal pin distribution</th><th>Adapted motor Flange</th></tr>
<tr><td>
<table>
<tr><th>Pin number</th><th>Signal name</th></tr>
<tr><td>7</td><td>5V</td></tr>
<tr><td>8</td><td>GND</td></tr>
<tr><td>4</td><td>SD+</td></tr>
<tr><td>5</td><td>SD-</td></tr>
<tr><td>3</td><td>Shield</td></tr>
<tr><td>1</td><td>Battery+</td></tr>
<tr><td>2</td><td>Battery-</td></tr>
</table>
</td><td></td></tr>
</table>

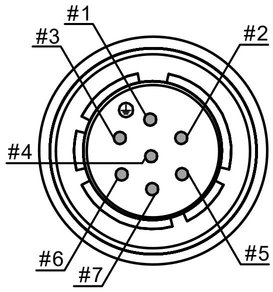
Table 4-8 Encoder cable pin connection relationship

Drive side J1394		Description	Motor side	
Pin number	Signal name		Rectangular plug pin number	Cable color
1	5V	Encoder +5v power	7	Blue
2	GND	Encoder power ground	8	Orange
5	SD+	Serial communication signal +	4	Green
6	SD-	Serial communication signal -	5	Brown
Shell	Shield	Shield	3	-
-	-	Battery+	1*	Pink
-	-	Battery-	2*	Pink-Black

✎**Note:** The color of the cable is subject to the actual product. The cables described in this manual are all cables of Wecon!

Table 4-9 Absolute value encoder cable connector (aviation plug)

<table>
<tr><th colspan="2">Connector shape and terminal pin distribution</th><th>Adapted motor Flange</th></tr>
<tr><td>
</td><td>
</td><td>110
130</td></tr>
</table>

Connector shape and terminal pin distribution	Adapted motor Flange
	

Pin number	Signal name
7	5V
5	GND
6	SD+
4	SD-
1	Shield
3	Battery+
2	Battery-

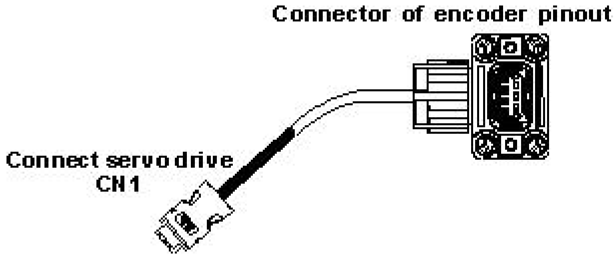
Table 4-10 Encoder cable pin connection relationship

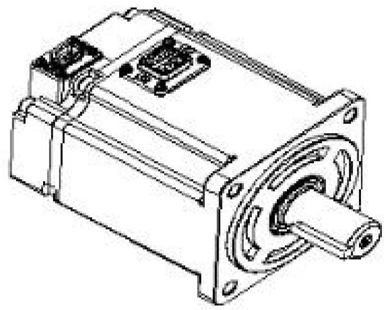
Drive side J1394		Description	Motor side	
Pin number	Signal name		Aviation plug pin number	Cable color
1	5V	Encoder +5v power	7	Blue
2	GND	Encoder power ground	5	Orange
5	SD+	Serial communication signal +	6	Green
6	SD-	Serial communication signal -	4	Brown
Shell	Shield	Shield	1	-
-	-	Battery+	3*	Pink
-	-	Battery-	2*	Pink-Black

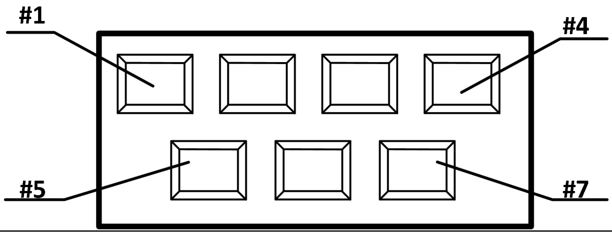
✎**Note:** The color of the cable is subject to the actual product. The cables described in this manual are all cables of Wecon!

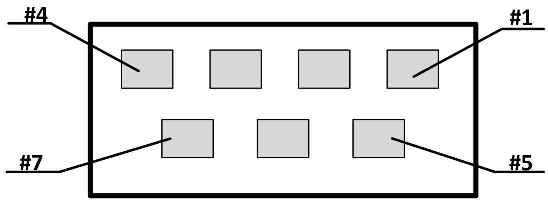
Table 4-11 Absolute value encoder cable connector (in-line type)

Connector shape and terminal pin distribution	Adapted motor Flange
(see drawings and pin table below)	60 80









Pin number	Signal name
7	5V
5	GND
6	SD+
4	SD-
1	Shield
3	Battery+
2	Battery-

Table 4-12 Encoder cable pin connection relationship

Drive side J1394		Description	Motor side	
Pin number	Signal name		Aviation plug pin number	Cable color
1	5V	Encoder +5v power	7	Blue
2	GND	Encoder power ground	5	Orange
5	SD+	Serial communication signal +	6	Green
6	SD-	Serial communication signal -	4	Brown
Shell	Shield	Shield	1	-
--	--	Battery positive pole	3*	Brown
--	--	Battery negative pole	2*	Black

✎**Note:** The color of the cable is subject to the actual product. The cables described in this manual are all cables of Wecon!

Table 4-13 Absolute value encoder cable connector L2 type (in-line type)

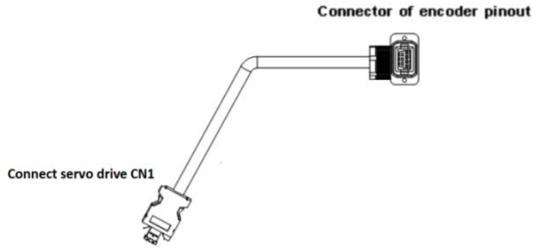
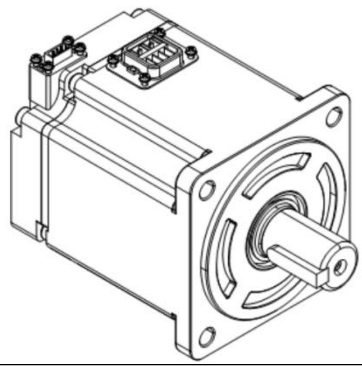
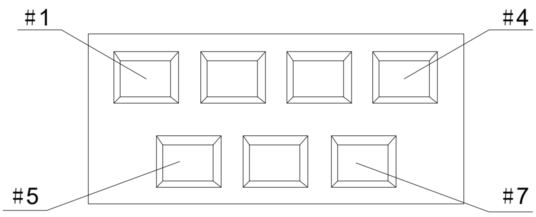
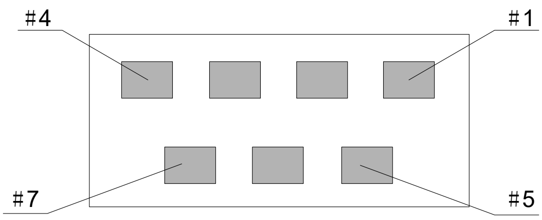
<table>
<tr><th colspan="2">Connector shape and terminal pin distribution</th><th>Adapted motor flange</th></tr>
<tr><td>
</td><td>
</td><td rowspan="3">60
80</td></tr>
<tr><td>
</td><td>
</td></tr>
<tr><td colspan="2">
<table>
<tr><th>Pin number</th><th>Signal name</th></tr>
<tr><td>1</td><td>5V</td></tr>
<tr><td>2</td><td>GND</td></tr>
<tr><td>3</td><td>SD+</td></tr>
<tr><td>4</td><td>SD-</td></tr>
<tr><td>5</td><td>Shield</td></tr>
<tr><td>6</td><td>Battery+</td></tr>
<tr><td>7</td><td>Battery-</td></tr>
</table>
</td></tr>
</table>

Table 4-14 Encoder cable pin connection relationship

Drive side J1394		Function description	Motor side	
Pin number	Signal name		Aviation plug pin number	Cable color
1	5V	Encoder+5V power supply	1	White
2	GND	Encoder power ground	2	Brown
5	SD+	Serial communication signal+	3	Green
6	SD-	Serial communication signal-	4	Yellow
Housing	Shield	Shield	5	--
--	--	Battery+	6*	Pink
--	--	Battery-	7*	Black

✎**Note:** Please be subject to the real object for the cable color. The cables described in this manual are all Wecon cables!

4.4 Servo Drive Control Input and Output Terminal Wiring

4.4.1 CN2 Pin Distribution

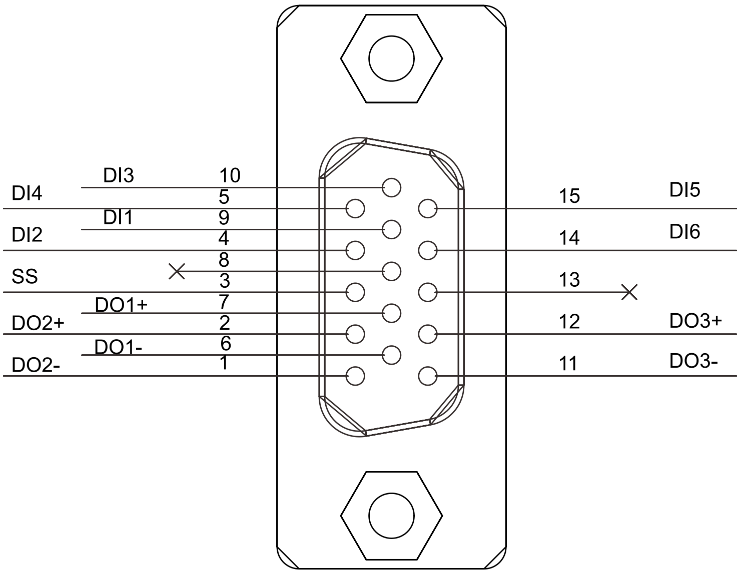


Figure 4-12 Shape and pin distribution of control input and output terminals

Table 4-15 CN2 Interface Definition

Pin number	Signal name	Pin number	Signal name	Pin number	Signal name
1	DO2-	6	DO1-	11	DO3-
2	DO2+	7	DO1+	12	DO3+
3	SS	8	-	13	-
4	DI2	9	DI1	14	DI6
5	DI4	10	DI3	15	DI5

4.4.2 Digital input and output signals

Table 4-16 DI/DO signal description

Pin number	Signal name	Default function
9	DI1	None
4	DI2	Fault and warning clear
10	DI3	Forward drive prohibition
5	DI4	Reverse drive prohibition
15	DI5	None
14	DI6	None
3	SS	Power input (12 ~ 24V)
6	DO1-	Rotation detection
7	DO1+	
1	DO2-	Fault signal
2	DO2+	
11	DO3-	Servo ready
12	DO3+	

1) Digital input circuit

Taking DI1 as an example, the interface circuits of DI1 ~ DI6 are exactly the same.

When the control device (HMI/PLC) is relay output

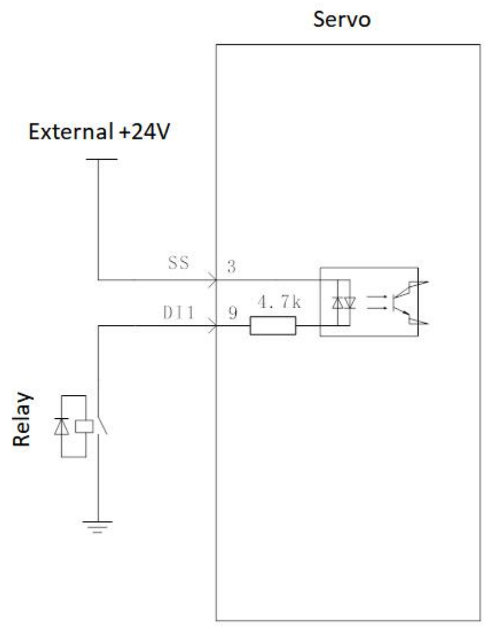


Figure 4-13 Relay output

When the control device (HMI/PLC) is open collector output

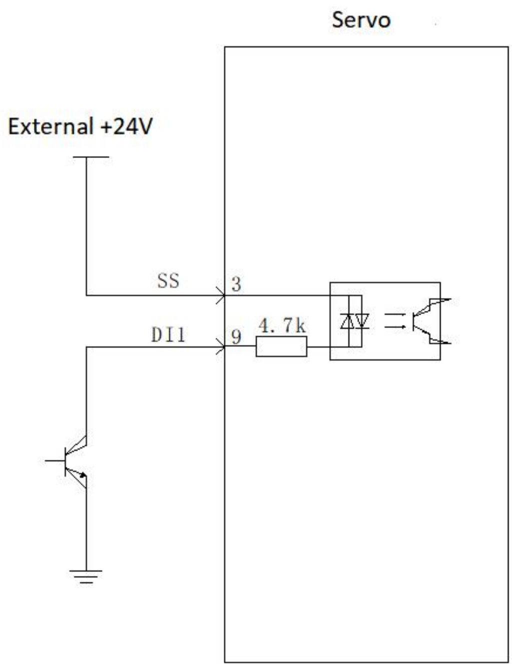


Figure 4-14 Open collector output

Digital output circuit

Taking DO1 as an example, the interface circuits of DO1 ~ DO3 are exactly the same.

When the control device (HMI/PLC) is relay input

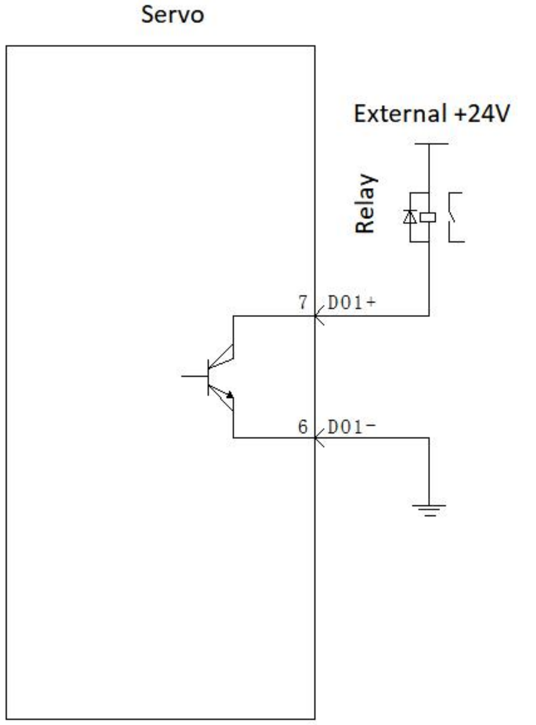


Figure 4-15 Relay input

When the control device (HMI/PLC) is optocoupler input

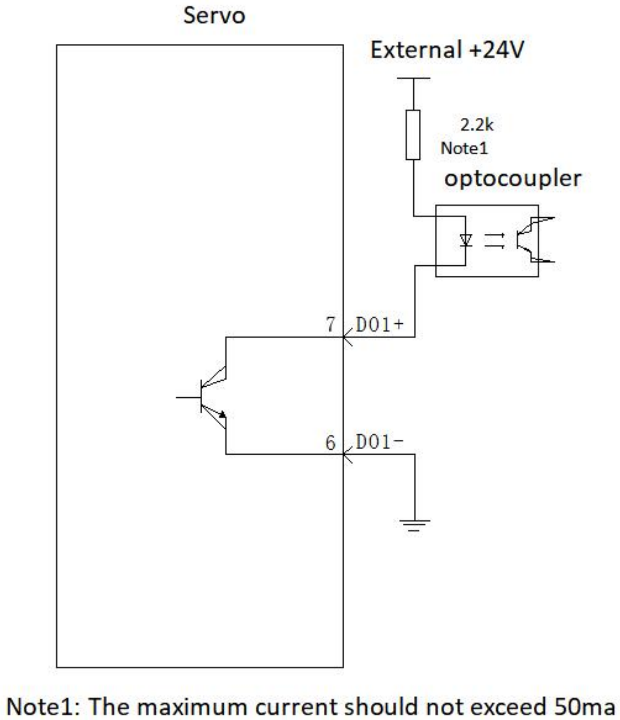


Figure 4-16 Optocoupler input

4.4.3 Brake wiring

The brake is a mechanism that prevents the servo motor shaft from moving when the servo drive is in a non-operating state, and keeps the motor locked in position, so that the moving part of the machine will not move due to its own weight or external force.

The brake input signal is non-polar, and the user needs to prepare 24V power supply. The standard connection diagram of brake signal BK and brake power supply is as follows:

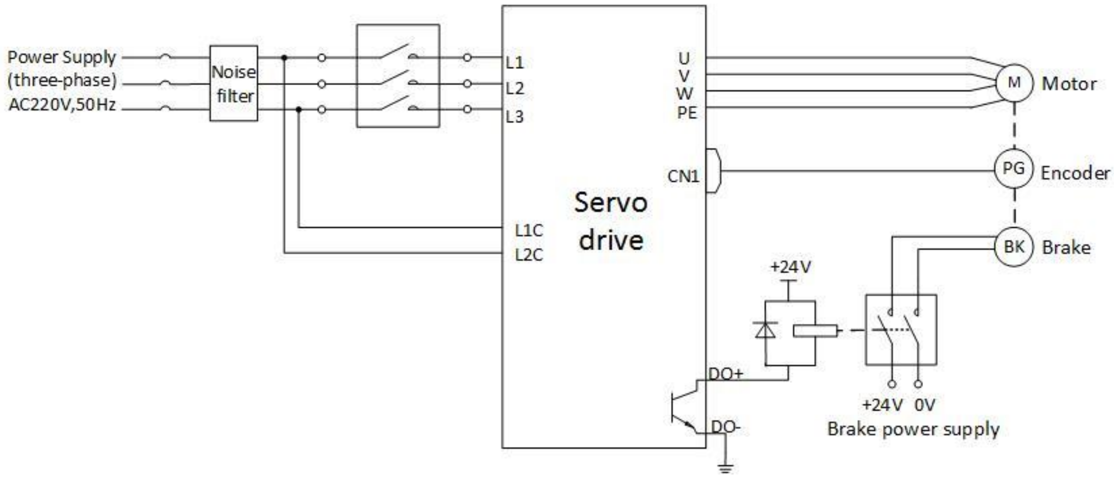


Figure 4-17 Brake wiring (taking three-phase 220V input as an example)

4.5 Communication Signal Wiring

The CN5 port of the first servo drive is connected to Wecon PLC LX6V

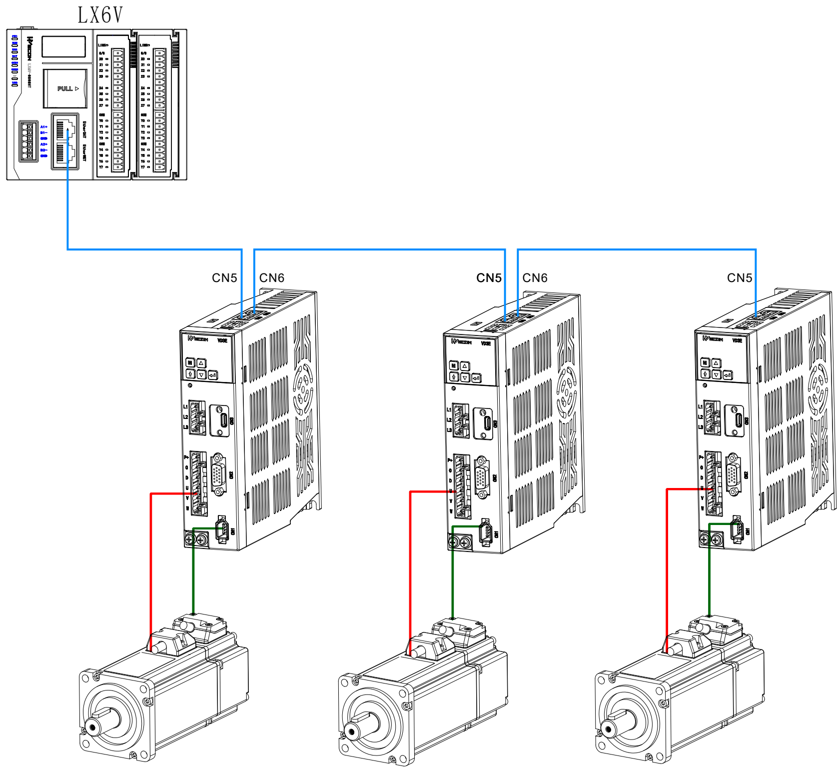


Figure 4-16 Communication topology networking schema

Table 4-16 CN5\ CN6 interface definition

Pin	Name	Function description
1	RX-	Computer sends negative terminal (drive receives negative)
2	RX+	Computer sends terminal (drive receives positive)
3	TX-	Computer receives negative terminal (drive sends negative)
4	GND	Ground terminal
5	Not used	Not used
6	TX+	Computer receives positive terminal (drive sends positive)
7	NC	Not used
8	NC	Not used

Chapter 5 Panel

5.1 Panel Composition

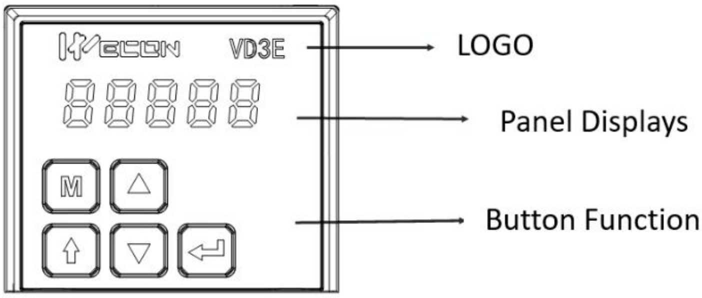
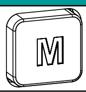
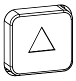
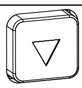
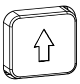
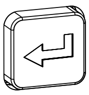


Figure 5-1 Appearance schematic diagram of servo drive panel

The panel of Wecon VD3E series bus servo drive is composed of a display (5-bit LED digital tube) and buttons, which can be used for various display and parameter setting functions of servo drive. Taking parameter setting as an example, the conventional functions of buttons are shown in Table 5-1.

Table 5-1 Brief introduction of key function

Icon	Name	Function
	Mode	Mode switching Return to the previous menu
	Increase	Increase the value of the LED flashing bit
	Down (decrease)	Decrease the value of the LED flashing bit
	SHIFT (Settings)	① Change the LED flashing bit ② View the high-order values of data with a length greater than 4 bits
	Confirm (Enter)	① Enter the next menu ②Execute instructions such as storing parameter setting values

5.2 Panel Display

When servo drive is in operation, the panel could be used for status display, parameter display, fault display and monitoring display of the servo.

Status display: Display the current operating status of servo drive.

Parameter display: Display the object dictionary and the setting value of the object dictionary corresponding to different functions.

Fault display: Display the fault code of servo drive.

Monitor display: Display the current operating parameter values of servo drive.

5.2.1 Display switching

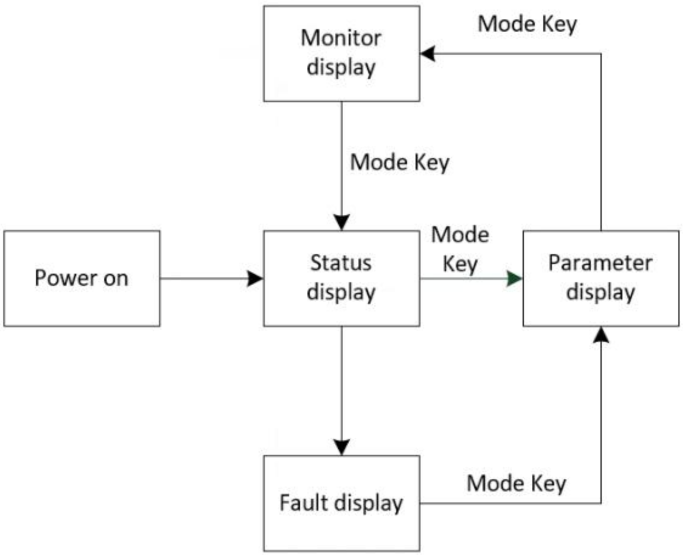


Figure 5-2 Switching schema of each display type of panel

Description:

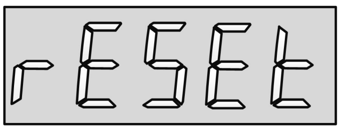
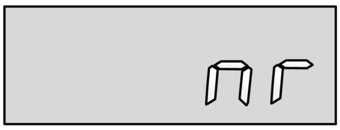
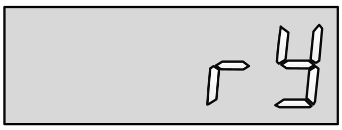
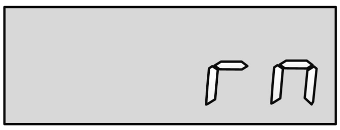
①Power on, the panel display of the servo drive enters [status display mode]

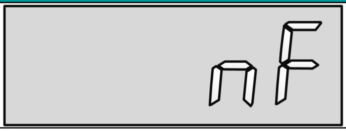
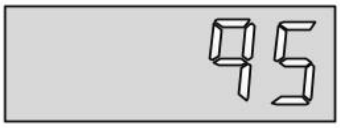
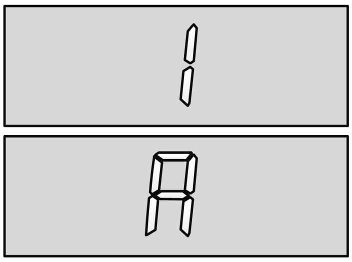
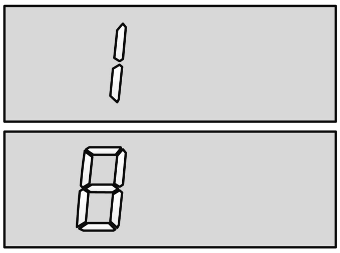
② When an operation failure occurs, the panel immediately switches to the bit failure display mode, and all the digital tubes flash synchronously, press the "mode" key to switch to the parameter display mode.

③Press the "Mode" key to switch between different display modes. The switching conditions are shown in Figure 5-2.

5.2.2 Status Display

Table 5-2 Status display example

Display	Name	Display occasion	Meaning
	Reset Servo initialization	Servo drive is powered on within 1 second	The servo drive is in an initialized or reset state. After waiting for initialization or reset to complete, automatically switch to other states
	nr Servo is not ready	After initialization is complete, but servo is not ready	The servo drive is in a non-operational state
	ry Servo ready	Servo ready	The servo is in a ready state, waiting for the upper computer to give an enable signal
	rn Servo is running	Servo enable signal is active (S-ON is ON state)	The servo drive is in operation

Display	Name	Display occasion	Meaning
	nF Servo trouble-free	Servo drive has no fault	Servo drive has no fault
	Qs Servo quick stop	Servo is in quick stop	Servo is in quick stop
	1-A Control mode	-	Displays the current operation mode of the servo drive in hexadecimal digital form: 1: Contour position mode 3: Contour velocity mode 4: Contour torque mode 6: Homing mode 8: Cyclic synchronous position mode 9: Periodic Synchronous speed mode A: Periodic synchronous torque mode
	1 - 8 Communication Status	-	Displays the Ether CAT status machine status of the slave station in character form: 1: Initialization status 2: Pre-operating status 4: Safe operation status 8: Operating status
	CN6 Interface Connection Indication	-	Keep dark constantly: No communication connection detected Keep bright constantly: A communication connection has been established
	CN5 Interface Connection Indication	-	

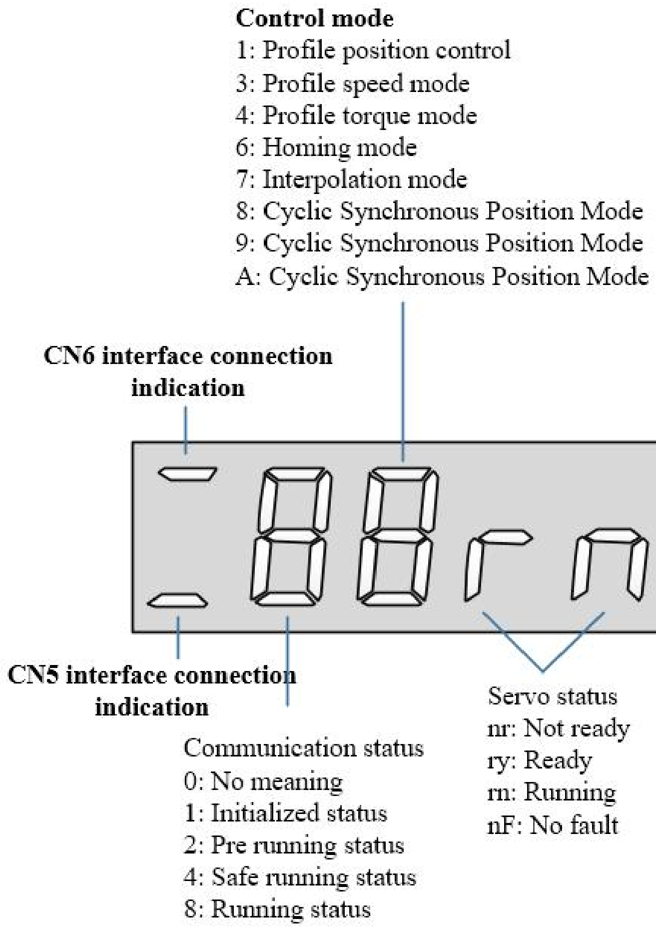


Figure 5-3 Status indication schema

5.2.3 Parameter Display

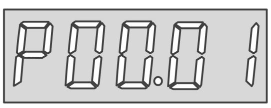
Wecon VD3E series bus servo drive is divided into 13 groups of function codes according to different parameters and functions, which can quickly locate the position of function codes according to the group of function codes. For specific parameters, please refer to “Chapter 8 Object Dictionary”.

(1) Parameter group display

The parameter display is the display of different function codes. The format of the function code is PXX.YY, where PXX represents the group number of the function code, and YY represents the number within the function code group.

Display	Name	Content
PXX.YY	Function code group number	Number in function code group

For example, the function code 2000.01 is shown as follows:

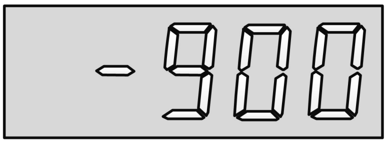
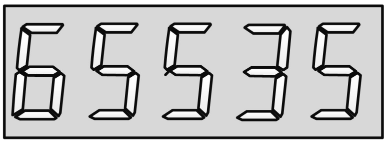
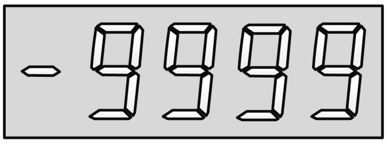
Display	Name	Content
	Function code 2000-01	00: Function code group number 01: Number in function code group

(2) Display of different length data

①Data display of four digits and below

Using single page display, if it is a signed number, the highest bit of the data is "-".

Examples:

Display		
		

Display Data more than five bits
Display in pages from low to high digits, each 4 bits is a page. Display method: current page + current value, as shown, switch the current page by pressing the "shift" key.
For example: 2147483646 is displayed as follows:

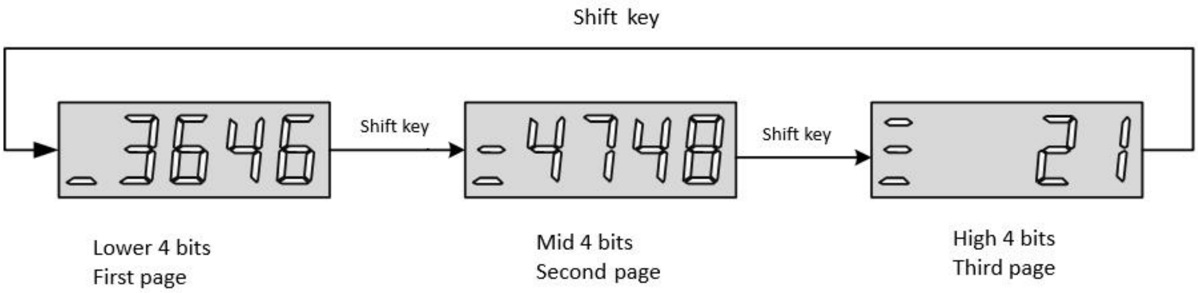


Figure 5-4 2147483646 Display Action

For example: -2147483647 is displayed as follows:

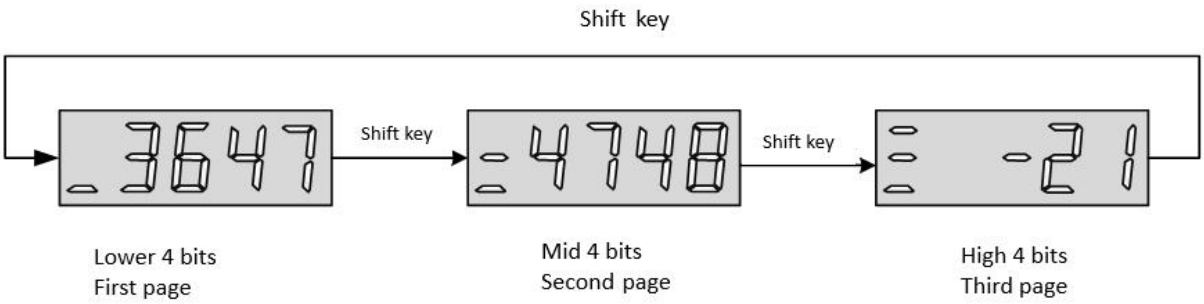
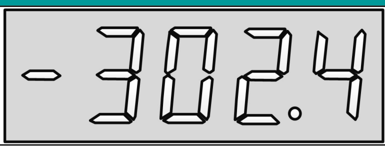
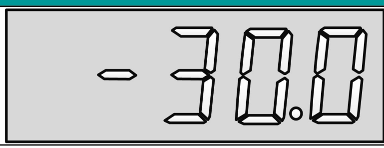


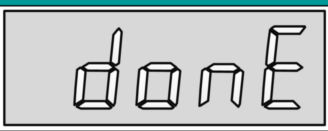
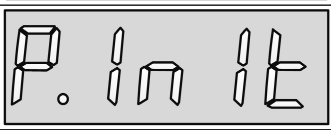
Figure 5-5 -2147483647 Display Operation

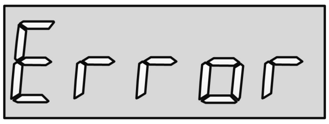
(3) Decimal point display
Digital tube of individual bit data ". "Represents the decimal point, and the decimal point". "No flashing, as shown below:

Display	
	

(4) Parameter setting display

Table 5-3 Parameter setting display

Display	Name	Display occasion	Meaning
	Done Parameter setting completed	Restore factory settings	
	P. Init Parameter restore factory setting	Restore factory settings	The servo drive is in the process of parameter restoration to factory settings

Display	Name	Display occasion	Meaning
	value		
	Error parameter error	Parameter setting exceeds the limit (Or not allowed to exceed the limit)	Prompt that the parameter setting exceeds the limit

5.2.4 Fault Display

The panel can display current or historical fault and warning codes. Please refer to the analysis and troubleshooting of faults and warnings"Chapter 7 Failure".

When a single fault or warning occurs, the panel immediately displays the current fault or warning code; when multiple faults or warnings occur, the highest fault code is displayed. When a fault occurs, when switching from the auxiliary function to the parameter display function, the corresponding fault or warning code will be displayed. You can view the current fault and warning codes and the past five fault and warning codes through the monitor display on the panel. You can view the current fault and warning codes and the last five fault and warning codes through the monitoring display of the panel.

Table 5-4 Warning display case

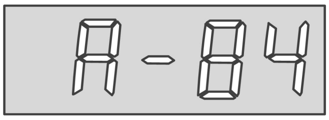
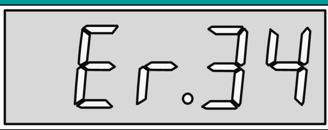
Display	Name	Content
	Parameter modification that needs to be powered on again	Modified the parameters that need to be re-powered on to take effect

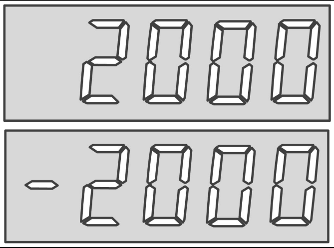
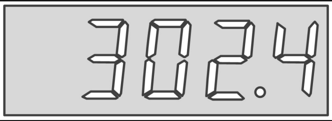
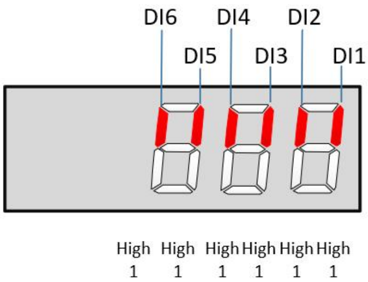
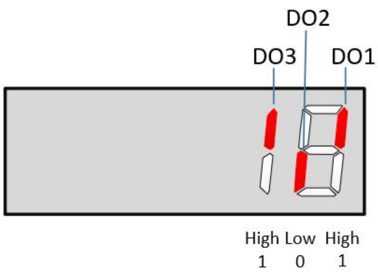
Table 5-5 Fault display case

Display	Name	Content
	Motor overload protection	Motor overload protection

5.2.5 Monitor Display

After the servo drive is powered on or the servo enable is turned on, you can press the "Mode" key to enter the monitoring display mode.

Table 5-6 Monitoring quantity display schema

Display	Monitoring volume	Name	Unit	Meaning
	U0-02	Servo motor speed	rpm	Indicates the actual running speed of servo motor, which is expressed in decimal system
	U0-31	Bus voltage	V	Represents the voltage value, the DC bus voltage between P+ and - of the drive
	U0-17	Input signal status	-	Indicates the level status corresponding to the 6 DI terminals. The upper half of the LED light indicates high level, and the lower half light indicates low level.
	U0-19	Output signal status	-	Indicates the level status corresponding to the 3 DO terminals. The upper half of the LED light indicates high level, and the lower half light indicates low level.

5.3 Panel Operation

5.3.1 Parameter setting

The servo drive panel can be used to set parameters. For details, please refer to "Chapter 6 Parameters" Taking 2000.01 as an example, the control mode of servo drive is changed from position control mode to speed control mode. The specific setting steps are shown in Figure 5-5.

Description:

The power supply is in Rdy state after power on.

Press "Mode" key to enter the function code parameter interface.

Press "Confirm" key to enter the function code value modification interface after completing the function code selection.

Press the "Up" and "Down" keys to modify the parameter value.

Press the "Confirm" key twice to complete the value modification.

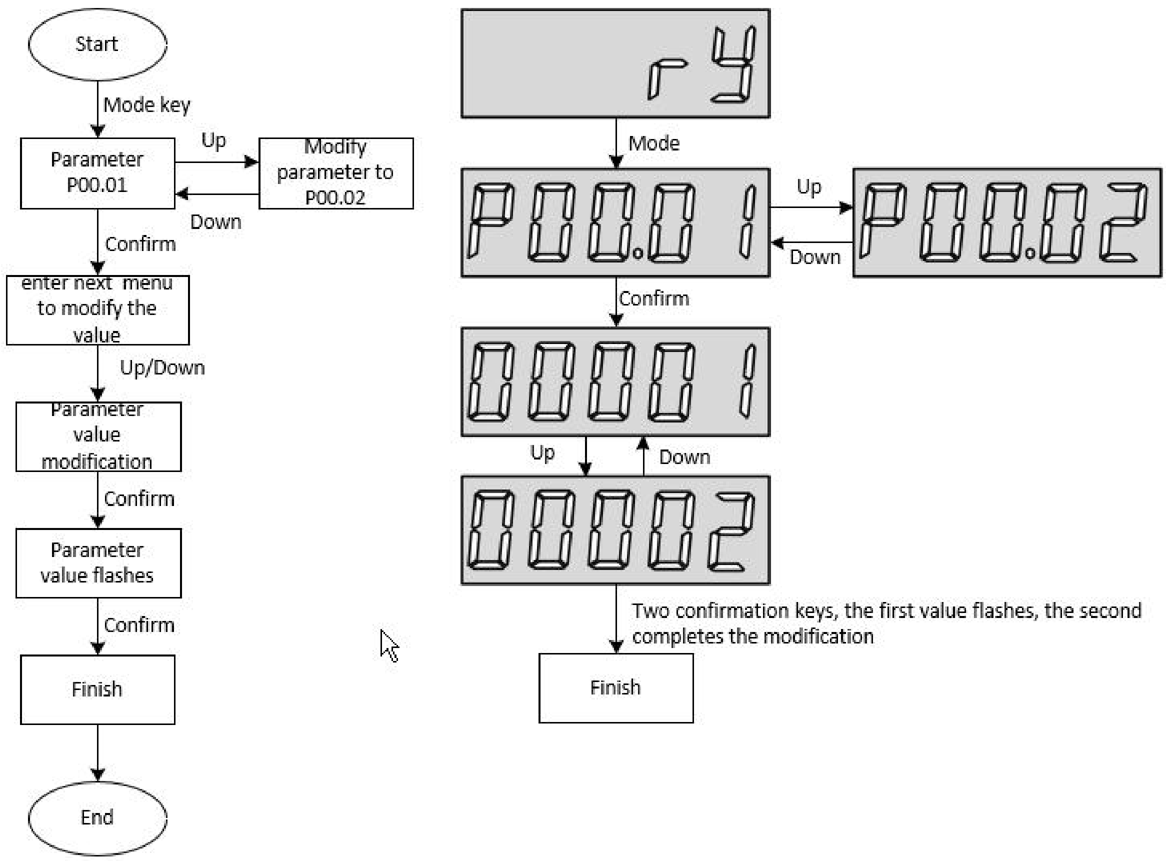


Figure 5-6 Schematic diagram of parameter setting steps

5.3.2 Jog operation

In order to test run the servo motor and the servo drive, you can use the jog running function. The operation steps are shown in .

Description:

① Adjust the function code to P10.01 after power on.

Press the "Enter" key to enter the next menu to set the JOG jog speed.

After the “JOG jog speed” setting is completed, press the "Enter" key, the panel displays “JOG” in a flashing state, press the "Enter" key again to enter the JOG mode.

Long press the "Up" key and "Down" key to realize the forward and reverse rotation of the motor.

Press the "Mode" key to exit the JOG mode.

Note 1: Press the Up/Down key for a long time, and the motor will continue to rotate; Press the Up/Down key, and the motor will be inching and rotating.

Note 2: Exit the "inching operation" status through the "Mode" keyboard and return to the superior menu at the same time.

Note 3: Display Error cause: Please refer to the corresponding fault code "Chapter 10 Failure".

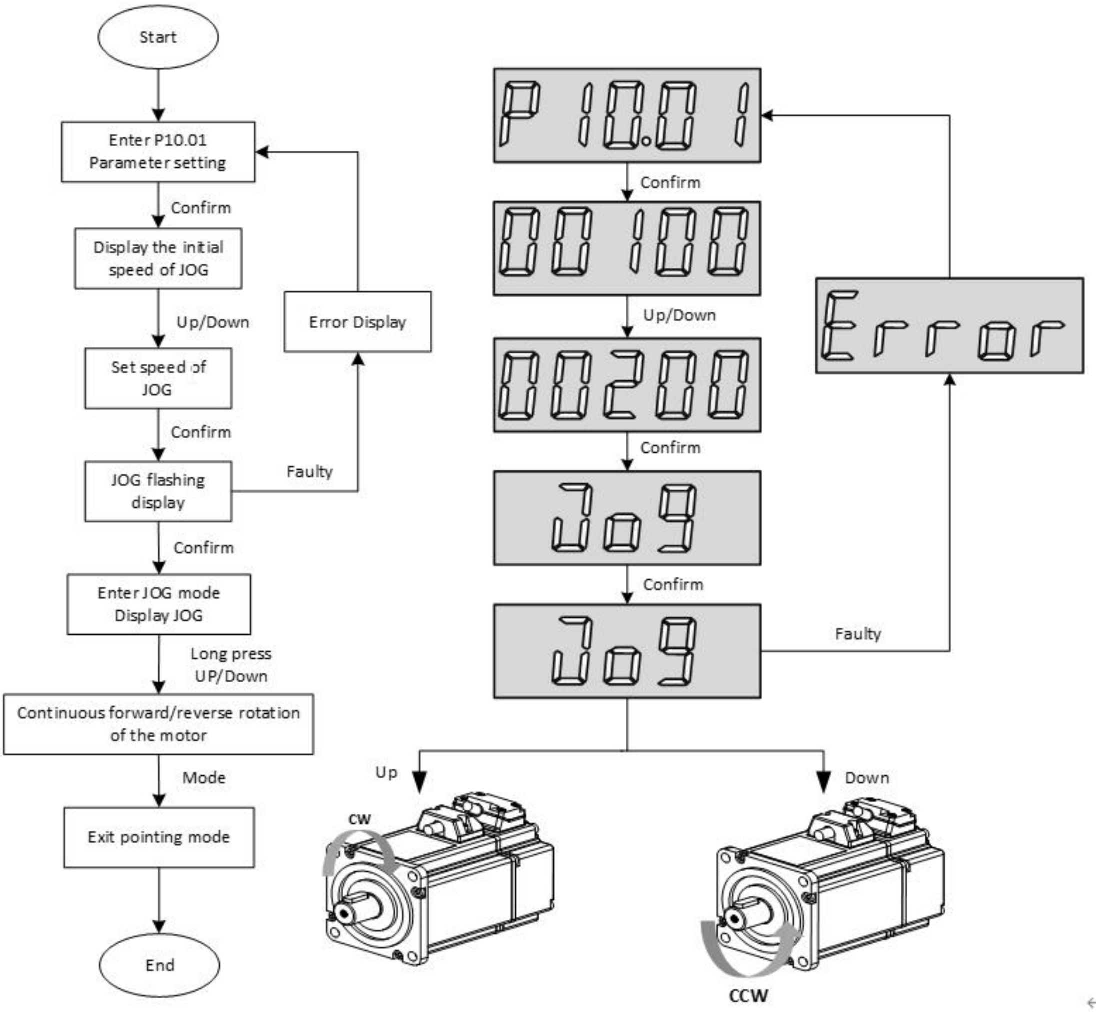


Figure 5-7 Inching operation setting step

5.3.3 Factory Reset

The factory settings can be restored through the servo drive panel. The specific operation steps are shown in Figure 5-8.

Illustrate:

After power on, modify the function code to P10.02.

Press the "Enter" key to enter the next menu to set the parameters.

③ After the parameter is set to 1, press the "Confirm" key, at this time, the digital tube flashes to display "00001", and press the "Confirm" key again, and the digital tube displays P.init.

④Long press the "Enter" key for 3s, the panel digital tube will gradually light up from left to right until 88888 is displayed.

⑤ You can release the "confirm" key during the display of 8.8. 8.8. 8.

⑥ Digital tube shows done, indicating that the factory settings are restored. At this time, it is recommended to re-power up and down the servo drive.

Note 1: Display Error Reason: When the parameter value of P10.02 is set beyond the set range (0 ~ 1), Error will be displayed.

Note 2: When the setting value is displayed as 0, press the Down key, and the panel will display Error. After displaying for 1 second, the setting value will automatically jump to 1.

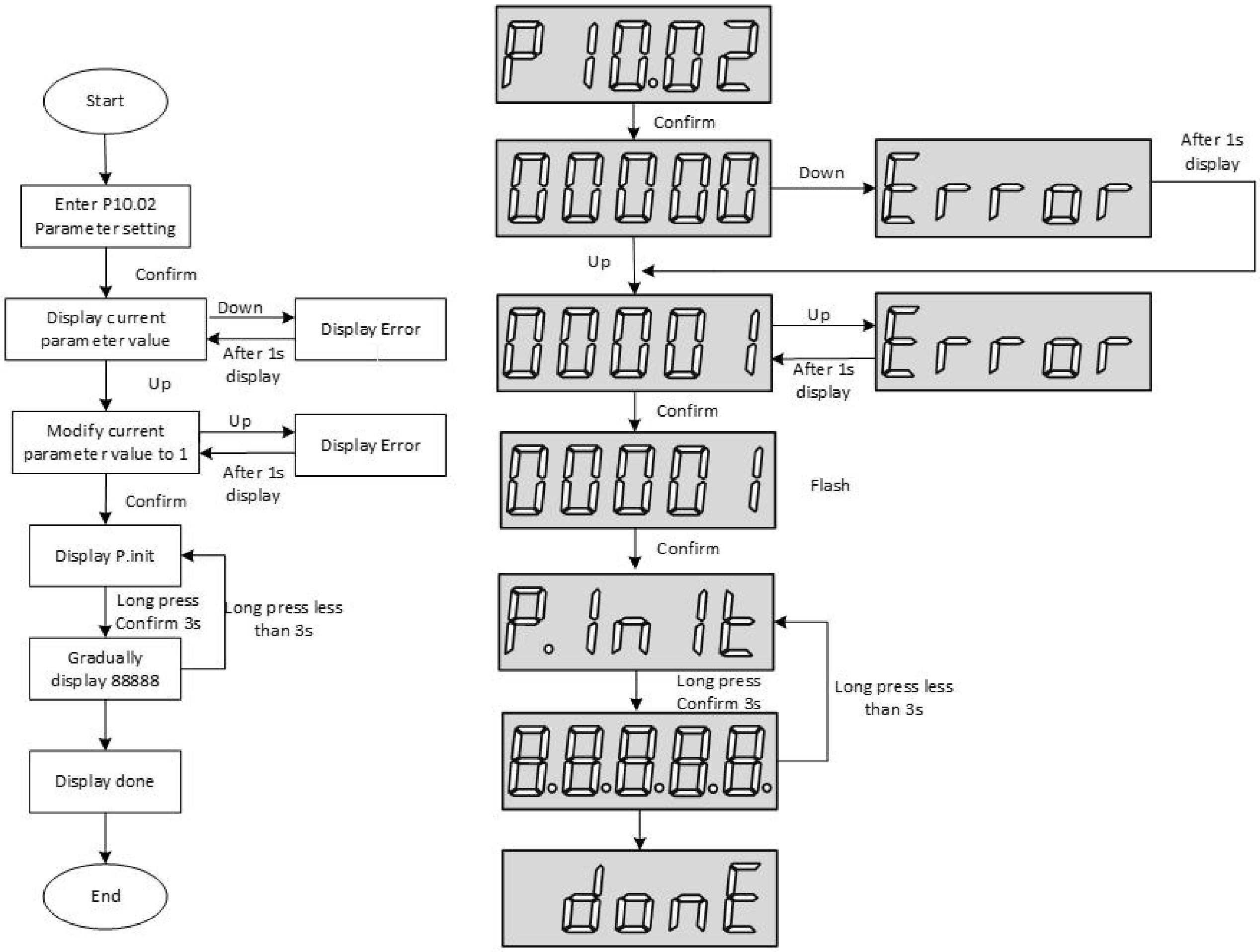


Figure 5-8 Restore factory setting steps

Chapter 6 Communication Network Configuration

6.1 EtherCAT Operation

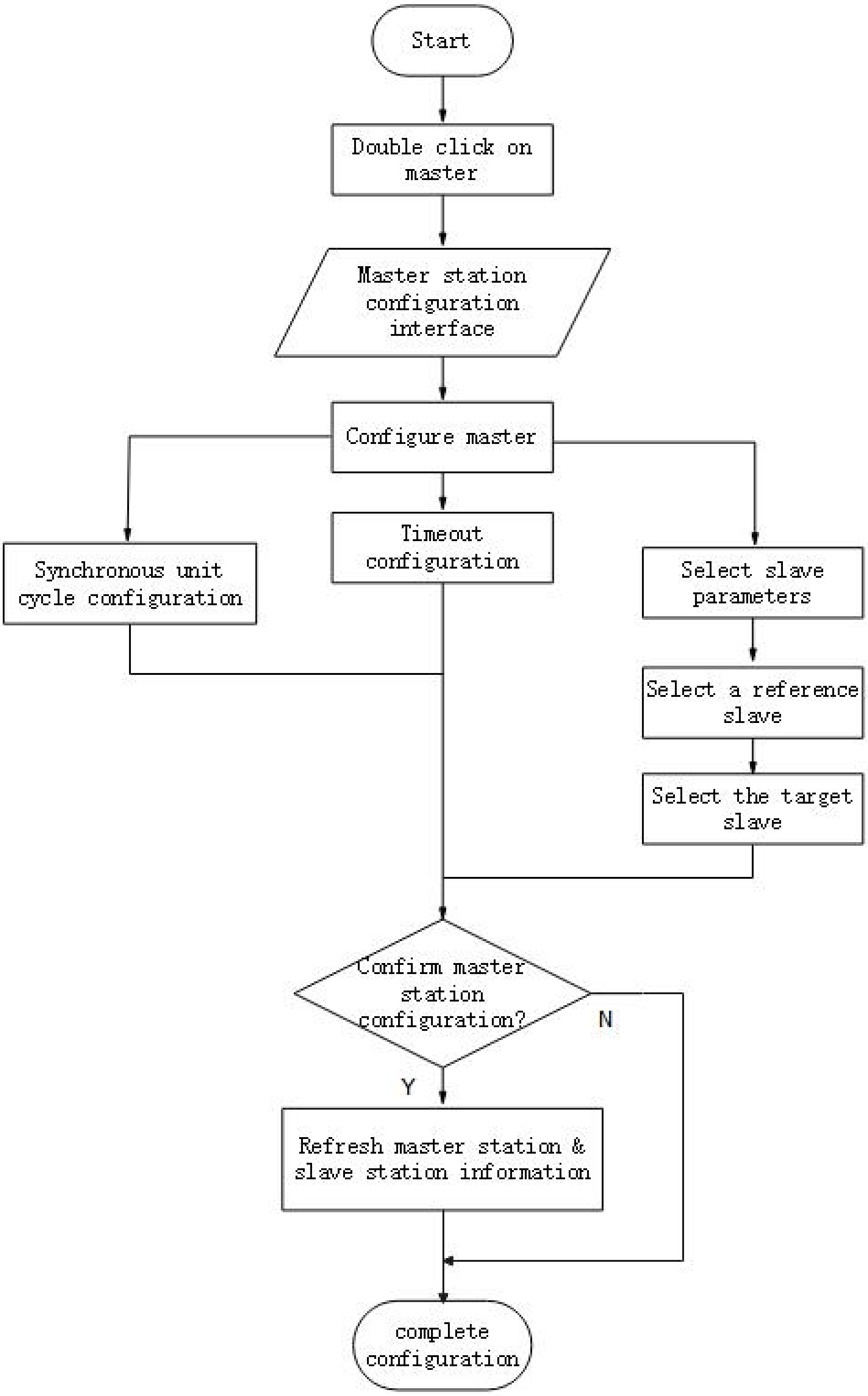


Figure 6-1 EtherCAT Operation Configuration Flow

6.2 EtherCAT Communication Fundamentals

6.2.1 EtherCAT communication specification

Hierarchy	Content	Specification
Application layer	PDO	Variable PDO mapping
	SDO	SDO request, SDO reply
	CIA 402	Cyclic Synchronous Position Mode (CSP) Origin return mode (HM)
Physical layer	Transport protocol	100BASE-TX (IEEE802.3)
	Communication interface	RJ45 Port * 2 (IN, OUT)

6.2.2 Communication structure

Wecon VD3E series bus servo drives adopt IEC 61800-7 (CiA402)-CANOpen motion control sub-protocol.

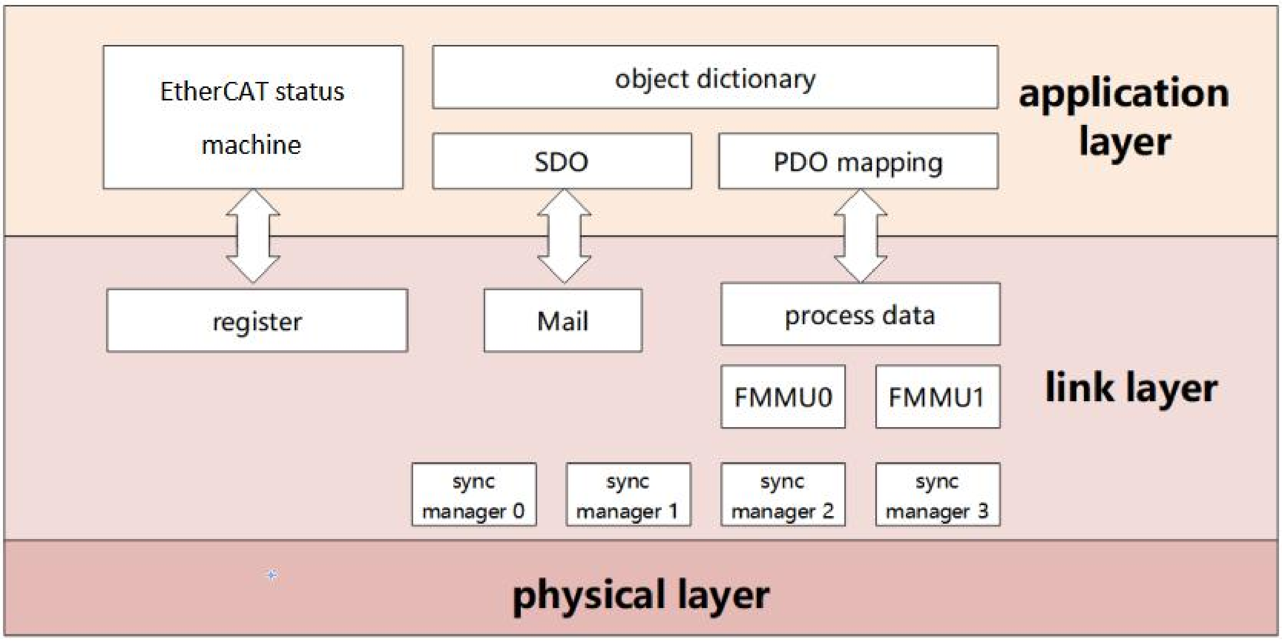


Figure 6-2 Communication structure

PDO (Process Data Object) is composed of Object Dictionary (Object Dictionary) which can be mapped in PDO, and the content of process data is defined according to PDO mapping.

Email is a kind of aperiodic communication and can read and write all object dictionaries.

6.2.3 State Machines

EtherCAT devices support four states and are responsible for coordinating the state relationship between master and slave applications at initialization and running:

Init: Initialization, abbreviated as I;
Pre-Operational: Pre-Operational, abbreviated as P;
Safe-Operational: Safe operation, abbreviated as S;
Operational: Operational, abbreviated as O.

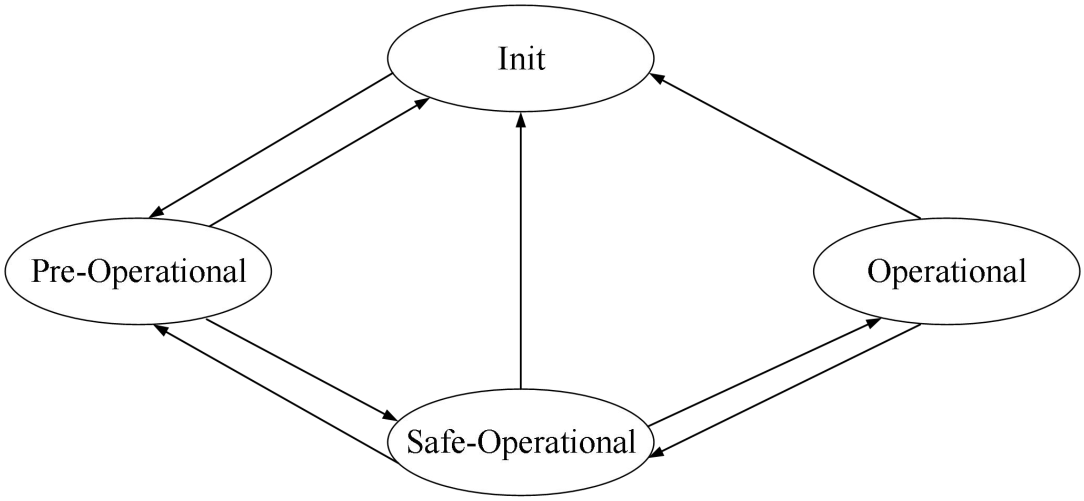


Figure 6-3 Communication structure

When changing from initialization state to operational state, it must be changed in the order of "initialization → pre-Operational → safe Operational → Operational"!
Leapfrog transition when returning from operational state. Refer to the following table for state transition operation and initialization process:

Status	Operation
Initialization	There is no communication in the application layer, and the master station can only read and write ESC registers
Initialization → pre-operational	The master station configures the site address of the slave station; Configure Email channels; Configure DC distributed clock; Request “pre-Operational" status
Pre-operation	Application Layer Email Data Communication (SDO)
Pre-operation → safe operation	The master station uses Email to initialize the process data mapping; The master station configures the SM channel used for process data communication; The main station is configured with FMMU; Request "safe status"
Safe operation	Allow input data to be read without output signal (SDO, TPDO)
Safe operation → operation	The master station sends valid output data; Request “operation" status
Operation	Input and output are all valid and can use Email communication (SDO, TPDO, RPDO)

6.2.4 Communication Indicator Lamp

The communication indicator for the VD3E servo drive is located on the CN5 (IN), CN6 (OUT) sockets, as shown INFigure 6-5As shown in.

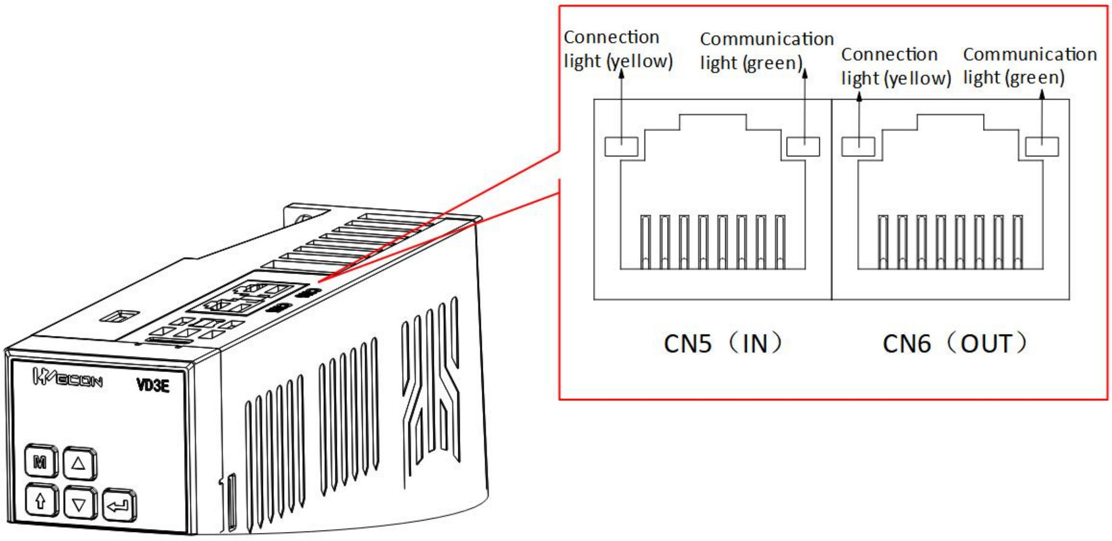


Figure 6-4 Communication indicator position

(1) Connection lamp (yellow)

Used to display the status of CN5 and CN6 communication interfaces, and the display contents are shown in the following table.

Connection lamp status	Explanation
OFF	The port is not connected to the network cable
ON	The port is connected to the network cable

(2) Communication lamp (green)

Used to display the status of CN5 and CN6 communication connections, as shown in the following table.

Connection lamp status	Explanation
ON	No communication connection was established with the master station
BLINKING	A communication connection has been established with the master station

6.2.5 Process Data PDO

PDO outputs process data in real time. PDO can be divided into RPDO (for receiving instructions from master station) and TPDO (for feeding back its own status from slave station).

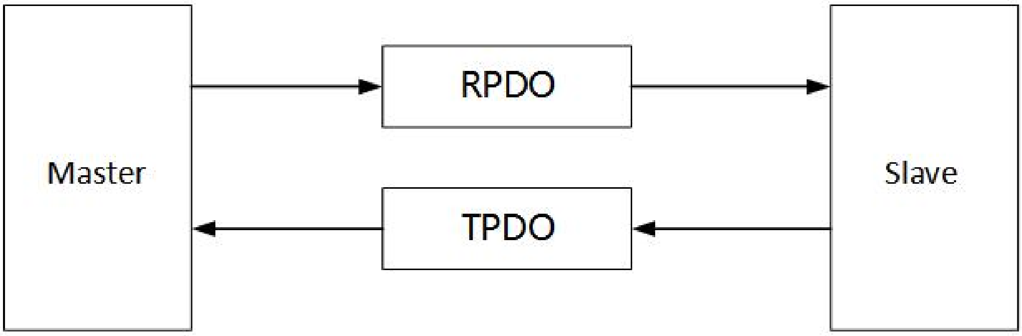


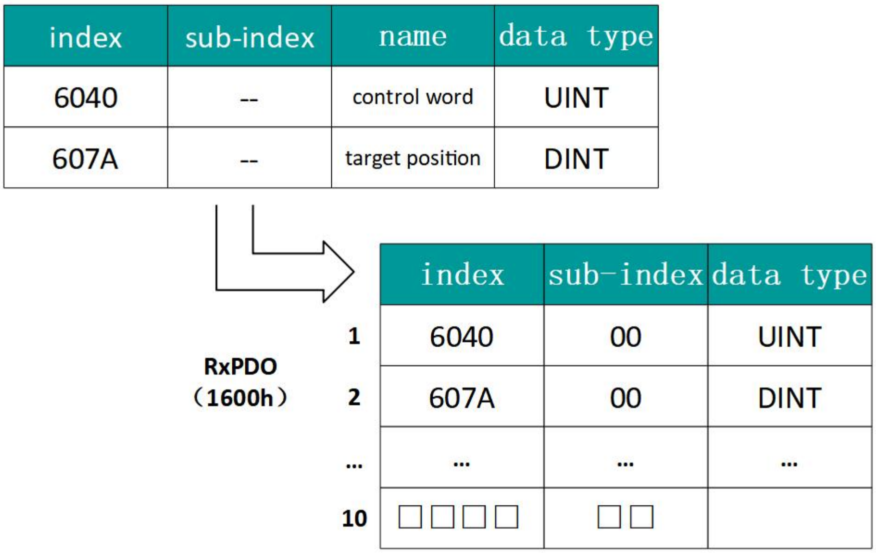
Figure 6-6 PDO schematic diagram

(1) PDO mapping parameters

PDO mapping is used to establish the mapping relationship between object dictionary and PDO. 1600h-17FFh is RPDO, 1A00h-1BFFh is TPDO:

Name	Parameter	Nature
RPDO	1600h	Variable mapping
	1701h ~ 1705h	Fixed mapping
TPDO	1A00h	Variable mapping
	1B01h	Fixed mapping

The following figure is an example of RxPDO mapping.



index	sub-index	name	data type
6040	--	control word	UINT
607A	--	target position	DINT

RxPDO (1600h)

	index	sub-index	data type
1	6040	00	UINT
2	607A	00	DINT
...	...	...	...
10	□□□□	□□	

Figure 6-7 Examples of RxPDO mapping

The data type is defined as follows:

Data type	Description	Numerical range
SINT	Signed 8bit	-128 ~ 127
USINT	Unsigned 8bit	0 ~ 255
INT	Signed 16bit	-32768 ~ 32767
UINT	Unsigned 16bit	0~65535
DINT	Signed 32bit	-21247483648 ~ 21247483647
UDINT	Unsigned 32bit	0 ~ 4294967295
STRING	String Value	ASCII

The following figure is an example of TxPDO mapping.

index	sub-index	name	data type
6041	--	control word	UINT
6064	--	position feedback	DINT
607A	--	actual speed	DINT

TxPDO (1A00h)

	index	sub-index	data type
1	6041	00	UINT
2	6040	00	DINT
3	606C	00	DINT
...	...	...	...
10	□□□□	□□	

Figure 6-8 Examples of TxPDO mapping

The following figure is an example of a SyncManager PDO mapping.

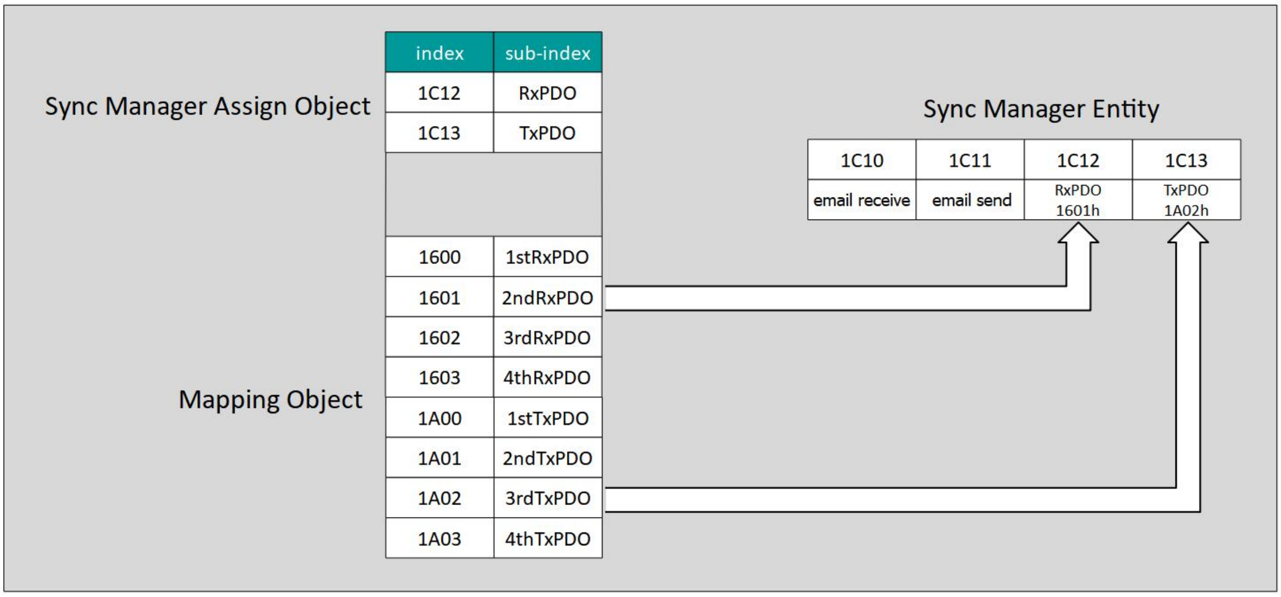


Figure 6-8 SyncManager PDO Mapping Example

(2) Synchronize management of PDO allocation settings

In EtherCAT periodic data communication, process data can contain multiple PDO mapping data objects. The data objects 0x1C10 ~ Ox1C2F used in CoE protocol define the corresponding PDO mapping object list of SM (Synchronous Management Channel), and multiple PDO can be mapped in different sub-indexes.

Index (hex)	Sub-index (hex)	Content
1C12	01	Choose to use one of 0x1600, 0x1701-0x1705 as the actual RPDO
1C13	01	Select to use one of 0x1A00, 0x1B01-0x1B04 as the actual TPDO

(3) PDO configuration

The PDO mapping parameter contains a pointer to the PDO corresponding process data that the PDO needs to send or receive, including index, sub-index and mapping object length. The sub-index 0 records the number N of objects mapped by the PDO, and the length of each PDO data can reach 4N bytes at most, which can map one or more objects at the same time. Sub-index ~ N is the mapping content. The mapping parameter content is defined as follows:

Number of digits	31	...	16	15	...	8	7	...	0
Description	Index			Sub-index			Object length		

The index and sub-index together determine the position of the object in the object dictionary, and the object length indicates the specific bit length of the object (hexadecimal representation)

Object length	bit length
08h	8
10h	16
20h	32

For example, the mapping parameter of 6040h-00 (control word) is 60400010h

Notice
The PDO configuration can only be designed when the EtherCAT communication state machine is in pre-operation (Pro-Operation, panel display 2), otherwise an error will be reported. The PDO configuration parameters cannot be stored in the EEPROM. Therefore, after each power-on, please reconfigure the mapping object, otherwise, the mapping object is the default parameter of the drive The SDO fault codes are returned when: Modify PDO parameters in non-pre-operation state; Pre-write values other than 1600/1701 ~ 1705 in 1C12; Values other than 1A00/1B01 ~ 1B04 are pre-written in 1C13. No more than 10 variable mappings can be added, otherwise the servo activation failure may occur.

6.2.6 Email Data SDO

EtherCAT Email data SDO is used to transmit aperiodic data, such as configuration of communication parameters, servo drive operation parameters and so on. EtherCAT's CoE service types include:

(1) Emergency information; ② SDO request; ③ SDO response; ④ TxPDO; ⑤ RxPDO; ⑥ Remote TxPDO sending request; ⑦ Remote RxPDO sending request; ⑦ SDO information.

Wecon VD3E series bus servo drives currently support ② SDO requests; ③ SDO response.

6.2.7 Distributed clock

Distributed clock enables all EtherCAT devices to use the same system time, thus controlling the synchronous execution of tasks of each device. The slave station device can generate a synchronization signal according to the synchronized system time. Wecon VD3E series bus servo drives only support DC synchronous mode.

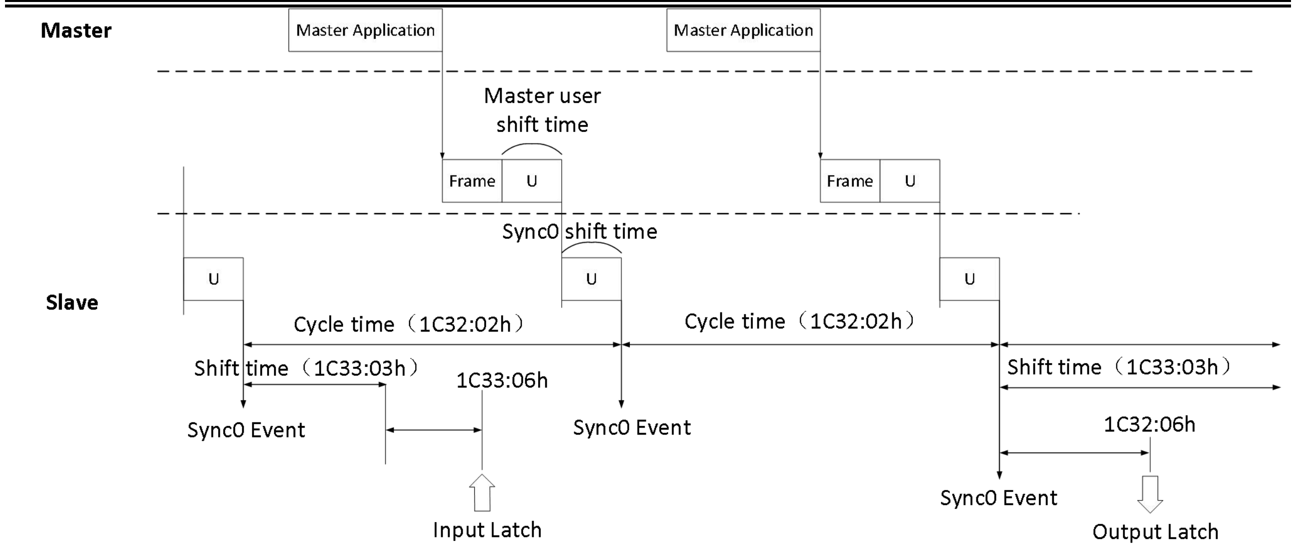


Figure 6-9 DC Synchronous Mode Schematic Diagram

6.2.8 Status Indication

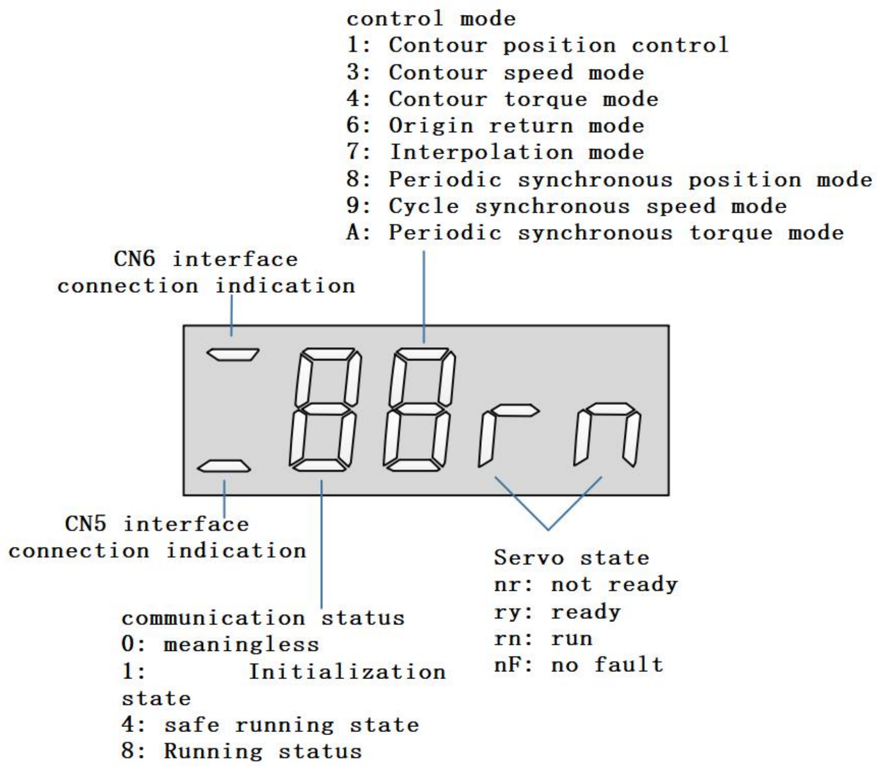


Figure 6-10 Status indication schema

Description:

(1) Communication connection status

The first digit tube from the left of the 5-bit LED indicator on the servo drive panel is used to display the connection status of the two Ethernet communication ports: upper "-" CN6 (OUT) and lower "-" CN5 (IN)

Long dark: No communication connectio**n detected**

Long Bright: A communication connection has been established

(2) Communication Operating status

The servo drive panel of the 5-bit LED indicator lamp is the second digit tube from the left, which is used to display the EtherCAT state machine status of the slave station in character form.

Panel display	Meaning
1	Initialization state
2	Pre-operation status
4	Safe operation status
8	Operating status

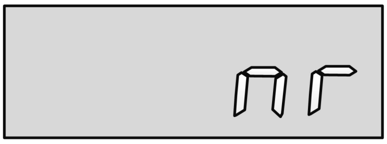
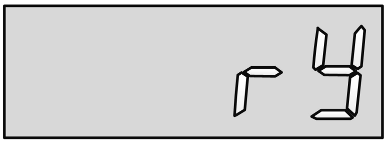
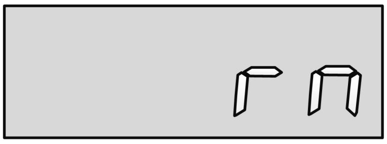
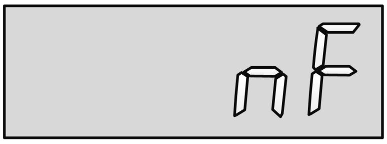
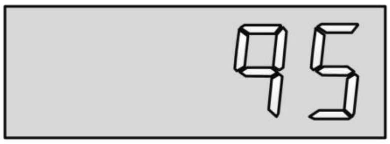
(3) Display of servo operation mode

Servo drive panel 5-bit LED indicator from the left of the third digit tube, used to display hexadecimal digital form display servo drive current operation mode.

Panel display	Meaning
1	Contour position control mode
3	Contour speed control mode
4	Contour torque control mode
6	Homing mode
7	Interpolation mode
8	Cyclic Synchronous Position mode
9	Periodic synchronous speed mode
A	Periodic synchronous torque mode

(4) **Servo status display**

Servo drive panel 5-bit LED indicator from the left of the fourth- and fifth-digit tube, used to display the servo status of the slave station.

Panel display	Definition
	Not ready nr
	Ready ry
	Run rn
	Failure-free nF
	Quick stop qs

6.2.9 Introduction to CiA402 Control

The use of Wecon VD3E Series Bus Type servo drives must be guided according to the procedure specified in Standard 402 Protocol.

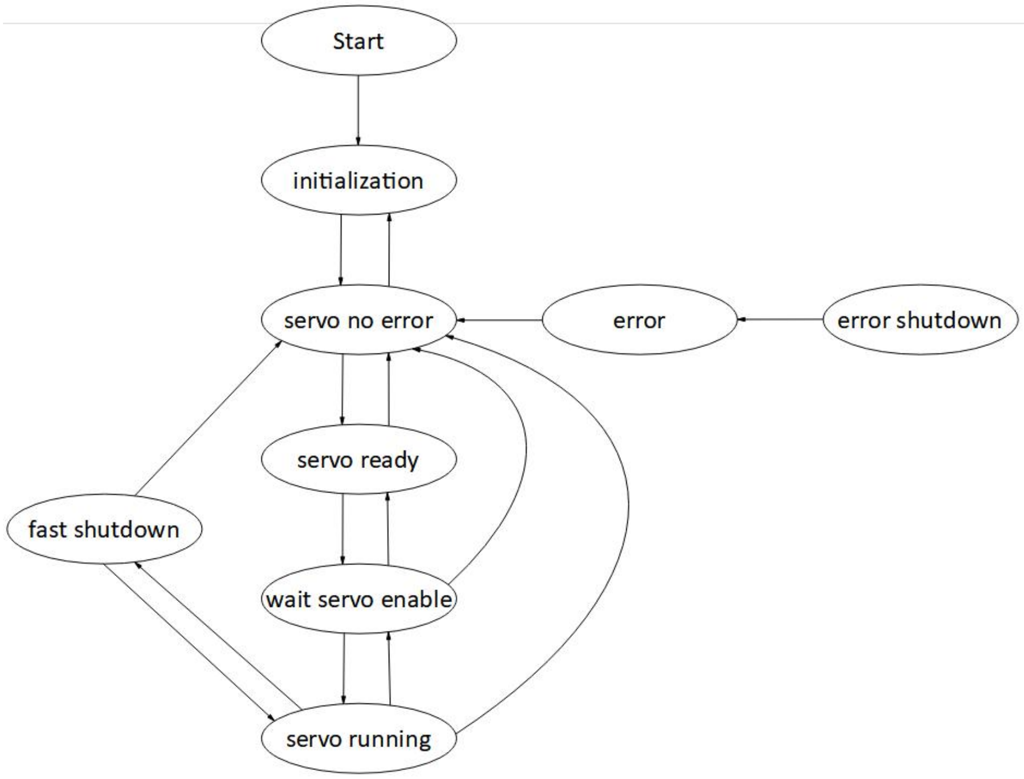


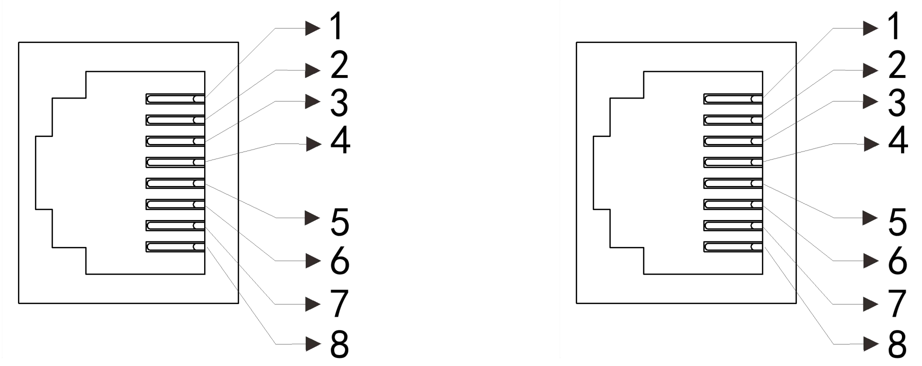
Figure 6-11 CiA402 state machine switching schema

Status	Description
Initialization	Drive initialization, internal self-test has completed. Parameters cannot be set, and servo drive function cannot be performed.
Servo trouble-free	There is no fault in the servo drive. Parameters can be set.
Servo ready	Servo drives are ready. Parameters can be set.
Wait to turn on servo enable	The servo drive waits to turn on the servo enable. Parameters can be set.
Servo operation	The servo drive is running normally.
Quick stop	The servo drive is performing the quick shutdown function. Only function codes with the attribute "Run valid" can be set.

Status	Description
Malfunction shutdown	The servo drive is performing the fault shutdown function. Only function codes with the attribute "Run valid" can be set.
Fault	Failure shutdown is complete, and all drive functions are disabled. Allow parameters to be changed to troubleshoot.

6.2.10 Basic Characteristics

EtherCAT network cable is connected to the CN5 (IN), CN6 (OUT) interfaces, and its electrical characteristics conform to IEEE 802.3 standard.



(a) EtherCAT Ethernet Communication Connection Port (IN)

(b) EtherCAT Ethernet Communication ConnectorMouth (OUT)

Figure 6-12 Communication port

Pin	Name	Function description
1	TX+	Sending data+
2	TX-	Sending data-
3	RX+	Receiving data+
4	-	-
5	-	-
6	RX-	Receiving data-
7	-	-
8	-	-

EtherCAT communication topology connections are very flexible, taking linear connections and ring connections as examples:

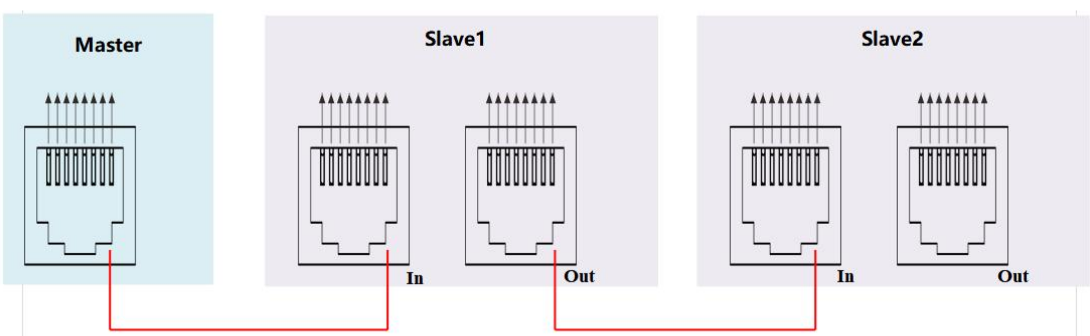


Figure 6-13 Linear connection

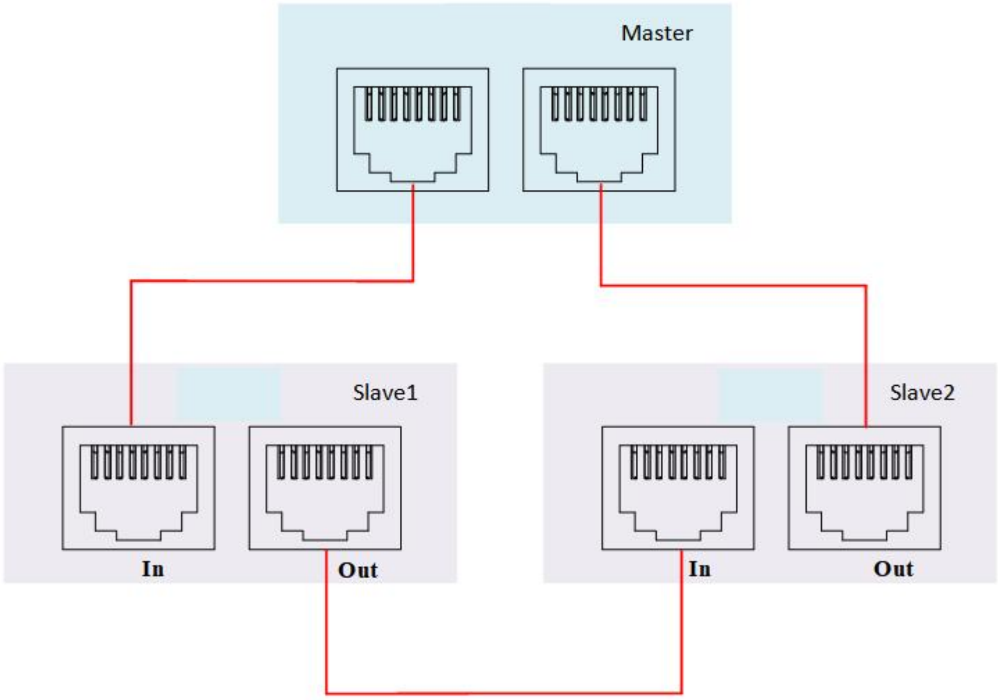


Figure 6-14 Ring connection

Chapter 7 Operation Running

7.1 Basic Settings

7.1.1 Pre-operation Inspection

Table 7-1 Check contents before operation

Number	Content
Wiring	
1	The main circuit input terminals (L1, L2 and L3) of servo drive must be properly connected.
2	The main circuit output terminals (U, V, W) of the servo drive and the main circuit cables (U, V, W) of the servo motor must have the same phase and be connected correctly.
3	The main circuit power input terminals (L1, L2 and L3) and the main circuit output terminals (U, V and W) of servo drive cannot be short-circuited.
4	The wiring of each control signal cable of the servo drive is correct: the external signal wires such as brake and overtravel protection have been reliably connected.
5	Servo drive and servo motor must be grounded reliably.
6	When using an external braking resistor, the short wiring between drive C and D must be removed.
7	The force of all cables is within the specified range.
8	The wiring terminals have been insulated.
Environment and Machinery	
1	There is no iron filings, metal, etc. that can cause short circuits inside or outside the servo drive.
2	The servo drive and external braking resistor are not placed on combustible objects.
3	The installation, shaft and mechanical structure of the servo motor have been firmly connected.

7.1.2 Power on

Connect the main circuit power supply

(1) After power on the main circuit, the bus voltage indicator shows no abnormality, and the panel display "ry", indicating that the servo drive is in an operational state, waiting for the upper computer to give the servo enable signal.

If the drive panel displays other fault codes, please refer to “Chapter 10 Faults” to analyze and eliminate the cause of the fault.

(2) Set the servo drive enable (S-ON) to invalid (OFF)

Please refer to "6.2.9 CiA402 Control Introduction" for relevant process description

7.1.3 Jog Operation

Inching operation is used to judge whether the servo motor can rotate normally, and whether there is abnormal vibration and abnormal sound when rotating. Inching operation can be through panel inching operation function, and the motor takes the current stored value of object dictionary P10-01 (200A-01) as inching speed.

(1) Panel jog operation

Enter P10-01 (200A-01) through panel key operation. After pressing the confirmation key, the panel will display the current inching speed. At this time, the inching running speed can be adjusted by pressing the "up" or "down" key; After adjusting the inching speed, press the "Confirm" key. At this time, the panel displays "JOG" and is in a flashing state. Press the "Confirm" key again to enter the inching operation mode (at this time, the motor is powered on!). Press the "up" key and "down" key for a long time to realize the continuous forward or reverse rotation of the motor. Press the "Mode" key to exit the inching operation mode. Please refer to "5.3.2 Inching display".

Index code	Name	Setting method	Valid time	Default	Range	Definition	Unit
200A-01	JOG speed	Execute Setting	Valid immediately	0	0~3000	JOG speed	rpm

(2) Jog operation of the servo debugging platform

Open the jog operation interface of the software “Wecon SCTool”, set the jog speed value in the "set rotating speed" in the "manual operation", click the "servo on" button on the interface, and then achieve the jog forward and reverse function through the "forward rotation" or "reverse rotation" button on the interface. After clicking the "Servo Close" button, exit the inching operation mode.

Notice

The communication control function of EtherCAT master station and the inching operation of servo drive can not be used at the same time;

If you enter the inching mode, you need to exit the inching operation before you can use EtherCAT to control;

If you enter the EhterCAT activation step, you need to exit the EtherCAT control before you can perform the inching operation of the servo drive.

7.1.4 Rotation Direction Selection

By setting the rotate direction, the rotate direction of the motor can be changed without changing the polarity of the input command

Index code	Name	Setting method	Valid time	Default	Range	Definition	Unit
2000-04	Rotate direction	Shutdown Setting	Valid immediately	0	0 to 1	Forward rotation: Face the motor shaft to watch 0: standard setting (CW is forward rotation) 1: reverse mode (CCW is forward rotation)	-

7.1.5 Braking Resistance

The servo motor is in the generator state when decelerating or stopping, the motor will transfer energy back to the drive, which will increase the bus voltage. When the bus voltage exceeds the braking point, The drive can consume the feedback energy in the form of thermal energy through the braking resistor. braking resistors can be built-in or external, but they cannot be used at the same time. When selecting an external braking resistor, the short tab on the servo drive needs to be removed.

The basis for judging whether the braking resistor is built-in or external.

(1) The maximum brake energy calculated value > the maximum brake energy absorbed by capacitor, and the brake power calculated value ≤ the built-in braking resistor power, use the built-in braking resistor.

(2) The maximum brake energy calculated value > the maximum brake energy absorbed by capacitor, and the brake power calculated value > the built-in braking resistor power, use external braking resistor.

Index code	Name	Setting method	Valid time	Default	Range	Definition	Unit
2000-09	Braking resistance setting	Execute Setting	Valid immediately	0	0 to 3	0: use built-in braking resistor 1: use external braking resistor and natural cooling 2: use external braking resistor and forced air cooling; (cannot be set) 3: No braking resistor is used, it is all absorbed by capacitor.	-
2000-0A	External braking resistor	Execute Setting	Valid immediately	50	0 to 65535	Used to set the resistance value of the external braking resistor	Ω

Index code	Name	Setting method	Valid time	Default	Range	Definition	Unit
	resistance					of a certain type of drive	
2000-0B	External braking resistor power	Execute Setting	Valid immediately	100	0 to 65535	It is used to set the external braking resistor power of a certain type of drive.	W

7.1.6 Servo operation

(1) Set servo enable (S-ON) to active (ON)

The servo drive is in an operation state, and the monitor displays "rn", but because there is no command input at this time, the servo motor does not rotate and is in a locked state.

S-ON can be configured and selected according to the function selection of DI terminal in DIDO configuration of object dictionary.

(2) Input the instruction and the motor rotates

Input appropriate instructions during operation, first run the motor at a low speed, and observe the rotation to see if it conforms to the set rotation direction. Through Wecon SCTools software, the actual running speed, bus voltage and other parameters of the motor were observed.

(3) Timing diagram of power on

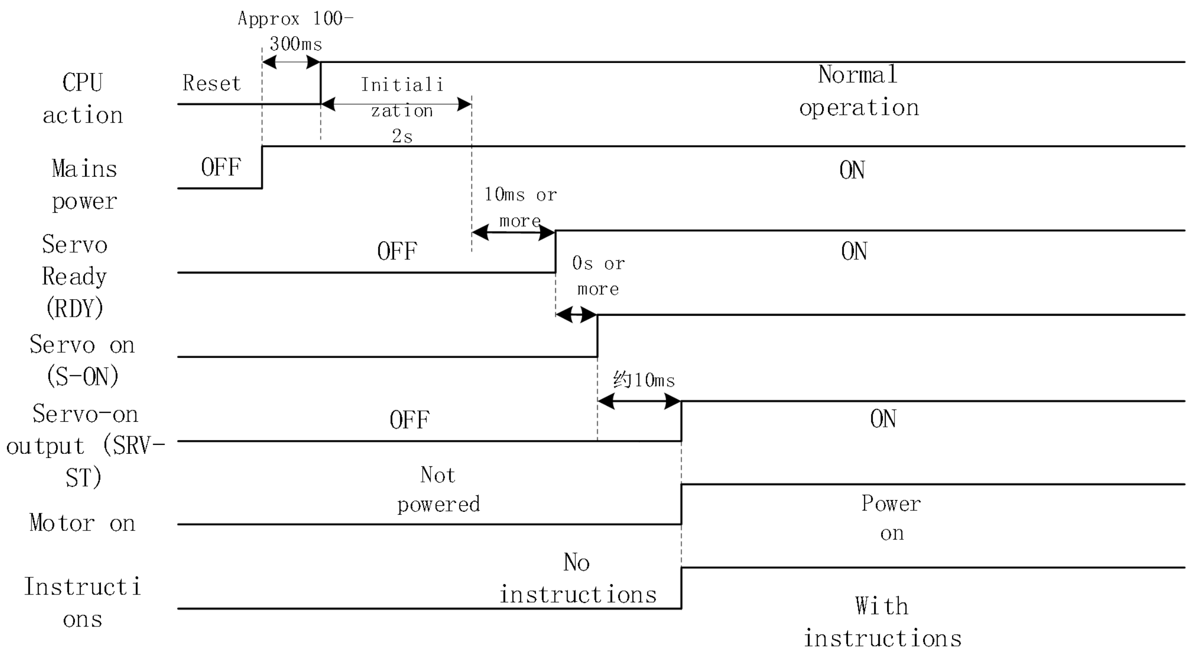


Figure 7-1 Power on timing diagram

7.1.7 Servo Stop

According to different shutdown modes, it can be divided into free shutdown and zero-speed shutdown, and their respective characteristics are shown in Table 7-2. According to the shutdown state, it can be divided into free running state and position keeping lock, as shown in Table 7-3:

Table 7-2 Comparison of two shutdown modes

Shutdown mode	Shutdown description	Shutdown characteristics
Free stop	Servo motor is not energized and decelerates freely to 0. The deceleration time is affected by factors such as mechanical inertia and mechanical friction.	Smooth deceleration, small mechanical shock, but slow deceleration process.
Zero-speed stop	The servo drive outputs reverse braking torque, and the motor quickly decelerates to zero-speed.	Rapid deceleration with mechanical shock, but fast deceleration process.

Table 7-3 Comparison of two shutdown states

Shutdown status	Free operation status	Position locked
Characteristics	After the motor stops rotating, the motor is not energized, and the motor shaft can rotate freely.	After the motor stops rotating, the motor shaft is locked and cannot rotate freely.

Servo enable (S-ON) OFF shutdown

Relevant parameters of servo OFF shutdown mode are shown in Table 7-4.

Table 7-4 Parameter details of servo OFF shutdown mode

Index code	Name	Setting method	Valid time	Default	Range	Definition	Unit
2000-05	Servo OFF shutdown mode	Shutdown Setting	Valid immediately	0	0 to 1	0: Free shutdown, and the motor shaft remains free state; 1: Zero speed shutdown, and the motor shaft remains in a free state.	-

(2) Emergency shutdown

It is free shutdown mode at present, and the motor shaft remains in a free state. The corresponding configuration and selection could be selected through the DI terminal function of the function code "DIDO configuration".

(3) Overtravel shutdown

Overtravel means that the movable part of the machine exceeds the set area. In some occasions where the servo moves horizontally or vertically, it is necessary to limit the movement range of the workpiece. The overtravel is generally detected by limit switches, photoelectric switches or the multi-turn position of the encoder, that is, hardware overtravel or software overtravel.

Once the servo drive detects the action of the limit switch signal, it will immediately force the speed in the current direction of rotation to 0 to prevent it from continuing, and it will not be affected for reverse rotation. The overtravel shutdown is fixed at zero speed and the motor shaft remains locked.

The corresponding configuration and selection can be selected through the DI terminal function of the object dictionary "DIDO configuration". The default function of DI3 is POT and DI4 is NOT, as shown

Function code	Name	Setting method	Valid time	Default	Range	Definition	Unit
P06-08	DI_3 channel function selection	Operation Setting	Power on again	3	0 to 32	0: Close (Not used) 01: S-ON Servo enable 02: A-CLR Fault and alarm clear 03: POT Forward drive forbidden 04: NOT Reverse drive forbidden 06: CL Clear 08: E-STOP Emergency stop 26: HOMEORG Homing mode Other: Reserved	-
P06-09	DI_3 channel logic selection	Operation Setting	Valid immediately	0	0 to1	DI port input logic valid function selection 0: Always on input, 1: Always off input.	-
P06-10	DI_3 input source selection	Operation Setting	Valid immediately	4	0 to 1	Select enabled Di_3 port type 0: Hardware DI_3 input terminal 1: Virtual DI_3 input terminal	-
P06-11	DI_4 channel function selection	Operation Setting	Valid immediately	0	0 to 1	0: Close (Not used) 01: S-ON Servo enable 02: A-CLR Fault and alarm clear 03:POT Forward drive forbidden 04: NOT Reverse drive	-

Function code	Name	Setting method	Valid time	Default	Range	Definition	Unit
						forbidden 06: CL Clear 08:E-STOP Emergency stop 26: HOMEORG Homing mode Other: Reserved	
P06-12	DI_4 channel logic selection	Operation Setting	Valid immediately	0	0 to 1	DI port input logic validity function selection 0: Always on input. Switch closed 1: Always off input.	-
P06-13	DI_4 input source selection	Operation Setting	Valid immediately	0	0 to 1	Select enabled DI_4 port type 0: Hardware DI_4 input terminal 1: Virtual DI_4 input terminal	-

(4) Malfunction shutdown

When the machine fails, servo will perform a fault shutdown operation. The current shutdown mode is fixed to the free shutdown mode, and the motor axis remains in a free status.

7.1.8 Brake Holding Device

The brake is a mechanism that prevents the servo motor axis from moving when the servo drive is in a non-operating state, and keeps the motor locked in position, so that the moving part of the machine will not move due to its own weight or external force.

Notice
The brake device is built into the servo motor, which is only used as a non-energized fixed special mechanism. It cannot be used for braking purposes, and can only be used when the servo motor is kept stopped; ✎ After the servo motor stops, turn off the servo enable (S-ON) in time; ✎The brake coil has no polarity; ✎When the brake coil is energized (that is, the brake is open), magnetic flux leakage may occur at the shaft end and other parts. If users need to use magnetic sensors and other device near the motor, please pay attention! ✎When the motor with built-in brake is in operation, the brake device may make a clicking sound, which does not affect the function.

(1) Wiring of brake device

Brake input signal is no polar. You need to use 24V power. The standard wiring between brake signal BK and brake power is as below.

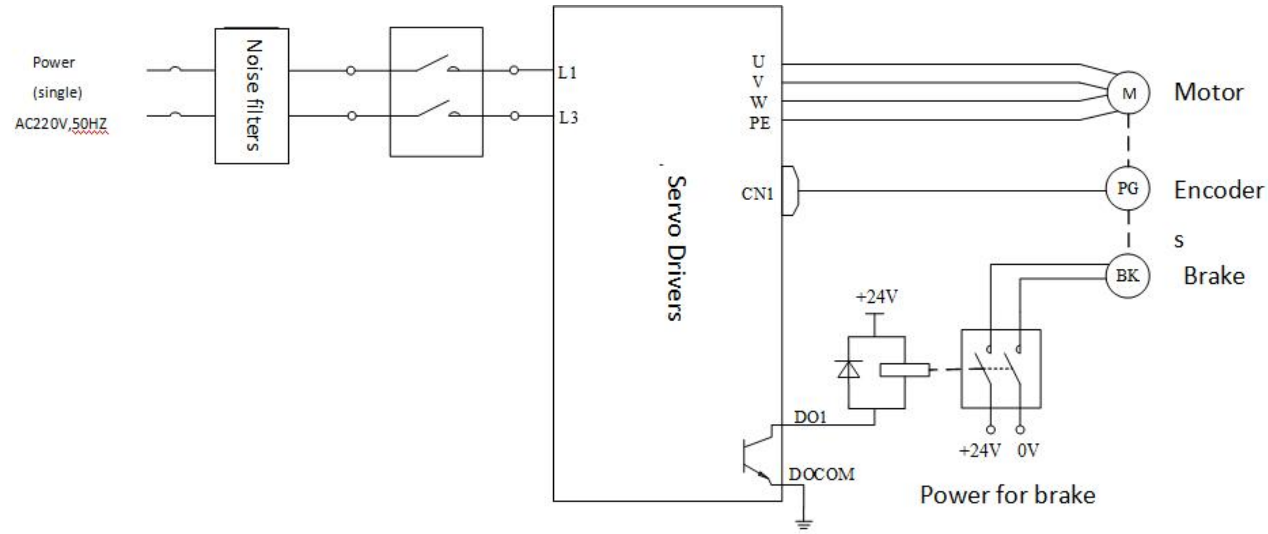


Figure 7-2 Brake wiring

Notice
① The length of the motor brake cable needs to fully consider the voltage drop caused by the cable resistance, and the brake operation needs to ensure that the voltage input is 24V. ② It is recommended to use the power supply alone for the brake device. If the power supply is shared with other electrical device, the voltage or current may decrease due to the operation of other electrical device, which may cause the brake to malfunction. ③It is recommended to use cables above 0.5 mm^2.

(2) Brake software setting

For a servo motor with brake, one DO terminal of servo drive must be configured as function 141 (BRK-OFF, brake output), and the valid logic of the DO terminal must be determined.

Related function code

DO function code	Function name	Function
141	BRK-OFF, brake output	The output signal indicates that the brake of the servo motor is released

Table 7-6 Relevant parameters of brake setting

Index code	Name	Setting method	Valid time	Default	Range	Definition	Unit
2001-1E	Delay from brake output to instruction reception	Execute Setting	Valid immediately	250	0 to 500	Set delay that from the brake (BRK-OFF) output is ON to servo drive allows to receive input instruction. Between. When the brake output (BRK-OFF) is not allocated, this function code has no effect.	ms
2001-1F	In the static state, delay from the brake output is OFF to the motor is not energized.	Execute Setting	Valid immediately	150	1 to 1000	When the motor is in a static state, set the delay time from the brake (BRK-OFF) output is OFF to the servo drive is in the non-powered state. When the brake output (BRK-OFF) is not allocated, this function code has no effect.	ms
2001-20	Rotation status, when the brake output OFF, the speed threshold.	Execute Setting	Valid immediately	30	0 to 3000	When the motor is rotating, the motor speed threshold that is allowed when the brake (BRK-OFF) output is OFF. When the brake output (BRK-OFF) is not allocated, this function code has no effect.	rpm

Index code	Name	Setting method	Valid time	Default	Range	Definition	Unit
2001-21	Rotation status, servo enable OFF to brake output OFF Delay	Operation Setting	Valid immediately	500	1~2000	The motor is rotating, the delay time that is allowed from the brake (BRK-OFF) output OFF to the servo enable (S-ON) OFF. When the brake output (BRK-OFF) is not allocated, this function code has no effect.	Ms

According to the state of the servo drive, the working sequence of the brake mechanism can be divided into the brake sequence in the normal state of the servo drive and the brake sequence in the fault state of the servo drive.

(3) Servo drive brake timing in normal state

The brake timing of the normal state can be divided into:

The servo motor is stationary (the actual speed of the motor is lower than 20rpm) and the servo motor is rotating (the actual speed of the motor is 20 rpm and above).

1) Brake timing when the servo motor is stationary

When the servo enable is changed from ON to OFF, if the actual speed of the current motor is lower than 20rpm, the servo drive acts according to the stationary braking timing, and the specific timing actions are as follows Figure 7-18 As shown in.

Notice
(1) After the brake output is set from OFF to ON, do not input the position/speed/torque command during 2001-1Eh, otherwise the command will be lost or run incorrectly. ✎When applied to a vertical axis, the external force or the weight of the mechanical moving part may cause the machine to move slightly. When the servo motor is stationary, and the servo enable is OFF, the brake output will be OFF immediately. However, the motor is still powered on within the time of 2001-1Fh to prevent mechanical movement due to its own weight or external force.

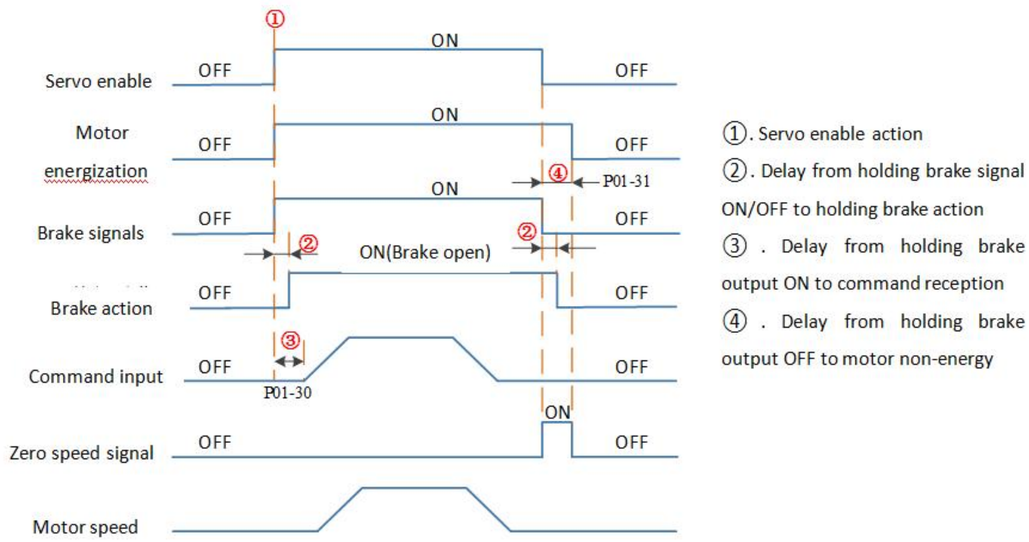


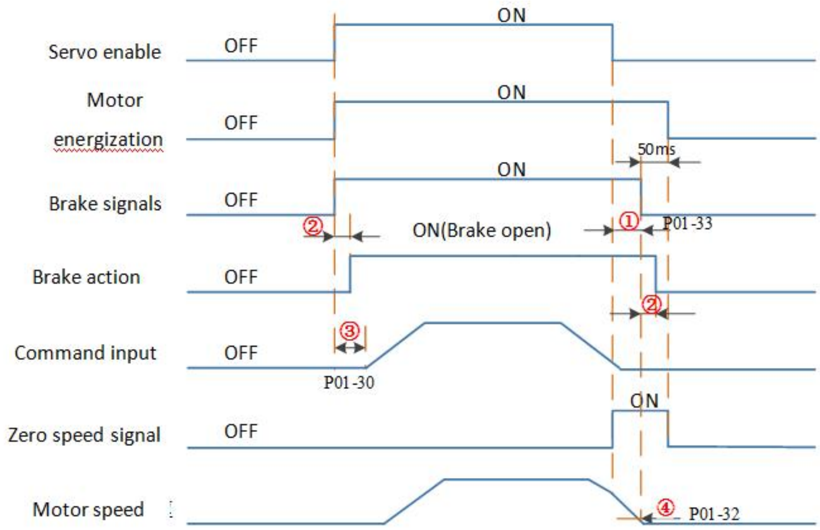
Figure 7-3 Braking timing when the motor is stationary

Note: Please refer to the relevant specifications of the motor for the delay time of the brake contact at ② in the figure.

2) The brake timing when the servo motor is rotating

When the servo enable is from ON to OFF, if the actual motor speed is greater than or equal to 20 rpm, the drive will act in accordance with the rotation brake sequence. The specific sequence action is shown in Figure 7-4.

Notice
When the servo enable is turned from OFF to ON, within 2001-30, do not input position, speed or torque instructions, otherwise the instructions will be lost or operation errors will be caused; ✎When the servo motor rotates, the servo enable is OFF and the servo motor is in the zero-speed shutdown state, but the brake output must meet any of the following conditions before it could be set OFF: 2001-21h time has not arrived, but the motor has decelerated to the speed set in 2001-20h; 2001-21h time is up, but the motor speed is still higher than the set value of 2001-20h. After the brake output changes from ON to OFF, the motor is still in communication within 50ms to prevent the mechanical movement from moving due to its own weight or external force.

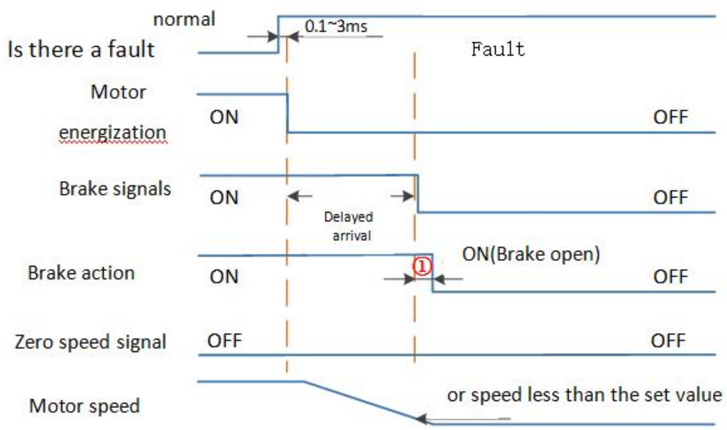


① . Servo enable off to holding brake output off time delay
② . delay from holding brake signal ON/OFF to holding brake action
③ . Delay from holding brake output ON to command reception
④ . Speed threshold when the

Figure 7-4 Braking timing when the motor rotates

(4) Brake timing when the servo drive fails

The brake timing (free shutdown) in the fault status is as follows.



①. Time delay from holding brake signal ON/OFF to holding brake action

Figure 7-5 Braking timing in fault state (free shutdown)

✎**Note:** The "delay arrival" of the brake signal is about 20ms, and the actual parameter is subject to the motor manufacturer.

7.2 Servo State Setting

The use of Wecon VD3E Series Bus Type servo drives must be guided according to the procedure specified in Standard 402 Protocol.

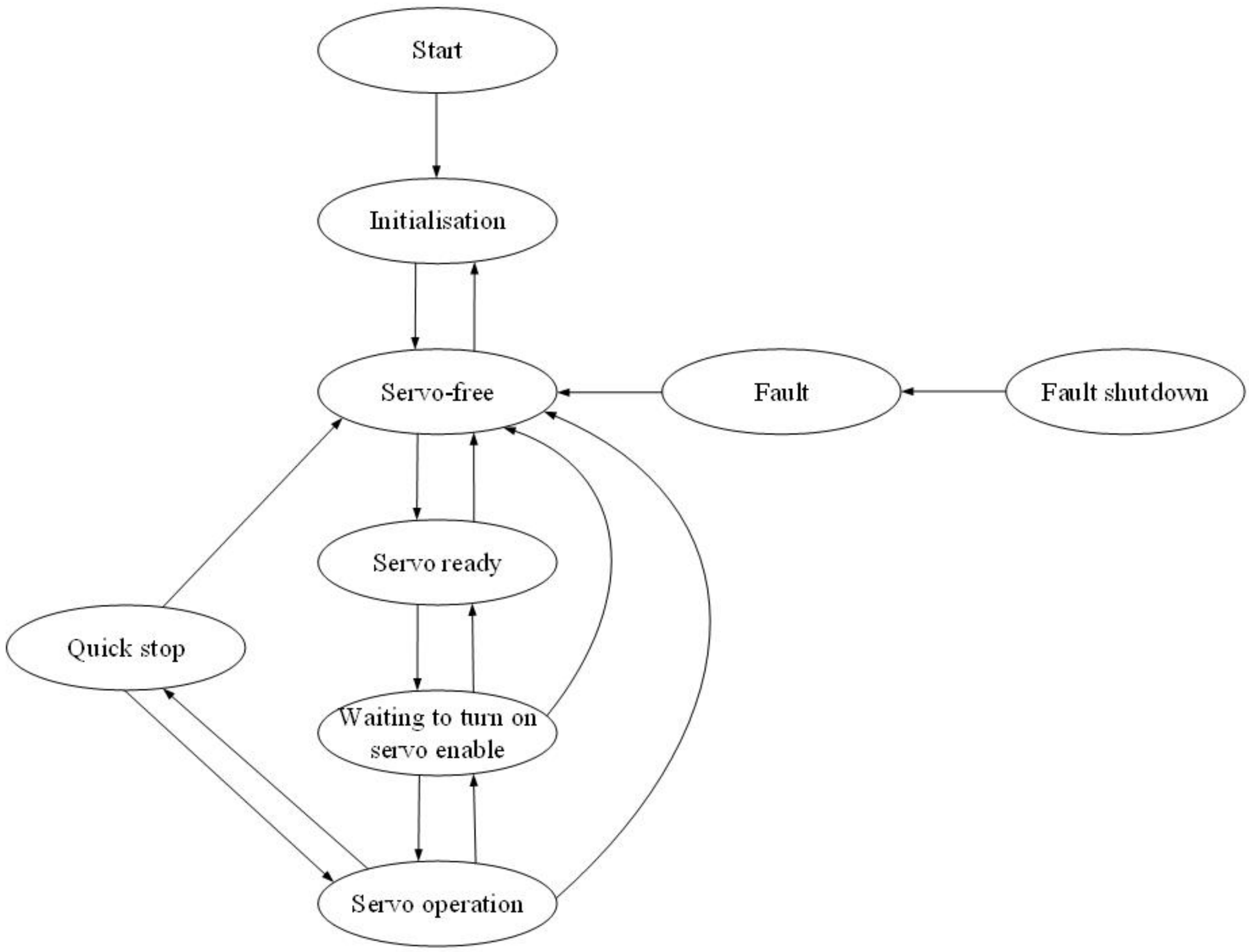


Figure 7-6 CiA402 state machine switching schema

Status	Description
Initialization	Drive initialization, internal self-test has completed. Parameters cannot be set, and servo drive function cannot be performed.
Servo trouble-free	There is no fault in the servo drive. Parameters can be set.
Servo ready	Servo drives are ready. Parameters can be set.
Wait to turn on servo enable	The servo drive waits to turn on the servo enable. Parameters can be set.
Servo operation	The servo drive is running normally.
Quick shutdown	The servo drive is performing the quick shutdown function. Only function codes with the attribute "Run valid" can be set.
Malfunction shutdown	The servo drive is performing the fault shutdown function. Only function codes with the attribute "Run valid" can be set.
Fault	Failure shutdown is complete, and all drive functions are disabled. Allow parameters to be changed to troubleshoot.

State switching	Control word 6040h
Power on =>Initialization	Natural transition without control instruction
Initialization =>Servo trouble-free	Natural transition without control instruction If there is an error in the initialization process, go directly to the "failure shutdown" state.
Servo trouble-free =>Servo ready	0x0006
Servo ready =>Wait to turn on servo enable	0x0007
Wait to turn on servo enable =>Servo operation	0x000F
Servo operation =>Wait to turn on servo enable	0x0007
Wait to turn on servo enable =>Servo ready	0x0006
Servo ready =>Servo trouble-free	0x0000
Servo operation =>Servo ready	0x0006
Servo operation =>Servo trouble-free	0x0000
Wait to turn on servo enable =>Servo trouble-free	0x0000
Servo operation =>Quick shutdown	0x0002
Quick shutdown =>Servo trouble-free	The quick shutdown mode 605A is selected as 0 ~ 3. After the shutdown is completed, it will transition naturally without control instruction.
=>Failure shutdown	Once the servo drive fails, it automatically switches to the "fault shutdown" state without control instruction.
Failure shutdown =>Malfunction	After the fault shutdown is completed, it will make a natural transition without control instructions.
Failure =>Servo trouble-free	0x80
Quick shutdown =>Servo operation	The quick shutdown mode 605A is selected as 0 ~ 3, and 0x0F is sent after the shutdown is completed.

7.2.1 Control word

6040h	Name	Setting method	Valid time	Default	Set range	Application category	Unit
	Control word	Operation setting	Valid immediately	0	0~65535	Basic settings	-

6040h	Name	Setting method	Valid time	Default	Set range	Application category	Unit

Used to set control instructions. It is meaningless to assign each bit of a control word separately, and it must be combined with other bits to form a certain control instruction.
bit0 ~ bit3 have the same meaning in each control mode of servo drive, and commands must be sent in sequence before the servo drive can be switched according to CiA402 state machine.

bit	Name	Description
0	Servo operation can be started	0: Invalid
		1: valid
1	Turn on the main circuit	0: Invalid
		1: valid
2	Quick shutdown	0: Invalid
		1: valid
3	Servo operation	0: Invalid
		1: valid
4 - 6	Operation mode	It is related to the operation mode of servo drive
7	Fault reset	Used to clear reset faults: The rising edge of bit7 is valid; bit7 is kept at 1, and other control instructions are invalid.

7.2.2 Status word

6041h	Name	Setting method	Valid time	Default	Set range	Application category	Unit
	Status word	Operation setting	Valid immediately	0	0~65535	-	-

Used to reflect the status of servo drive.

Bit	Name	Description
0	Servo ready	0: Invalid 1: Valid
1	Servo operation can be started	0: Invalid 1: Valid
2	Servo operation	0: Invalid 1: Valid
3	Fault	0: Invalid 1: Valid
4	Electrical connection of main circuit	0: Invalid 1: Valid
5	Quick shutdown	0: Invalid 1: Valid
6	Servo is not operational	0: Invalid 1: Valid
7	Warning	0: Invalid 1: Valid
8	-	-
9	Remote control	0: Invalid 1: Valid
10	Target arrival	0: Invalid 1: Valid
……		

Bit 0 ~ bit 9 have the same meaning in all control modes of servo drive. After the control word 6040h sends commands in sequence, the servo feeds back the determined state.

Setting value (binary number)	Description
xxxx xxxx x0xx 0000	Servo is not ready
xxxx xxxx x1xx 0000	Startup failure
xxxx xxxx x01x 0001	Servo ready
xxxx xxxx x01x 0011	Start up
xxxx xxxx x01x 0111	Servo enable
xxxx xxxx x00x 0111	Fault shutdown valid
xxxx xxxx x0xx 1111	Fault response valid
xxxx xxxx x0xx 1000	Fault

7.3 Servo Mode Settings

7.3.1 Servo Mode Introduction

The object dictionary 6060h is used to display servo modes supported by servo drives.

6060h	Name	Setting method	Valid time	Default	Set range	Application category	Unit
	Servo mode selection	Stop setting	Valid immediately	0	0 ~ 10	-	-

Setting value	Name	Remark
0	-	
1	Contour position control mode	
2	-	
3	Contour speed control mode	
4	Contour torque control mode	Please refer to "7.7 Profile torque mode (PT)" for details
5	-	
6	Origin return mode	Please refer to "7.8 Homing Mode (HM)" for details
7	Interpolation mode	
8	Cyclic Synchronous Position mode	Please refer to "7.4 Cyclic Synchronous Position mode (CSP)" for details
9	Periodic synchronous speed mode	Please refer to "7.5 Cyclic Synchronous Velocity mode (CSV)" for details-
10	Periodic synchronous torque mode	Please refer to "7.6 Cyclic Synchronous Torque mode (CST)" for details

Used to set the operation mode of servo drive.

7.3.2 Mode switching

Pay attention to the following when switching modes:

① Whatever the servo drive state is, the unexecuted position command will be discarded after switching from the Cyclic Synchronous Position mode to other modes.

② Whatever the servo drive state is, after switching into other modes from the periodic synchronous speed mode, servo first executes ramp shutdown, and then switch into other modes after the shutdown is completed.

③ When the servo drive is running the origin return mode, it is not allowed to switch to other modes; When origin return is completed or interrupted (failure or invalid enable), other modes can be switched into.

④ When the servo drive is in run state, when switching from other modes to periodic synchronous mode, please send command at an interval of at least 1ms, otherwise instructions will be lost or wrong.

7.3.3 Communication cycles supported by different modes

Mode / Cycle time	Cyclic Synchronous Position mode	Cyclic Synchronous Velocity mode	Homing Mode
125us	✔	✔	✔

7.4 Cyclic Synchronous Position Mode (CSP)

7.4.1 Control Block Diagram

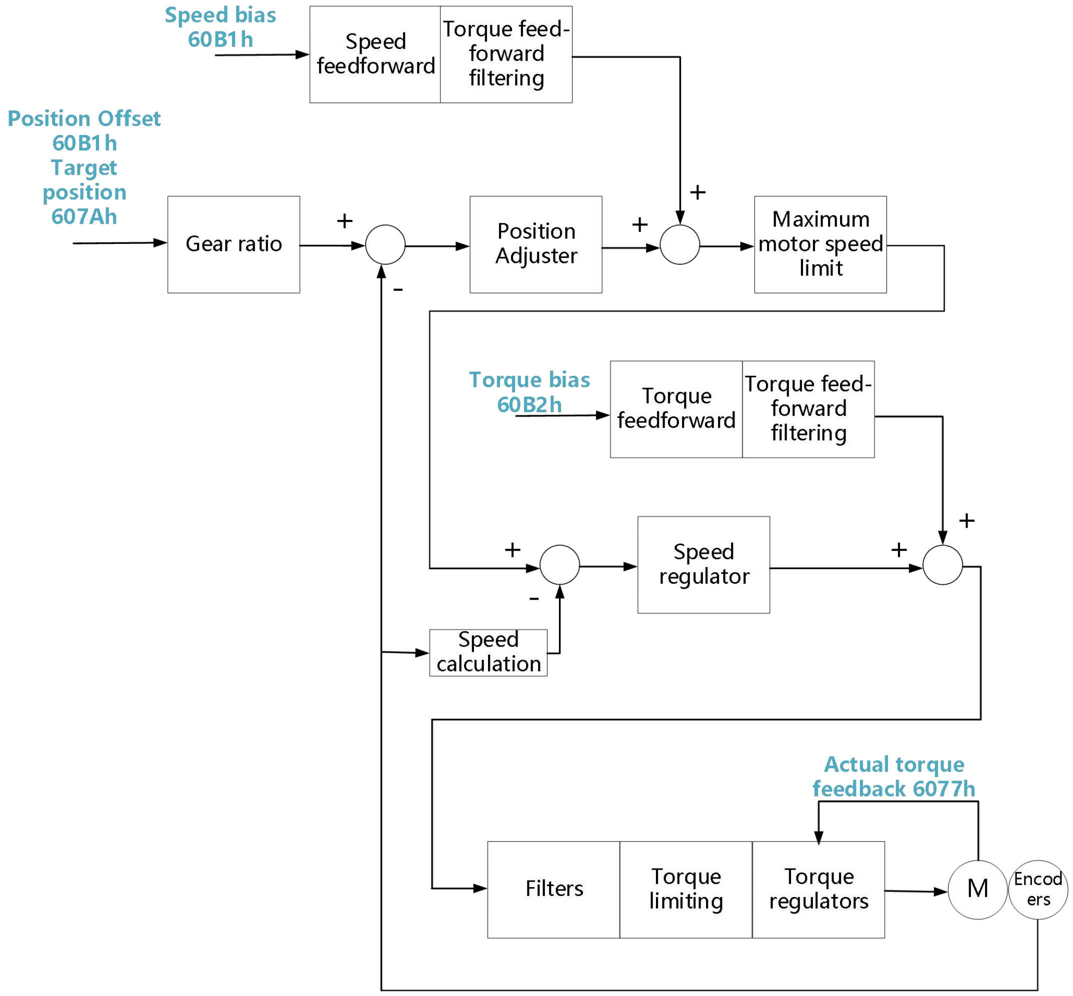


Figure 7-7 Periodic synchronization position mode control block diagram

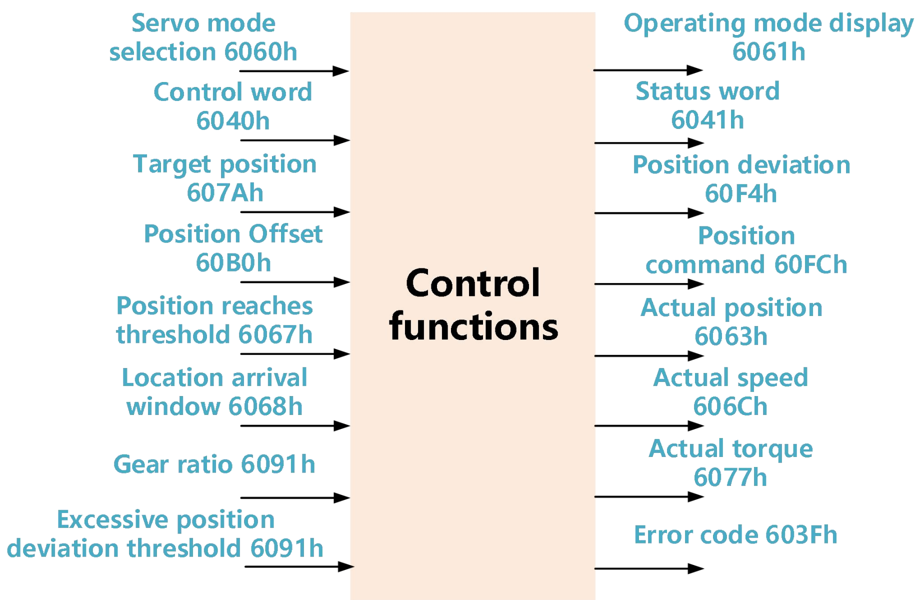


Figure 7-8 Input and output object

7.4.2 Related objects

(1) Control word 6040h

Bit	Name	Description
0	Servo operation can be started	When bit0 to bit3 are all 1, it indicates the start of operation
1	Turn on the main circuit	
2	Quick shutdown	
3	Servo operation	

(2) Status word 6041h

Bit	Name	Description
10	Target arrival	-
11	Software internal position overrun	-
12	Slave station following instruction	-
13	Following error	-
14	DDL motor angle identification complete	-
15	Origin return completed	-

Index (Hex)	Object dictionary name	Accessibility	Unit	Bit length	Set range
603F	Error code	RO	-	16	0 to 65535
6040	Control word	RW	-	16	0 to 65535
6041	Status word	RO	-	16	0 to 65535
6060	Servo mode selection	RW	-	8	0 to 10
6061	Run mode display	RO	-	8	0 to 10
6062	Position instruction	RO	Instruction unit	32	-
6063	Position feedback	RO	Encoder unit	32	-
6064	Position feedback	RO	Instruction unit	32	-
6065	Threshold of excessive position deviation	RW	Instruction unit	32	0 to 2^{32}-1
6067	Position reaches threshold	RW	Encoder unit	32	0 to 2^{32}-1
6068	Position arrival window	RW	ms	32	0 to 65535
606C	Actual speed	RO	Instruction		-

Index (Hex)	Object dictionary name	Accessibility	Unit	Bit length	Set range
			unit/s		
6077	Actual torque	RO	0.1%		-5000 to 5000
607A	Target location	RW	Instruction unit	32	-2^{31} to 2^{31}-1
6091: 01	Electronic gear ratio numerator	RW	-	32	1 to 2^{32}-1
6091: 02	Electronic gear ratio denominator	RW	-	32	1 to 2^{32}-1
2002-01	1st position loop gain	RW	0.1Hz	16	0 to 6200
2002-02	1st speed loop gain	RW	0.1Hz	16	0 to 35000
2002-03	1st speed loop integral time constant	RW	0.1ms	16	10 to 65535
2002-09	Speed feedforward gain	RW	0.1%	16	0 to 1000
2002-0A	Speed feedforward filter time constant	RW	0.01ms	16	0 to 500
2002-0B	Torque feedforward gain	RW	0.1%	16	0 to 2000
2002-0C	Torque feedforward filter time constant	RW	0.01ms	16	0 to 10000

7.4.3 Related Function settings

(1) Positioning Completed

Index (Hex)	Name	Content
6067	Positioning completion threshold	When the position deviation is in the range of 6067 and the time reaches 6068, the positioning completion signal is valid.
6068	Positioning completion window	

(2) Position deviation limit

Index (Hex)	Name	Content
6065	Threshold of excessive position deviation	When the position deviation is greater than the set value of this parameter, Er.36 (excessive position deviation) will occur.

7.4.4 Recommended configuration

Please refer to the following table for the basic configuration of this mode:

RPDO	TPDO	Remark
6040 (Control word)	6041 (Status word)	Required
607A (Target location)	6064 (Position feedback)	Required
6060 (Servo mode selection)	6061 (Running mode display)	Optional

7.5 Cyclic Synchronous velocity (CSV)

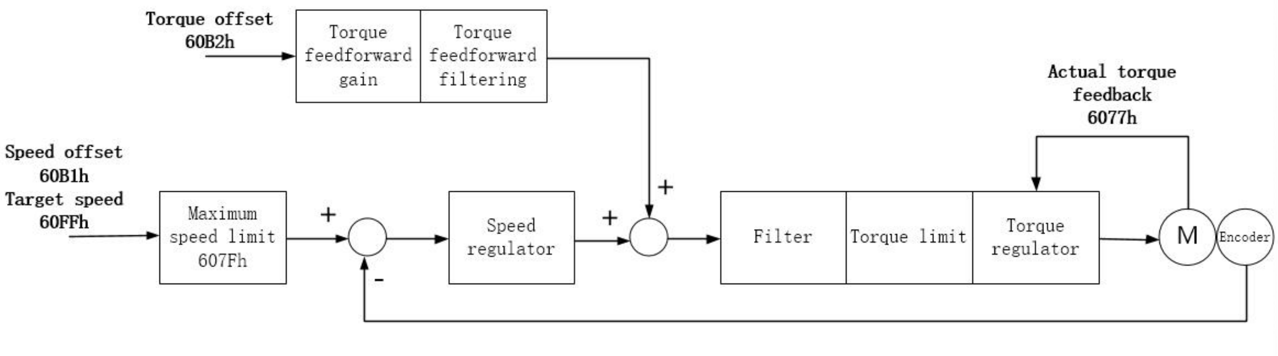


Figure 7-9 Cyclic synchronous speed mode control block diagram

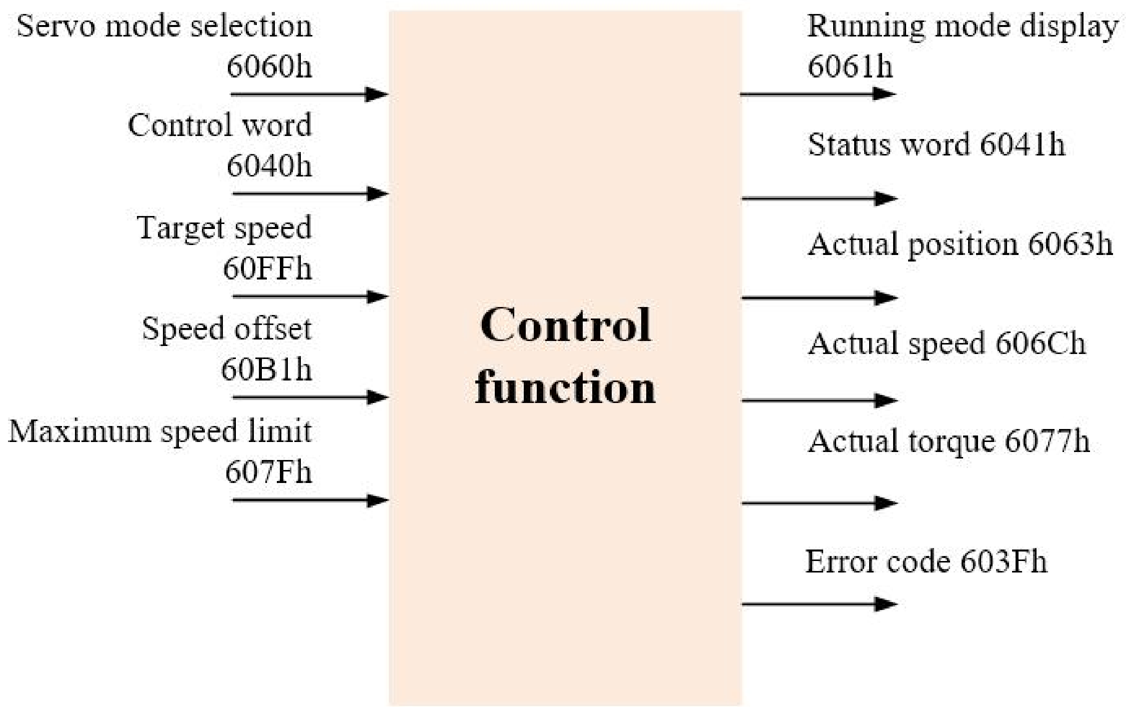


Figure 7-10 Input and output objects

7.5.2 Related objects

(1) Control word 6040h

Bit	Name	Description
0	Servo operation can be started	When all of bit0-bit3 is 1, it means that it starts running
1	Connect the main circuit	
2	Quick stop	
3	Servo running	
8	Pause	

(2) Status word 6041h

Bit	Name	Description
10	Target reach	--
11	Software internal position overrun	--
12	Slave station following instruction	--
15	Homing completed	--

Index (Hex)	Object dictionary name	Accessibility	Unit	Bit length	Range
603F	Error code	Read only	--	16	0 to 65535
6040	Control word	Read and write	--	16	0 to 65535
6041	Status word	Read only	--	16	0 to 65535
6060	Servo mode selection	Read and write	--	8	0 to 10
6061	Running mode display	Read only	--	8	0 to 10
6063	Position feedback	Read only	Encoder unit	32	--
6064	Position feedback	Read only	Instruction unit	32	--
606C	Actual speed	Read only	Instruction unit/s	32	--
6077	Actual torque	Read only	0.1%		-3000 to 3000
607F	Maximum speed	Read and write	Instruction unit/s	32	0 to 2^{32}-1
6083	Acceleration	Read and write	Instruction unit/s^2	32	0 to 2^{32}-1
6084	Deceleration	Read and write	Instruction unit/s^2	32	0 to 2^{32}-1
60B1	Velocity bias	Read and write	Instruction unit/s	32	-2^{31}~2^{31}-1
60B2	Torque offset	Read and write	0.1%	32	-3000 to 3000
60E0	Forward direction maximum torque limit	Read and write	0.1%	16	0 to 3000
60E1	Reverse direction maximum torque limit	Read and write	0.1%	16	0 to 3000
60FF	Target velocity	Read and write	Instruction unit/s	32	-2^{31}~2^{31}-1
2002-02	1st speed loop gain	Read and write	0.1Hz	16	1 to 35000
2002-03	1st velocity loop	Read and	0.1ms	16	100 to 65535

Index (Hex)	Object dictionary name	Accessibility	Unit	Bit length	Range
	integration time constant	write			
2002-0B	Torque feedforward gain	Read and write	0.1%	16	0 to 2000
2002-0C	Torque feedforward filter time constant	Read and write	0.01ms	16	0 to 10000

7.5.3 Related Function Settings

(1) Speed arrival function

<table>
<tr><th>Index (Hex)</th><th>Name</th><th>Content</th></tr>
<tr><td>606D</td><td>Speed reached threshold</td><td rowspan="2">When the difference between the target speed 60FF (converted to motor speed/rpm) and the actual motor speed is in the ±606D interval, and the time reaches 606E, the speed arrival signal is valid.</td></tr>
<tr><td>606E</td><td>Velocity arrival window</td></tr>
</table>

7.5.4 Recommended configuration

Please refer to the following table for the basic configuration of this mode:

RPDO	TPDO	Remark
6040 (Control word)	6041 (Status word)	Required
60FF (Target speed)	/	Required
/	6064 (Position feedback)	Optional
/	606C (Speed feedback)	Optional
6060 (Servo mode selection)	6061 (running mode display)	Optional

7.6 Cyclic Synchronous Torque Mode (CST)

7.6.1 Control block diagram

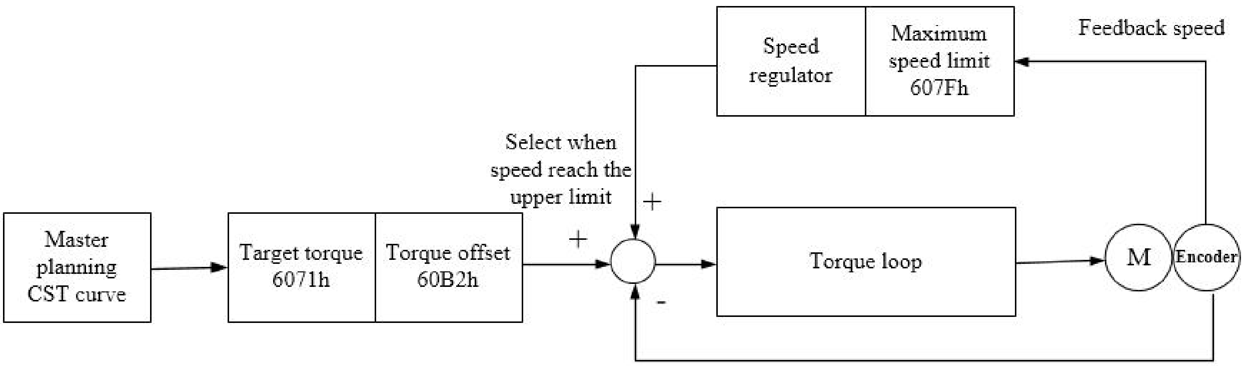


Figure 7-11 Cyclic synchronous torque mode control block diagram

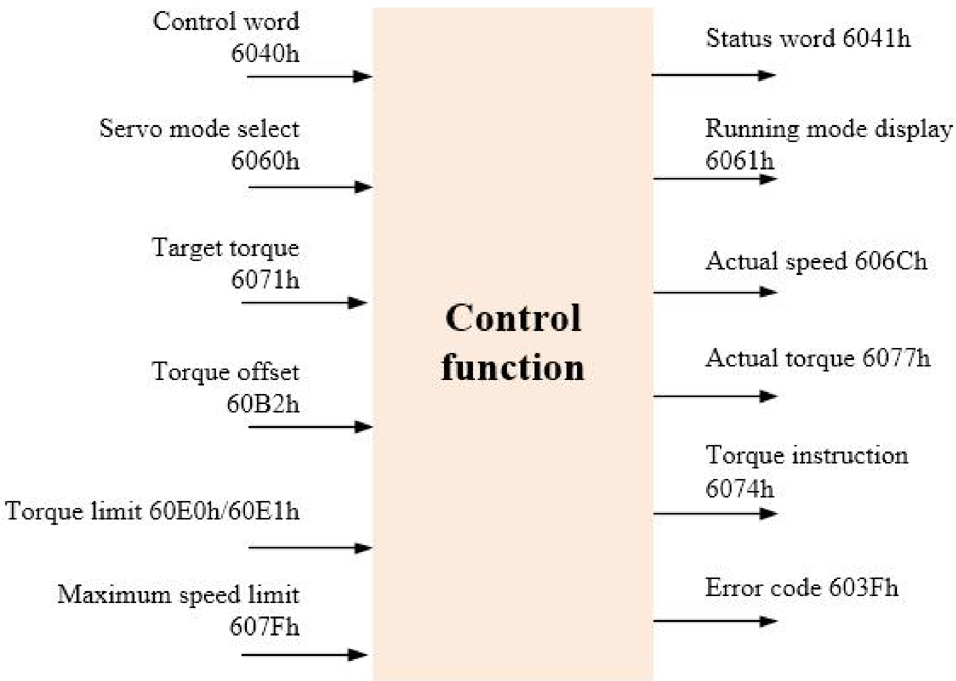


Figure 7-12 Input and output objects

7.6.2 Related objects

(1) Control word 6040h

Bit	Name	Description
0	Servo operation can be started	When all of bit0-bit3 is 1, it means that it starts running
1	Connect the main circuit	
2	Quick stop	
3	Servo running	
8	Pause	0: Servo settings at bit0~bit3 1: The servo is set at 60D5h

(2) Status word 6041h

Bit	Name	Description
10	Target reach	--
12	Slave station following instruction	--
15	Homing completed	--

Index (Hex)	Object dictionary name	Accessibility	Unit	Bit length	Range
603F	Error code	Read only	--	16	0 to 65535
6040	Control word	Read and write	--	16	0 to 65535
6041	Status word	Read only	--	16	0 to 65535
6060	Servo mode selection	Read and write	--	8	0 to 10
6061	Running mode display	Read only	--	8	0 to 10
606C	Actual speed	Read only	Instruction unit/s		--
6071	Target torque	Read and write	0.1%	16	-3000 to 3000
6074	Torque instruction	Read only	0.1%	16	-3000 to 3000
6077	Actual torque	Read only	0.1%	16	-3000 to 3000
607F	Maximum speed	Read and write	Instruction unit/s	32	0 to 2^{32}-1
60B2	Torque offset	Read and write	0.1%	32	-3000 to 3000
60E0	Forward direction maximum torque limit	Read and write	0.1%	16	0 to 3000
60E1	Reverse direction maximum torque limit	Read and write	0.1%	16	0 to 3000
2002-02	1st speed loop gain	Read and write	0.1Hz	16	1 to 35000
2002-03	1st velocity loop integration time constant	Read and write	0.1ms	16	100 to 65535
2002-0B	Torque feedforward gain	Read and write	0.1%	16	0 to 2000
2002-0C	Torque feedforward filter time constant	Read and write	0.01ms	16	0 to 10000

7.6.3 Recommended configuration

Please refer to the following table for the basic configuration of this mode:

RPDO	TPDO	Remark
6040 (Control word)	6041 (Status word)	Required
6071 (Target torque)	/	Required
/	6064(Position feedback)	Optional
/	606C (Speed feedback)	Optional
/	6077 (torque feedback)	Optional
6060 (Servo mode selection)	6061 (running mode display)	Optional

7.7 Profile Torque Mode (PT)

7.7.1 Control block diagram

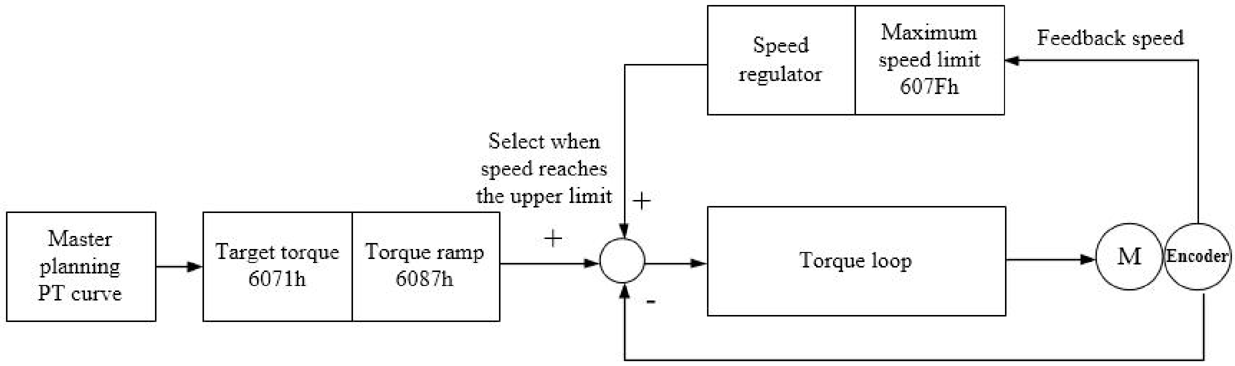


Figure 7-13 Profile torque mode control block diagram

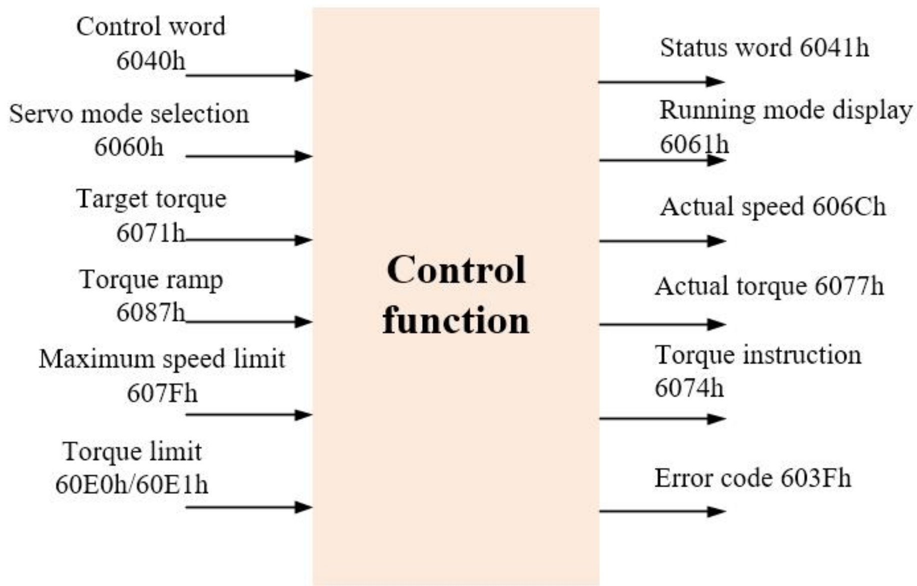


Figure 7-14 Input and output objects

7.7.2 Related objects

(1) Control word 6040h

Bit	Name	Description
0	Servo can be started	When all of bit0-bit3 is all 1, it means that it starts running
1	Connect the main circuit	
2	Quick stop	
3	Servo running	
8	Pause	0: Servo settings at bit0-bit3 1: The servo is set at 60D5h

(2) Status word 6041h

Bit	Name	Description
10	Target reach	--
11	Software internal position exceeds limit	--
15	Homing completed	--

Index (Hex)	Object dictionary name	Accessibility	Unit	Bit length	Range
603F	Error code	Read only	--	16	0 to 65535
6040	Control word	Read and write	--	16	0 to 65535
6041	Status word	Read only	--	16	0 to 65535
6060	Servo mode selection	Read and write	--	8	0 to 10
6061	Running mode display	Read only	--	8	0 to 10
606C	Actual speed	Read only	Instruction unit/s		--
6071	Target torque	Read and write	0.1%	16	-3000 to 3000
6072	Maximum torque	Read and write	0.1%	16	-3000 to 3000
6074	Torque instruction	Read only	0.1%	16	-3000 to 3000
6077	Actual torque	Read only	0.1%	16	-3000 to 3000
607F	Maximum speed	Read and write	Instruction unit/s	32	0 to 2^{32}-1
6087	Torque ramp	Read and write	0.1%/s	32	0 to 2^{32}-1
60E0	Forward direction maximum torque limit	Read and write	0.1%	16	0 to 3000
60E1	Reverse direction maximum torque limit	Read and write	0.1%	16	0 to 3000
2002-02	1st speed loop gain	Read and write	0.1Hz	16	1 to 35000
2002-03	1st velocity loop integration time constant	Read and write	0.1ms	16	100 to 65535
2002-0B	Torque feedforward gain	Read and write	0.1%	16	0 to 2000
2002-0C	Torque feedforward filter time constant	Read and write	0.01ms	16	0 to 10000

7.7.3 Recommended configuration

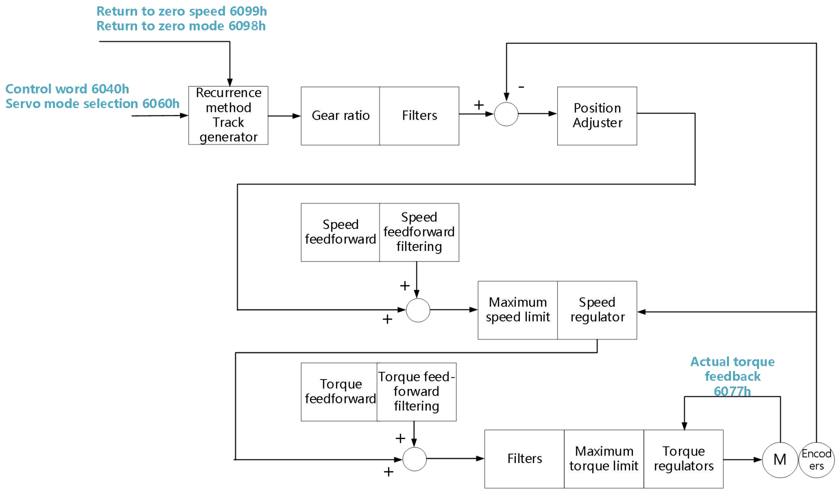
Please refer to the following table for the basic configuration of this mode:

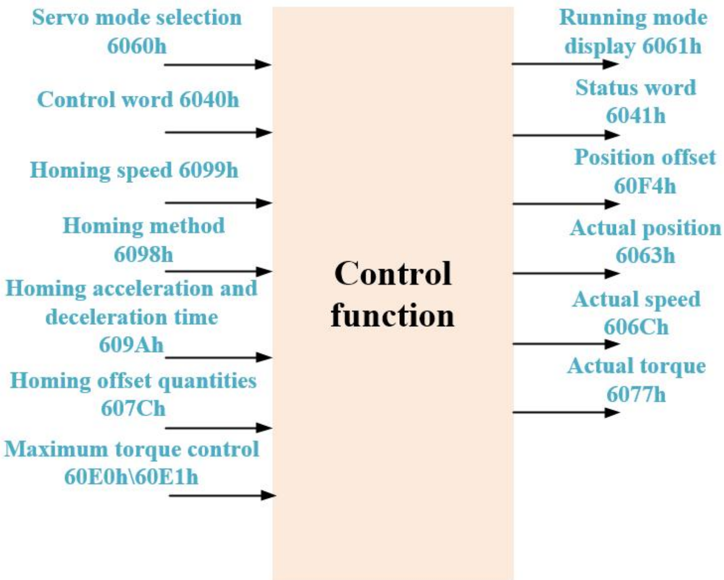
RPDO	TPDO	Remark
6040 (Control word)	6041 (Status word)	Required
6071 (Target torque)	/	Required
/	6064 (Position feedback)	Optional
/	606C (Speed feedback)	Optional
/	6077 (Torque feedback)	Optional
6060 (Servo mode selection)	6061 (Running mode display)	Optional

7.8 Homing Mode (HM)

The homing mode is used to find the mechanical origin and locate the positional relationship between the mechanical origin and the mechanical zero.
Mechanical origin: A fixed position on the machine can correspond to a certain origin switch, which can correspond to the Z signal of the motor.
Mechanical origin: Mechanical absolute origin position.
After the origin returns to zero, the stop position of the motor is the mechanical origin. By setting 607Ch, the relationship between the mechanical origin and the mechanical zero can be set:
Mechanical origin = mechanical zero + 607Ch (origin offset)
When 607Ch=0, the mechanical origin is the same with mechanical zero.

7.8.1 Control Block Diagram





7.8.2 Related objects

(1) Control word 6040h

Bit	Name	Description
0	Servo operation can be started	When bit0 to bit3 are all 1, it indicates the start of operation
1	Turn on the main circuit	
2	Quick shutdown	
3	Servo operation	
4	Homing	0 → 1: Start homing 1 → 0: End homing

(2) Status word 6041h

Bit	Name	Description
10	Target arrival	-
12	Slave station following instruction	-
13	Following error	-
15	Origin return completed	-

7.8.3 Introduction of homing Mode

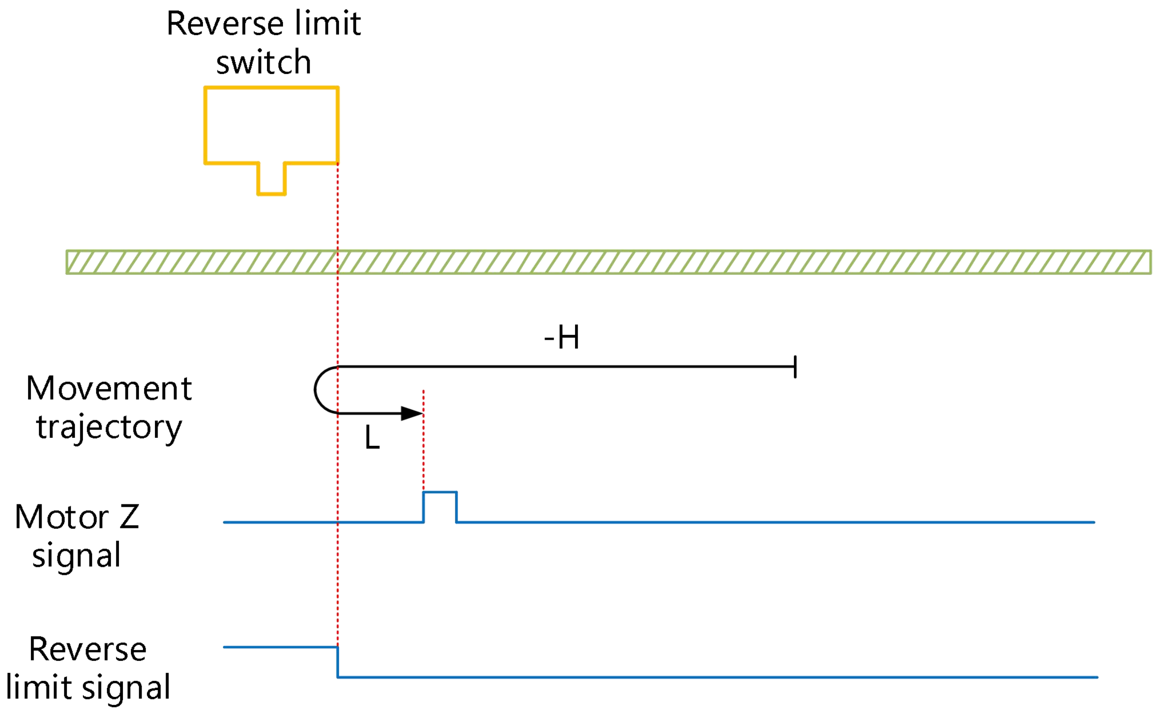
Note: In the figure, "H" stands for 6099: 01h (search for deceleration point signal speed), and "L" stands for 6099: 02h (search for origin signal speed).

(1) 6098H = 1

Mechanical origin: Z signal of motor

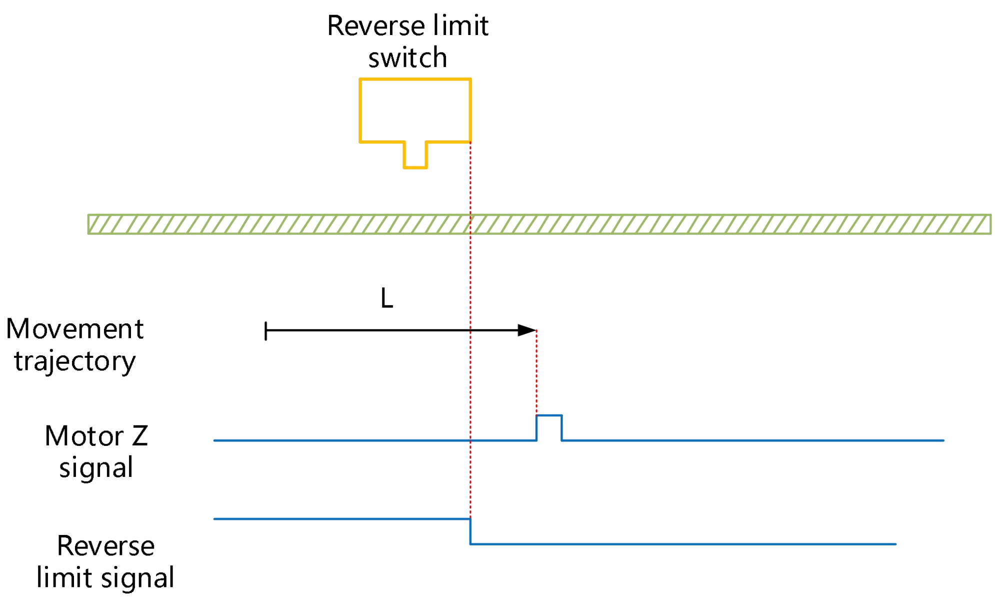
Deceleration point: Reverse limit switch (NOT)

① The deceleration point signal is invalid when starting homing.



NOT=0 when starting homing, start homing in reverse direction at high speed. After the rising edge of NOT, slow down, change running direction and run in forward direction at low speed, and stop at first Z signal when encountering the falling edge of NOT.

② The deceleration point signal is valid when starting homing



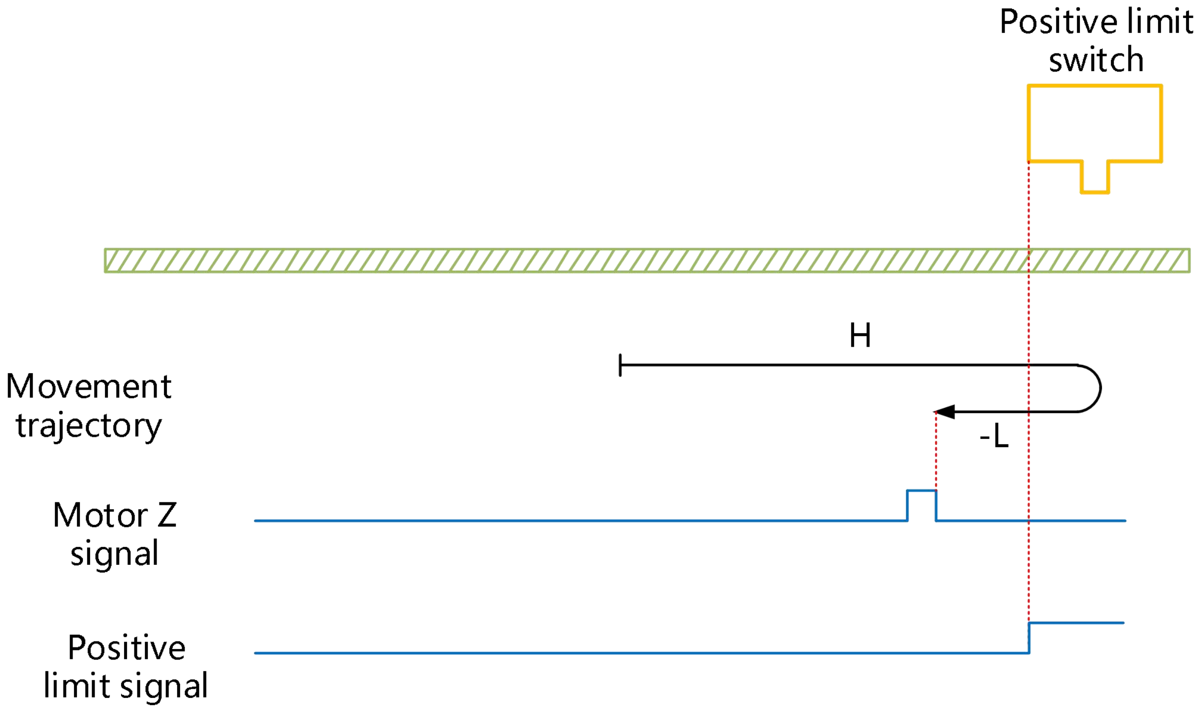
NOT=1 when starting homing, run in forward direction immediately at low speed and start homing, and stop at the first Z signal when encountering the falling edge of NOT.

(2) 6098H = 2

Mechanical origin: Z signal of motor

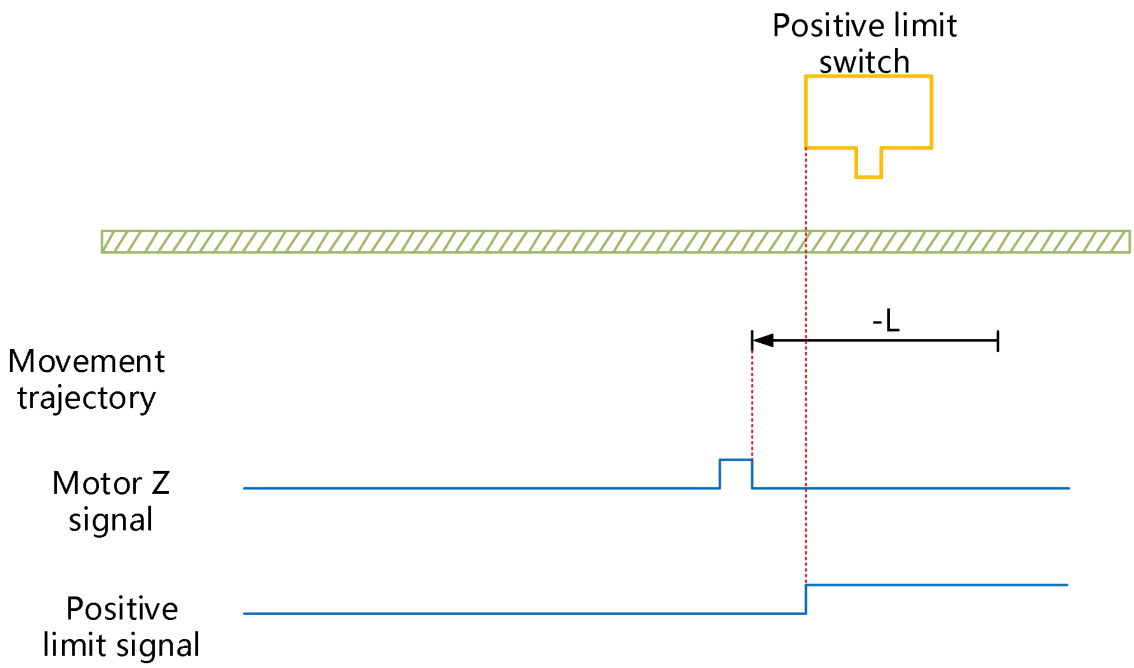
Deceleration point: Forward limit switch (POT)

① The deceleration point signal is invalid when starting homing



POT=0 when starting homing, run at a high speed in the forward direction. After encountering the rising edge of POT, motor will decelerate, run in reverse direction at low speed, and stop at the first Z signal after encountering the falling edge of POT.

② The deceleration point signal is valid when starting homing



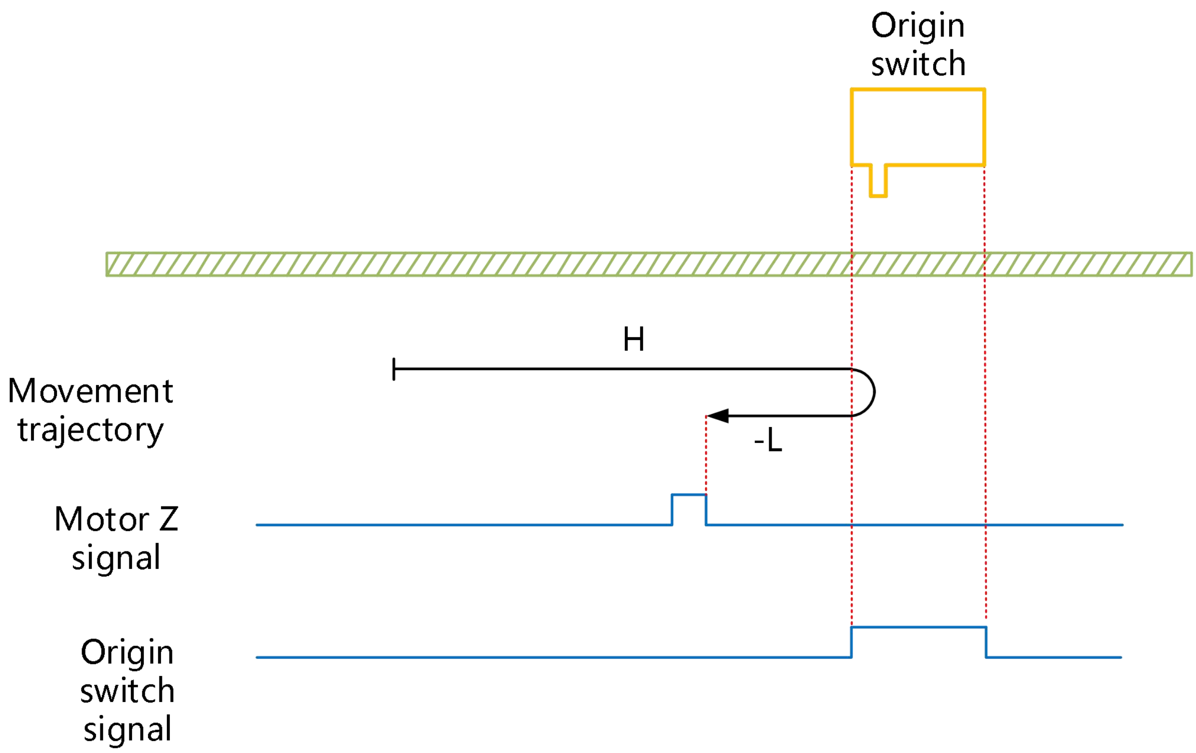
POT=1 when starting homing, run at low speed directly in the reverse direction, and stops at the first Z signal after encountering the falling edge of POT.

(3) 6098H = 3

Mechanical origin: Z signal of motor

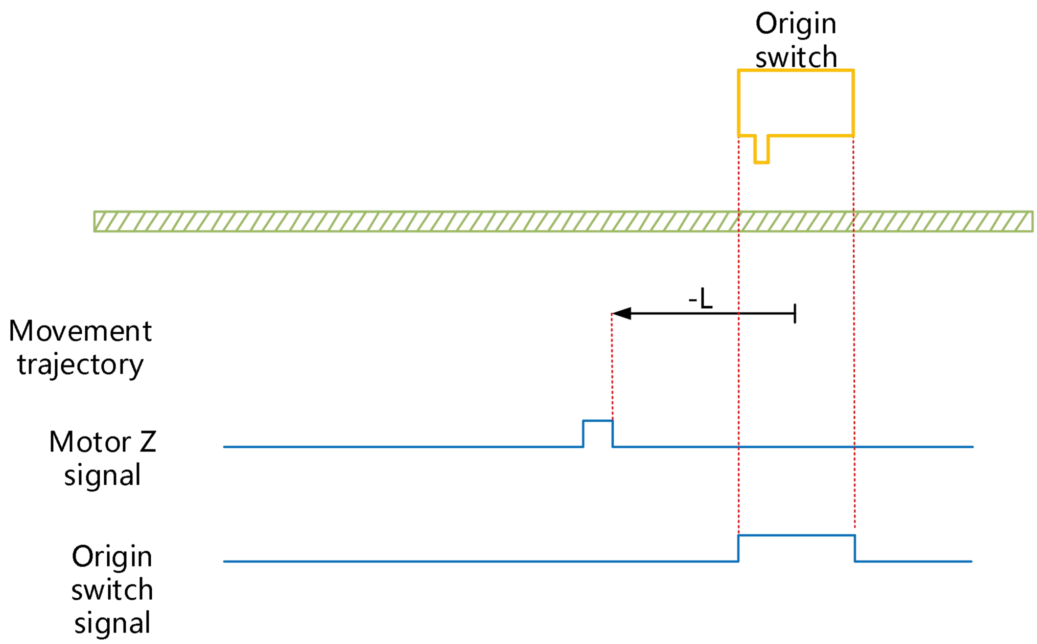
Deceleration point: Origin switch (HW)

① The deceleration point signal is invalid when starting homing



HW=0 when starting homing, start homing in forward direction at high speed. After encountering rising edge of HW, slow down, run in reverse direction at low speed. After encountering the falling edge of HW, continue to run, and then stop when encountering the first Z signal.

② The deceleration point signal is valid when starting homing



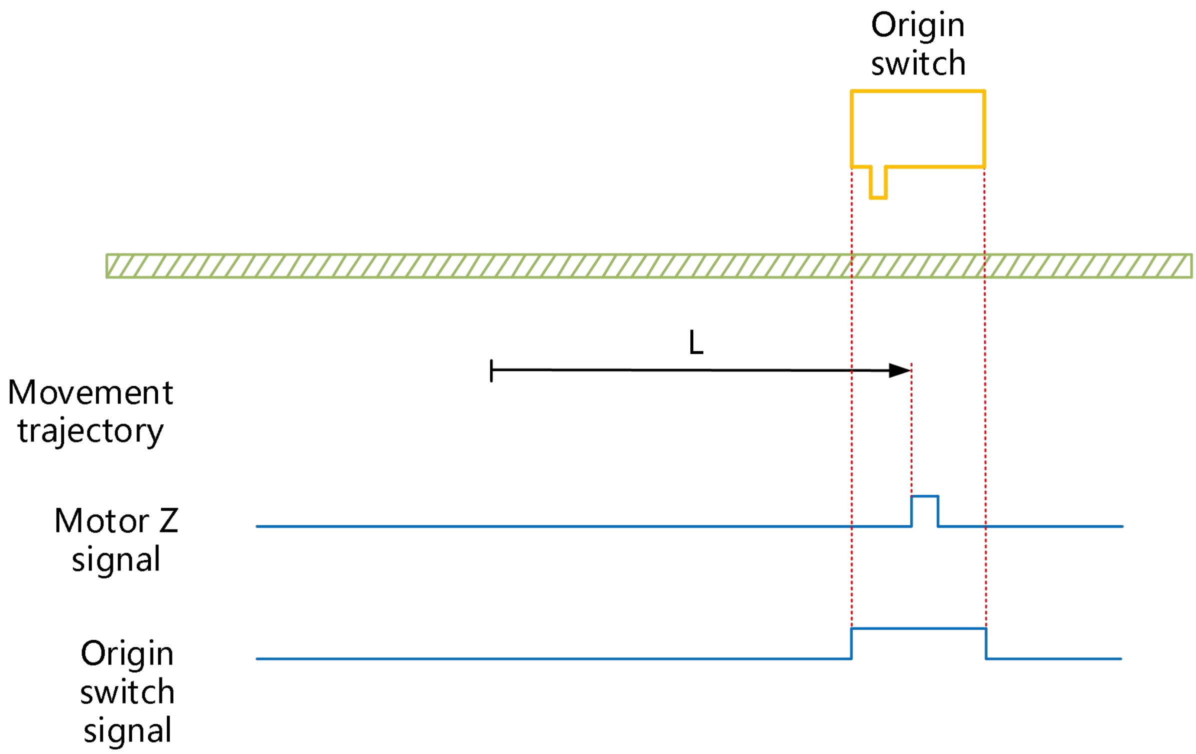
HW=1 when starting homing, start homing at low speed in reverse direction directly, and stop at the first Z signal after encountering the falling edge of HW;

(4) 6098H = 4

Mechanical origin: Z signal of motor

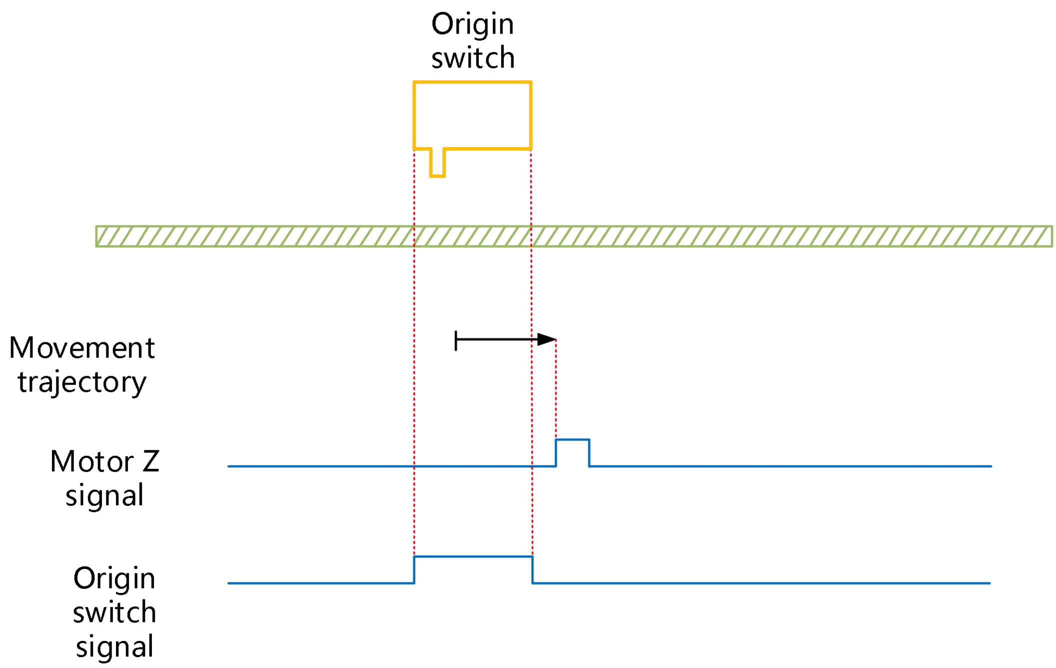
Deceleration point: Origin switch (HW)

① The deceleration point signal is invalid when starting homing



HW=0 when starting homing, start to homing at low speed in forward direction directly, and stop at the first Z signal after encountering the rising edge of HW;

② The deceleration point signal is valid when starting homing



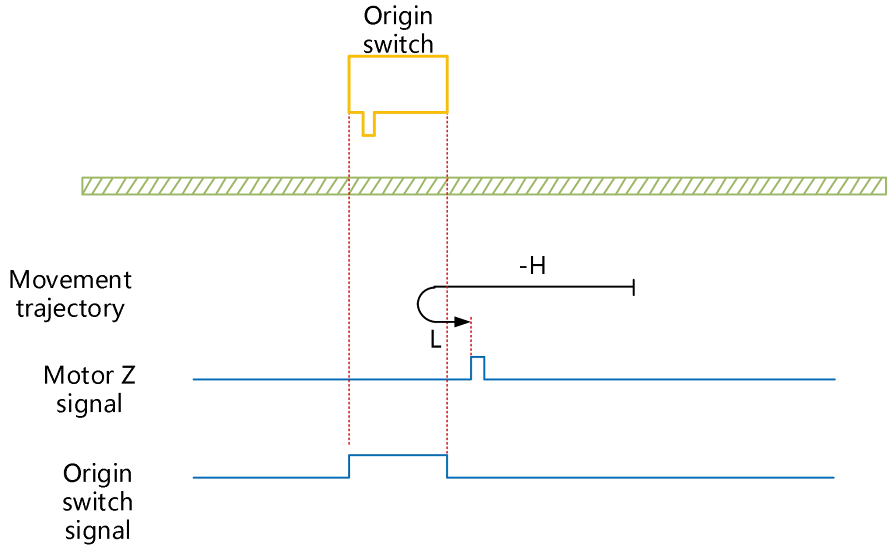
HW=1 when starting homing, start return to zero at high speed in reverse direction, slow down after encountering the falling edge of HW, change running direction and run in forward direction at low speed, and stop at the first Z signal after encountering the rising edge of HW;

(5) 6098H = 5

Mechanical origin: Z signal of motor

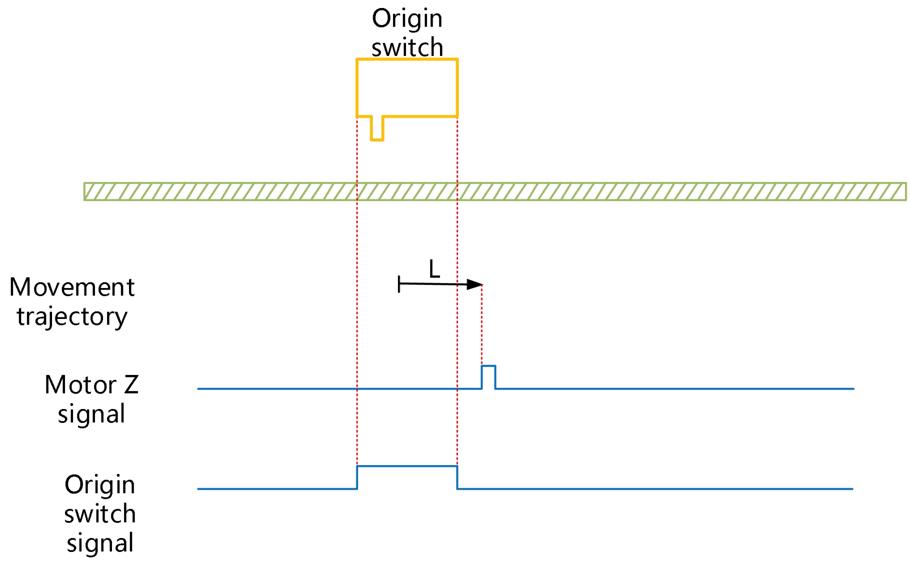
Deceleration point: Origin switch (HW)

① The deceleration point signal is invalid when starting homing



HW=0 when starting to return to zero, start to return to zero at high speed in reverse direction, slow down after encountering the rising edge of HW, change running direction and run in forward direction at low speed, and stop at the first Z signal after encountering the falling edge of HW;

② The deceleration point signal is valid when starting to return to zero



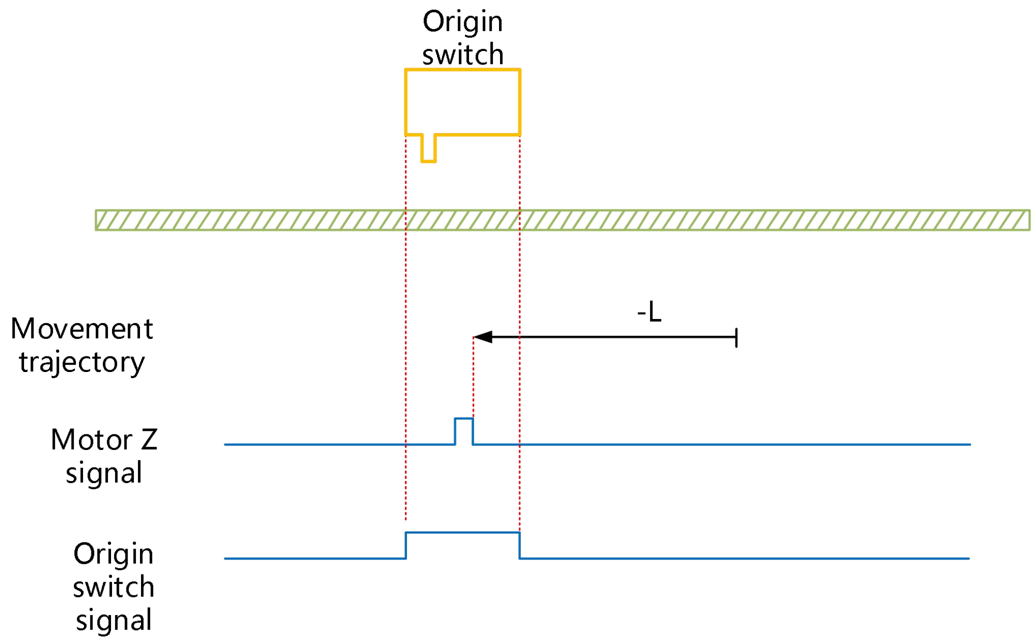
HW=1 when starting to return to zero, start to return to zero at low speed in forward direction directly, and stop at the first Z signal after encountering the falling edge of HW will stop;

(6) 6098H = 6

Mechanical origin: Z signal of motor

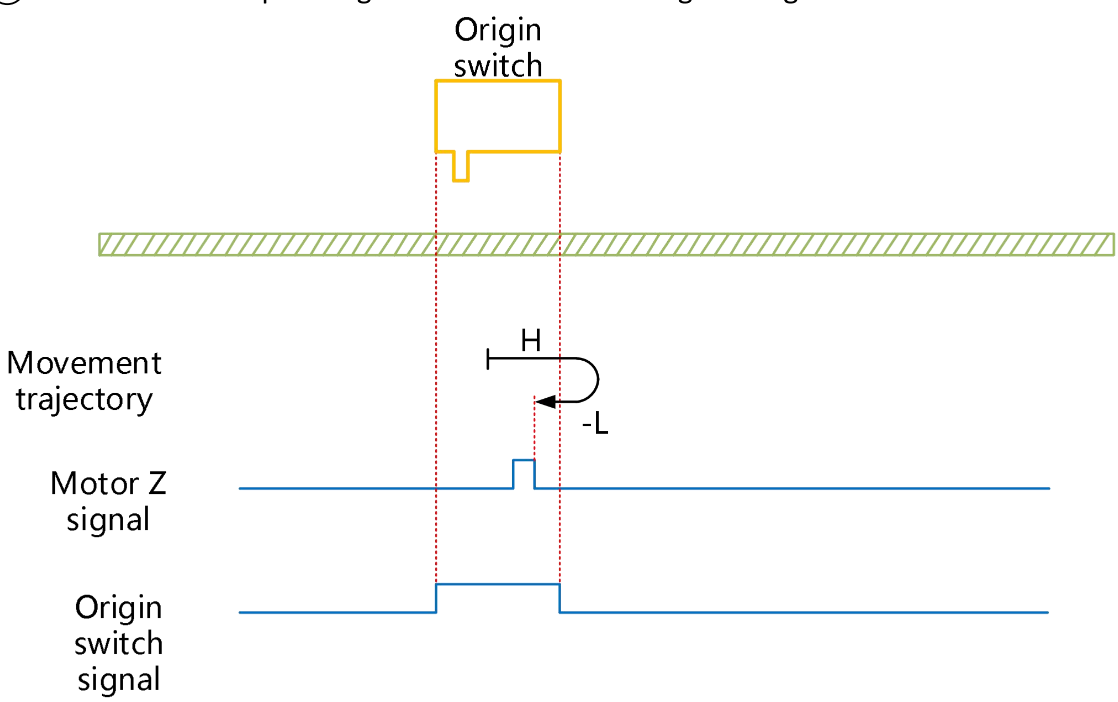
Deceleration point: Origin switch (HW)

① The deceleration point signal is invalid when starting homing



HW=0 when starting homing, start to return to zero at low speed in reverse direction directly, and stop at the first Z signal after encountering the rising edge of HW;

② The deceleration point signal is valid when starting homing



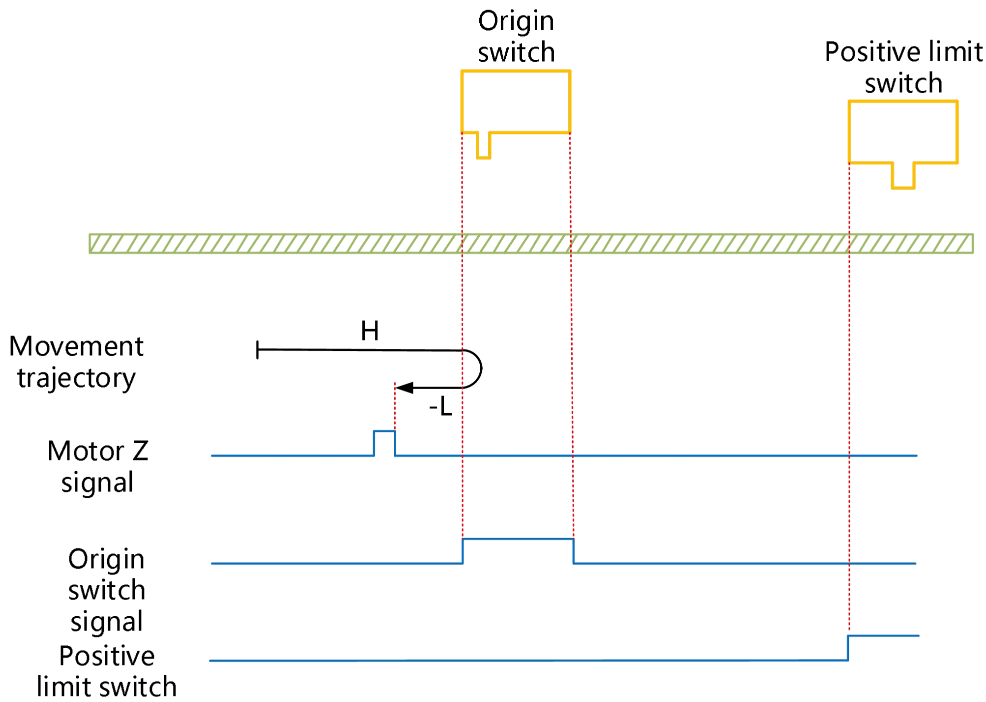
HW=1 when starting homing, start homing at high speed in forward direction, slow down after encountering the falling edge of HW, change running direction and run in reverse direction at low speed, and stop at the first Z signal after encountering the rising edge of HW;

(7) 6098H = 7

Mechanical origin: Z signal of motor

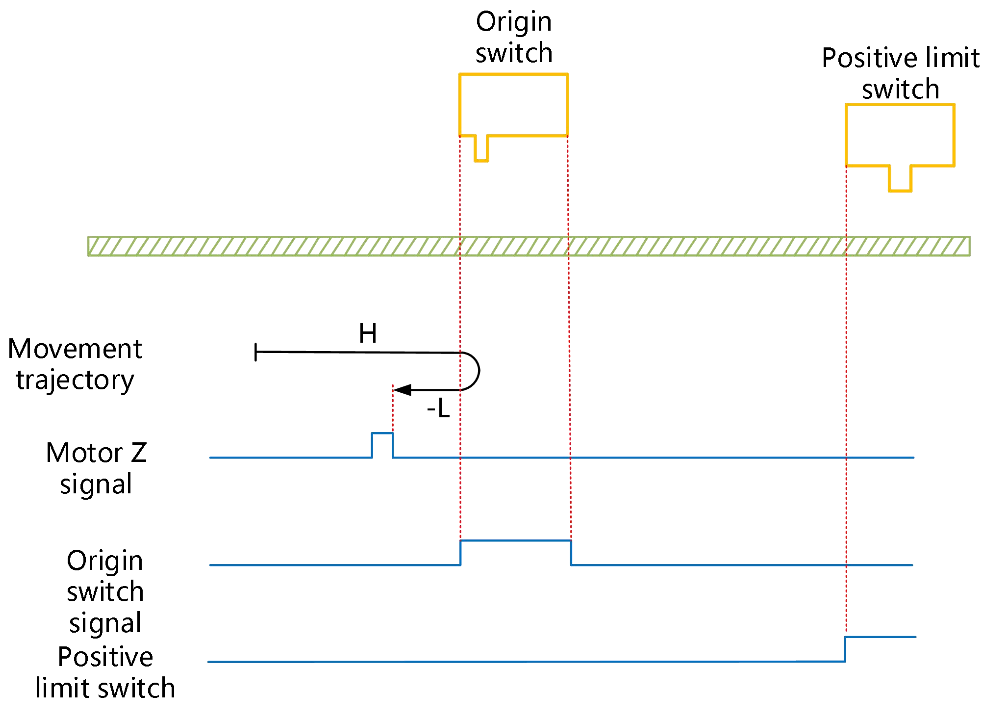
Deceleration point: Origin switch (HW)

① The deceleration point signal is invalid when starting homing, the forward limit switch is not encountered



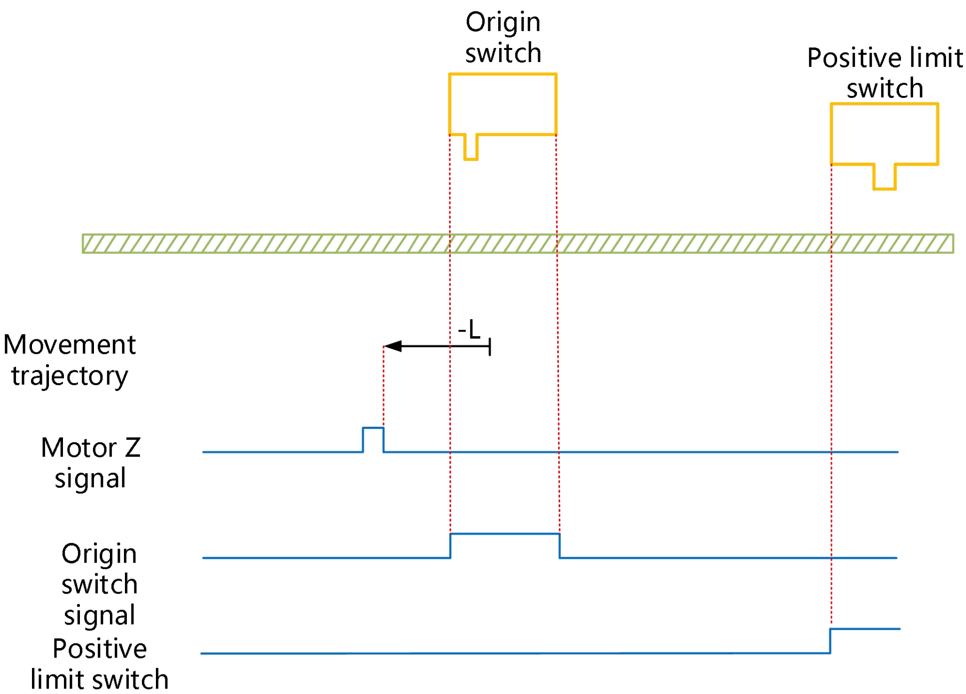
HW=0 when starting to return to zero, start homing at high speed in forward direction. If the limit switch is not encountered, after encountering the rising edge of HW, slow down, change running direction and run in reverse direction at low speed, and stop at the first Z signal after encountering the falling edge of HW;

② The deceleration point signal is invalid when starting homing, the forward limit switch is encountered



HW=0 when starting to return to zero, start homing at high speed in forward direction. If the limit switch is encountered, automatically change running direction and run in reverse direction at high speed. After encountering HW rising edge, slow down and continue to run at low speed in reverse direction, stop at the first Z signal after encountering the falling edge of HW;

③ The deceleration point signal is valid when starting homing



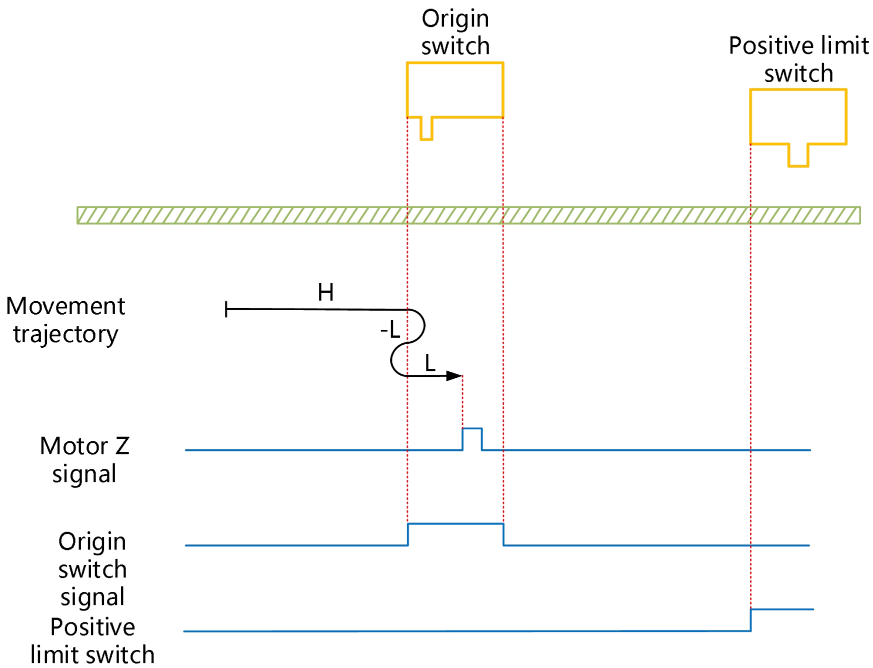
HW=1 when starting to return to zero, start to return to zero at low speed in reverse direction directly, and stop at the first Z signal after encountering the falling edge of HW;

(8) 6098H = 8

Mechanical origin: Z signal of motor

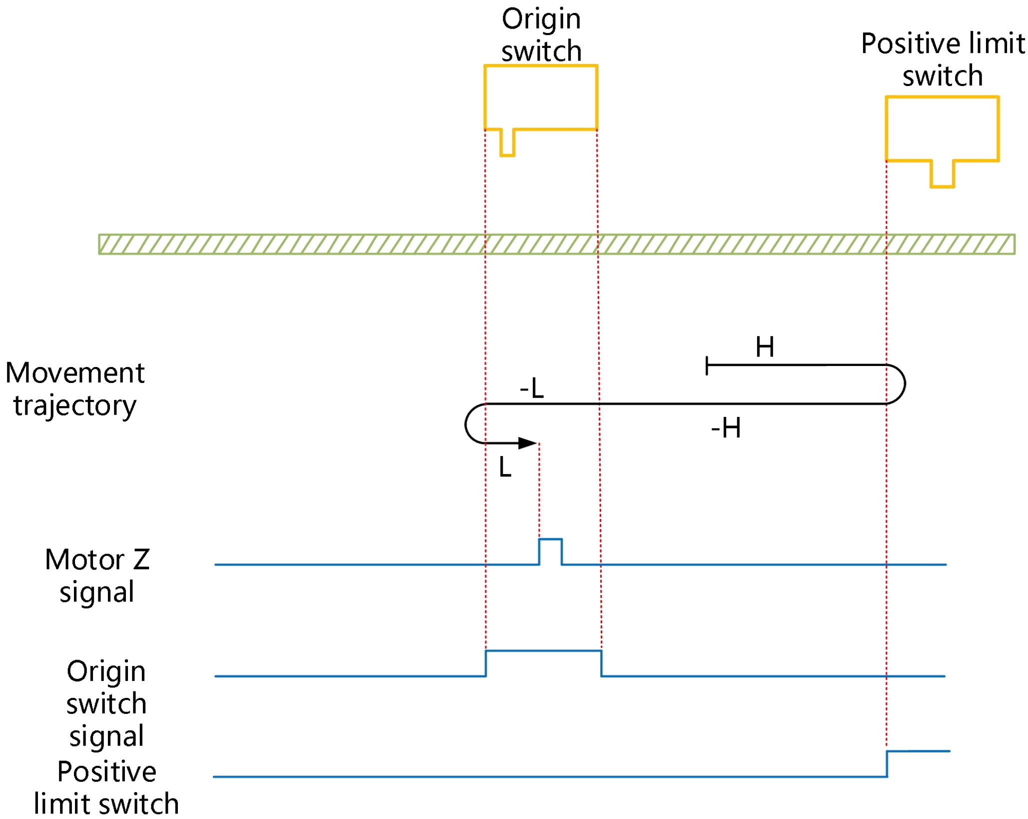
Deceleration point: Origin switch (HW)

① The deceleration point signal is invalid when starting to return to zero, the forward limit switch is not encountered



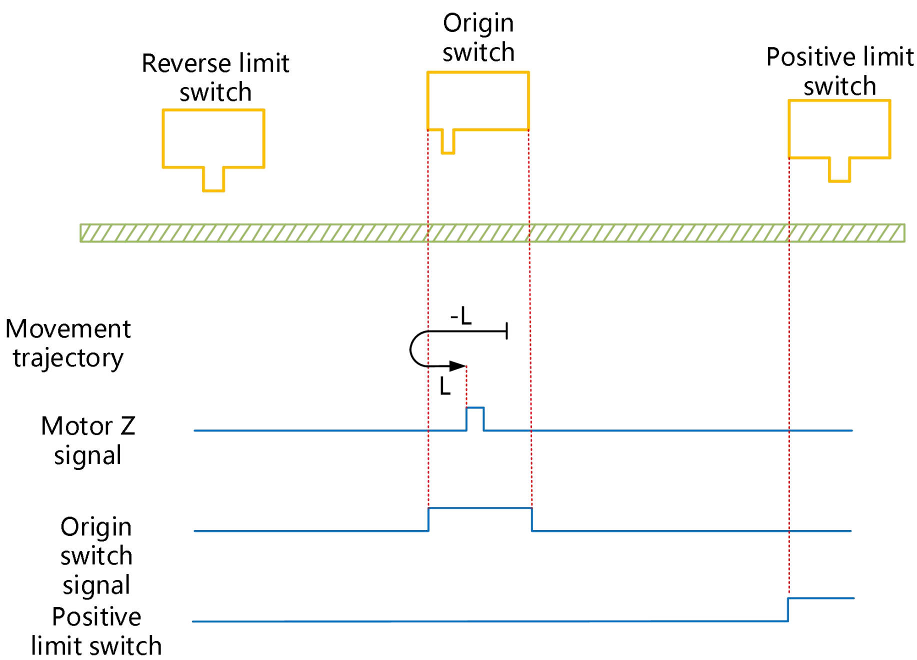
HM-0 when starting homing, start homing at high speed in forward direction. If the limit switch is not encountered, after encountering the rising edge of HW, slow down and change running direction and run in reverse direction at low speed. After encountering the falling edge of HW, change the running direction and run in forward direction at low speed, and stop at the first Z signal after encountering the rising edge of HW;

② The deceleration point signal is invalid when starting to return to zero, the forward limit switch is encountered



HW=0 when starting homing, start homing at high speed in forward direction. If limit switch is encountered, automatically change running direction and run in reverse direction at high speed, slow down and run in reverse direction at low speed after encountering HW rising edge; change running direction and run in reverse direction at low speed after encountering HW falling edge, and stop at the first Z signal after encountering HW rising edge;

③ The deceleration point signal is valid when starting homing



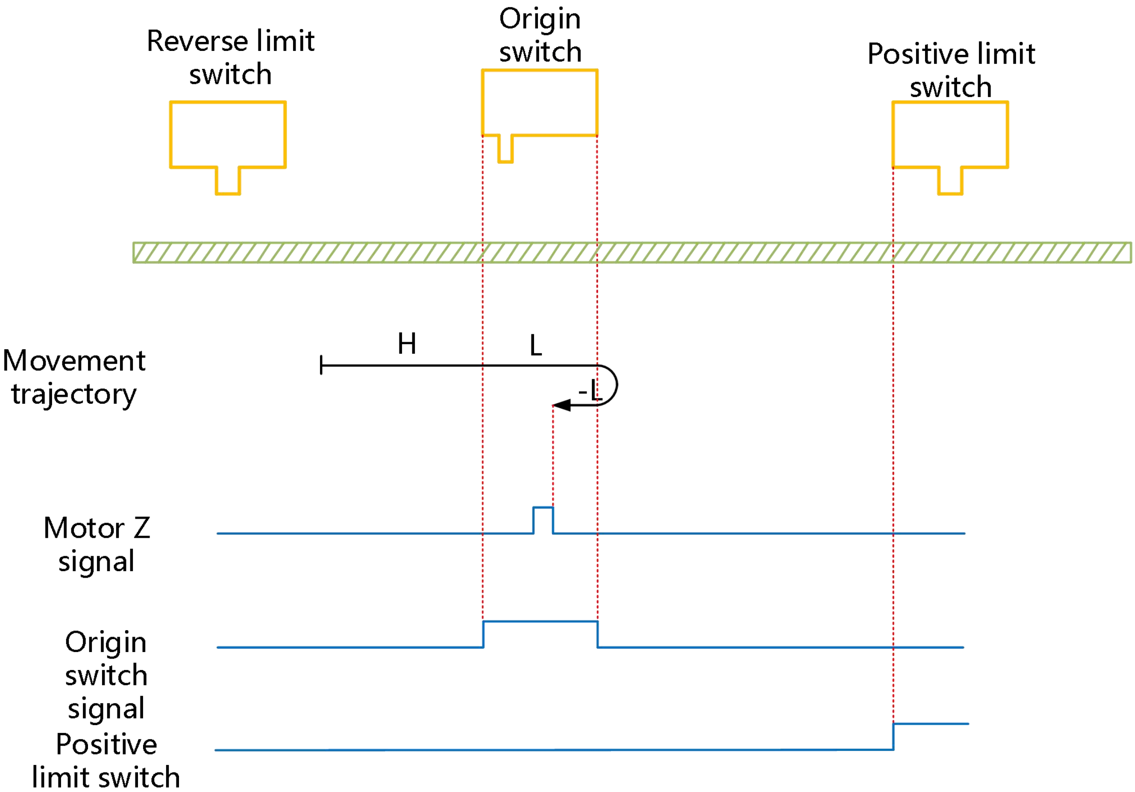
HM=-1 when starting homing, start homing at low speed in reverse direction directly. After encountering the falling edge of HW, change running direction and run in forward direction at low speed, and stop at the first Z signal after encountering the rising edge of HW;

(9) 6098H = 9

Mechanical origin: Z signal of motor

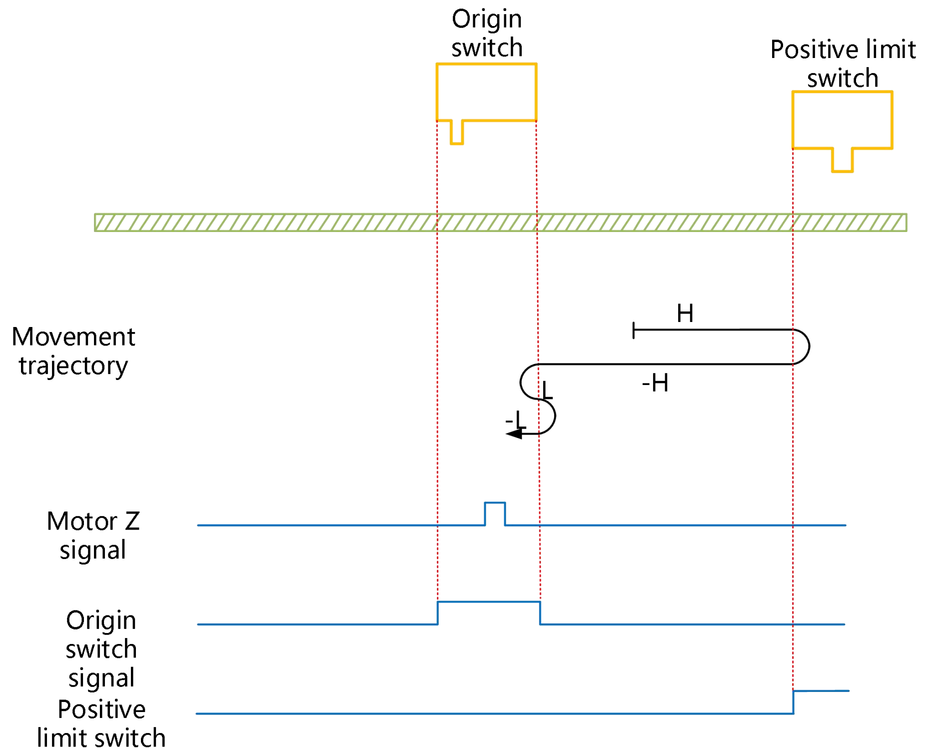
Deceleration point: Origin switch (HW)

① The deceleration point signal is invalid when starting homing, the forward limit switch is not encountered



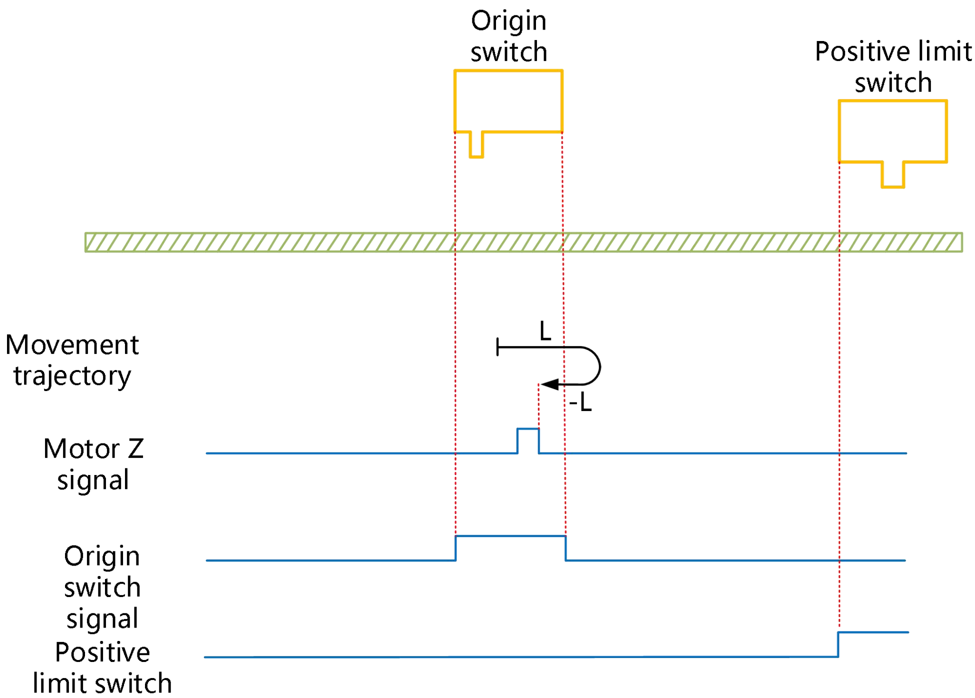
HW=0 when starting homing, start homing at high speed in forward direction. If the limit switch is not encountered, slow down after encountering the rising edge of HW, run at low speed in forward direction; change running direction and run in reverse direction at low speed after encountering the falling edge of HW, and stop at the first Z signal after encountering the rising edge of HW;

② The deceleration point signal is invalid when starting homing, the forward limit switch is encountered



HW=0 when starting homing, start homing at high speed in forward direction. If the limit switch is encountered, change the running direction automatically and run in reverse direction at high speed; slow down and change the running direction after encountering the rising edge of HW to resume forward operation. Run in forward direction at low speed and change the running direction after encountering the falling edge of HW; stops at first Z signal after encountering the rising edge of HW during running in reverse direction at low speed;

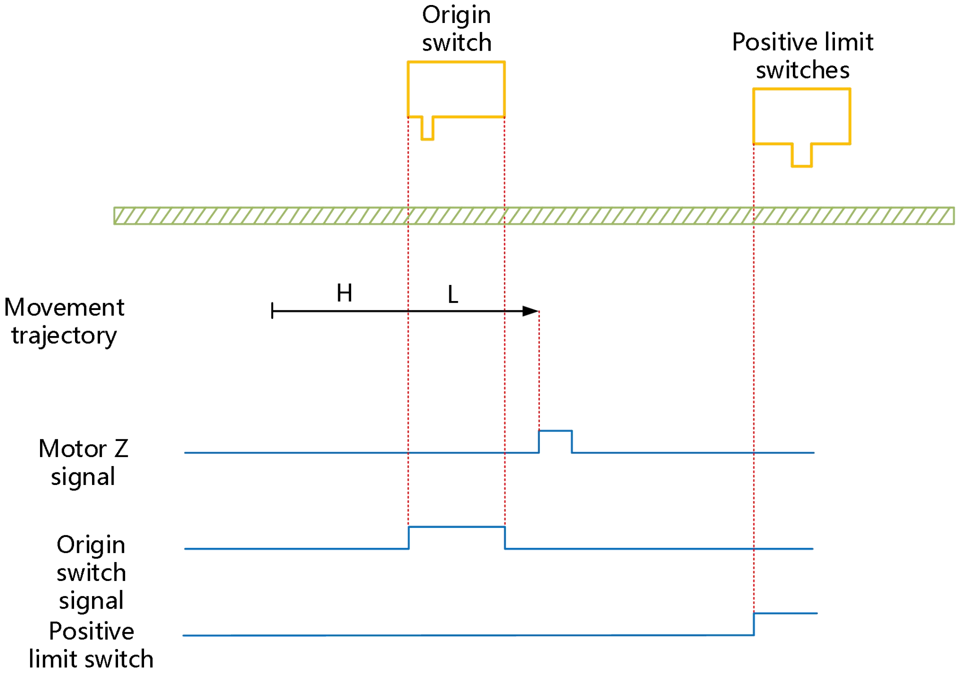
③ The deceleration point signal is valid when starting homing



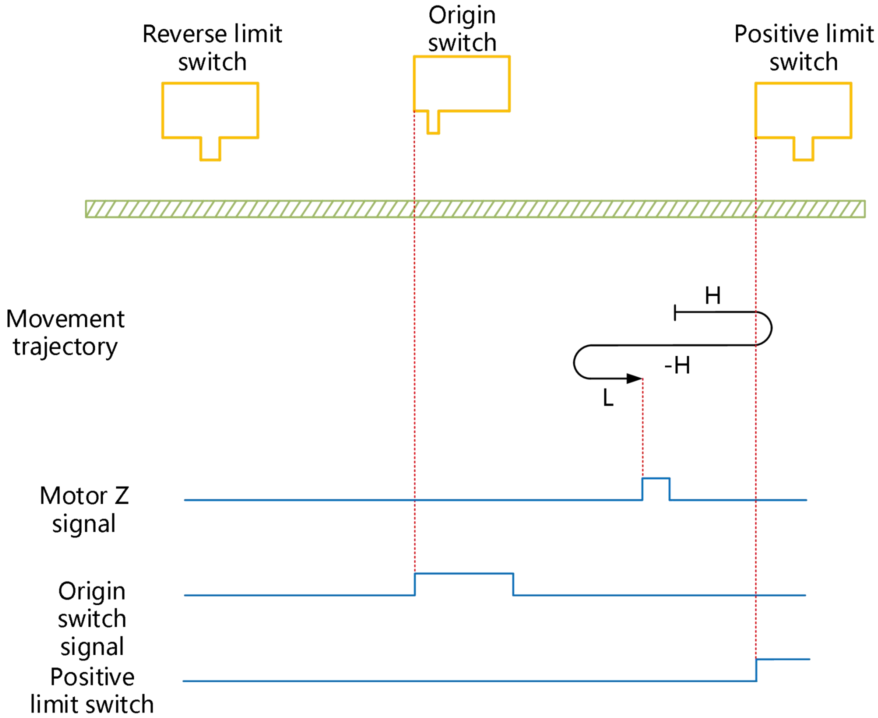
HW=1 when starting homing, start to return to zero directly at low speed in forward direction. After encountering the falling edge of HW, change the running direction and stop at the first Z signal after encountering the rising edge of HW during running in reverse direction at low speed;

(10) 6098H=10

Mechanical origin: Z signal of motor
Deceleration point: Origin switch (HW)
① The deceleration point signal is invalid when starting homing, the forward limit switch is not encountered

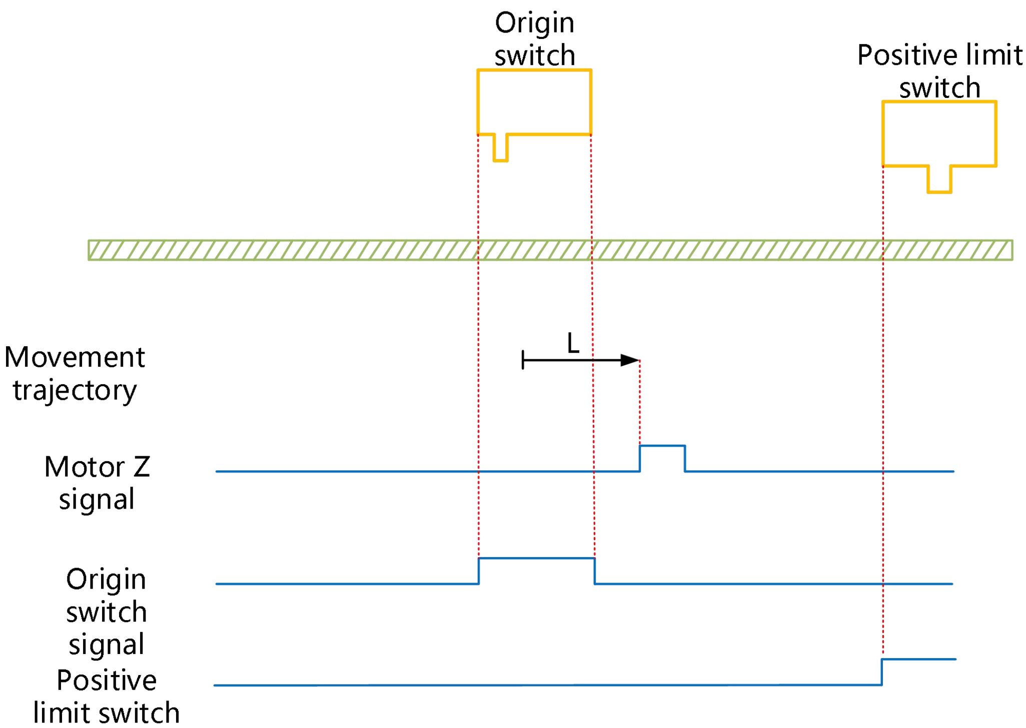


HW=0 when starting homing, start homing at high speed in forward direction. If the limit switch is not encountered, slow down and run at low speed in forward direction after encountering the rising edge of HW. After encountering the falling edge of HW, continue to run at low speed in forward, and then stop at the first Z signal encountered;
② The deceleration point signal is invalid when starting homing, the forward limit switch is encountered



HW=0 when starting homing, start homing at high speed in forward direction. If the limit switch is encountered, change the running direction automatically and run in reverse direction at high

speed. After encountering the rising edge of HW, slow down and change the running direction to resume forward operation, and stop at the first Z signal after encountering the falling edge of HW during running in forward direction at low speed;
③ The deceleration point signal is valid when starting homing



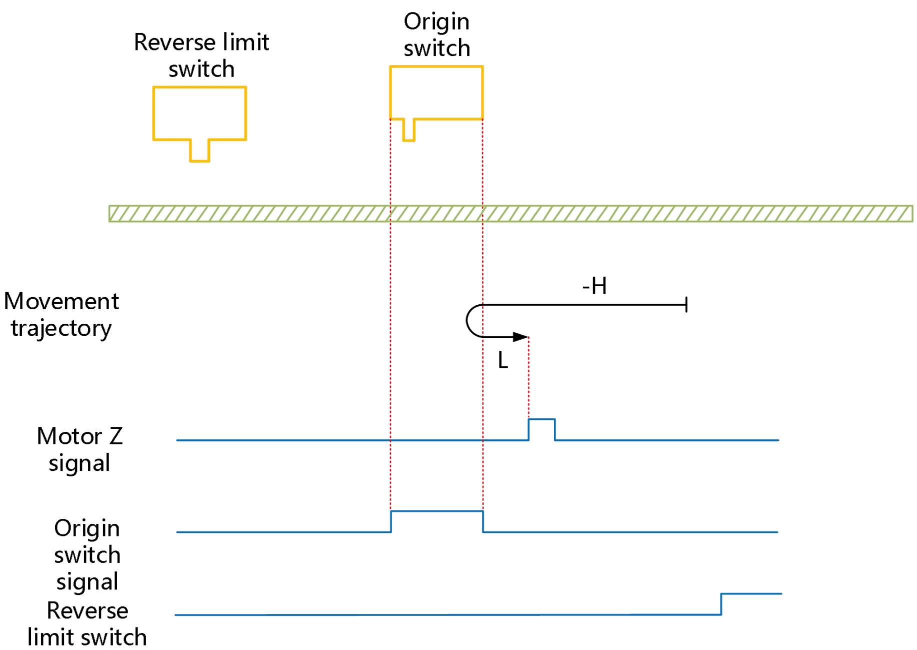
HW=1 when starting homing, start homing directly in forward direction at low speed, and stop at the first Z signal after encountering the falling edge of HW;

(11) 6098H=11

Mechanical origin: Z signal of motor

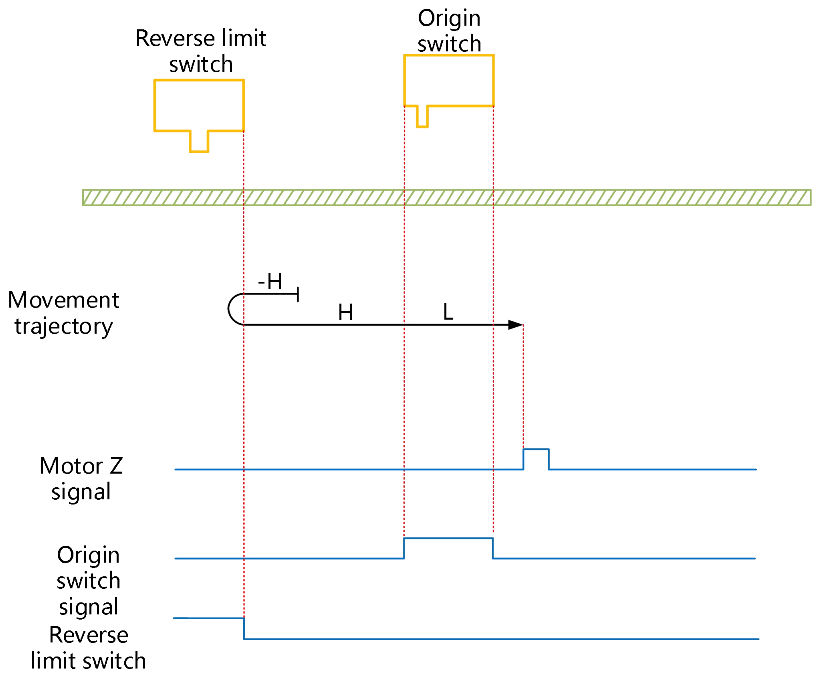
Deceleration point: Origin switch (HW)

① The deceleration point signal is invalid when starting homing the reverse limit switch is not encountered



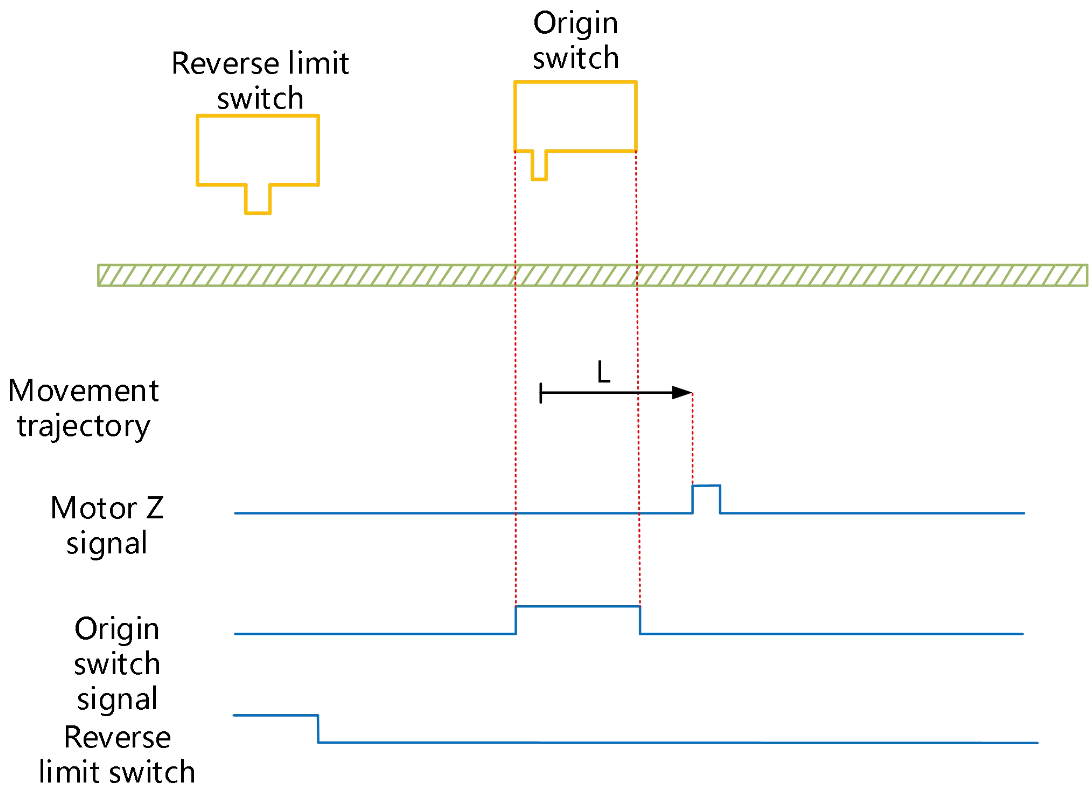
HW=0 when starting homing, start homing at high speed in reverse direction. If the limit switch is not encountered, slow down and change the running direction after encountering the rising edge of HW, and run in forward direction at low speed and stop at the first Z signal after encountering the falling edge of HW;

② The deceleration point signal is invalid when starting homing, the reverse limit switch is encountered



HW=0 when starting homing, start to homing at high speed in reverse direction. If limit switch is encountered, change the running direction automatically and run in forward direction at high speed. After encountering HW rising edge, slow down and continue to run in forward direction at low speed. Stop at the first Z signal after encountering HW falling edge;

③ The deceleration point signal is valid when starting homing



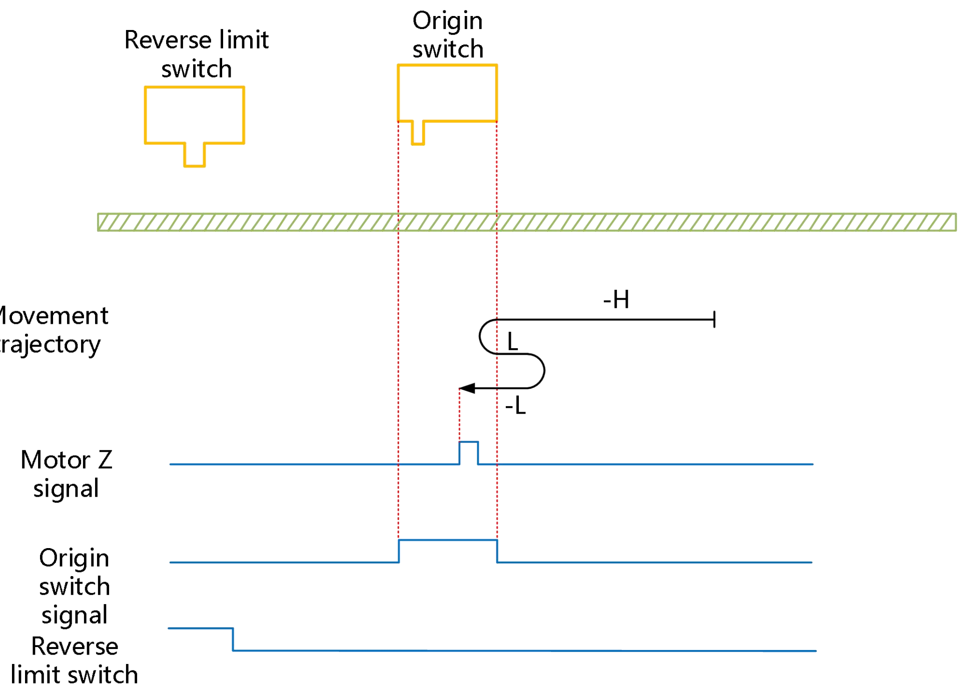
HW=1 when starting homing, it will start homing directly in forward direction at low speed, and stop at the first Z signal after encountering the falling edge of HW;

(12) 6098H=12

Mechanical origin: Z signal of motor

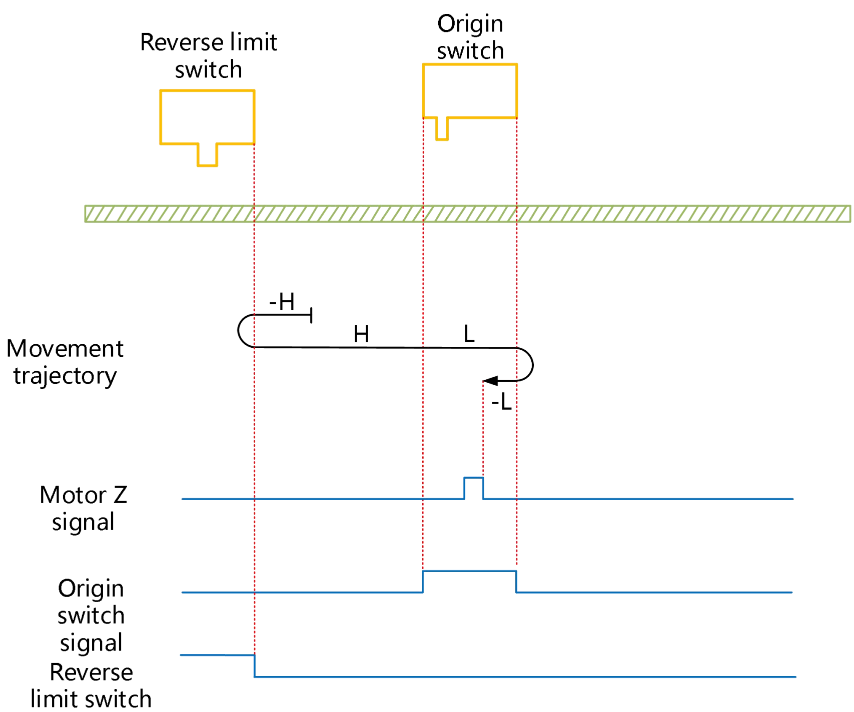
Deceleration point: Origin switch (HW)

① The deceleration point signal is invalid when starting homing, the reverse limit switch is not encountered



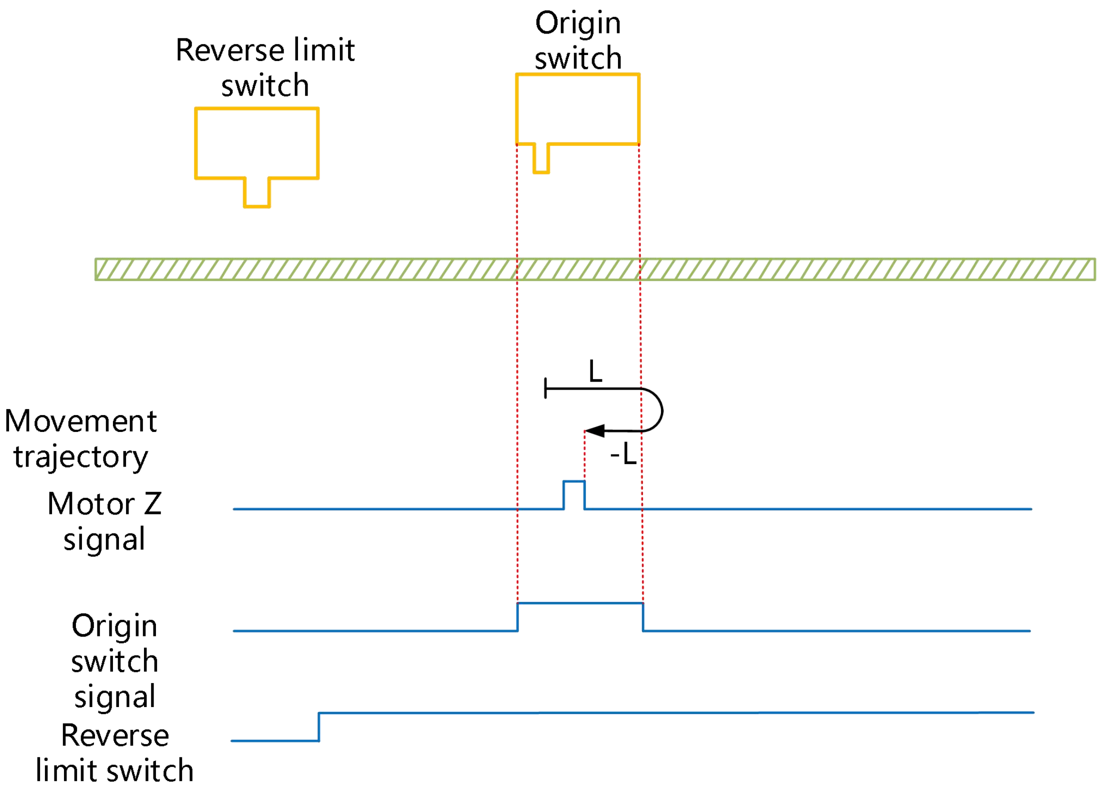
HW=0 when starting homing, start homing in reverse direction at high speed; if limit switch is not encountered; slow down and change the running direction after encountering HW rising edge, run in forward direction at low speed; after encountering HW falling edge, change the running direction and run in reverse direction at low speed and stop at the first Z signal after encountering HW rising edge;

② The deceleration point signal is invalid when starting homing, the reverse limit switch is encountered



HW=0 when starting to return to zero, start to return to zero in reverse direction at high speed, change the running direction automatically when encountering limit switch and run in forward direction at high speed; slow down after encountering HW rising edge and run in forward direction at low speed; change the running direction after encountering HW falling edge, and run in reverse direction at low speed and stop at the first Z signal after encountering HW rising edge;

③ The deceleration point signal is valid when starting to return to zero



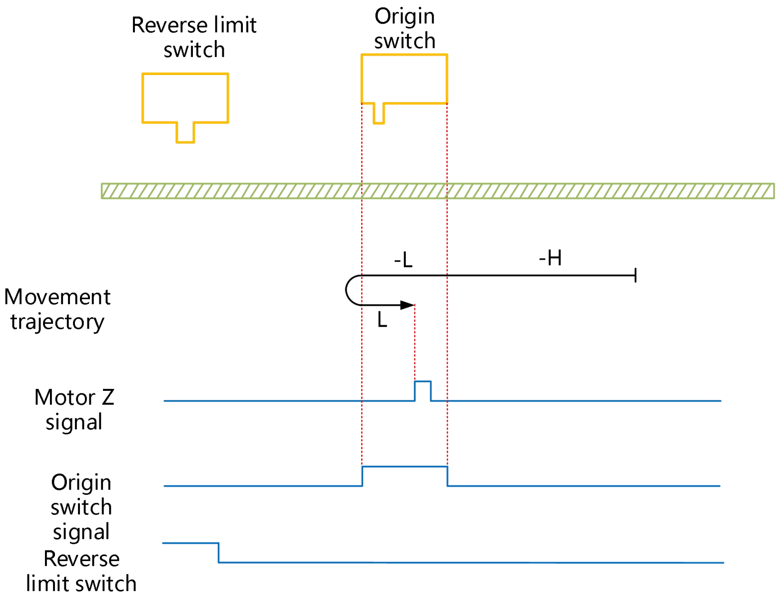
HW=1 when starting homing, start homing in forward direction at low speed. After encountering the falling edge of HW, change the running direction and run in reverse direction at low speed, and stop at the first Z signal after encountering the rising edge of HW;

(13) 6098H=13

Mechanical origin: Z signal of motor

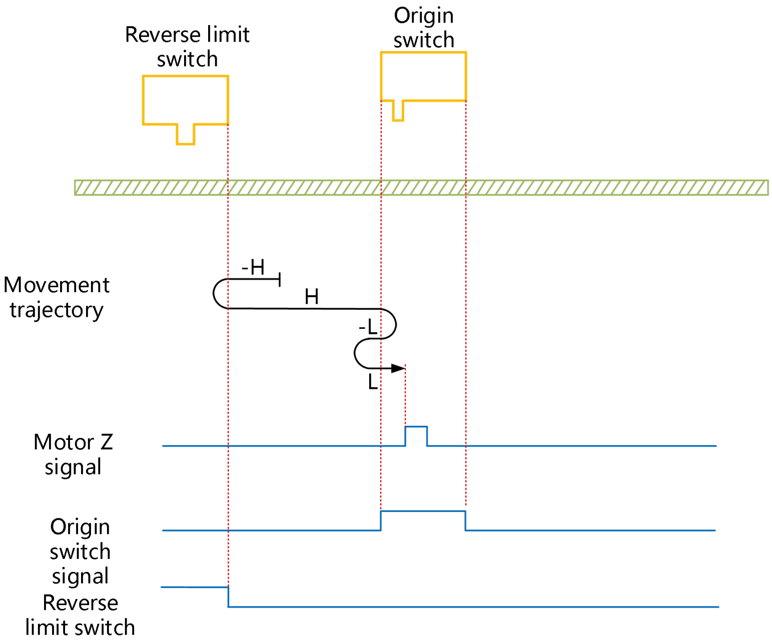
Deceleration point: Origin switch (HW)

① The deceleration point signal is invalid when starting homing, the reverse limit switch is not encountered



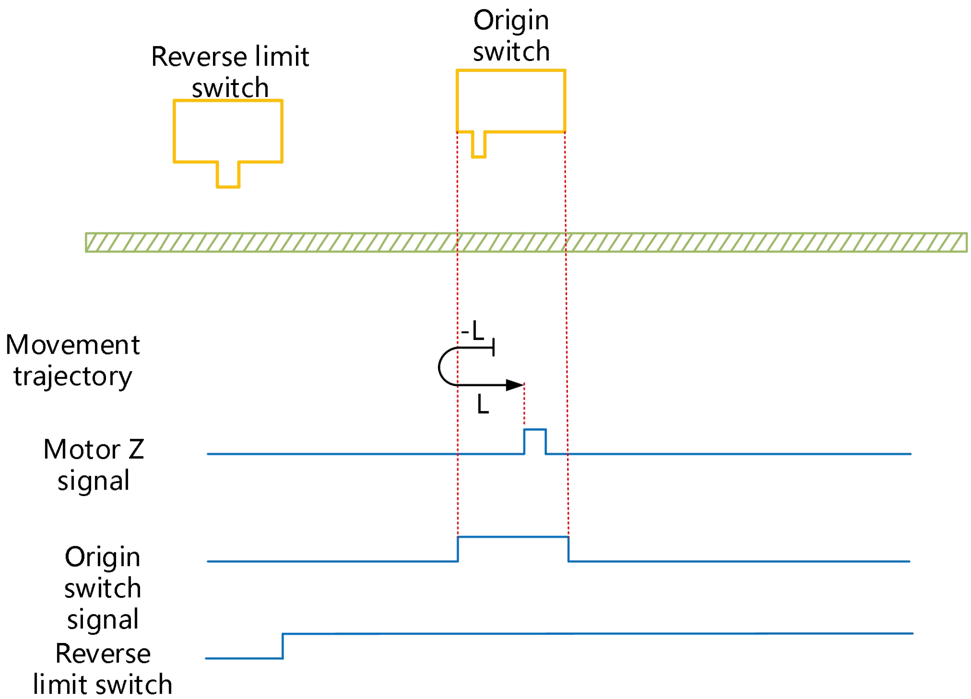
HW=0 when starting homing, start homing in reverse direction at high speed. If the limit switch is not encountered, slow down and run in reverse direction at low speed after encountering the rising edge of HW. After encountering the falling edge of HW, change the running direction and run in forward direction at low speed, and stop at the first Z signal after encountering the rising edge of HW;

② The deceleration point signal is invalid when starting homing, the reverse limit switch is encountered



HW=0 when starting homing, start homing in reverse direction at high speed, change the running direction automatically and run in forward direction at high speed when encountering limit switch, slow down and change the running direction after encountering HW rising edge; run in reverse direction at low speed and change the running direction after encountering HW falling edge; stop at the first Z signal after encountering HW rising edge during running in forward direction at low speed;

③ The deceleration point signal is valid when starting homing



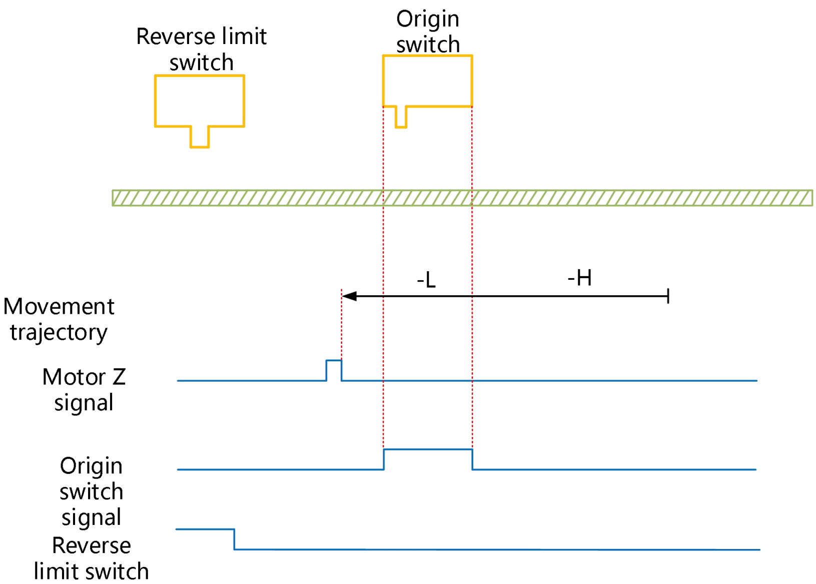
HW=1 when starting homing, start homing directly in reverse direction at low speed. After encountering the falling edge of HW, change the running direction; stop at the first Z signal after encountering the rising edge of HW during running in forward direction at low speed;

(14) 6098H=14

Mechanical origin: Z signal of motor

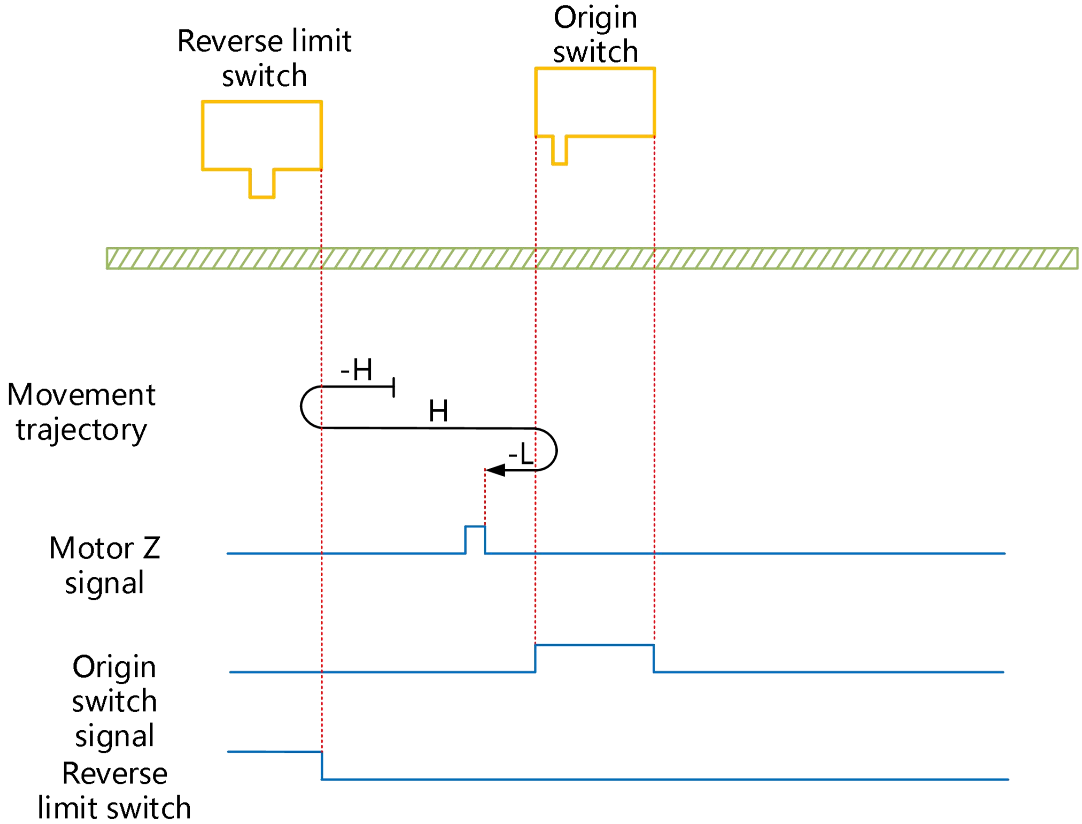
Deceleration point: Origin switch (HW)

① The deceleration point signal is invalid when starting to return to zero, the reverse limit switch is not encountered



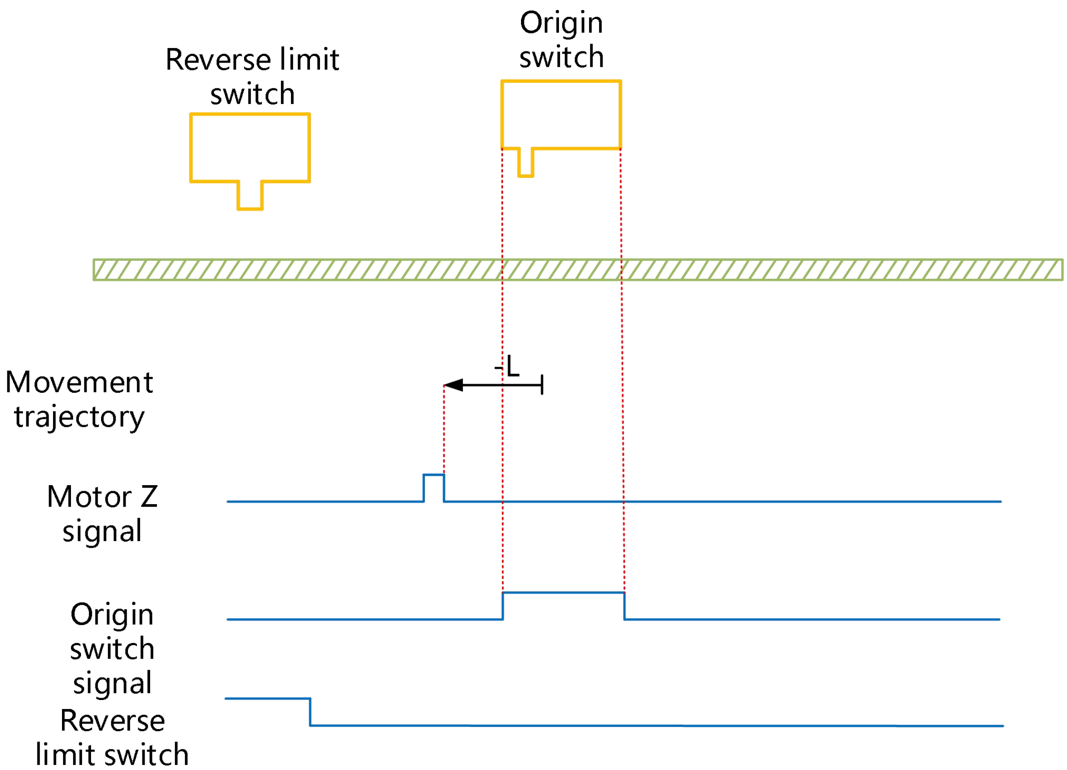
HW=0 when starting homing, start to return to zero in reverse direction at high speed; if limit switch is not encountered; slow down and run in reverse direction at low speed after encountering HW rising edge; after encountering HW falling edge, continue to run in reverse direction at low speed, and then stop at the first Z signal encountered;

② The deceleration point signal is invalid when starting homing, the reverse limit switch is encountered



HW=0 when starting homing, start homing in reverse direction at high speed; change the running direction automatically and run in forward direction at high speed when encountering limit switch; slow down and change the running direction when encountering HW rising edge, and stop at the first Z signal after encountering HW falling edge during running in reverse direction at low speed;

③ The deceleration point signal is valid when starting homing



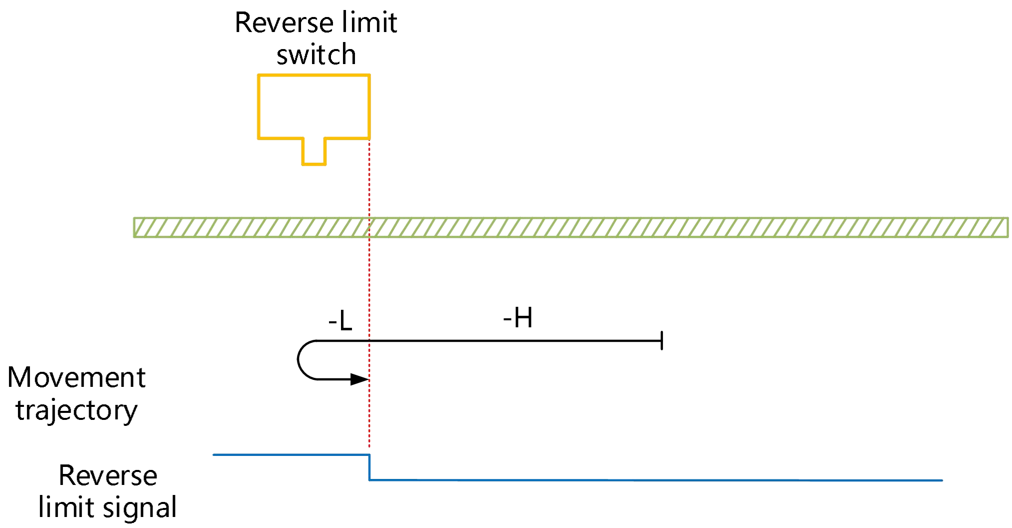
HW=1 when starting homing, start homing in reverse direction at low speed directly, and stop at the first Z signal after encountering the falling edge of HW;

(15) 6098H=17

Mechanical origin: reverse overrun switch (NOT)

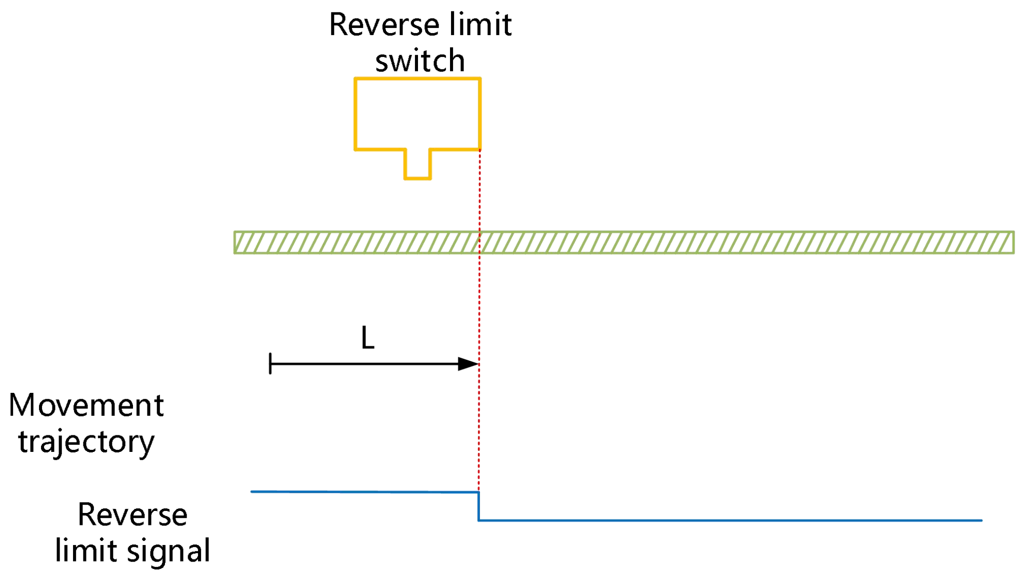
Deceleration point: Reverse overrun switch (NOT)

① The deceleration point signal is invalid when starting homing



NOT=0 when starting homing, start homing in reverse direction at high speed, slow down and change the running direction after encountering the rising edge of NOT, and run in forward direction at low speed, and stop after encountering the falling edge of NOT;

② The deceleration point signal is valid when starting homing



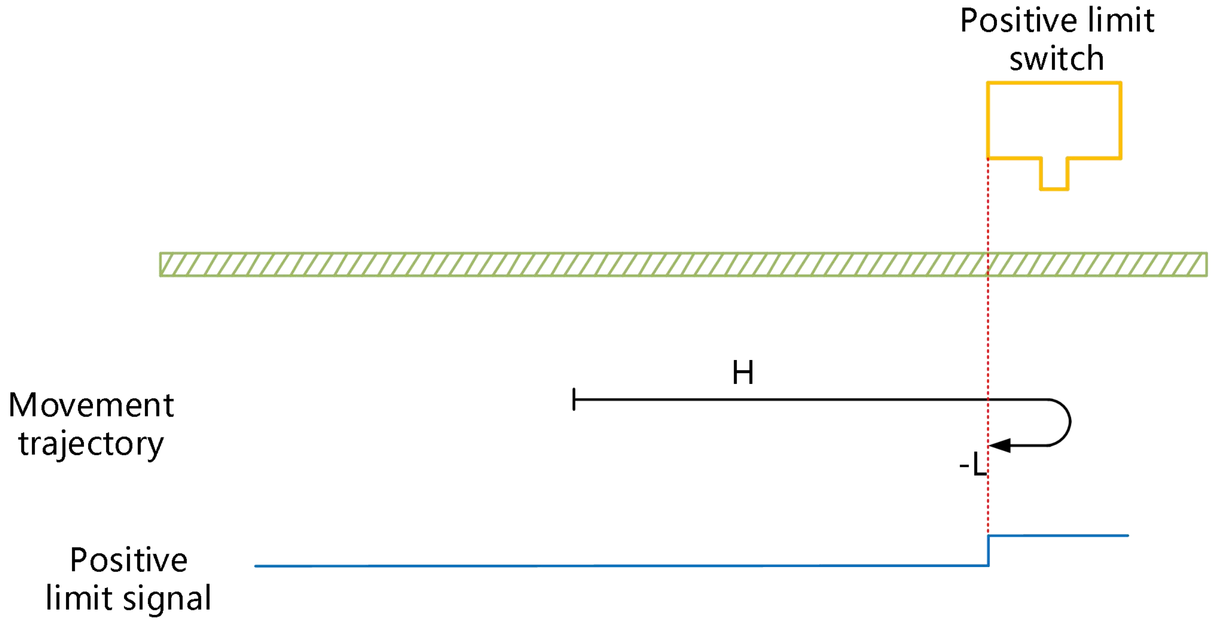
NOT = 1 when starting to return to zero, start homing in forward direction at low speed directly, and stop after encountering the falling edge of NOT.

(16) 6098H=18

Mechanical origin: Forward overtravel switch (POT)

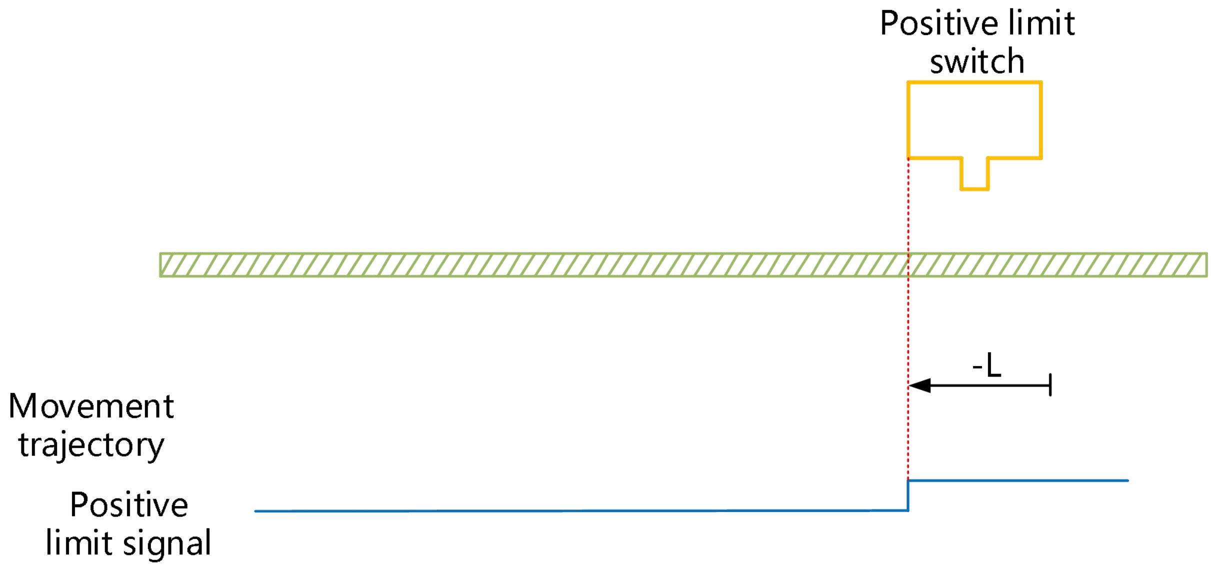
Deceleration point: Forward overtravel switch (POT)

① The deceleration point signal is invalid when starting homing



POT=0 when starting homing, start homing in forward direction at high speed, slow down and change the running direction after encountering the rising edge of POT, run in reverse direction at low speed, and stop after encountering the falling edge of POT;

② The deceleration point signal is valid when starting homing



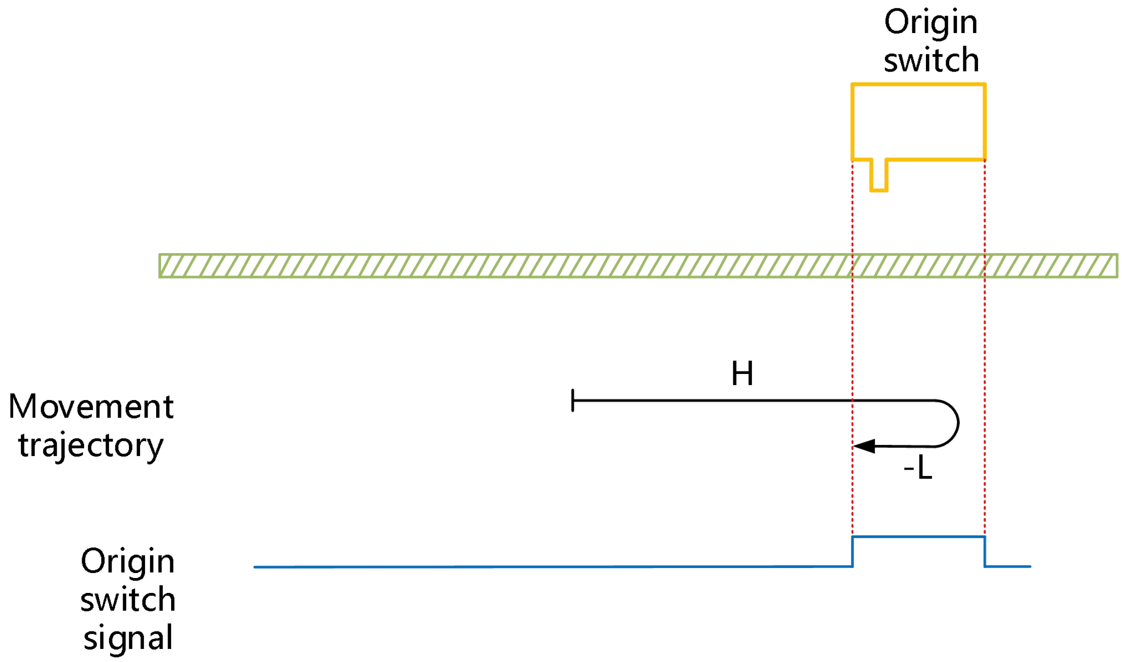
POT=1 when starting homing, start homing in reverse direction at low speed directly, and stop when encountering POT falling edge;

(17) 6098H=19

Mechanical Origin: Origin Switch (HW)

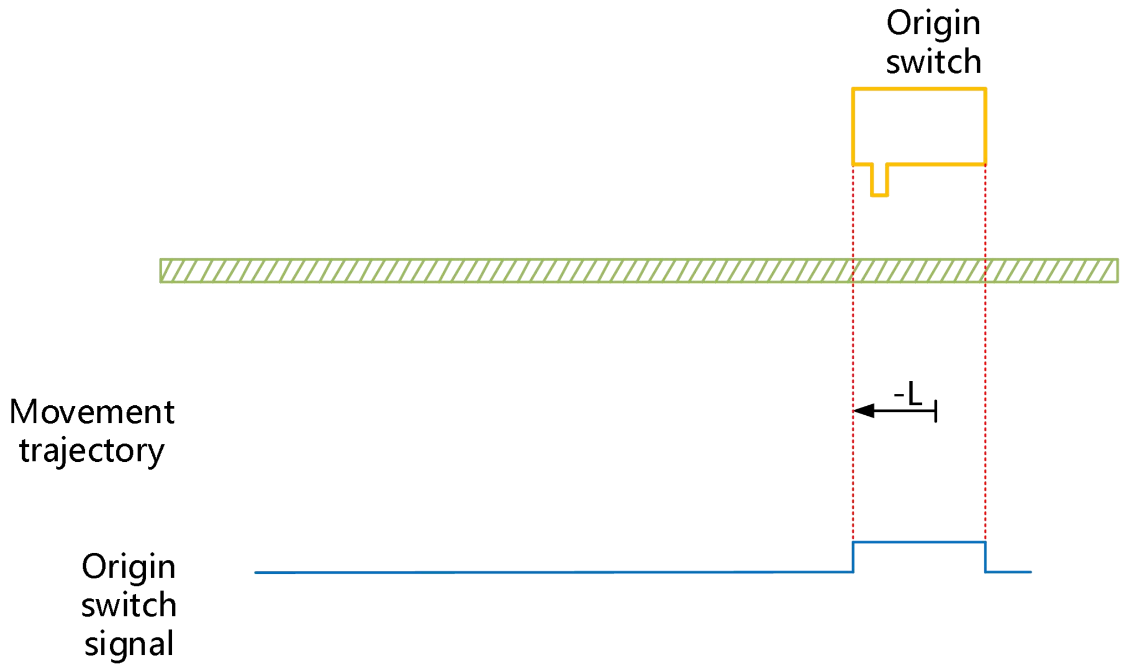
Deceleration point: Origin switch (HW)

① The deceleration point signal is invalid when starting homing



HW=0 when starting homing, start homing in forward direction at high speed, slow down and change the running direction after encountering the rising edge of HW, and run in reverse direction at low speed, and stop when encountering the falling edge of HW;

② The deceleration point signal is valid when starting homing



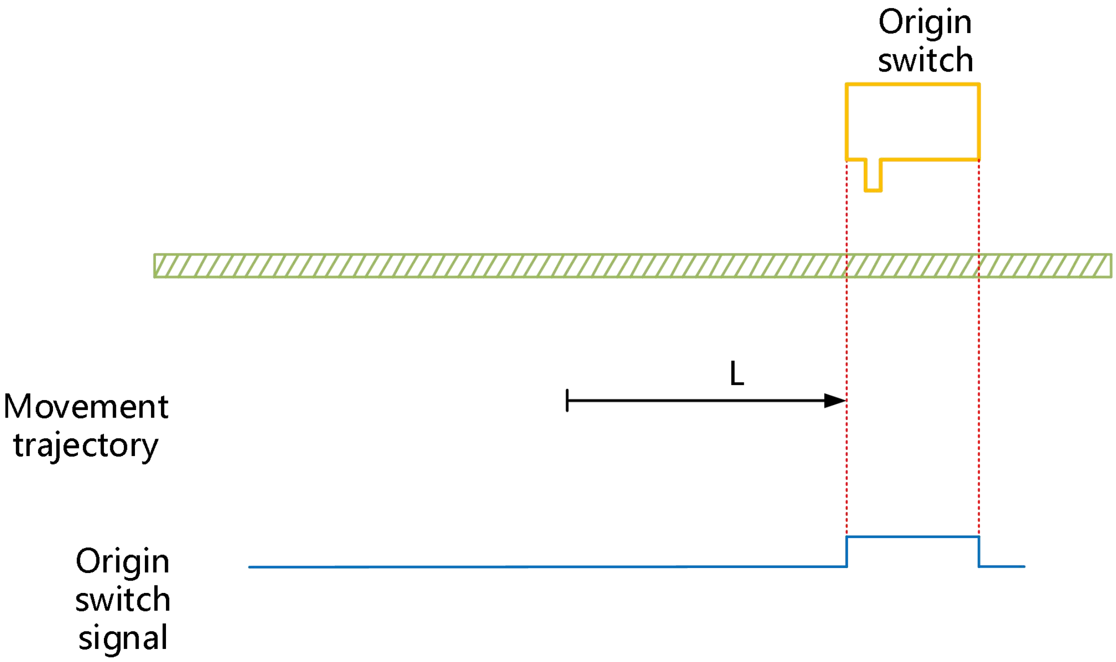
HW=1 when starting homing, start homing in reverse direction at low speed directly, and stop when encountering HW falling edge;

(18) 6098H=20

Mechanical Origin: Origin Switch (HW)

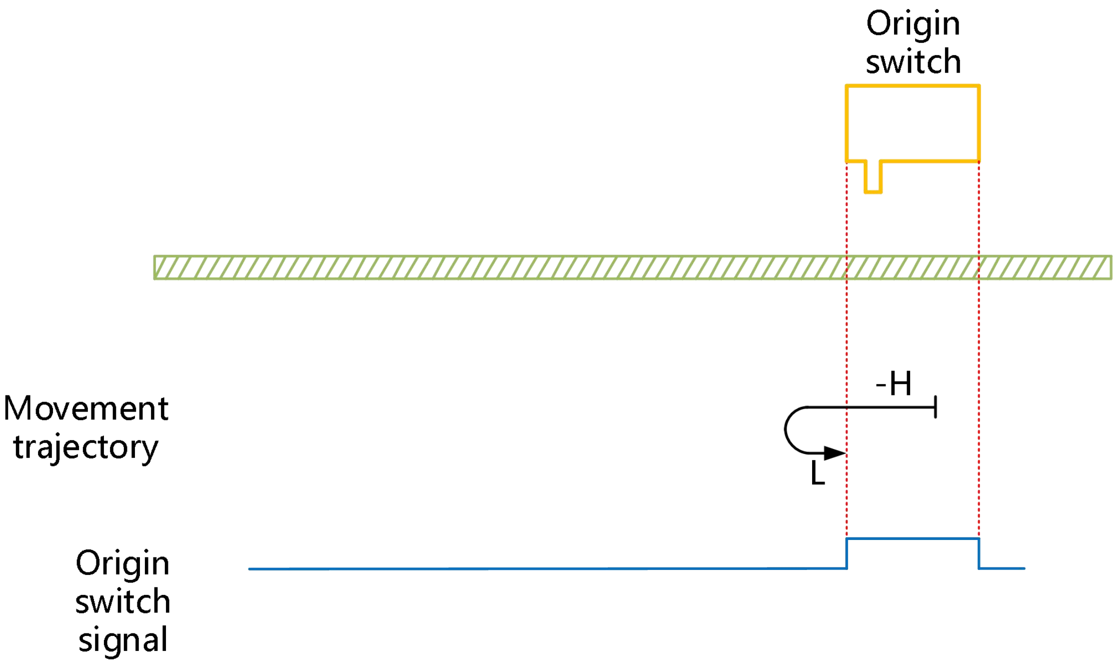
Deceleration point: Origin switch (HW)

① The deceleration point signal is invalid when starting homing



HW=0 when starting homing, start homing forward direction at low speed directly, and stop after encountering the rising edge of HW;

② The deceleration point signal is valid when starting homing



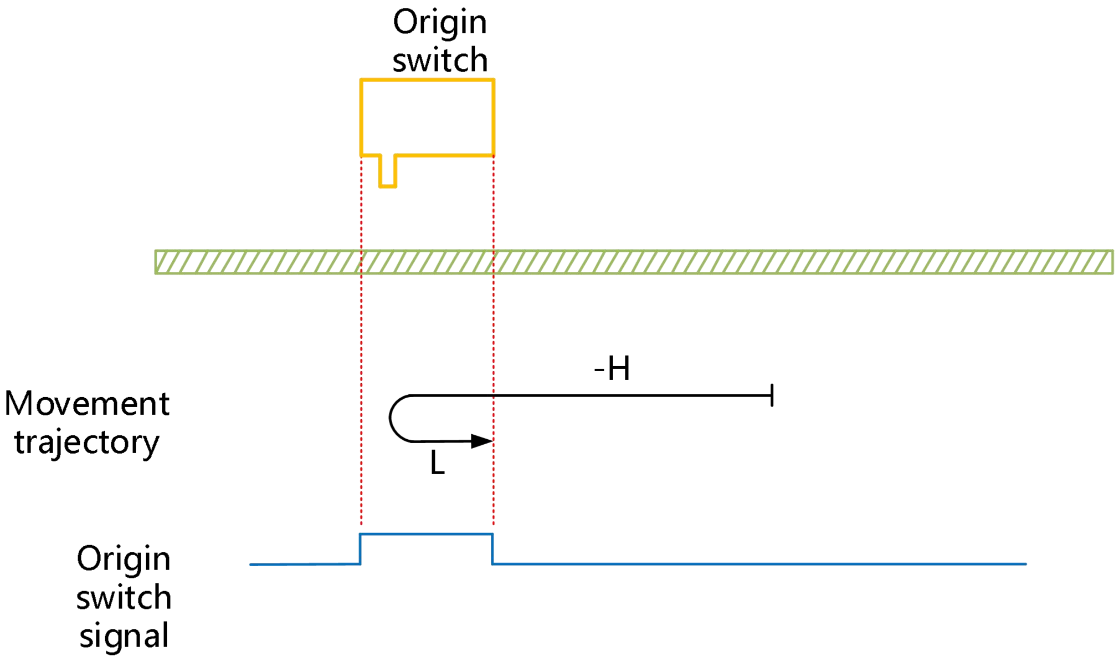
HW=1 when starting homing, start to return to zero in reverse direction at high speed, slow down and change the running direction after encountering HW falling edge, run in forward direction at low speed, and stop when encountering HW rising edge;

(19) 6098H=21

Mechanical Origin: Origin Switch (HW)

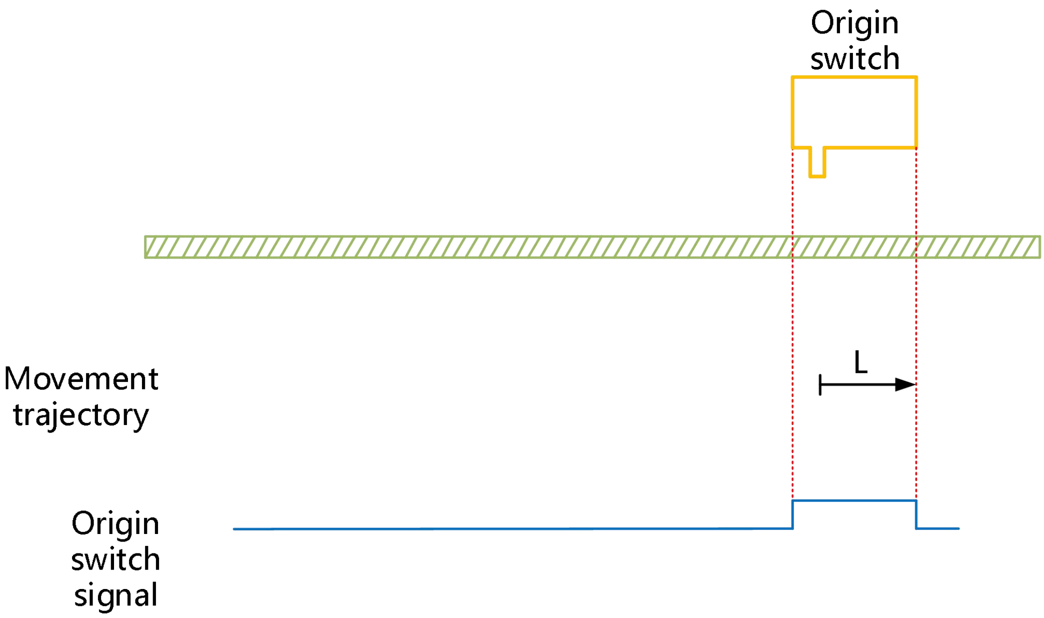
Deceleration point: Origin switch (HW)

① The deceleration point signal is invalid when starting homing



HW=0 when starting homing, start homing in reverse direction at high speed, slow down and change the running direction after encountering the rising edge of HW, run in forward direction at low speed, and stop when encountering the falling edge of HW;

② The deceleration point signal is valid when starting homing



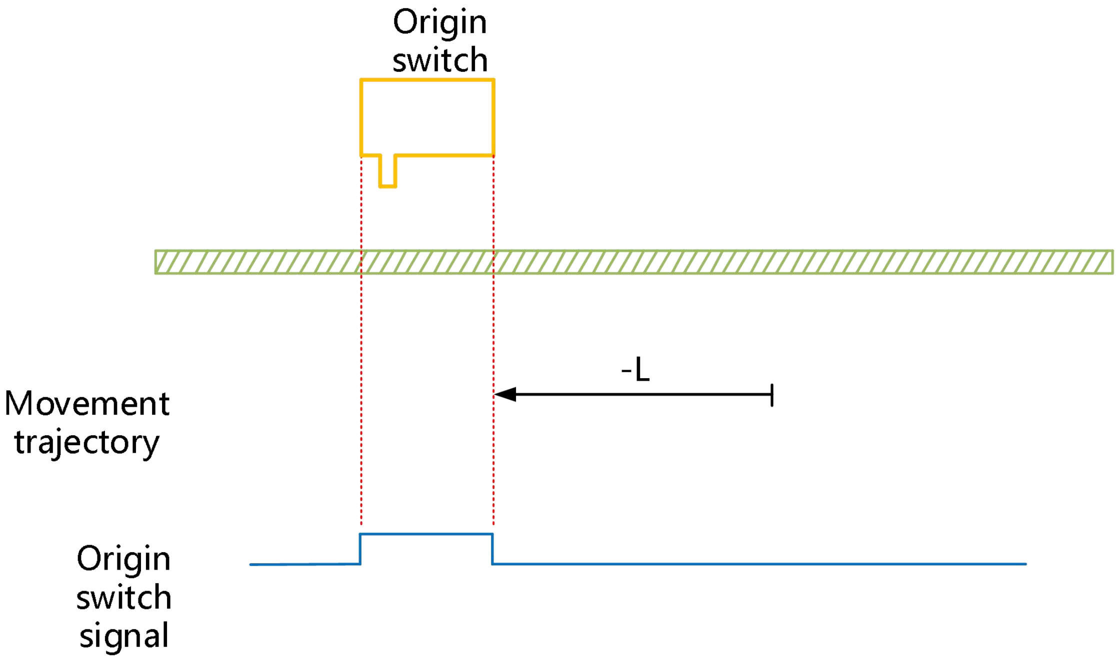
HW=1 when starting homing, start homing in forward direction at low speed directly, and stop after encountering the falling edge of HW;

(20)6098H=22

Mechanical Origin: Origin Switch (HW)

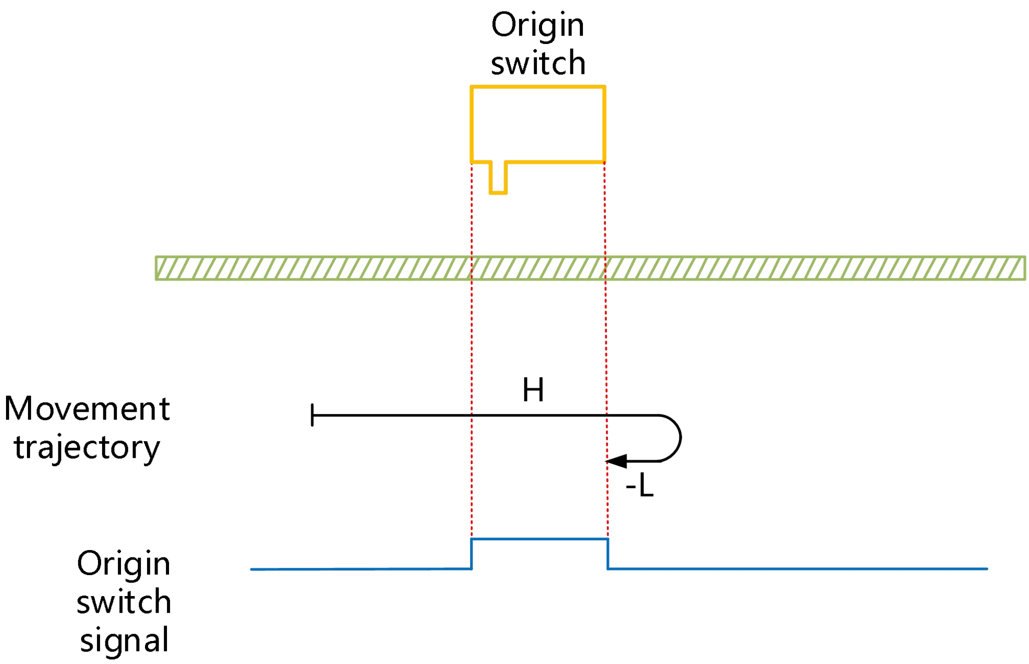
Deceleration point: Origin switch (HW)

① The deceleration point signal is invalid when starting to return to zero



HW=0 when starting homing, start homing in reverse direction at low speed directly and stop when encountering HW rising edge;

② The deceleration point signal is valid when starting homing



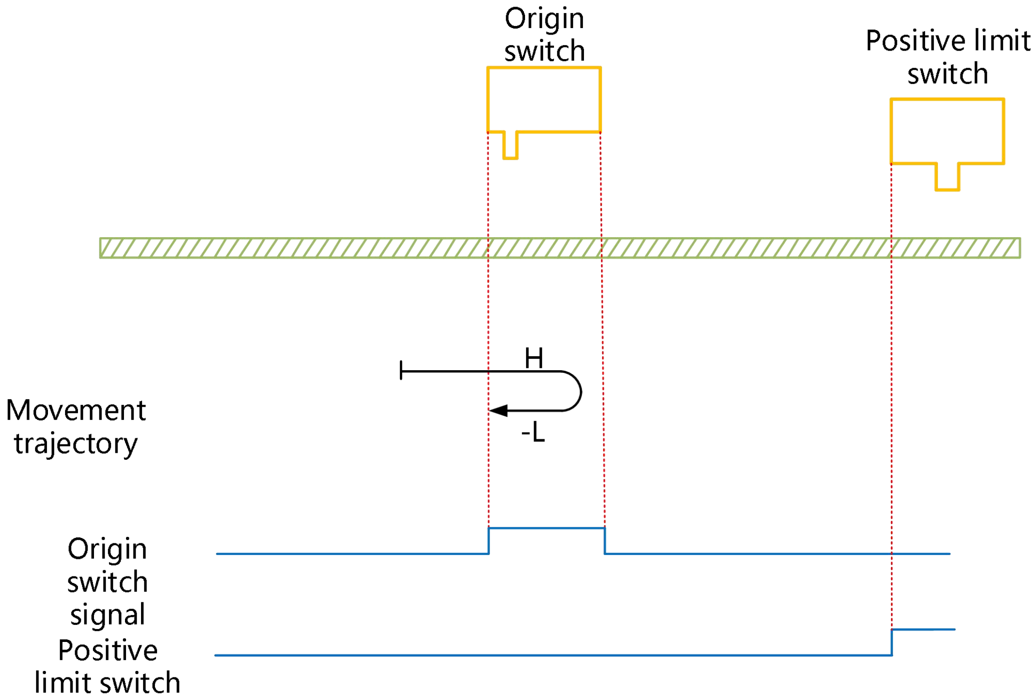
HW=1 when starting to return to zero,start to return to zero in forward direction at high speed, slow down and change the running direction after encountering HW falling edge, run in reverse direction at low speed, and stop when encountering HW rising edge;

(21)6098H=23

Mechanical Origin: Origin Switch (HW)

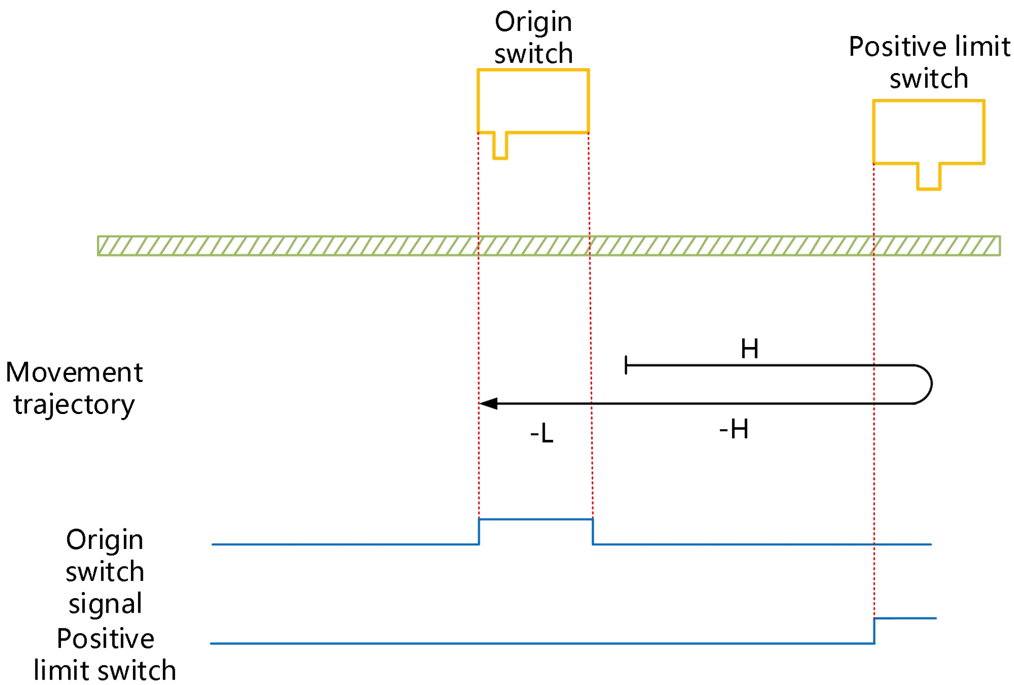
Deceleration point: Origin switch (HW)

① The deceleration point signal is invalid when starting homing, the forward limit switch is not encountered



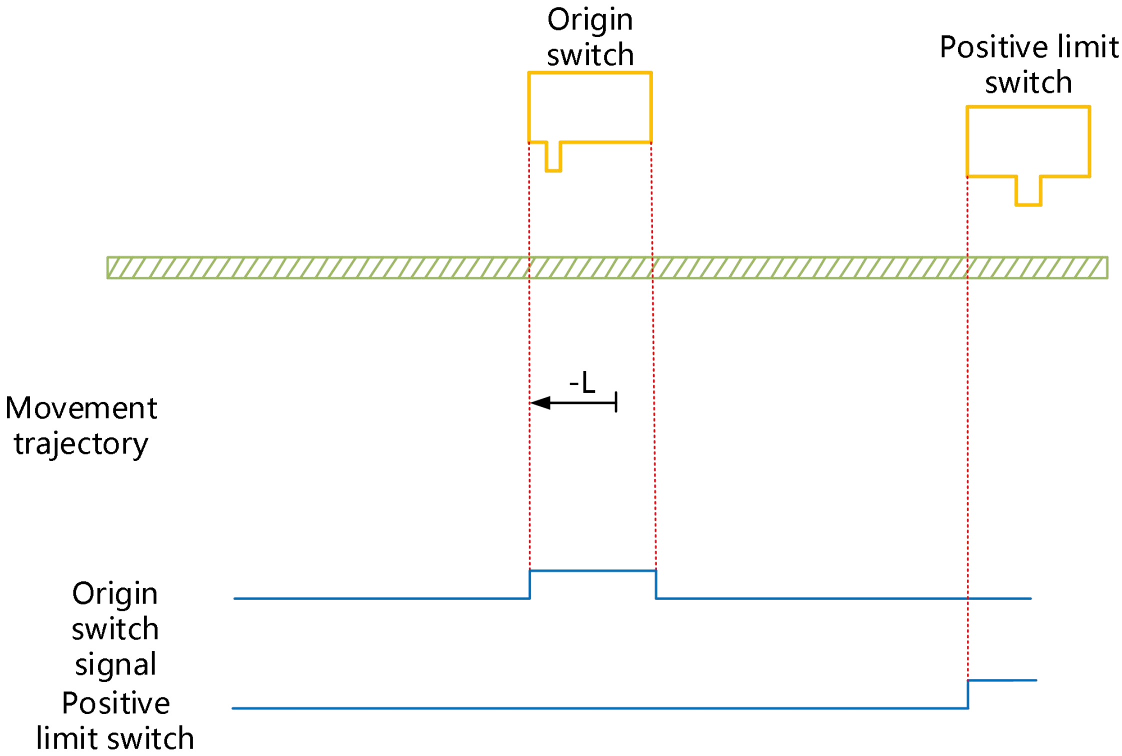
HW=0 when starting homing, start homing in forward direction at high speed; limit switch is not encountered; slow down and change the running direction after encountering HW rising edge; run in reverse direction at low speed and stop when encountering HW falling edge;

② The deceleration point signal is invalid when starting homing, the forward limit switch is encountered



HW=0 when starting to return to zero, start to return to zero in forward direction at high speed, change the running direction automatically when encountering limit switch, run in reverse direction at high speed and slow down when encountering HW rising edge, continue to run in reverse direction at low speed, and stop when encountering HW falling edge;

③ The deceleration point signal is valid when starting homing



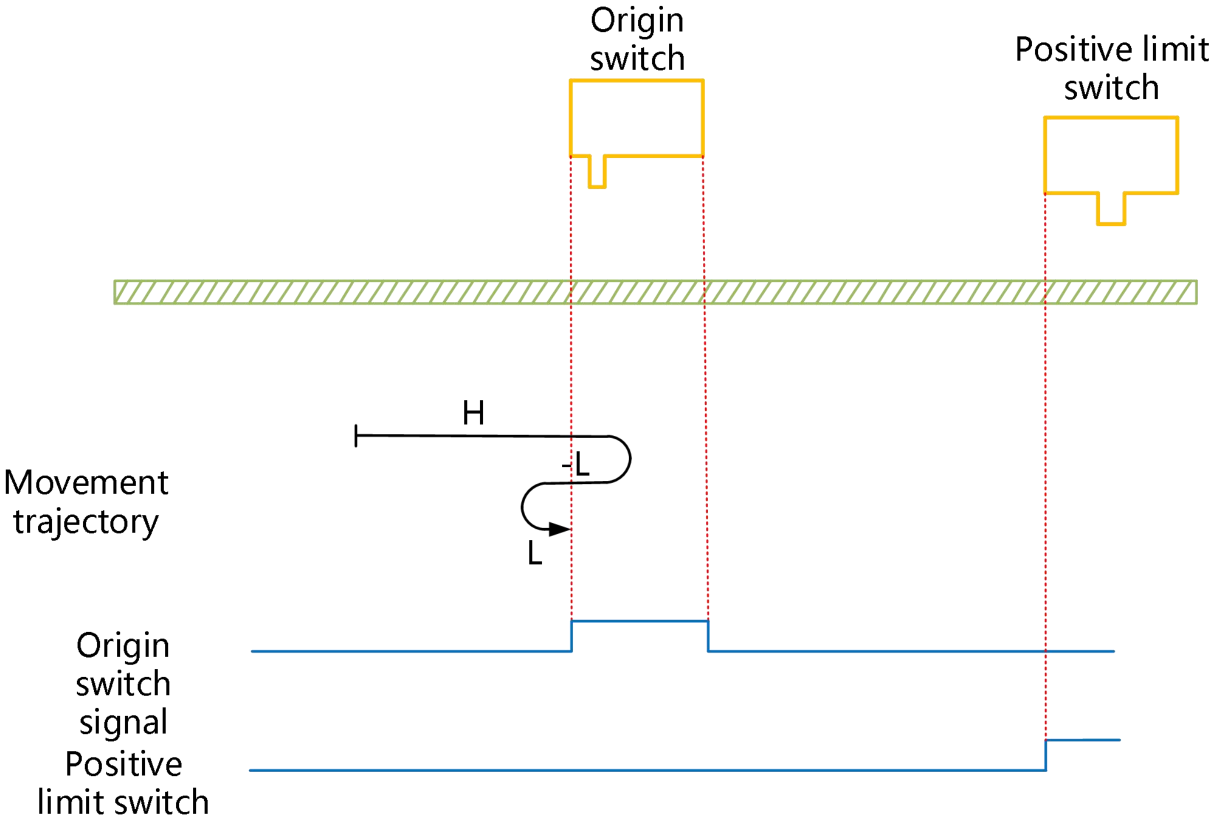
HW=0 when starting homing, start homing in forward direction at high speed, change the running direction automatically when encountering limit switch, run in reverse direction at high speed and slow down when encountering HW rising edge, continue to run in reverse direction at low speed, and stop when encountering HW falling edge;

(22)6098H=24

Mechanical Origin: Origin Switch (HW)

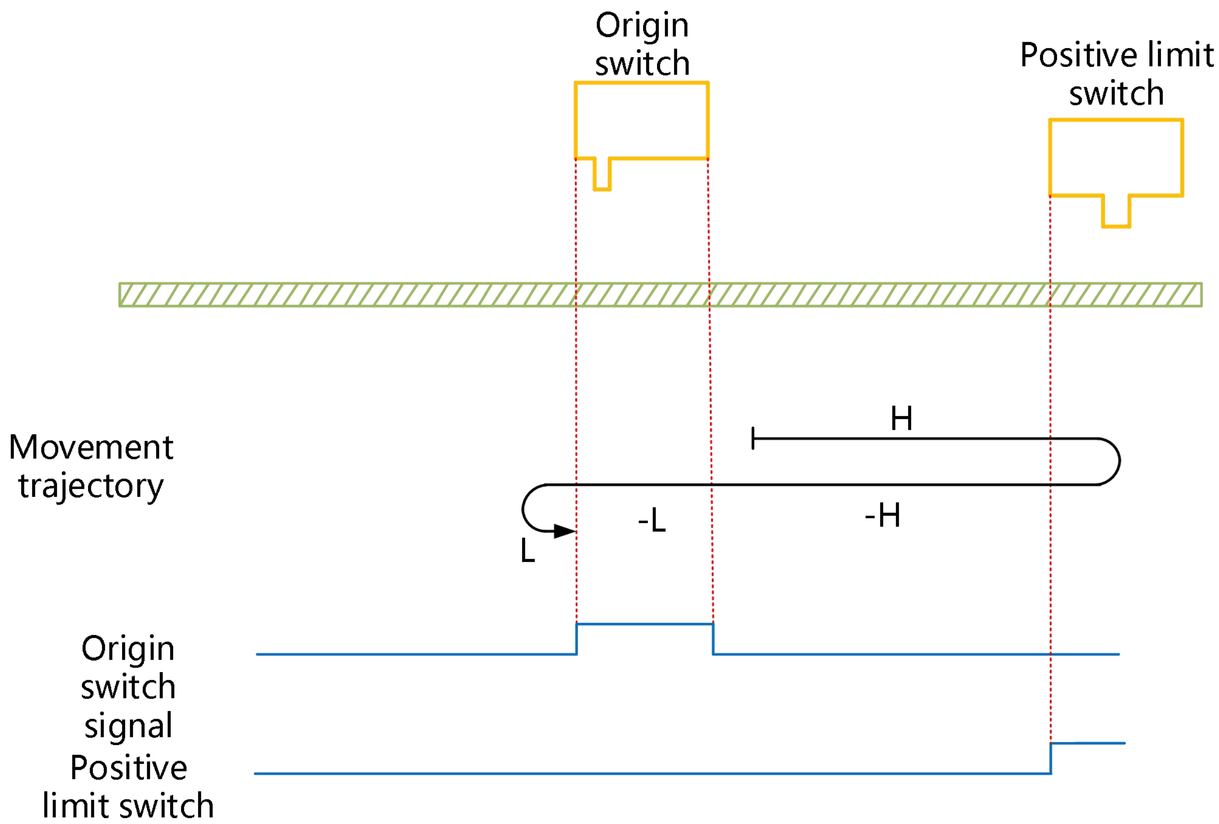
Deceleration point: Origin switch (HW)

① The deceleration point signal is invalid when starting homing, the forward limit switch is not encountered



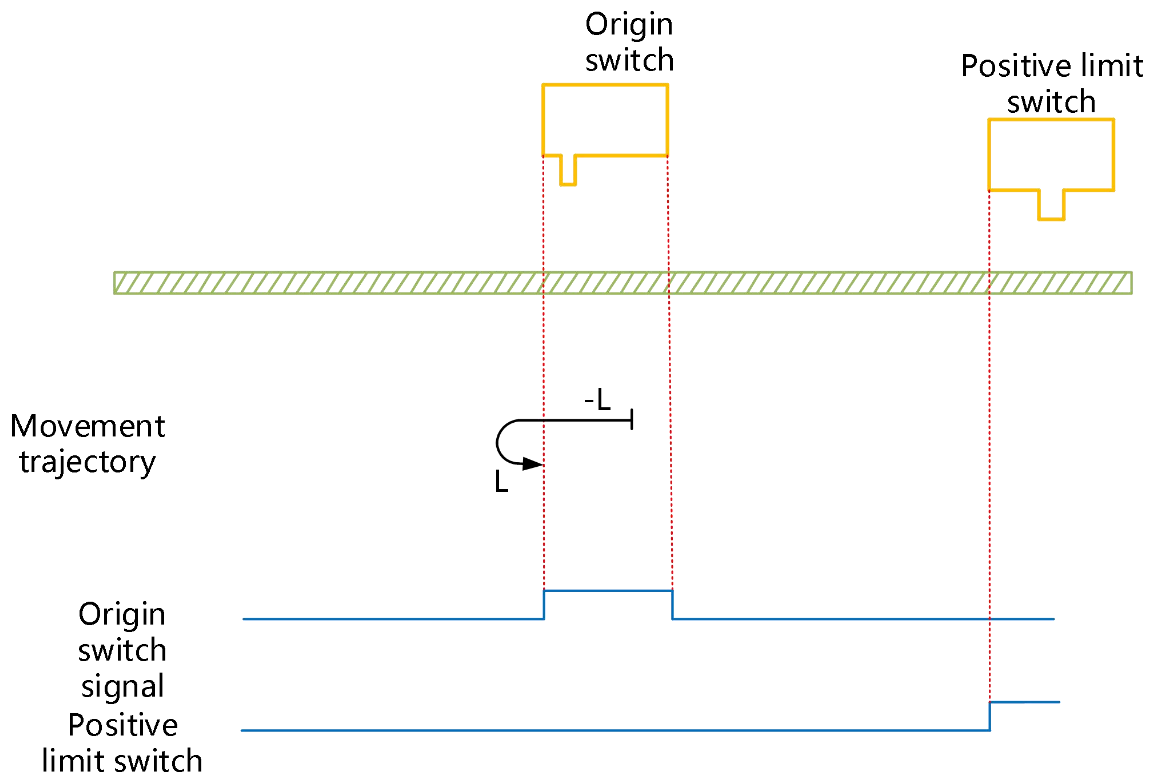
HW=0 when starting homing, start homing in forward direction at high speed; limit switch is not encountered; slow down and change the running direction after encountering HW rising edge, then run in reverse direction at low speed, and change the running direction when encountering HW falling edge, run in forward direction at low speed and stop when encountering HW rising edge;

② The deceleration point signal is invalid when starting homing, the forward limit switch is encountered



HW=0 when starting homing, start homing in forward direction at high speed; change the running direction automatically when encountering limit switch, run in reverse direction at high speed and slow down and run in reverse direction at low speed when encountering HW rising edge; change the running direction and run in forward direction at low speed when encountering HW falling edge, and stop when encountering HW rising edge;

③ The deceleration point signal is valid when starting homing



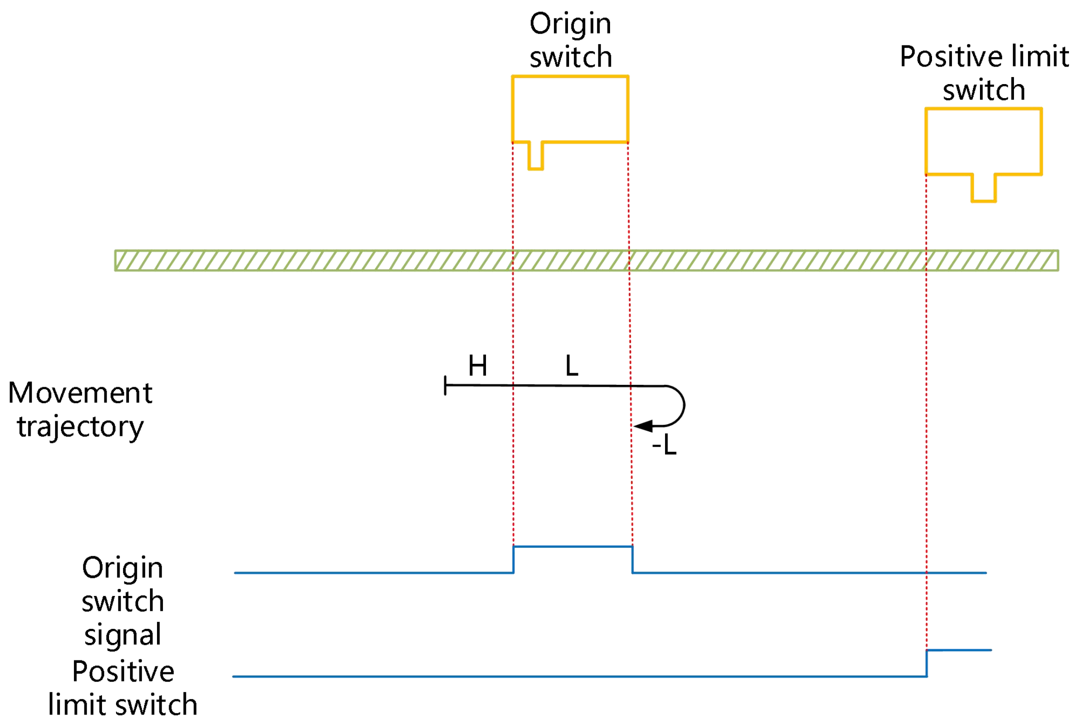
HW=1 when starting homing, start homing in reverse direction at low speed directly; after encountering the falling edge of HW, change the running direction and run in forward direction at low speed, and stop when encountering the rising edge of HW;

(23)6098H=25

Mechanical Origin: Origin Switch (HW)

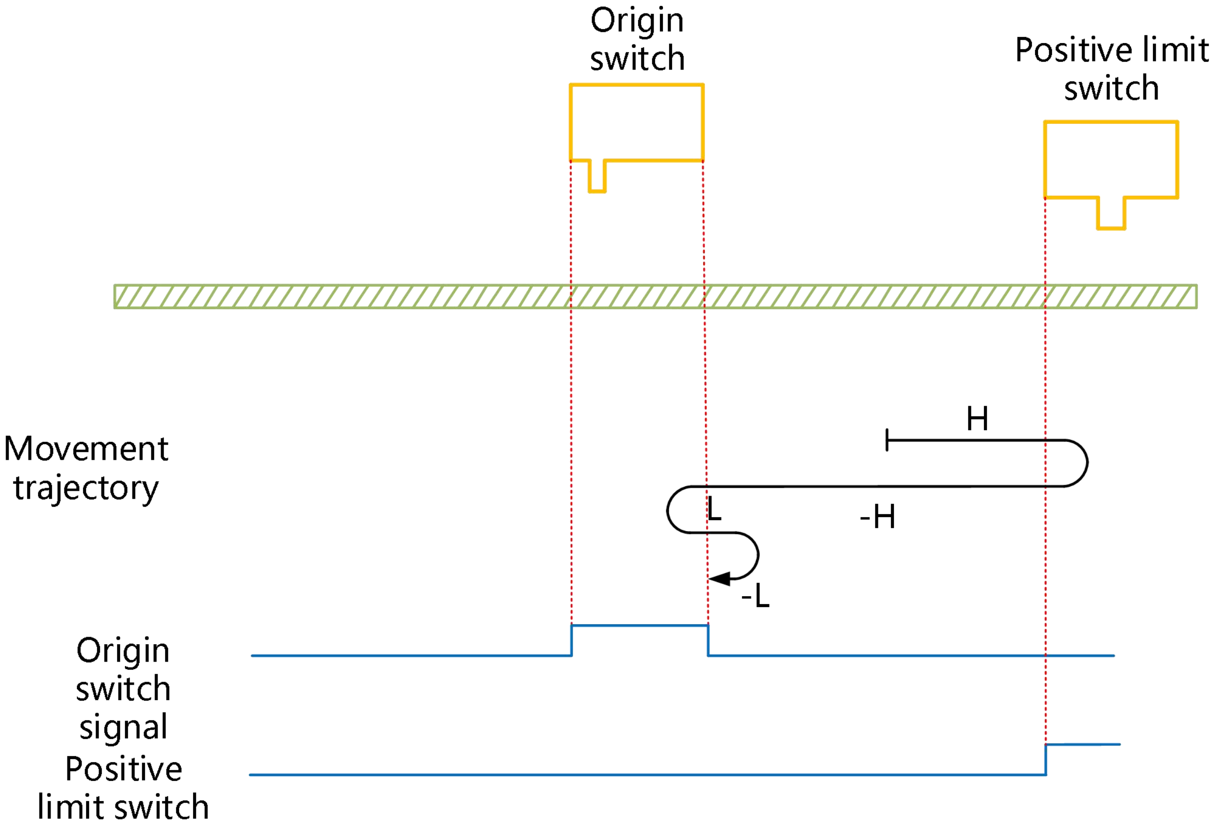
Deceleration point: Origin switch (HW)

① The deceleration point signal is invalid when starting homing, the forward limit switch is not encountered



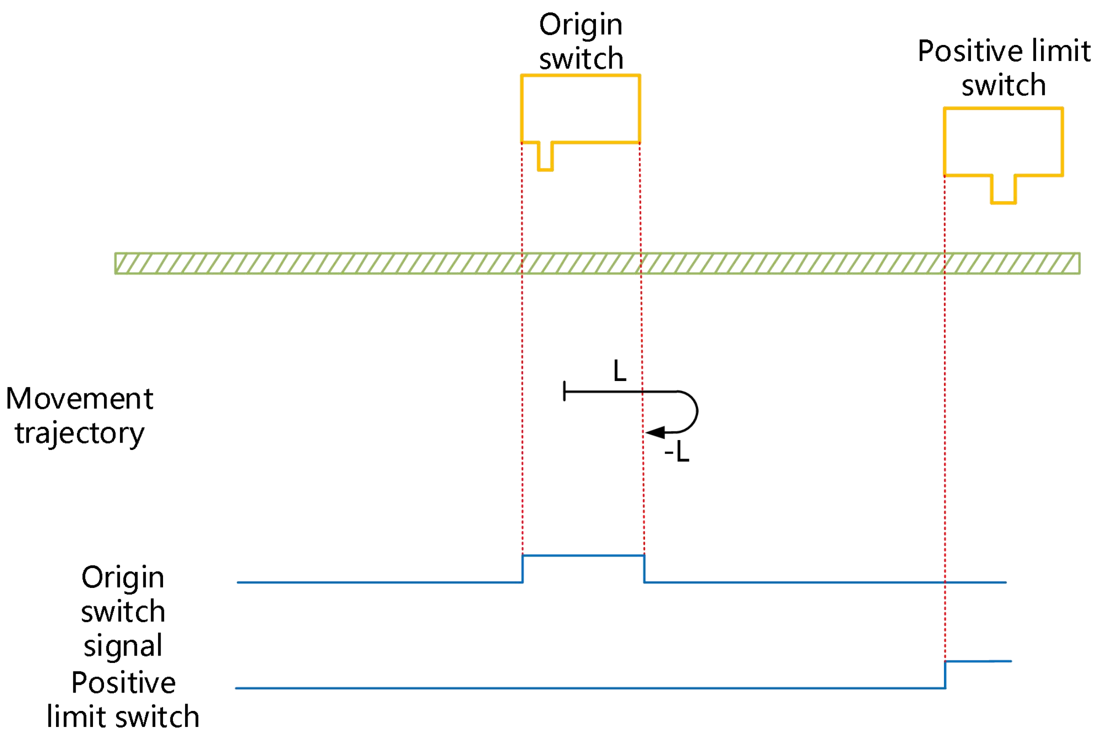
HW=0 when starting homing, start homing in forward direction at high speed; limit switch is not encountered; slow down after encountering HW rising edge, run in forward direction at low speed, change the running direction and run in reverse direction at low speed after encountering HW falling edge, and stop when encountering HW rising edge;

② The deceleration point signal is invalid when starting homing, the forward limit switch is encountered



HW=0 when starting homing, start homing in forward direction at high speed, change the running direction automatically and run in reverse direction at high speed when encountering limit switch; slow down and change the running direction after encountering HW rising edge to resume forward operation; run in forward direction at low speed and change the running direction after encountering HW falling edge; run in reverse direction at low speed and stop when encountering HW rising edge;

③ The deceleration point signal is valid when starting homing



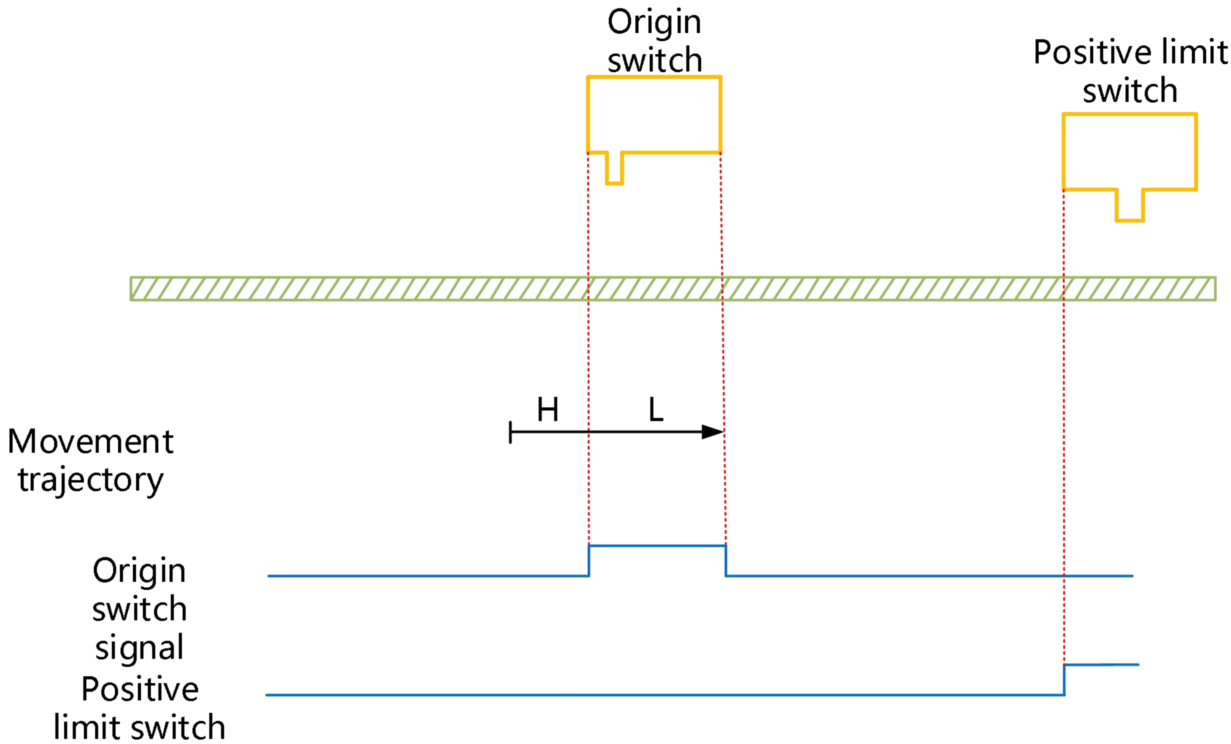
HW=1 when starting homing, when, start homing in the forward direction at low speed directly. After encountering the falling edge of HW, change the running direction and run in verse direction at low speed and stop when encountering the rising edge of HW.

(24) 6098H=26

Mechanical Origin: Origin Switch (HW)

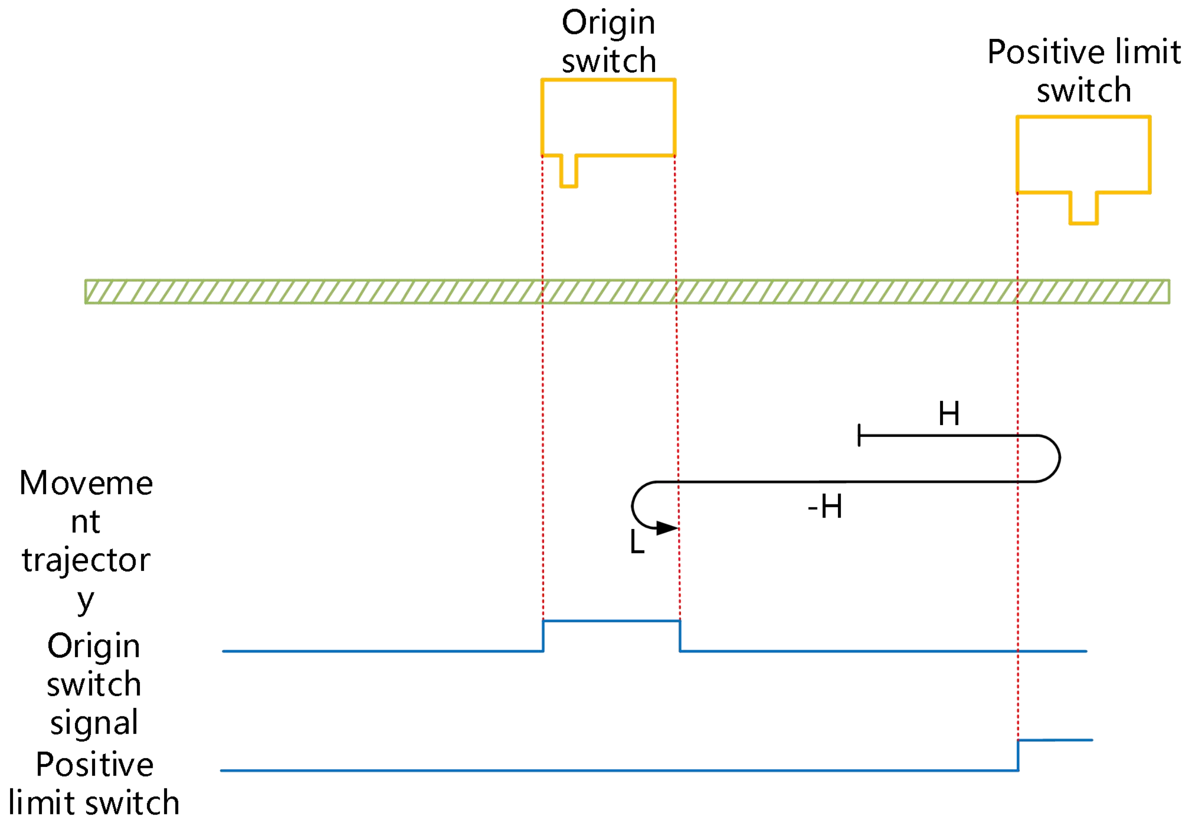
Deceleration point: Origin switch (HW)

① The deceleration point signal is invalid when starting homing, the forward limit switch is not encountered



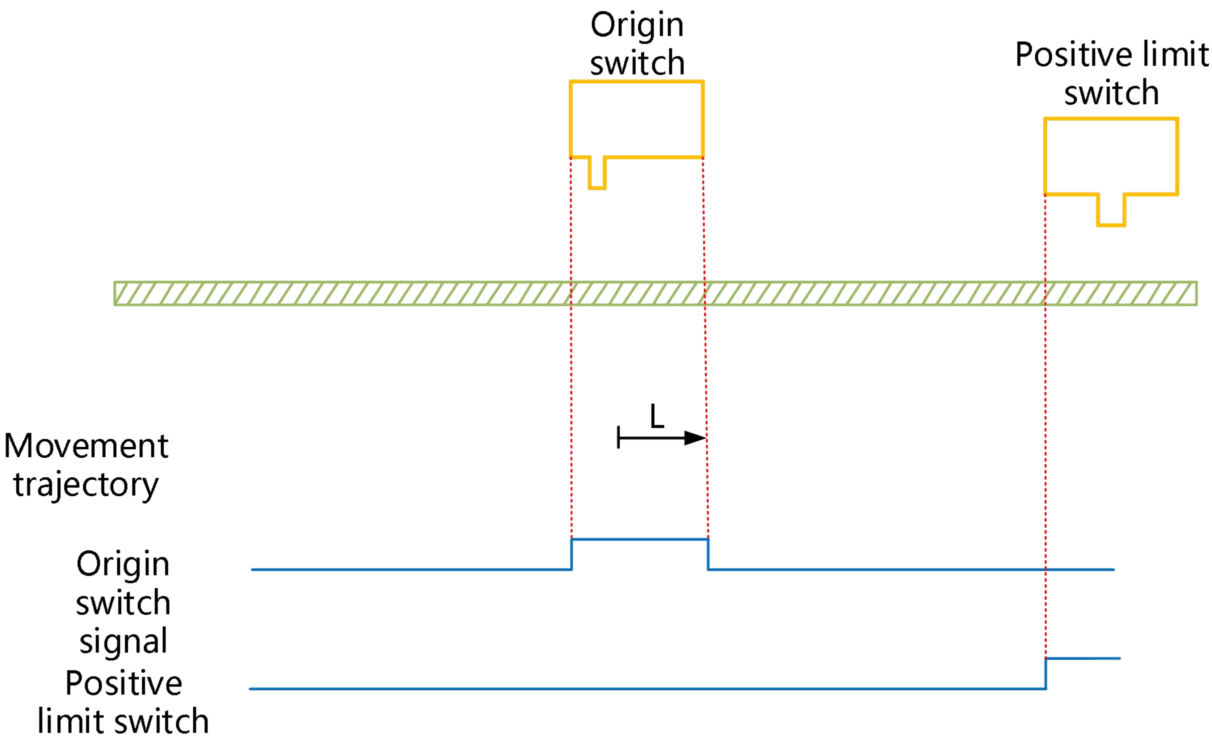
HW=0 when starting homing, start homing in forward direction at high speed; limit switch is not encountered; slow down after encountering HW rising edge, run in forward direction at low speed, and stop when encountering HW falling edge;

② The deceleration point signal is invalid when starting homing, the forward limit switch is encountered



HW=0 when starting homing, start homing in forward direction at high speed, change the running direction automatically and run in reverse direction at high speed when encountering limit switch; slow down and change the running direction when encountering HW rising edge to resume forward operation, run in forward direction at low speed and stop when encountering HW falling edge;

③ The deceleration point signal is valid when starting homing



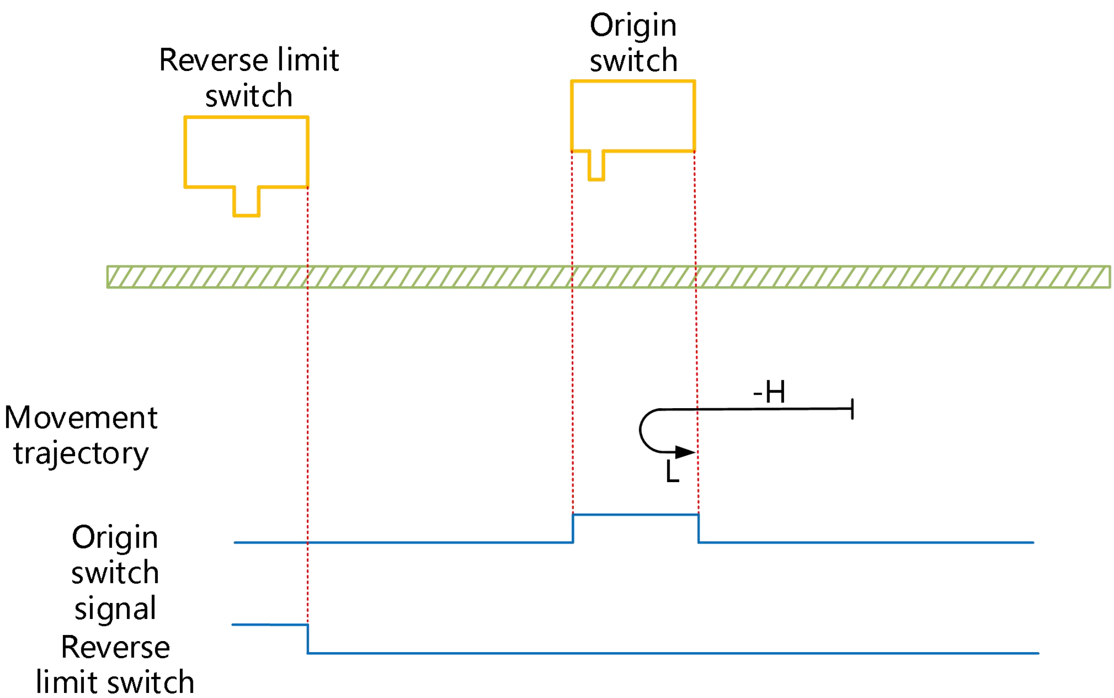
HW=1 when starting to return to zero, start homing in forward direction at low speed directly, and stop when encountering HW falling edge;

(25) 6098H=27

Mechanical Origin: Origin Switch (HW)

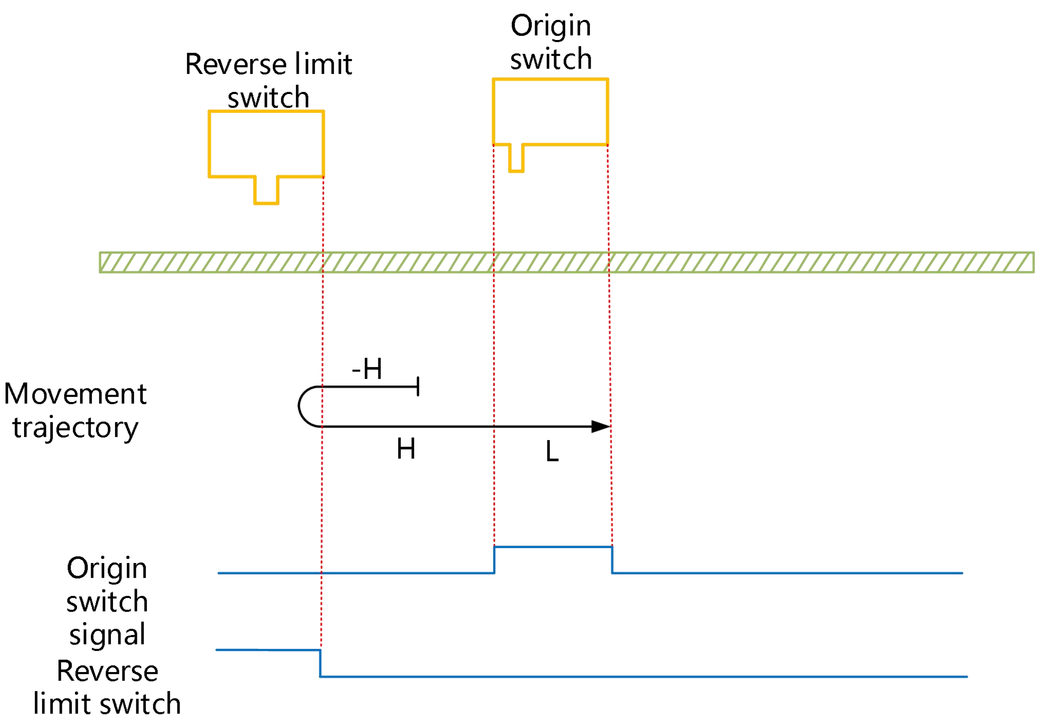
Deceleration point: Origin switch (HW)

① The deceleration point signal is invalid when starting homing, the reverse limit switch is not encountered



HW=0 when starting homing, start homing in reverse direction at high speed; limit switch is not encountered; slow down and change the running direction after encountering rising edge of HW, run in forward direction at low speed and stop when encountering HW falling edge;

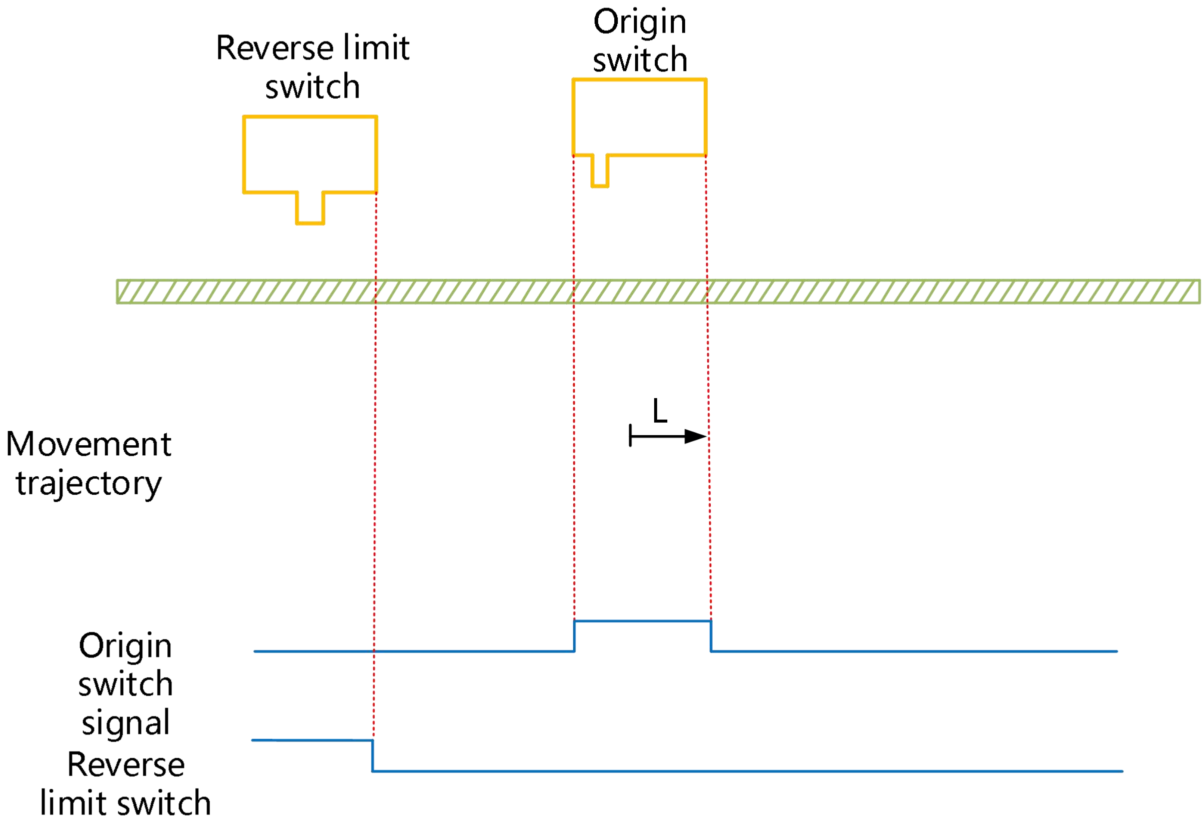
② The deceleration point signal is invalid when starting homing, the reverse limit switch is encountered



HW=0 when starting homing, start homing in reverse direction at high speed, change the running direction automatically when encountering limit switch and run in forward direction at high speed;

slow down when encountering HW rising edge, continue to run in forward direction at low speed and stop when encountering HW falling edge;

③ The deceleration point signal is valid when starting homing



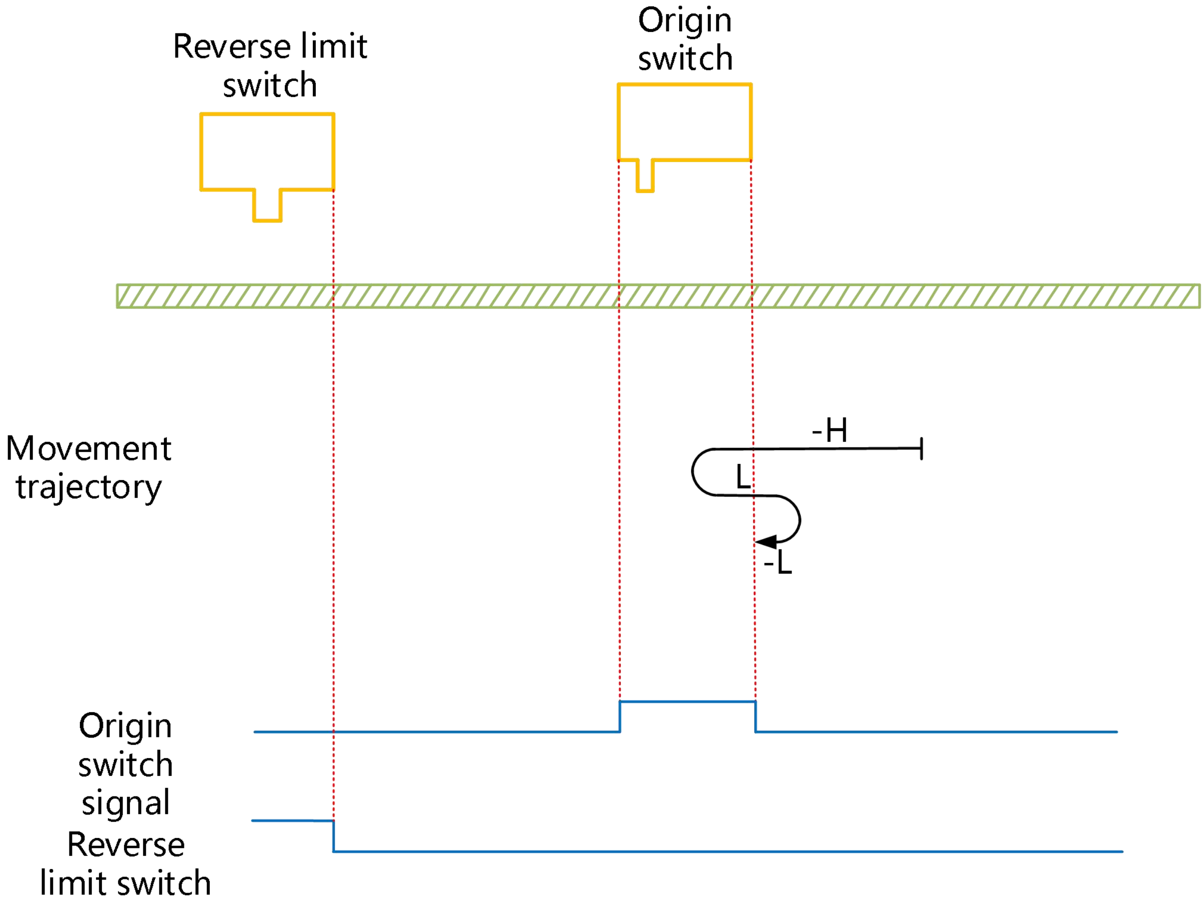
HW=1 when starting homing, start homing in forward direction at low speed directly, and stop when encountering HW falling edge;

(26) 6098H=28

Mechanical Origin: Origin Switch (HW)

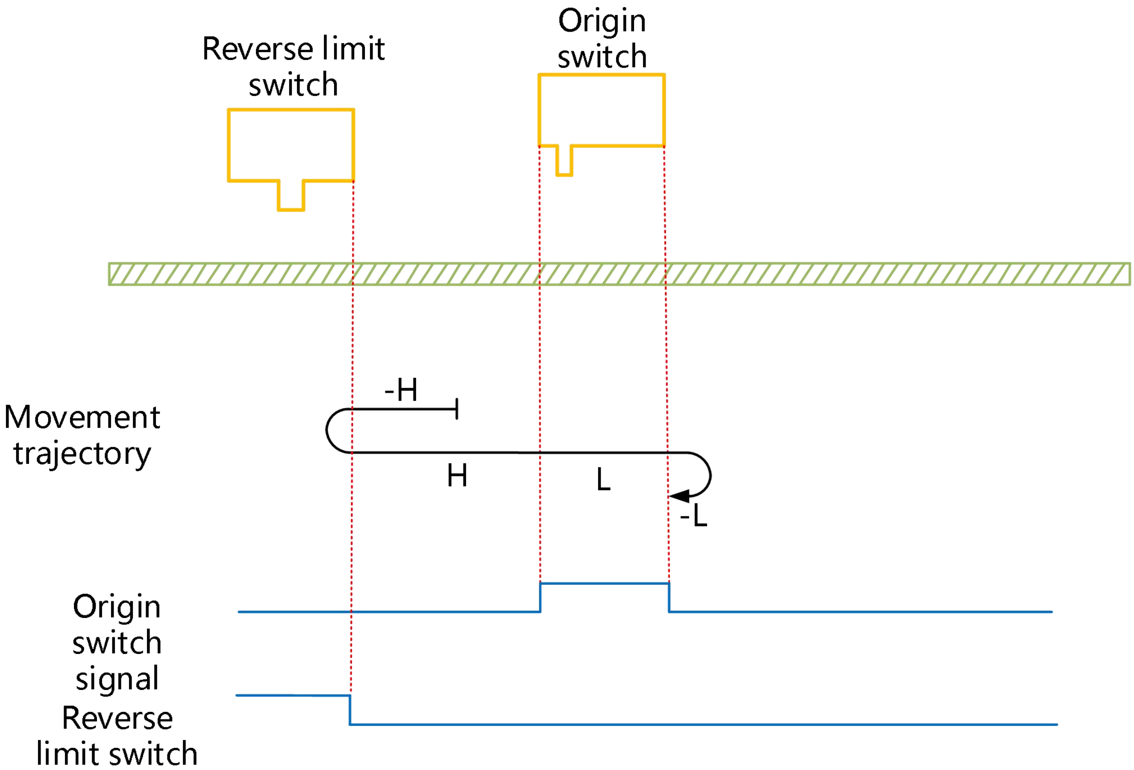
Deceleration point: Origin switch (HW)

① The deceleration point signal is invalid when starting homing, the reverse limit switch is not encountered



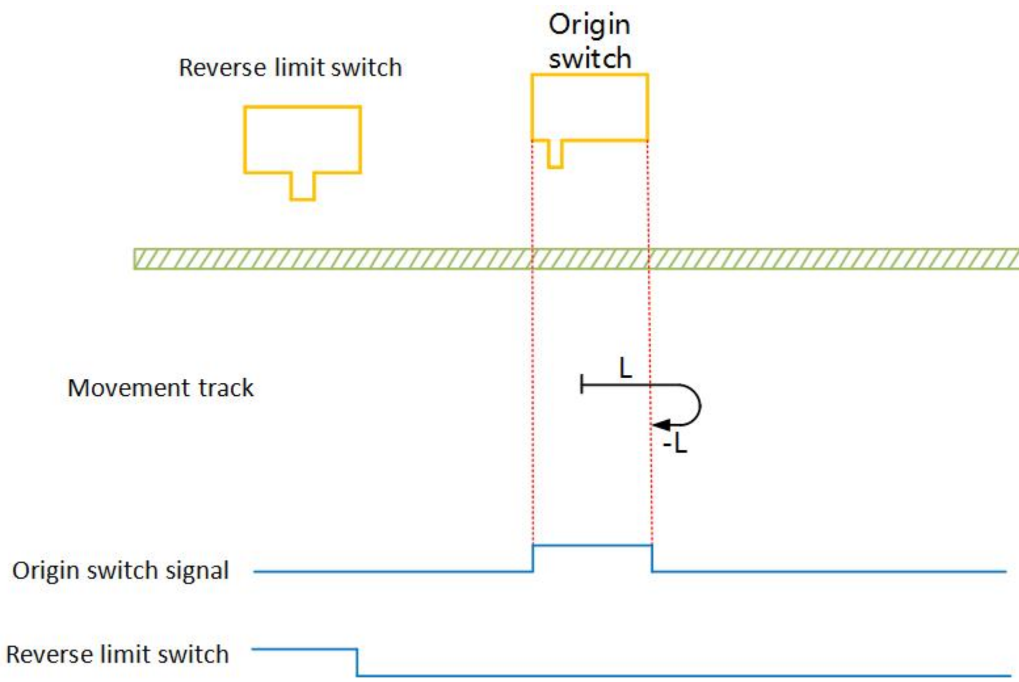
HW=0 when starting homing, start homing in reverse direction at high speed; limit switch is not encountered; slow down and change the running direction after encountering HW rising edge, run in forward direction at low speed; change the running direction after encountering HW falling edge, run in reverse direction at low speed and stop when encountering HW rising edge;

② The deceleration point signal is invalid when starting homing, the reverse limit switch is encountered



HW=0 when starting homing, start homing in reverse direction at high speed, change the running direction automatically when encountering limit switch and run in forward direction at high speed; slow down and run in forward direction at low speed when encountering HW rising edge; change the running direction and run in reverse direction at low speed when encountering HW falling edge, and stop when encountering HW rising edge;

③ The deceleration point signal is valid when starting homing



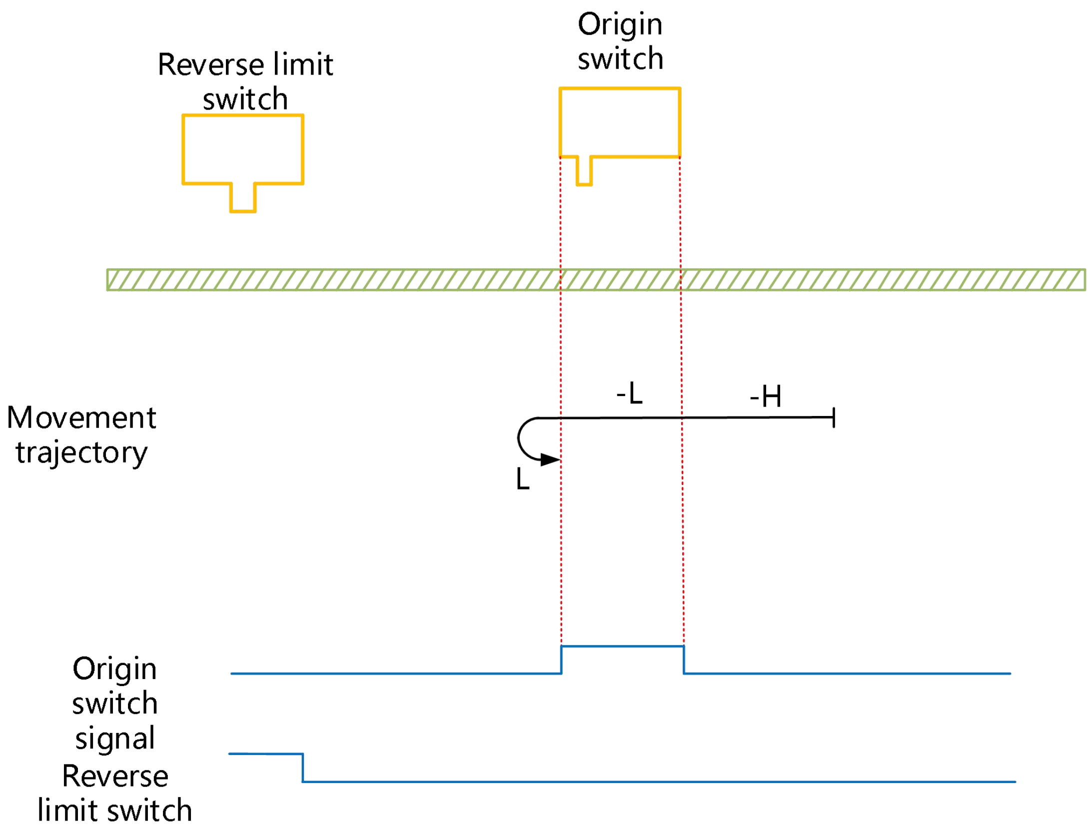
HW=1 when starting homing, start homing in forward direction at low speed directly. After encountering the falling edge of HW, change the running direction and run in reverse direction at low speed and stop when encountering the rising edge of HW;

(27) 6098H=29

Mechanical Origin: Origin Switch (HW)

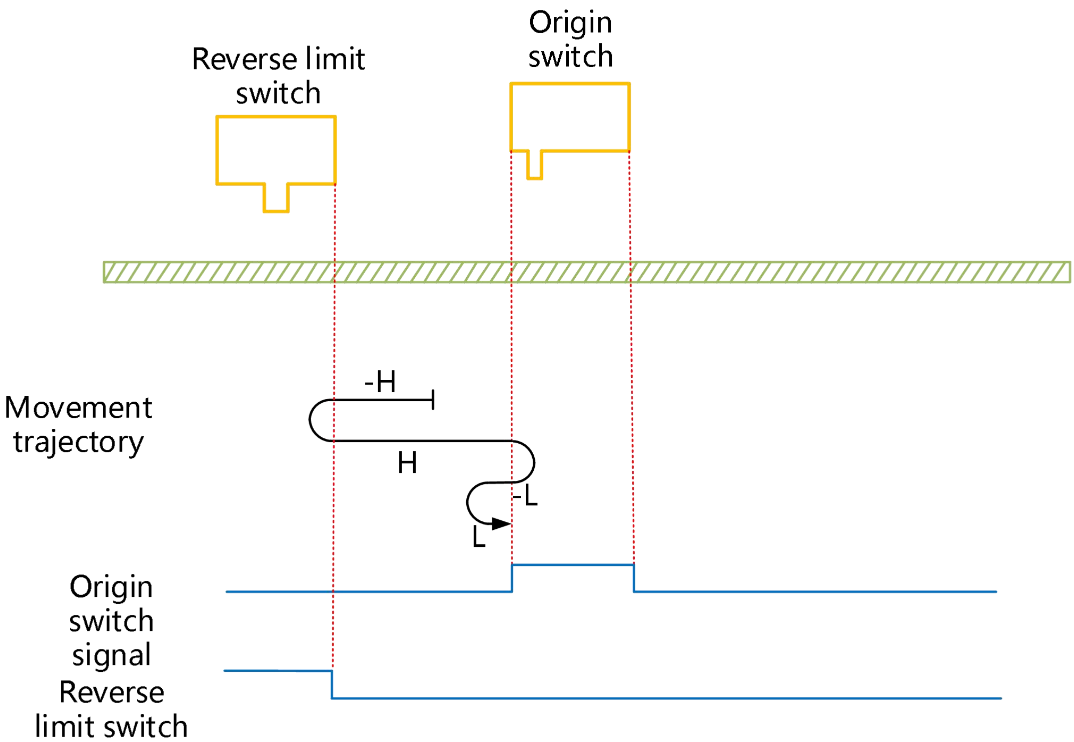
Deceleration point: Origin switch (HW)

① The deceleration point signal is invalid when starting homing, the reverse limit switch is not encountered



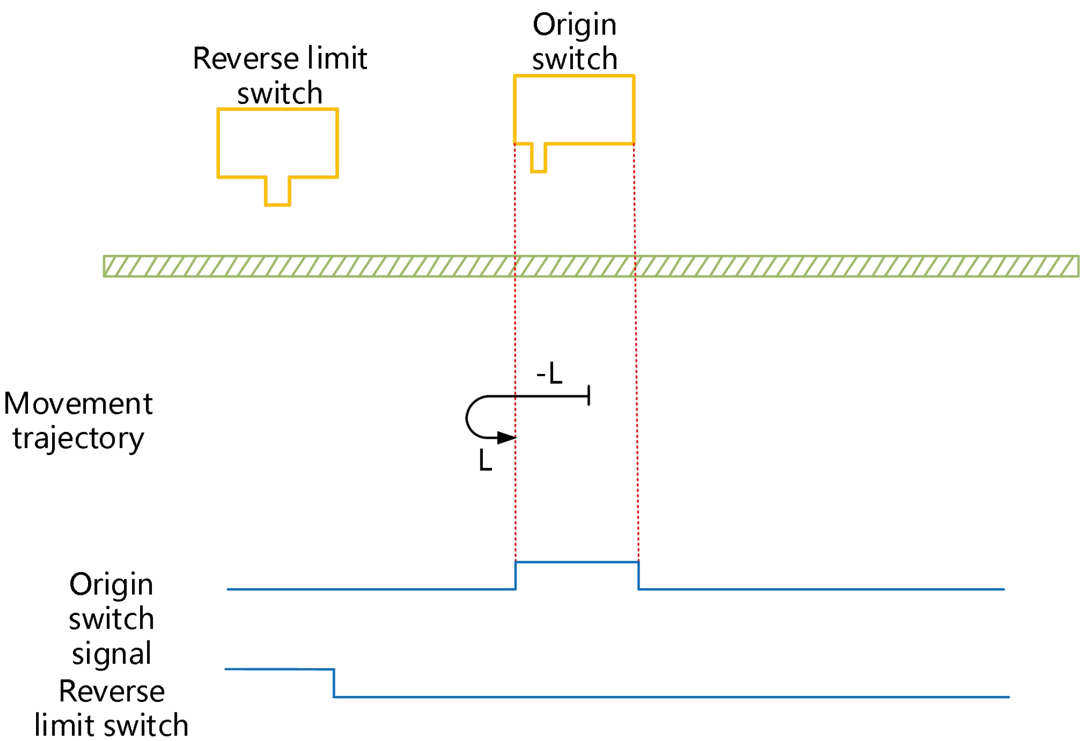
HW=0 when starting homing, start homing in reverse direction at high speed directly; limit switch is not encountered; slow down after encountering HW rising edge, run in reverse direction at low speed; change the running direction after encountering HW falling edge and run in forward direction at low speed and stop when encountering HW rising edge;

② The deceleration point signal is invalid when starting homing, the reverse limit switch is encountered



HW=0 when starting homing, start homing in reverse direction at high speed, change the running direction automatically when encountering limit switch and run in forward direction at high speed; slow down and change the running direction when encountering HW rising edge; run in reverse direction at low speed; change the running direction after encountering the falling edge of HW, then run in forward direction at low speed and stop when encountering HW rising edge;

③ The deceleration point signal is valid when starting homing



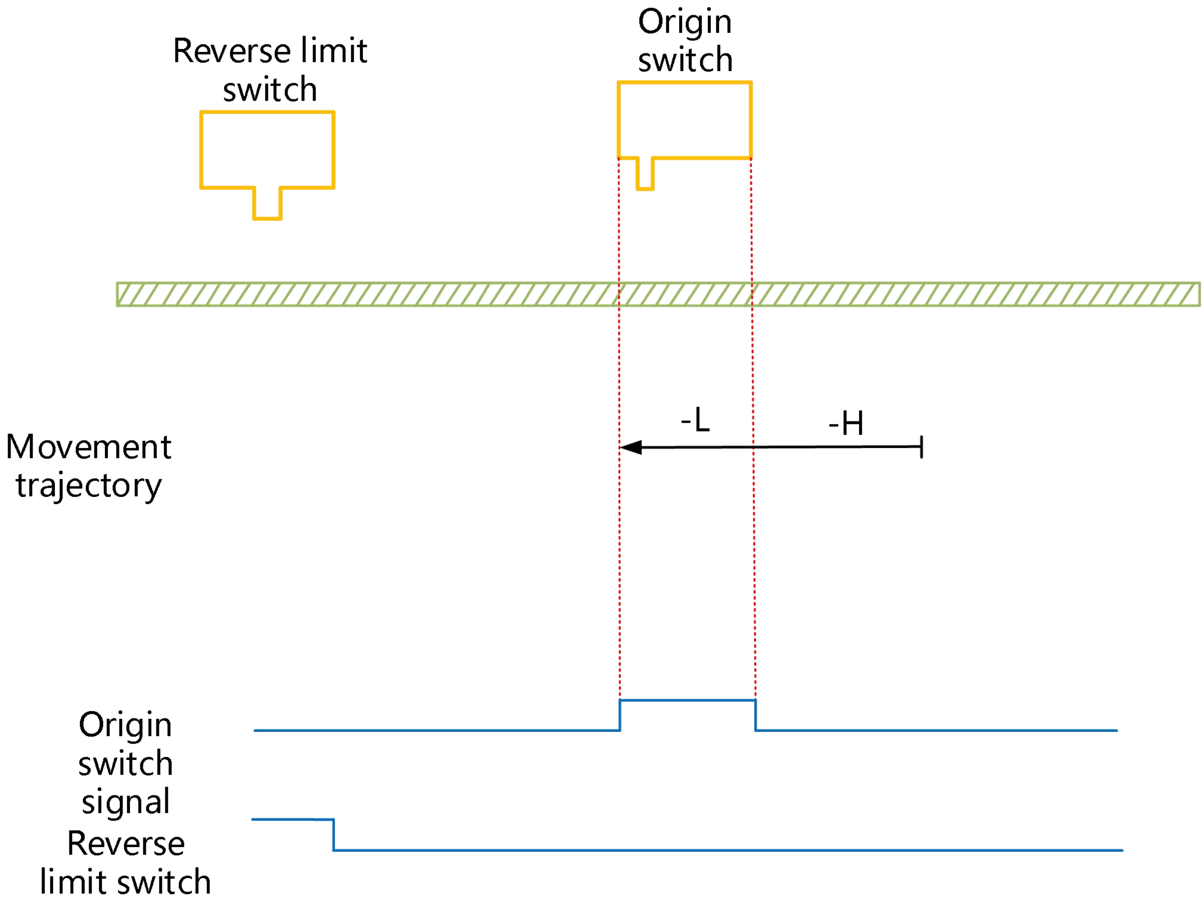
HW=1 when starting homing, start to return to zero in reverse direction at low speed directly. After encountering the falling edge of HW, change the running direction; stop when encountering the rising edge of HW during running in forward direction at low speed.

(28) 6098H=30

Mechanical Origin: Origin Switch (HW)

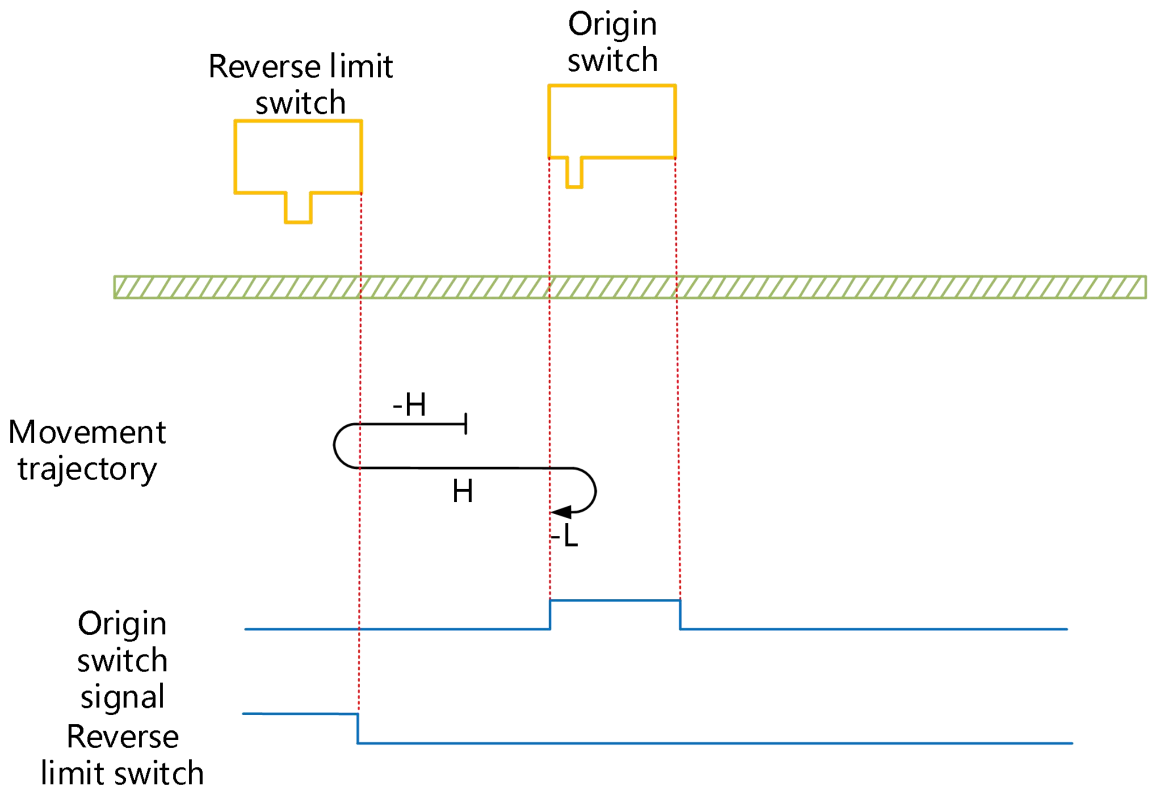
Deceleration point: Origin switch (HW)

① The deceleration point signal is invalid when starting homing, the reverse limit switch is not encountered



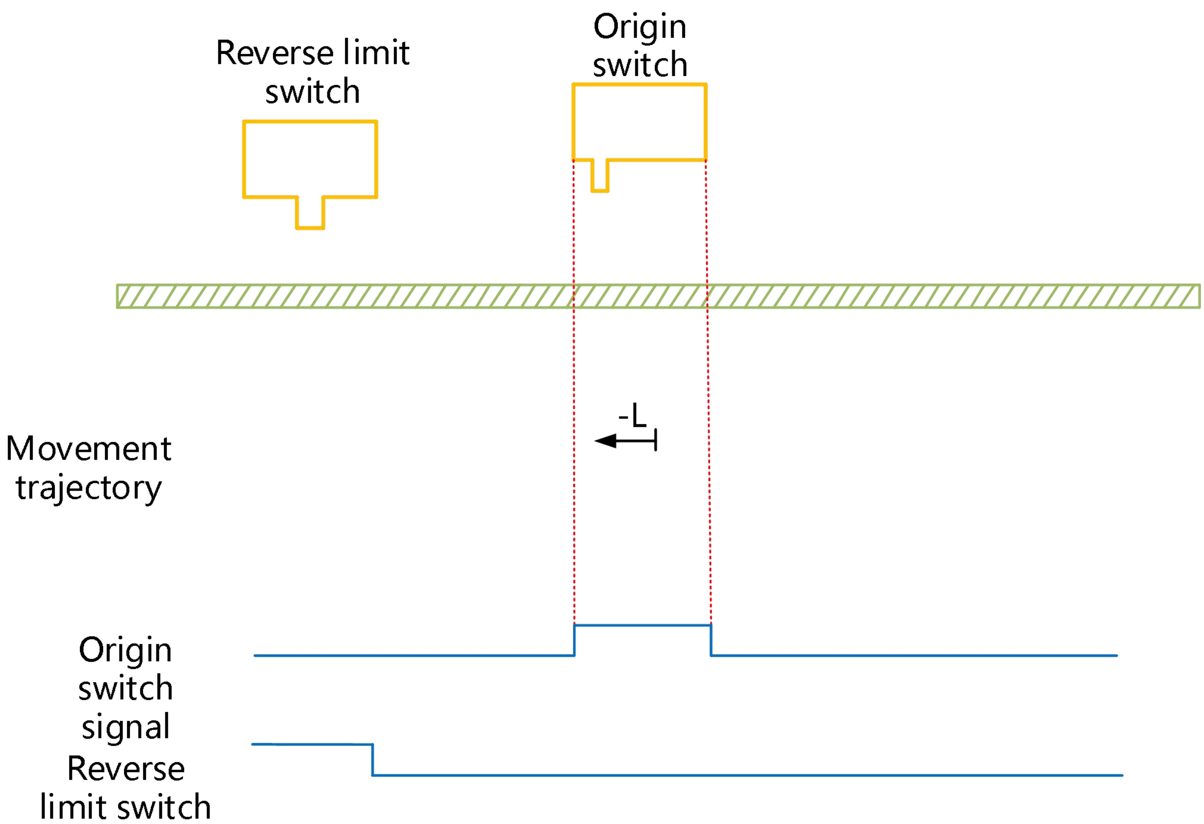
HW=0 when starting homing, start to return to zero in reverse direction at high speed; limit switch is not encountered; slow down after encountering HW rising edge, run in reverse direction at low speed, and stop when encountering HW falling edge;

② The deceleration point signal is invalid when starting homing, the reverse limit switch is encountered



HW=0 when starting homing, start homing in reverse direction at high speed, change the running direction automatically when encountering limit switch and run in forward direction at high speed; slow down and change the running direction when encountering HW rising edge, and stop when encountering HW falling edge during running in reverse direction at low speed;

③ The deceleration point signal is valid when starting homing



HW=1 when starting homing, start to return to zero in reverse direction at low speed directly, and stop when encountering HW falling edge;

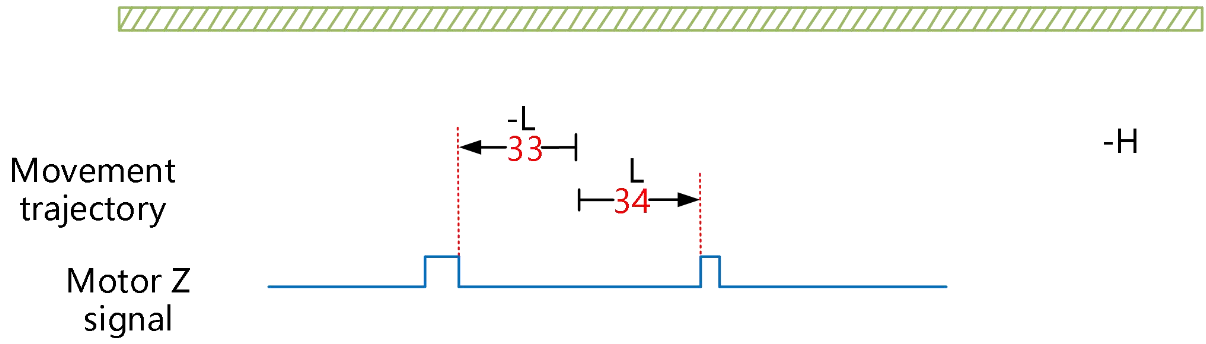
(29) 6098H=33 and 34

Mechanical origin: Z signal

Deceleration point: None

Zero return mode 33: running in reverse direction at low speed, stop at the first Z signal encountered

Zero return mode 34: running in forward direction at low speed, stop at the first Z signal encountered



(30) 6098h=35

Zero returning mode 35: take the current position as the mechanical origin, and after triggering the origin to return to zero (6040 control word: 0xOF → 0x1F). After the zero return is completed, the position feedback 6064h is set to the origin offset 607Ch.

7.9 Accessibility Function

7.9.1 Touch Probe

The probe function refers to the function of the servo drive recording the current position information (command unit) and storing it in the specified register when the DI signal or motor Z signal specified by the external device changes. Please pay attention to the following when using it:

① In the case of the same probe, try to avoid using the rising edge and the falling edge at the same time;

② When using the Z signal, only the rising edge can be used, not the falling edge;

③ For single-trigger probes, if you need to trigger again, please clear 60B8h to 0 before setting the value. The VD3E bus servo drive supports 2 types of probe functions, then DI5 is probe 1 and DI6 is probe 2.

BIT	Touch Probe Function(60B8h)	Touch Probe Status Word (60B9h)
0	Probe 1 enable 0: Disable probe 1 1: Enable probe 1	Probe 1 enable 0: Disable probe 1 1: Enable probe 1
1	Probe 1 trigger mode. 0: Single trigger 1: Continuous trigger	Probe 1 rising edge latch. 0: Probe 1 rising edge latch not executed 1: Probe 1 rising edge latch executed
2	Probe 1 trigger signal selection. 0: DI5 trigger 1: Z signal trigger	Probe 1 falling edge latch. 0: Probe 1 falling edge latch not executed 1: Probe 1 falling edge latch executed
3	Reserve	Reserve
4	Probe 1 rising edge latch. 0: Do not use probe 1 rising edge latch 1: Use probe 1 rising edge latch	Reserve
5	Probe 1 falling edge latch. 0: Do not use probe 1 falling edge latch 1: Use probe 1 falling edge latch	Reserve
6	Reserve	Probe 1 trigger signal selection. 0: DI5 trigger 1: Z signal trigger
7	Reserve	Probe 1 triggers DI signal selection. 0: DI5 is low level

		1: DI5 is high level
8	Probe 2 enable 0: Disable probe 2 1: Enable probe 2	Probe 2 enable 0: Disable probe 2 1: Enable probe 2
9	Probe 2 trigger mode. 0: Single trigger 1: Continuous trigger	Probe 2 rising edge latch. 0: Probe 2 rising edge latch not executed 1: Probe 2 rising edge latch executed
10	Probe 2 trigger signal selection. 0: DI6 trigger 1: Z signal trigger	Probe 2 falling edge latch. 0: Probe 2 falling edge latch not executed 1: Probe 2 falling edge latch executed
11	Reserved	Reserved
12	Probe 2 rising edge latch. 0: Do not use probe 2 rising edge latch 1: Use probe 2 rising edge latch	Reserve
13	Probe 2 falling edge latch. 0: Do not use probe 2 falling edge latch 1: Use probe 2 falling edge latch	Reserve
14	Reserve	Probe 2 trigger signal selection. 0: DI6 trigger 1: Z signal trigger
15	Reserve	Probe 2 triggers DI signal selection. 0: DI6 is low level 1: DI6 is high level

1. Set the probe to trigger the DI signal: The DI functions corresponding to probe 1 and probe 2 are DI5 and DI6 by default.

Note: ◆ If other functions such as command inversion are set for P6-14 and P6-17, the use of the probe function will not be affected. That is, when DI5 or DI6 is started, the probe function and the corresponding function code function will take effect together and will not affect each other.

Servo Parameter	Description
P6-14	The default setting of DI5 terminal function is probe 1
P6-17	The default setting of DI6 terminal function is probe 2
P6-15	DI5 logic selection. 0: Low level is valid 1: High level is valid
P6-18	DI6 logic selection. 0: Low level is valid 1: High level is valid

2. Set the probe function (60B8h) and probe status word (60B9h). The meaning of each bit is shown in the following table. For example, if you use the rising and falling edges of probe 1 and probe 2, and DI single trigger, set 60B8h=3131h (12593 in decimal). When DI5 and DI6 signals are rising, probe 1 and probe 2 will latch at 60 BAh and 60BCh respectively; when DI5 and DI6 signals are falling, probe 1 and probe 2 will latch at 60 BBh and 60BDh respectively. If you want to perform single trigger again, you need to set 60B8h=0, 60B8h=3131h.

Index (Hex)	Object dictionary	R/O	Unit	Bits	Setting range
60B8	Touch probe function	Read and write	-	16	0~65535
60B9	Touch probe status word	Read only	-	16	0~65535
60BA	Probe 1 rising edge position	Read only	Instruction unit	32	-2147483648~2147483647
60BB	Probe 1 falling edge position	Read only	Instruction unit	32	-2147483648~2147483647
60BC	Probe 2 rising edge position	Read only	Instruction unit	32	-2147483648~2147483647
60BD	Probe 2 falling edge position	Read only	Instruction unit	32	-2147483648~2147483647

Chapter 8 Object Dictionary

8.1 Overview of Object Dictionaries

8.1.1 Object Dictionary Area Allocation

The object dictionary of CoE (CANopen over EtherCAT) specified in CIA 402 and the object dictionary of VD3E series are composed as follows:

Index	Content
0000h~ 0FFFh	Data type region
1000h~ 1FFFh	Communication subprotocol area
2000h~ 5FFFh	Vendor customized area
6000h~ 9FFFh	Standard equipment subprotocol area
A000h~ FFFFh	Reserved

8.1.2 Explanation of Related Terms in Object Dictionary

★Index: The position of objects of the same class in the object dictionary, expressed in hexadecimal.

★Sub-index: Under the same index, there are multiple objects, and each object is biased under the same index.

★Accessibility: See the following table for details:

Accessibility	Description
RW	Read and write
RO	Read only
WR_PREOP	Writable in preop mode

★Can you map: See the following table for details:

Accessibility	Description
NO	Unmappable
RPDO	Can be used as RPDO
TPDO	Can be used as TPDO

★Set to take effect: See the following table for details:

Set conditions	Description	Set conditions	Description
Shutdown setting	It can be set in the shutdown state	Valid immediately	The set value will take effect immediately after the parameter is modified and downloaded

Operation setting	Can be set in any state	Power-on again	After the parameters are modified and downloaded, the servo drive needs to be powered down and then powered up, and the set value can take effect

★Data display range: upper and lower limits of parameters.

★Default value: The factory setting value of the parameter.

★Data type: The type of data, as shown in the following table:

Data type	Description	Numerical range
SINT	Signed 8bit	-128 ~ 127
USINT	Unsigned 8bit	0 ~ 255
INT	Signed 16bit	-32768 ~ 32767
UINT	Unsigned 16bit	0~65535
DINT	Signed 32bit	-21247483648 ~ 21247483647
UDINT	Unsigned 32bit	0 ~ 4294967295
STRING	String Value	ASCII

★Related modes: See the following table for specific contents:

Accessibility	Description
ALL	This parameter is related to all modes
CSP/CSV/HM	This parameter is only related to the corresponding mode
-	This parameter is independent of the control mode

8.2 Communication Sub-protocol Area (1000h to 1FFFh)

1000	Parameter name	Accessibility	Data mapping	Data type	Data display range	Default	Correlation mode
	Device Type (Device Type)	RO	No	UDINT	-	-	-
Used to describe the CoE device subprotocol type.							

1001	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Error register (Error register)	RO	No	USINT	-	0x00	-
Used to describe error records.							

1008	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Device name (Device name)	RO	No	STRING	-	-	-
Used to describe the device name.							

1009	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Manufacturer hardware version (Manufacturer Hardware Version)	RO	No	STRING	-	-	-
Used to describe the manufacturer hardware version							

100A	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Manufacturer software version (Manufacturer	RO	No	STRING	-	-	-

100A	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Software Version)						
Used to describe the Manufacturer software version							

1018	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	ID Object (ID Object)	-	-	-	-	-	-
Used to describe device information.							
01h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Vendor ID (Vendor ID)	RO	No	UDINT	-	0x00000EFF	-
Serial number used to describe the drive.							
02h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Product Code (Product Code)	RO	No	UDINT	-	0x10003101	-
Used to describe the encoding inside the drive.							
03h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Revision Number (Revision Number)	RO		UDINT	-	0x00000001	-
Upgrade record number used to describe the drive.							
04h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Serial Number (Serial Number)	RO	No	UDINT	-	0x00001419	-

1018	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
Used to describe a serial number.							

1600	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	RxPDO	-	-	-	-	-	-
Mapping object for setting RxPDO.							
01h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	First mapping object (RxPDO_SI1)	RW	RPDO	UDINT	-	0x60400010	-
Mapping object for setting RxPDO1.							
02h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Second mapping object (RxPDO_SI2)	RW	RPDO	UDINT	-	0x607A0020	-
Mapping object for setting RxPDO2.							
03h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Third mapping object (RxPDO_SI3)	RW	RPDO	UDINT	-	0x60B80010	-
Mapping object for setting RxPDO3.							
04h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Fourth mapping object (RxPDO_SI3)	RW	RPDO	UDINT	-	0x60600008	-
Mapping object for setting RxPDO4.							

1701	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	RxPDO	-	-	-	-	-	-
Mapping object for setting RxPDO.							
01h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	First mapping object (RxPDO_SI1)	RW	RPDO	UDINT	-	0x60400010	-
Mapping object for setting RxPDO1.							
02h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Second mapping object (RxPDO_SI2)	RW	RPDO	UDINT	-	0x607A0020	-
Mapping object for setting RxPDO2.							
03h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Third mapping object (RxPDO_SI3)	RW	RPDO	UDINT	-	0x60B80010	-
Mapping object for setting RxPDO3.							
04h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	The fourth mapping object (RxPDO_SI4)	RW	RPDO	UDINT	-	0x60600008	-
Mapping object for setting RxPDO4.							

1702	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	RxPDO	-	-	-	-	-	-
Mapping object for setting RxPDO.							

	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
01h	First mapping object (RxPDO_SI1)	RW	RPDO	UDINT	-	0x60400010	-
Mapping object for setting RxPDO1.							
02h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Second mapping object (RxPDO_SI2)	RW	RPDO	UDINT	-	0x607A0020	-
Mapping object for setting RxPDO2.							
03h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Third mapping object (RxPDO_SI3)	RW	RPDO	UDINT	-	0x60FF0020	-
Mapping object for setting RxPDO3.							
04h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	The fourth mapping object (RxPDO_SI4)	RW	RPDO	UDINT	-	0x60710008	-
Mapping object for setting RxPDO4.							
05h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	The fifth mapping object (RxPDO_SI5)	RW	RPDO	UDINT	-	0x60600008	-
Mapping object for setting RxPDO5.							
06h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Sixth mapping object	RW	RPDO	UDINT	-	0x60B80010	-

	(RxPDO_SI6)						
Mapping object for setting RxPDO6.							
07h	**Parameter name**	**Accessibility**	**Data mapping**	**Data structure**	**Data display range**	**Default**	**Correlation mode**
	The seventh mapping object (RxPDO_SI7)	RW	RPDO	UDINT	-	0x607F0020	-
Mapping object for setting RxPDO7.							

1A00	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	TxPDO	-	-	-	-	-	-
Mapping object for setting TxPDO.							
01h	**Parameter name**	**Accessibility**	**Data mapping**	**Data structure**	**Data display range**	**Default**	**Correlation mode**
	First mapping object (TxPDO_SI1)	RW	TPDO	UDINT	-	0x60410010	-
Mapping object for setting TxPDO1.							
02h	**Parameter name**	**Accessibility**	**Data mapping**	**Data structure**	**Data display range**	**Default**	**Correlation mode**
	Second mapping object (TxPDO_SI2)	RW	TPDO	UDINT	-	0x60640020	-
Mapping object for setting TxPDO2.							
03h	**Parameter name**	**Accessibility**	**Data mapping**	**Data structure**	**Data display range**	**Default**	**Correlation mode**
	Third mapping object (TxPDO_SI3)	RW	TPDO	UDINT	-	0x60B90010	-
Mapping object for setting TxPDO3.							
04h	**Parameter name**	**Accessibility**	**Data mapping**	**Data structure**	**Data display range**	**Default**	**Correlation mode**

	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	The fourth mapping object (TxPDO_SI4)	RW	TPDO	UDINT	-	0x60BA0020	-
Mapping object for setting TxPDO4.							
05h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	The fifth mapping object (TxPDO_SI5)	RW	TPDO	UDINT	-	0x60BC0020	-
Mapping object for setting TxPDO5.							
06h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Sixth mapping object (TxPDO_SI6)	RW	TPDO	UDINT	-	0x603F0010	-
Mapping object for setting TxPDO6.							
07h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	The seventh mapping object (TxPDO_SI7)	RW	TPDO	UDINT	-	0x60610008	-
Mapping object for setting TxPDO7.							

1B01	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	TxPDO	-	-	-	-	-	-
Mapping object for setting TxPDO.							
01h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	First mapping object (TxPDO_SI1)	RW	TPDO	UDINT	-	0x603F0010	-
Mapping object for setting TxPDO1.							
02h	Parameter	Accessibility	Data	Data	Data	Default	Correlation

	name		mapping	structure	display range		mode
	Second mapping object (TxPDO_SI2)	RW	TPDO	UDINT	-	0x60410010	-
Mapping object for setting TxPDO2.							
03h	**Parameter name**	**Accessibility**	**Data mapping**	**Data structure**	**Data display range**	**Default**	**Correlation mode**
	Third mapping object (TxPDO_SI3)	RW	TPDO	UDINT	-	0x60640020	-
Mapping object for setting TxPDO3.							
04h	**Parameter name**	**Accessibility**	**Data mapping**	**Data structure**	**Data display range**	**Default**	**Correlation mode**
	The fourth mapping object (TxPDO_SI4)	RW	TPDO	UDINT	-	0x60770010	-
Mapping object for setting TxPDO4.							
05h	**Parameter name**	**Accessibility**	**Data mapping**	**Data structure**	**Data display range**	**Default**	**Correlation mode**
	The fifth mapping object (TxPDO_SI5)	RW	TPDO	UDINT	-	0x60F40020	-
Mapping object for setting TxPDO5.							
06h	**Parameter name**	**Accessibility**	**Data mapping**	**Data structure**	**Data display range**	**Default**	**Correlation mode**
	Sixth mapping object (TxPDO_SI6)	RW	TPDO	UDINT	-	0x606100108	-
Mapping object for setting TxPDO6.							

1C12	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	RxPDO assign	-	-	-	-	-	-
Used to set up RPDO assignments.							
01h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Index of objects allocated by RPDO (RPDO Index)	RW	No	ARR	-	0x1701	-
The index used to set the allocation object of RPDO.							

1C13	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	TxPDO assign	-	-	-	-	-	-
Used to set TPDO assignments.							
01h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Index of objects assigned by TPDO (TPDO Index)	RW	No	ARR	-	0x0001	-
The index of the allocation object used to set TPDO.							

1C32	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Synchronize management of output parameters (SM output parameter)	-	-	-	-	-	-
Used to describe synchronization management output parameters.							
01h	Parameter name	Accessibility	Data	Data	Data display	Default	Correlation

1C32	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
			mapping	structure	range		mode
	Synchronization type (Synchronization Type)	RW	No	UINT	-	0x0001	-
Used to set the synchronization type.							
02h	**Parameter name**	**Accessibility**	**Data mapping**	**Data structure**	**Data display range**	**Default**	**Correlation mode**
	Synchronization type (Synchronization Type)	RW	No	UINT	-	0x0001	-
Used to set the synchronization type.							
04h	**Parameter name**	**Accessibility**	**Data mapping**	**Data structure**	**Data display range**	**Default**	**Correlation mode**
	Synchronization Types support (Synchronization Types support)	RO	No	UDINT	-	0x8007	-
Displays the type of distributed clock.							
05h	**Parameter name**	**Accessibility**	**Data mapping**	**Data structure**	**Data display range**	**Default**	**Correlation mode**
	Minimum cycle time (Minimum Cycle Time)	RO	No	UINT	-	0x0001E848	-
Displays the minimum synchronization period supported by the slave station in ns.							

1C33	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	SM input parameter (SM input parameter)	-	-	-	-	-	-

1C33	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
Used to describe synchronization management input parameters.							
01h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Synchronization type (Synchronization Type)	RW	No	UINT	-	0x0022	-
Used to set the synchronization type.							
04h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Synchronization Types support (Synchronization Types support)	RO	No	UDINT	-	0x8007	-
Displays the type of distributed clock.							
05h	Parameter name	Accessibility	Data mapping	Data structure	Data display range	Default	Correlation mode
	Minimum cycle time (Minimum Cycle Time)	RO	No	UINT	-	0x0001E848	-
Displays the minimum synchronization period supported by the slave station in ns.							

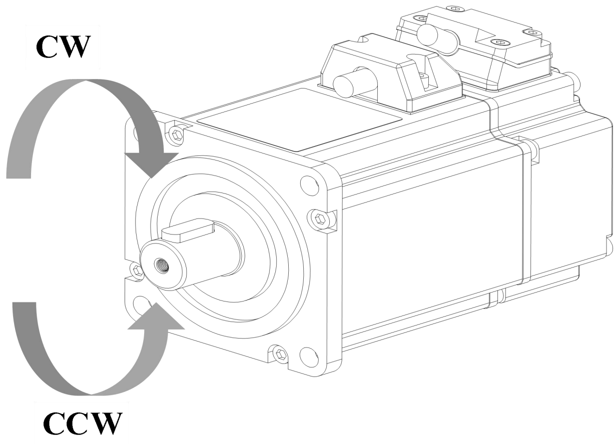
8.3 Vendor Customized Area (2000h to 2FFFh)

Group 2000h: Basic Settings

P00-04 2000-04	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Rotatation direction **RotationDir**	Stop setting	Effective immediately	0	0 to 1	Basic settings	-

Set the positive direction of the motor rotation when viewed from the motor axis.

Setting value	Rotation direction	Remark
0	Take CW as the forward direction	Viewed from the motor axis, the motor rotates clockwise
1	Take CCW as the forward direction	Viewed from the motor axis, the motor rotates counterclockwise



P00-09 2000-09	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Braking resistor setting **ExtResSel**	Operation setting	Effective immediately	0	0 to 3	Basic settings	-

Used to set the mode of absorbing and releasing braking energy.

Setting value	Brake resistance setting	Remark
0	Use built-in braking resistor	Please refer to "7.1.5 Braking Resistance" to select the appropriate braking mode
1	Use external braking resistor and natural cooling	
2	Use external braking resistor and forced air cooling (not settable)	
3	No braking resistors are used, and all are absorbed by capacitance	

P00-10 2000-0A	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	External braking resistor resistance value **ExtResVal**	Operation setting	Valid immediately	50	0 to 65535	Basic settings	Ω

Used to set the power of external braking resistor of servo drive. When the maximum braking energy calculated value is greater than the maximum braking energy absorbed by capacitor, and the braking power calculated value is greater than the built-in braking resistor power, use external braking resistor.

If the value of P00-10 is too large, Er.25 (too large braking resistor value) or Er.22 (main power supply is over voltage) will occur.

When external braking resistor is connected, please disconnect the short tab between C and D and connect the external braking resistor between P + and C. Please refer to "2.1.2 Composition of servo drive" for specific operation.

P00-11 2000-0B	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	External braking resistor power **ExtResPwr**	Operation setting	Effctive immediately	100	0~65535	Basic settings	W

Used to set the power of the external braking resistor of the servo drive.

External braking resistor power "P00-11" is not allowed to be less than the calculated value of braking resistor power!

P00-23 **2000-17**	Parameter name	Setting method	Effective time	Default	Set range	Application category	Unit
	Z pulse output OZ polarity **PulseOutPcPolarity**	Operation setting	Power-on again	0	0 to 1	Basic settings	-

Used to set the logic level of Z pulse.

Setting value	Function
0	Z pulse is active at high level
1	Z pulse is active at low level

P00-24 **2000-18**	Parameter name	Setting method	Effective time	Default	Set range	Application category	Unit
	Z pulse output width PulseOutZWidth	Operation setting	Power on again	3	1~200	Basic settings	ms

Set the width of Z pulse output.

Setting value	Function
1	Pulse width 1ms
2	Pulse width 2ms
···	···
200	Pulse width 200ms

P00-30 2000-1E	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Shield multi-turn absolute encoder battery fault EncBatErrMask	Operation setting	Power-on again	0	0 to 1	Basic settings	-

Used to set the battery fault alarm setting function of multi-turn absolute value encoder.

Setting value	Function	Remark
0	Unshielded	Detect battery undervoltage and battery low voltage faults of multi-turn absolute value encoder
1	Shielded	Shield multi-turn absolute encoder battery under voltage and battery low-voltage fault. This would cause mechanical failure, please use with caution.

P00-31 **2000-1F**	Parameter name	Setting method	Effective time	Default	Set range	Application category	Unit
	Encoder read-write verification exception threshold setting EncCommWarmThreshold	Operation setting	Effective immediately	20	0 to 100	Basic settings	-

Encoder read-write verification exception is too frequent. Alarm threshold setting.

0: no alarm;

Others: When this setting value is exceeded, report A-93.

P00-32 **2000-20**	Parameter name	Setting method	Effective time	Default	Set range	Application category	Unit
	Encoder read-write verification exception threshold setting ECAT pdo TimeOut	Operation setting	Effective immediately	2	2 to 14	Basic settings	-

When main station and drive is exchanging data periodically, it can be used to set the tolerance for PDO receive event loss. When the amount of error exceeded the set threshold, it will report ER.09.

Group 2001h: Control Parameters

P01-09 2001-09	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Speed limit source In torque mode **Torque Mode Speed Source**	Stop setting	Effective immediately	0	0~2	Protection and restriction	-

Used to set the limit value of the maximum speed in torque mode.

Setting value	Function	Remark
0	Internal forward and reverse restriction	Forward speed limit through P1-17 torque mode and reverse speed limit torque P1-18 torque mode
1	AI_2 analog input	Not support yet!
2	the set EtherCAT communication	Set the limit of in torque mode through the corresponding EtherCAT communication

P01-10 2001-0A	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Maximum speed threshold MaxSpeedLimit	Operation setting	Valid immediately	3600	0~8000	Protection and restriction	rpm

Used to set the maximum speed limit value. If the actual speed of motor exceeds this value, Er.32 would occur (Exceed the maximum speed of motor).

P01-11 2001-0B	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Warning speed threshold WarmSpeedTh	Operation setting	Valid immediately	3300	0 ~8000	Protection and restriction	rpm
Used to set the limit value of maximum speed. If the actual speed of motor exceeds this value, A-81 would occur (Exceed the maximum speed of motor).							

P01-12 2001-0C	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Forward speed threshold PosSpeedTh	Operation setting	Valid immediately	3000	0~6000	Protection and restriction	rpm
Used to set the limit value of forward speed.							

P01-13 2001-0D	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	NegSpeedTh NegSpeedTh	Operation setting	Valid immediately	3000	0~6000	Protection and restriction	rpm
Used to set the limit value of reverse speed							

P01-14 2001-0E	Parameter name	Setting method	Effective time	Default	Set range	Application category	Unit
	Torque limit source ToqLimitSrc	Shutdown setting	Effective immediately	0	0 to 2	Protection and restriction	-

Used to set the torque limit source.

Setting value	Restricted source	Remarks
0	Internal	Internal torque limit.
1	Reserved	Reserved
2	EtherCAT	External torque limit, controlled by object dictionaries 6072, 60E0 and 60E1 through EtherCAT communication.

P01-15 2001-0F	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Forward torque limit FToqLim	Operation setting	Valid immediately	3000	0~3000	Protection and restriction	0.1%

When P01-14 is set to 0 (internal), the set value of this function code is used as the limit value of positive torque.

If the value of P01-15 and P01-16 is set too small, the servo motor may be insufficient torque phenomenon when performing acceleration and deceleration movements. Please refer to "6.4.3 Torque command limit".

P01-16 2001-10	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Reverse torque limit **RToqLim**	Operation setting	Effective immediately	3000	0 to 3000	Protection and restriction	0.1%

When P01-14 is set to 0 (internal), the setting value of this function code is reverse torque limit value

P01-17 2001-11	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Froward speed limit in torque mode **Torque Mode PSpd Limit**	Operation setting	Effective immediately	3000	0 to 6000	Protection and restriction	rpm
When P01-09 is set to 0 (internal), the setting value of this function code is forward speed limit.							

P01-18 2001-12	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Reverse speed limit in torque mode **Torque Mode NSpd Limit**	Operation setting	Effective immediately	3000	0 to 6000	Protection and restriction	rpm
When P01-09 is set to 0 (internal), the setting value of this function code is reverse speed limit.							

P01-19 2001-13	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Torque Limit Time ToqLimTime	Operation setting	Valid immediately	1000	0~65535	Protection and restriction	ms
When torque is limited by the setting value of P01-15 or P01-16, and exceeds the setting time, drive would report fault “abnormal torque saturation”. ✎**Note:** When the value of this function code is set to 0, the torque saturation timeout fault detection is not done, and this fault is ignored.							

P01-20 2001-14	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Software overcurrent detection SoftOverCurrentDt	Operation setting	Valid immediately	8	0~65535	Protection and restriction	ms
Software overcurrent detection window (set to 0 to block software overcurrent alarm)							

P01-30 2001-1E	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Delay from brake output ON to instruction reception BK_ONtoCmdEnaDelay	Operation setting	Valid immediately	250	0~500	-	ms
Used to set the braking (BRK-OFF) output ON, until the servo drive allows the start of receiving the input command. When the brake output (BRK-OFF) is not allocated, this function code has no effect.							

P01-31 2001-1F	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	In the static state, delay from the brake output is OFF to the motor is not energized. BK_OFFtoPwmOFFDelay	Operation setting	Valid immediately	150	1~1000	-	ms
When the motor is in a static state, set the delay time from the brake (BRK-OFF) output is OFF to the servo drive is in the non-powered state. When the brake output (BRK-OFF) is not allocated, this function code has no effect.							

P01-32 2001-20	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Rotation status, when the brake output OFF, the speed threshold. BK_OFFSpdTh	Operation setting	Valid immediately	30	0~3000	-	rpm
When the motor is rotating, the motor speed threshold that is allowed when the brake (BRK-OFF) output is OFF. When the brake output (BRK-OFF) is not allocated, this function code has no effect.							

P01-33 2001-21	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Rotation status, Delay from servo enable OFF to brake output OFF BK_OFFSinceSofDelay	Operation setting	Valid immediately	500	1~2000	-	ms
When the motor rotates, the delay time from the servo enable (S-ON) OFF to the brake (BRK-OFF) output OFF is allowed. When the brake output (BRK-OFF) is not allocated, this function code has no effect.							

P01-37 2001-25	Parameter name	Setting method	Effective time	Default	Set range	Application category	Unit
	JOG acceleration time SpdRefJOGAccTime	Operation setting	Effective immediately	500	1 to 5000	-	ms
The time for JOG instruction to accelerate from 0 to 1000rpm.							

P01-38 2001-26	Parameter name	Setting method	Effective time	Default	Set range	Application category	Unit
	JOG deceleration time SpdRefJOGDecTime	Operation setting	Effective immediately	500	1 to 5000	-	ms
The time for JOG instruction to decelerate from 1000rpm to 0.							

Group 2002h: Gain Adjustment

P02-01 2002-01	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	1st position loop gain PosLoop1stGain	Operation setting	Effective immediately	450	0~6200	Gain control	0.1Hz
It is used for setting the proportional gain of the first position loop to determine the responsiveness of the position control system.							

P02-02 2002-02	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	first speed loop gain SpdLoop1stGain	Operation setting	Effective immediately	250	0~35000	Gain control	0.1Hz
It is used for setting the proportional gain of the first position loop to determine the responsiveness of the position control system.							

P02-03 2002-03	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	First speed loop integral time constant SpdLoop1stIntgTime	Operation setting	Effective immediately	230	10~65535	Gain control	0.1ms
Used to set the integral constant of the first speed loop. The smaller the set value, the stronger the integral effect.							

P02-04 2002-04	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Second position loop gain PosLoop2stGainAS	Operation setting	Effective immediately	300	0 to 6200	Gain control	0.1Hz
Used to set the integral constant of the first speed loop. The smaller the set value, the stronger the integral effect.							

P02-05 2002-05	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Second speed loop gain SpdLoop2stGain	Operation setting	Effective immediately	160	0-35000	Gain control	0.1Hz
Used to set the integral constant of the first speed loop. The smaller the set value, the stronger the integral effect.							

P02-06 2002-06	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Second speed loop integral time constant SpdLoop2stIntgTime	Operation setting	Effective immediately	350	10~65535	Gain control	0.1ms
Used to set the integral constant of the first speed loop. The smaller the set value, the stronger the integral effect.							

P02-07 2002-07	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Second gain switch mode **Second Gain Switch Mode**	Operation setting	Effective immediately	0	0 to 1	Gain control	-
Used to set second gain swtich mode							

Setting value	Functions
0	Fix the first gain. Use DI function 10(GAIN-SEl, gain switch) to switch DI logic invalid: PI control DI logic valid: P control
1	Switch the first gain and the second gain through the set value of P02-08

P02-08 2002-08	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	speed loop 1st integral time Second Gain Fun Select	Operation setting	Valid immediately	0	0 to 10	Gain control	0.1ms

Used to set the integral constant of the first speed loop. The smaller the set value, the stronger the integral effect.

Setting value	Gain switch condition	Functions
0	First gain fixed	Fix the first gain.
1	Use DI terminal to switch	Use DI function 10 (GAIN-SEl, gain switch) DI logic invalid: First gain(P02-01-P02-03) DI logic valid: Second gain (P02-04-P02-06)
2	When torque instruction is larger	In the previous first gain, when the absolute value of the torque instruction exceeds (level + hysteresis), it switches to the second gain; In the previous second gain, when the absolute value of the torque instruction is less than (level - hysteresis) for a period of delay time, it returns to the first gain.
3	When actual torque is larger	In the previous first gain, when the absolute value of the actual torque exceeds (level + hysteresis), it switches to the second gain; In the previous second gain, when the state where the absolute value of the actual torque is less than (level - hysteresis) continues for the delay time, it returns to the first gain.
4	When speed instruction is larger	In the previous first gain, when the absolute value of the speed instruction exceeds (level + hysteresis), it switches to the second gain; In the previous second gain, when the absolute value of the speed instruction is less than (level - hysteresis) for a period of time, it returns to the first gain.
5	When actual speed is larger	In the previous first gain, when the absolute value of the actual speed exceeds (level + hysteresis), it switches to the second gain; in the previous second gain, when the state where the absolute value of the actual speed is less than (level - hysteresis) continues during the delay time, it returns to the first gain.
6	Change ratio of speed instruction is larger	In the previous first gain, when the absolute value of the speed command change rate exceeds (level + hysteresis), switch to the second gain; in the previous second gain, when the absolute value of the speed command change rate is less than (level - hysteresis)

		for a period of delay time, return to the first gain.
7	When position offset is larger	In the previous first gain, when the absolute value of the position deviation exceeds (level + hysteresis), it switches to the second gain; in the previous second gain, when the absolute value of the position deviation is less than (level - hysteresis) for a period of time, it returns to the first gain.
8	Position instruction	In the previous first gain, if the position command is not 0, switch to the second gain; In the previous second gain, if the position command is 0 during the delay time, return to the first gain.
9	Positioning completed	If positioning is not completed in the previous first gain, switch to the second gain; If positioning is not completed during the delay time in the previous second gain, return to the first gain.
10	Position instruction + actual velocity	In the previous first gain, if the position command is not 0, switch to the second gain; In the previous second gain, if the position command is 0 during the delay time, keep the second gain; When the delay time is reached, if the absolute value of the current actual speed does not reach (level), the speed integral time constant is fixed at the second integral time constant, and the others return to the first gain. If the absolute value of the actual speed does not reach (level-hysteresis), all return to the first gain.

P02-09 **2002-09**	**Parameter name**	**Setting method**	**Valid time**	**Default**	**Set range**	**Application category**	**Unit**
	Speed feedforward gain **SpdFeedForwardGain**	Operation setting	Valid immediately	0	0~1000	Gain control	0.1 %
It is used for setting the proportional gain of the second position loop to determine the responsiveness of the position control system.							

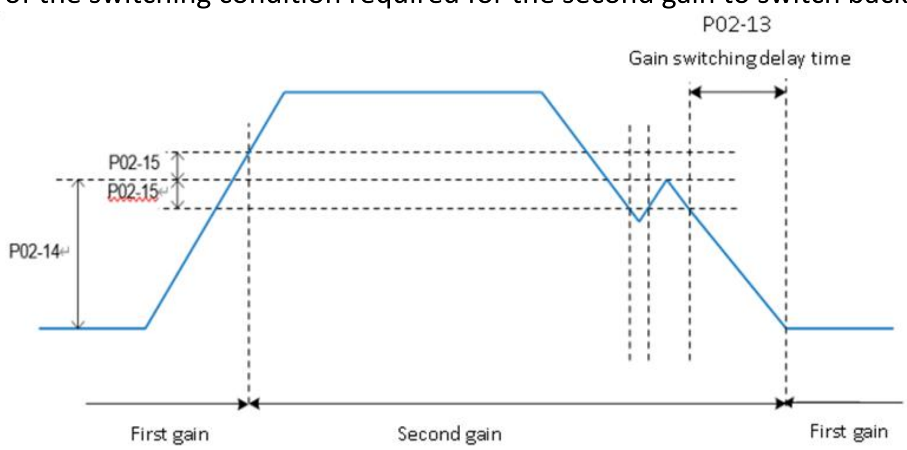
P02-10 **2002-0A**	**Parameter name**	**Setting method**	**Effective time**	**Default**	**Set range**	**Application category**	**Unit**
	Speed feed forward filter constant **SpdFeedForwardFilter**	Operation setting	Effective immediately	3	0 to 500	Gain control	1ms
Used to set the time constant of the one power delay filter associated with the speed feedforward input.							

P02-11 2002-0B	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Torque feedforward gain **ToqFeedForwardGain**	Operation setting	Effective immediately	0	0 to 2000	Gain control	0.1%
Used to set the torque feedforward gain.							

P02-12 2002-0C	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Torque feedforward filter time constant **ToqFeedForwardFilter**	Operation setting	Effective immediately	50	0 to 10000	Gain control	0.01ms
Used to set the time constant of the primary delay filter associated with the torque feedforward input.							

P02-13 2002-0D	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Torque feedforward filter time constant ToqFeedForwardFilter	Operation setting	Effective immediately	50	0~10000	Gain control	0.01ms

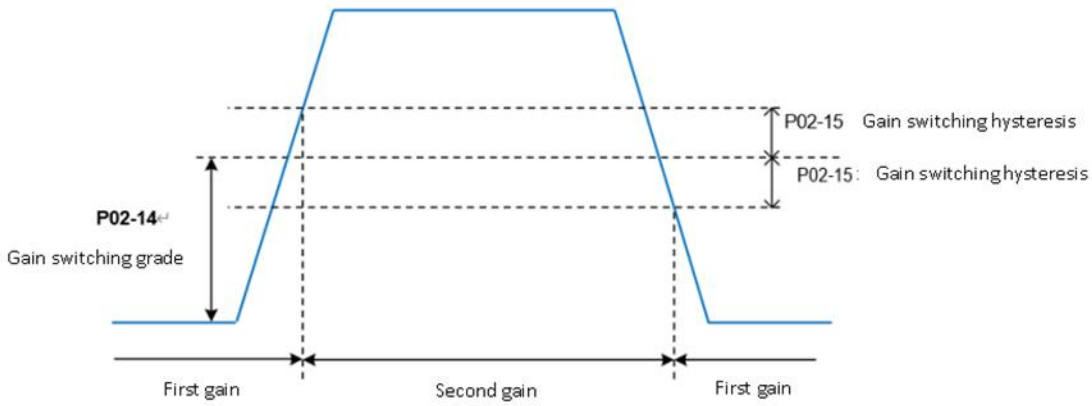
The duration of the switching condition required for the second gain to switch back to the first gain.



✎Note: This parameter is only valid when the second gain is switched back to the first gain.

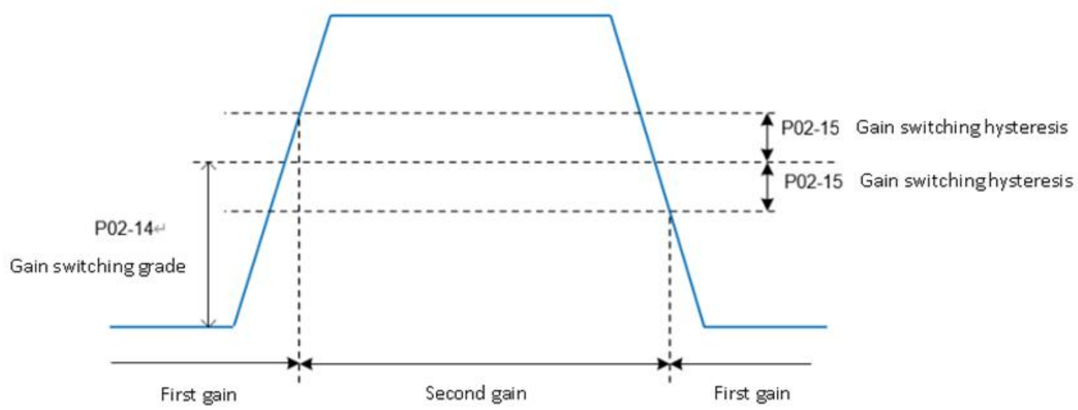
P02-14 2002-0E	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Torque feedforward filter time constant ToqFeedForwardFilter	Operation setting	Effective immediately	50	0~20000	Gain control	0.01ms

Set the grade of the gain condition. The generation of the actual switching action is affected by the two conditions of grade and hysteresis.



P02-15 2002-0F	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Torque feedforward filter time constant ToqFeedForwardFilter	Operation setting	Effective immediately	50	0~20000	Gain control	0.01ms

Set the hysteresis to meet the gain switching condition.



P02-16 2002-10	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Torque feedforward filter time constant ToqFeedForwardFilter	Operation setting	Effective immediately	50	0~10000	Gain control	0.01ms
Used to set the time constant of the first-order delay filter associated with the torque feedforward input.							

P02-20 2002-14	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Torque feedforward filter time constant ToqFeedForwardFilter	Operation setting	Effective immediately	50	0~10000	Gain control	0.01ms
Used to set the time constant of the primary delay filter associated with the torque feedforward input.							

P02-21 2002-15	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Torque feedforward filter time constant ToqFeedForwardFilter	Operation setting	Effective immediately	50	0~10000	Gain control	0.01ms
Used to set the time constant of the primary delay filter associated with the torque feedforward input.							

P02-22 2002-16	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Torque feedforward filter time constant ToqFeedForwardFi	Operation setting	Effective immediately	50	0~10000	Gain control	0.01ms

	lter						
Used to set the time constant of the primary delay filter associated with the torque feedforward input.							

P02-23 2002-17	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Torque feedforward filter time constant **ToqFeedForwardFilter**	Operation setting	Effective immediately	50	0~10000	Gain control	0.01ms
Used to set the time constant of the primary delay filter associated with the torque feedforward input.							

P02-24 2002-18	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Torque feedforward filter time constant **ToqFeedForwardFilter**	Operation setting	Effective immediately	50	0~10000	Gain control	0.01ms
Used to set the time constant of the primary delay filter associated with the torque feedforward input.							

P02-25 2002-19	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Torque feedforward filter time constant **ToqFeedForwardFilter**	Operation setting	Effective immediately	50	0~10000	Gain control	0.01ms
Used to set the time constant of the primary delay filter associated with the torque feedforward input.							

Group 2003h: self-adjusting Parameters

P03-01 2003-01	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Load inertia ratio **LoadInerRatio**	Operation setting	Effective immediately	300	100~10000	Automatic parameter tuning	0.01

Used to set the load inertia ratio, 1.00 ~ 100.00 times.

P03-02 2003-02	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Load rigidity selection RigiditySel	Operation setting	Effective immediately	14*	0~31	Automatic parameter tuning	-

Used to set the load inertia ratio, 1.00 ~ 100.00 times.

P03-03 2003-03	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Self-adjusting mode selection SelfAdjustMode	Operation setting	Effective immediately	0	0 to 2	Automatic parameter tuning	-

Used for setting different gain adjustment modes, the related gain parameters can be set manually or automatically according to the rigidity grade table.

Setting value	Function	Description
0	Self-adjusting mode.	Position loop gain, speed loop gain, speed loop integral time constant, torque filter parameter settings are automatically adjusted according to the rigidity grade setting.
1	Manual setting	The user manually sets the position loop gain, speed loop gain, speed loop integral time constant and torque filter parameter settings.
2	Online automatic self-adjusting mode	Not yet realized.

P03-04 2003-04	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Online inertia identification sensitivity InerIdOnline	Operation setting	Effective immediately	0	0 to 2	Automatic parameter tuning	-
Not realized yet.							

P03-05 2003-05	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Number of cycles of inertia identification InerIdCircle	Shutdown setting	Effective immediately	2	1 to 20	Automatic parameter tuning	Circle
Used to set the load inertia identification process and set the number of rotations of the motor.							

P03-06 2003-06	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Maximum speed of inertia identification InerIdMaxSpd	Shutdown setting	Effective immediately	1000	300 to 2000	Automatic parameter tuning	rpm
Used to set the maximum allowable motor speed command in offline inertia identification mode. The faster the speed during inertia identification, the more accurate the identification result will be. Generally, keep the default value.							

P03-07 2003-07	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Parameter identification rotation direction InerIdRollMode	Shutdown setting	Effective immediately	0	0 to 2	Automatic parameter tuning	-

Used to set parameters identification rotation direction.

Setting value	Rotation direction
0	Forward and reverse reciprocating rotation
1	Forward one-way rotation
2	Reverse one-way rotation

P03-08 2003-08	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Parameter identification waiting time **InerIdWaitTime**	Shutdown setting	Effective immediately	1000	300 to 10000	Automatic parameter tuning	ms

During offline inertia identification, the time interval between two consecutive speed instructions

Group 2004h: Vibration suppression

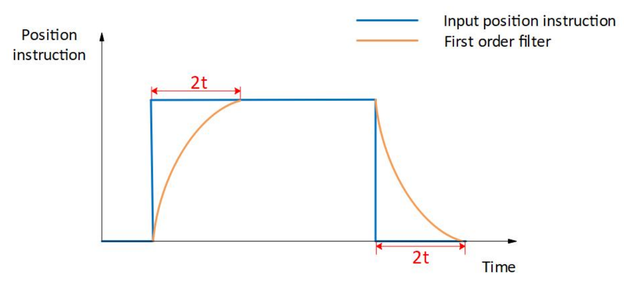
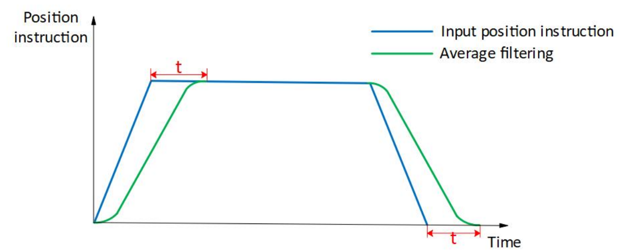
	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
P04-01 **2004-01**	Pulse instruction filtering method PulseFilterType	Shutdown setting	Effective immediately	0	0 to 1	Position mode	-

Used for setting different gain adjustment modes, the related gain parameters can be set manually or automatically according to the rigidity grade table.

Setting value	Filtering method
0	First-order low-pass filtering method
1	Mean filtering method

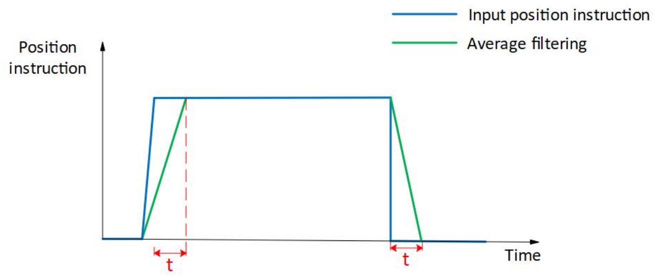
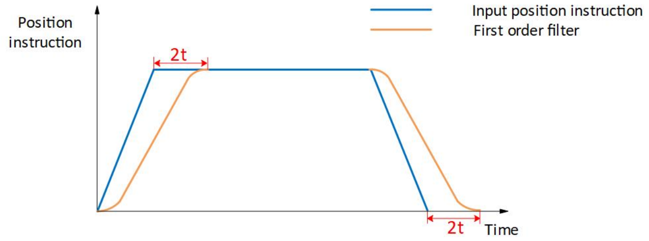
	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
P04-02 **2004-02**	Position command first-order low-pass Filtering time constant **LowpassFilterTime**	Shutdown setting	Effective immediately	0	0~1000	Position mode	ms

It is used to set the filtering time constant of the first-order low-pass filtering mode.

The position instructions are rectangular waves	
The position instructions are trapezoidal waves	

P04-03 2004-03	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	position command average filter time constant AveragingFilterTime	Shutdown setting	Effective immediately	0	0 to 128	Position mode	ms

Used to set average filtering time constant.

The position commands is rectangular waves	
The position command is trapezoidal wave	

P04-04 2004-04	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Torque filter time constant TogFiltertTime	Operation setting	Effective immediately	50	10~2500	Vibration suppression	0.01ms

Used to set torque filtering time constant. When the function code P03-03(Self-adjustment mode selection) is set to 0, the parameter is automatically set by servo.

P04-05 2004-05	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	1st notch filter frequency NotchFilter1_Freq	Operation setting	Effective immediately	300	250 to 5000	Vibration suppression	Hz

Use to set the center frequency of the 1st notch filter. When the function code is set to 5000, the function of the notch filter is invalid.

P04-06 2004-06	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	1st notch filter depth NotchFilter1_Deep	Operation setting	Effective immediately	100	0 to 100	Vibration suppression	-

It is use to set the notch filter depth grade (the ratio between input and output at the center frequency of the notch filter). The larger the set value of this function code is, the smaller the notch filter depth is, and the weaker the suppression effect of mechanical vibration is. However, setting too large could cause system instability.

P04-07 2004-07	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	1st notch filter width NotchFilter1_Band	Operation setting	Effective immediately	4	0 to 12	Vibration suppression	-

Use to set the notch filter width grade (the ratio between input and output at the center frequency of the notch filter)

P04-08 2004-08	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	2nd notch filter frequency NotchFilter2_Freq	Operation setting	Effective immediately	500	250 to 5000	Vibration suppression	Hz

Use to set the center frequency of the 2nd notch filter. When the function code is set to 5000, the function of the notch filter is invalid.

P04-09 2004-09	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	2nd notch filter depth NotchFilter2_Deep	Operation setting	Effective immediately	100	0 to 100	Vibration suppression	-

P04-10 2004-0A	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	2nd notch filter width NotchFilter2_Band	Operation setting	Effective immediately	4	0 to 12	Vibration suppression	-

P04-18 2004-12	**Parameter name**	**Setting method**	**Effective time**	**Default**	**Set range**	**Application category**	**Unit**
	Speed feedback filter time SpdFdbFilterTime	Operation setting	Effective immediately	10	1 to 1000	Vibration suppression	0.01ms

Group 2005h: signal input and output

P05-16 2005-10	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Rotation detection speed threshold RotateSpdDtTh	Operation setting	Effective immediately	20	0~1000	Speed mode	rpm
Set the speed threshold that triggers the motor rotation signal. The motor rotation signal (TGON) is used to confirm that the motor has rotated.							

P05-19 2005-13	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Zero speed output signal threshold SpdZeroOutTh	Operation setting	Effective immediately	10	0~6000	Speed mode	rpm
Use to set the speed threshold that triggers the motor rotation signal. Motor output zero speed signal (ZSP) means that the actual speed of the motor is close to stationary.							

P05-23 2005-17	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Probe filter 1 time parameters TouchprobeFilter1Time	Operation setting	Effective immediately	200	0 to 500	-	10ns
Set the filter time of probe 1; 0-10us.							

P05-24 2005-18	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Probe filter 2 time parameters TouchprobeFilter2Time	Operation setting	Effective immediately	200	0 to 500	-	10ns
Set the filter time of probe 2; 0-10us.							

P05-25 2005-19	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	TouchprobeDiOnCompensationTime	Operation setting	Effective immediately	500	-10000 to 10000	-	10ns
The compensation probe action time when it is turned on, set to positive to move in the direction of motion.							

P05-26 2005-1A	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	TouchprobeDiOnCompensationTime	Operation setting	Effective immediately	500	-10000 to 10000	-	10ns
The compensation probe action time when it is turned off, set to positive to move in the direction of motion.							

Group 2006h: DIDO configuration

P06-02 2006-02	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DI_1 channel function selection Di1FunSel	Operation setting	Power-on again	0	0~32	DI/DO	-

Set DI functions corresponding to hardware DI_1. Refer to the following table for the functions corresponding to the set value:

Setting value	DI channel function
0	OFF (not used)
1	SON (servo enabled)
2	A-CLR (Fault and warning clear)
3	POT (Forward drive prohibition)
4	NOT (Reverse drive prohibition)
6	CL (deviation counter cleared)

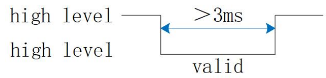
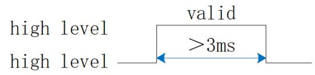
Setting value	DI channel function
8	E-STOP (Emergency stop)
18	Probe 1
19	Probe 2
26	HOMEORG (origin signal)
Other	None

If P06-02 is set to a value other than that in the preceding table, the DI port function is not require

The same DI channel function could not be allocated to multiple DI ports, otherwise servo drive will occur A-89 (duplicate DI port configuration)

P06-03 2006-03	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DI_1 channel logic selection Di1LogSel	Operation setting	Effective immediately	0	0 to 1	DI/DO	-

DI port input logic validity function selection

Setting value	Content	Specification
0	Normally open input. Active low level (switch on);	
1	Normally closed input. Active high level (switch off);	

P06-04 2006-04	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DI_1 input source selection Di1SrcSel	Operation setting	Effective immediately	0	0 to 1	DI/DO	-

Select the enabled DI_1 port type

Setting value	Port category
0	Hardware DI_1 input terminal
1	Virtual VDI_1 input terminal

P06-05 2006-05	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DI_2 channel function selection **Di2FunSel**	Operation setting	Power-on again	2	0~32	DI/DO	-

P06-06 2006-06	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DI_2 channel logic selection **Di2LogSel**	Operation setting	Effective immediately	0	0 to 1	DI/DO	-

P06-07 2006-07	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DI_2 input source	Operation setting	Effective immediately	0	0 to 1	DI/DO	-

	selection **Di2SrcSel**						

P06-08 2006-08	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DI_3 channel function selection **Di3FunSel**	Operation setting	Power-on again	3	0~32	DI/DO	-

P06-09 2006-09	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DI_3 channel logic selection **Di3LogSel**	Operation setting	Effective immediately	0	0 to 1	DI/DO	-

P06-10 2006-0A	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DI_3 input source selection **Di3SrcSel**	Operation setting	Effective immediately	0	0 to 1	DI/DO	-

P06-11 2006-0B	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DI_4 channel function selection **Di4FunSel**	Operation setting	Power-on again	4	0~32	DI/DO	-

P06-12 2006-0C	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DI_4 channel logic selection **Di4LogSel**	Operation setting	Effective immediately	0	0 to 1	DI/DO	-

P06-13 2006-0D	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DI_4 input source selection **Di4SrcSel**	Operation setting	Effective immediately	0	0 to 1	DI/DO	-

P06-14 2006-0E	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DI_5 channel function selection Di5FunSel	Operation setting	Power-on again	0	0~32	DI/DO	-

P06-15 2006-0F	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DI_5 channel logic selection **Di5LogSel**	Operation setting	Effective immediately	0	0 to 1	DI/DO	-

P06-16 2006-10	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DI_5 input source selection Di5SrcSel	Operation setting	Effective immediately	0	0 to 1	DI/DO	-

P06-17 2006-11	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DI_6 channel function selection Di6FunSel	Operation setting	Power-on again	0	0~32	DI/DO	-

P06-18 2006-12	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DI_6 channel logic selection	Operation setting	Effective immediately	0	0 to 1	DI/DO	-

	Di6LogSel						

P06-19 2006-13	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DI_6 input source selection Di6SrcSel	Operation setting	Effective immediately	0	0 to 1	DI/DO	-

P06-26 2006-1A	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DO_1 channel function selection Do1FunSel	Operation setting	Effective immediately	132	128 ~ 148	DI/DO	-

Use to set DO functions corresponding to hardware DO_1. Refer to the following table for the functions corresponding to the set value:

Setting value	DI channel function	Setting value	DI channel function
128	OFF (not used)	139	T-LIMIT (Torque limit)
129	RDY (Servo ready)	140	V-LIMIT (speed limited)
130	ALM (Fault signal)	141	BRK-OFF (brake output)
131	WARN (warning signal)	142	SRV-ST (Servo on state output)
132	TGON (rotation detection)	145	COM_VDO1 (communication VDO1 output)
133	ZSP (zero speed signal)	146	COM_VDO1 (communication VDO1 output)
134	P-COIN (positioning completed)	147	COM_VDO1 (communication VDO1 output)
137	V-NEAR (speed approach)	Others	None
138	T-COIN (torque arrival)		

If P06-26 is set to a value other than that in the preceding table, the DO port function is not required

The same DO channel function could not be allocated to multiple DO ports, otherwise servo drive will occur A-90 (duplicate DO port configuration)

P06-27 2006-1B	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DO_1 channel logic selection Do1LogSel	Operation setting	Effective immediately	0	0 to 1	DI/DO	-

DO Port input logic validity function selection.

Setting value	Content
0	Output transistor is on when the output is valid, and output transistoris off when the output is invalid.
1	Output transistor is off when the output is valid, and output transistor is on when the output is invalid.

P06-28 2006-1C	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DO_2 channel function selection **Do2FunSel**	Operation setting	Effective immediately	130	128 to 148	DI/DO	-

P06-29 2006-1D	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DO_2 channel logic selection **Do2LogSel**	Operation setting	Effective immediately	0	0 to 1	DI/DO	-

P06-30 2006-1E	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DO_3 channel function selection **Do3FunSel**	Operation setting	Effective immediately	129	128 to 148	DI/DO	-

P06-31 2006-1F	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	DO_3 channel logic selection Do3LogSel	Operation setting	Effective immediately	0	0 to 1	DI/DO	-

P06-34 2006-20	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	ECAT forces DO to output state CompDoOutputStatu	Operation setting	Effective immediately	0	0 to 1	Auxiliary function	-

When the master station changes from online to offline, the DO output state changes (when the DO forced output enable of 60FE-02h is not turned on, it is not affected by this function code)

0: Keep the current state;

1: Initialize state

Group 200Ah: Auxiliary Function

P10-01 200A-01	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	JOG speed SpdRefJOG	Operation setting	Effective immediately	100	0~3000	Auxiliary function	rpm
Used to set JOG speed							

P10-02 200A-02	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Factory value resetting RstFuncFac	Shutdown setting	Effective immediately	0	0 to 1	Auxiliary function	-

Used to restore function code parameters to factory values.

Setting value	Operational meaning
0	No operation
1	Restore factory setting value

P10-03 200A-03	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Fault clearing ServoErrClear	Operation setting	Effective immediately	0	0 to 1	Auxiliary function	-

Fault reset operation selection

Setting value	Function	Remark
0	No operation	-
1	Fault clearing	For clearable faults, after the cause of fault is removed, and write 1 to the function code, the drive will stop the fault display and enter the Rdy (or RUN) state again.

✎Note: If the servo S-ON is valid, when the fault is removed and cleared, the servo will directly enter the Run state. When performing fault clearing actions, be sure to stop sending control instructions such as pulses to ensure personal safety.

P10-04 200A-04	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Motor overload protection time factor MotOLProtect_Coef	Operation setting	Effective immediately	100	0 to 800	Accessibility	%

Set the time for code A-82 (Motor overload warning) and Er.34 (Motor overload protection fault) through this function code.

According to the heating condition of the motor, modifying this value can make the overload protection time fluctuate up and down the reference value, 50 corresponds to 50%, that is, the time is reduced by half; 300 corresponds to 300%, that is, the time is extended to 3 times. When it is set to 0, the overload protection fault detection function will be shielded, so please use it carefully!

P10-05 200A-05	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Motor type **MotorTypeSel**	Operation setting	Power on again	0	0 to 65535	Auxiliary function	-

The motor model is used together with P10-7 to manually set the motor code. When P10-7 is set to 1, the motor code uses the value set by P10-5. When P10-7 is set to 0, the current motor model code, please query U0-53.

P10-06 200A-06	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Multi-turn absolute encoder reset **AbsEncRst**	Stop setting	Effective immediately	0	0 to 65535	Auxiliary function	-

Used to clear the rotation number of multi-turn absolute encoder (U0-55), current position (U0-56) or clear the encoder fault alarms

Setting value	Function
0	No operation
1	Clear multi-turn data, encoder current position and encoder fault alarms
2	retain
3	Only clear the fault alarm of multi-turn absolute encoder
-	Other values are invalid

✎**Note:** After reset (P10-06 is set to 1), the absolute position of the encoder will change suddenly, and the mechanical origin return operation is required.

P10-07 200A-07	Parameter name	Setting method	Effective time	Default	Set range	Application category	Unit
	Manual setting motor code ManualSetMotoCode	Operation setting	Power-on again	0	0 to 1	Auxiliary function	-

Used to modify the Motor Code of the servo drive. When it is set to 0, Motor Code is read from motor. When it is set to 1, Motor code is read from P10-5 motor model.

✎**Note:** Do not modify it casually, otherwise it will cause motor damage.

P10-11 **200A-0B**	**Parameter name**	**Setting method**	**Valid time**	**Default**	**Set range**	**Application category**	**Unit**
	Motor stall over-temperature enable **Motor Stuck Over Temp Enable**	Operation setting	Effective immediately	0	0 to 1	Auxiliary function	-

Used to turn on and off motor

Setting value	**Function**
0	Enable motor stall overtemperature detection. When the motor stalls, the driver reports [ER.45] motor stall overtemperature protection;
1	Shielded motor stall overtemperature detection. (After stall detection, the torque is automatically reduced to 70.7% of the rated value)

✎**Note:** After reset (P10-06 is set to 1), the absolute position of the encoder will change suddenly, and the mechanical origin return operation is required.

Group 200Dh Communication Input and Output Terminal

P13-01 200D-01	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Virtual VDI_1 input value CommVdi_1	Operation setting	Valid immediately	0	0 to 1	DI/DO	-

When P06-04 is set to 1, DI_1 channel logic is controlled by this function code.

Setting value	VDI_1 input level
0	Low level
1	High level

P13-02 200D-02	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Virtual VDI_2 input value CommVdi_2	Operation setting	Effective immediately	0	0 to 1	DI/DO	-

When P06-07 is set to 1, DI_2 channel logic is controlled by this function code.

P13-03 200D-03	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Virtual VDI_3 input value CommVdi_3	Operation setting	Effective immediately	0	0 to 1	DI/DO	-

When P06-10 is set to 1, DI_3 channel logic is control by this function code.

P13-04 200D-04	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Virtual VDI_4 input value CommVdi_4	Operation setting	Effective immediately	0	0 to 1	DI/DO	-

When P06-13 is set to 1, DI_4 channel logic is control by this function code.

P13-05 200D-05	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Virtual VDI_5 input value CommVdi_5	Operation setting	Effective immediately	0	0 to 1	DI/DO	-
When P06-16 is set to 1, DI_5 channel logic is control by this function code.							

P13-06 200D-06	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Virtual VDI_6 input value CommVdi_6	Operation setting	Effective immediately	0	0 to 1	DI/DO	-
When P06-19 is set to 1, DI_6 channel logic is control by this function code.							

P13-11 200D-0B	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Virtual VDO_1 output value CommVdo_1	Operation setting	Effective immediately	0	0 to 1	DI/DO	-

Used to set the input level logic when the DO function selected by VDO_1 is active.

Setting value	VDO_1 input level
0	Low level
1	High level

P13-12 200D-0C	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Virtual VDO_2 output value **CommVdo_2**	Operation setting	Effective immediately	0	0 to 1	DI/DO	-

P13-13 200D-0D	Parameter name	Setting method	Valid time	Default	Set range	Application category	Unit
	Virtual VDO_3 output value **CommVdo_3**	Operation setting	Effective immediately	0	0 to 1	DI/DO	-

Group 201Eh Universal Monitoring

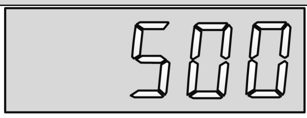
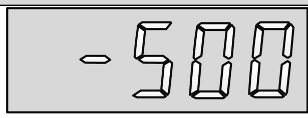
U0-01 201E-01	Monitoring name	Range	Category	Panel display	Unit	Data type
	Servo status SrvStatus	0 ~8	Universal	Decimal	-	16 Bit

Display the status of servo drive.

Display value	Status	Display value	Status
0	Power-on	5	Servo operation
1	Initialization	6	Quick shutdown
2	Failure-free (nF)	7	Malfunction shutdown
3	Servo ready (Ry)	8	Fault
4	Wait for servo enabled		

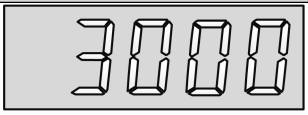
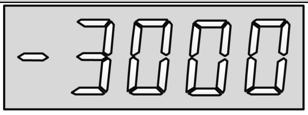
U0-02 201E-02	Monitoring name	Range	Category	Panel display	Unit	Data type
	Servo motor speed **SpeedDis**	-6000~6000	Universal	Decimal	rpm	16 Bit

Display the actual speed of servo drive. The accuracy is 1 rpm. The display of servo drive panel is as below.

500rpm display	-500rpm display
	

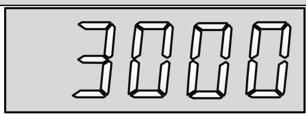
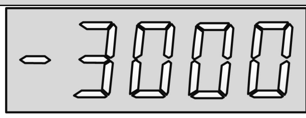
U0-03 201E-03	Monitoring name	Range	Category	Panel display	Unit	Data type
	Input speed instruction **SpdCmd**	-6000~6000	Universal	Decimal	rpm	16 Bit

Display servo input speed instruction. The accuracy is 1 rpm. The display of servo drive panel is as below.

3000rpm display	**-3000rpm display**
	

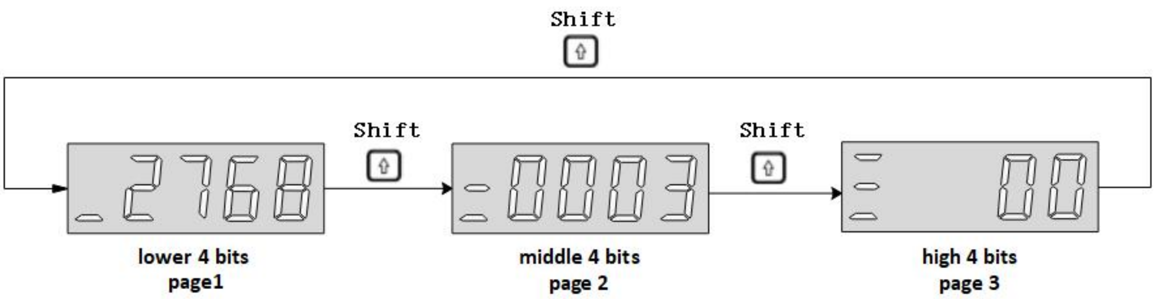
U0-04 201E-04	Monitoring name	Range	Category	Panel display	Unit	Data type
	Corresponding speed of position command PosCmdToSpd	-5000~5000	Universal	Decimal	rpm	16 Bit

Display the current speed instruction value of servo drive in position mode. The accuracy is 1 rpm. The display of servo drive panel is as below.

3000rpm display	**-3000rpm display**
	

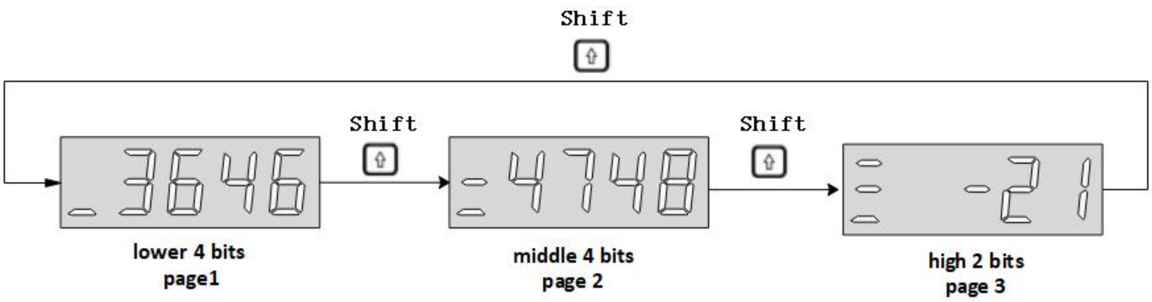
U0-05 201E-05	Monitoring name	Range	Category	Panel display	Unit	Data type
	Pulse deviation PulsErr	-2^{31}~2^{31}	Universal	Decimal	Equivalent pulse deviation	32 Bit

Display pulse deviation. If U0-05 is 32768, the display of the servo drive panel is:



U0-09 201E-09	Monitoring name	Range	Category	Panel display	Unit	Data type
	Input instruction pulse number PulsTotal	-2^{31}~2^{31}	Universal	Decimal	Instruction unit	32 Bit

Display instruction pulse number that input the servo drive. If U0-09 is set to -2147483646, the panel of servo drive is displayed as below.



U0-13 201E-0D	Monitoring name	Range	Category	Panel display	Unit	Data type
	Encoder cumulative position (Low 32 bits) EncTotal_LowWord	-2^{31}~2^{31}	Universal	Decimal	Encoder unit	32 Bit

U0-15 201E-0F	Monitoring name	Range	Category	Panel display	Unit	Data type
	Encoder cumulative position (High 32 bits) EncTotal_HighWord	-2^{31}~2^{31}	Universal	Decimal	Encoder unit	32 Bit

Display the cumulative data of encoder position. It is used with U0-13 cooperatively.

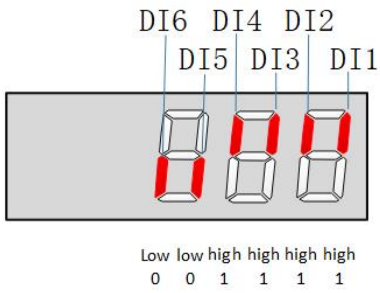
U0-17 201E-11	Monitoring name	Range	Category	Panel display	Unit	Data type
	DI input signal status	00000000 ~	Universal	Binary	Encoder unit	16 Bit

	DiData1	11111111				

Displays the current level status of 6 DI terminals.

Display mode: The upper part of the digital tube of the servo drive panel is bright to indicate high level (represented by "1"); The lower light indicates low level (denoted by "0").

Take the DI1~DI4 terminal as the high level and DI5~D16 as the low level as the example: the corresponding binary code is "001111", and Wecon servo control device debugging platform U0-17 displays the 0b0000 1111. The panel of servo drive is displayed as below:

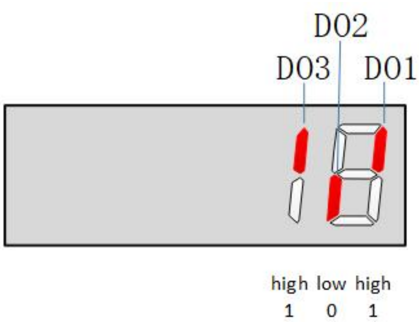


U0-19 201E-13	Monitoring name	Range	Category	Panel display	Unit	Data type
	DO output signal status DoData1	00000000 ~ 00001111	Universal	Binary	Encoder unit	16 Bit

Displays the current level status of 3 DO terminals.

Display mode: The upper part of the digital tube of the servo drive panel is bright to indicate high level (represented by "1"); The lower light indicates low level (denoted by "0").

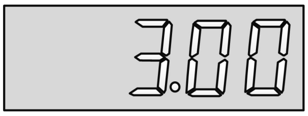
Take the DO1, DO2 and DO3 terminals as the high level and DO2 as the low level as an example. The corresponding binary code is "101", and Wecon servo upper computer debugging platform U0-17 displays the current binary value is 0b0000 0101. The panel of servo drive is displayed as below.



U0-20 201E-1	Monitoring name	Range	Category	Panel display	Unit	Data type

4	Real-time load inertia ratio InerRatioReal	-	Universal	Decimal	%	16 Bit

Displays the current load inertia ratio. If the load inertia ratio is 3 times (300%), the panel of servo drive is displayed as below.

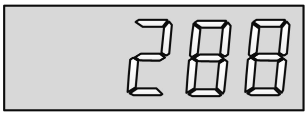


U0-23 201E-17	Monitoring	Range	Category	Panel	Unit	Data type
	Vibration Frequency DisVibFreq	-	Universal	Decimal	Hz	16 Bit

U0-24 201E-18	Monitoring name	Range	Category	Panel display	Unit	Data type
	Vibration Amplitude DisVibMag	-	Universal	Decimal	rpm	16 Bit

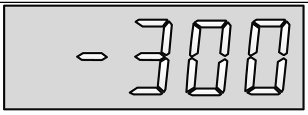
U0-25 201E-19	Monitoring name	Range	Category	Panel display	Unit	Data type
	Forward torque limit value PToqLimitDis	0~300	Universal	Decimal	%	16 Bit

Display the set value of P01-15 (forward torque limit) of servo drive. If U0-25 is 288%, the panel of servo drive is displayed as below.



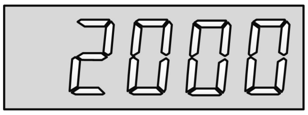
U0-26 201E-1A	Monitoring name	Range	Category	Panel display	Unit	Data type
	Reverse torque limit value NToqLimitDis	-300~0	Universal	Decimal	%	16 Bit

Display the set value of P01-16 (reverse torque limit) of servo drive. If U0-26 is 300%, the panel of servo drive is displayed as below.



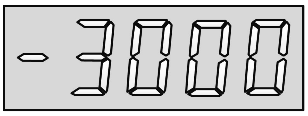
U0-27 201E-1B	Monitoring name	Range	Category	Panel display	Unit	Data type
	Forward speed limit value PSpdLimitDis	0~6000	Universal	Decimal	rpm	16 Bit

Display the set value of P01-12 (forward speed threshold) of servo drive. If P01-12 is set to 2000, the panel of servo drive is displayed as below.



U0-28 201E-1C	Monitoring name	Range	Category	Panel display	Unit	Data type
	Reverse speed limit value NSpdLimitDis	-6000~0	Universal	Decimal	rpm	16 Bit

Display the set value of P01-13 (reverse speed threshold) of servo drive. If P01-13 is set to 3000, the panel of servo drive is displayed as below.



U0-29 201E-1D	Monitoring name	Range	Category	Panel display	Unit	Data type
	Mechanical angle MachineAngle	0~359	Universal	Decimal	°	16 Bit

Display current mechanical angle of motor. 0 corresponds to a mechanical angle of 0 degree.

U0-30 201E-1E	Monitoring name	Range	Category	Panel display	Unit	Data type
	Electrical angle ElecAngle	0~359	Universal	Decimal	°	16 Bit

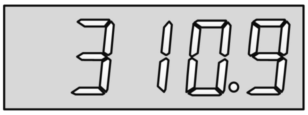
Display current electrical angle of motor. The accuracy is 1°. When the motor rotates, the electrical angle range is 360°.

When the motor is 4 poles, every time the motor is rotated one turn, it undergoes a change process of 0° to 359° for four times.

U0-31 dain201E-1F	Monitoring name	Range	Category	Panel display	Unit	Data type
	Bus voltage DcBusVoltDisp	-	Universal	Decimal	V	16 Bit

Display the DC bus voltage of the main circuit input voltage of servo drive after rectification.

If the bus voltage is 310.9, the panel of servo drive is displayed as below.



U0-32 201E-20	Monitoring name	Range	Category	Panel display	Unit	Data type
	Radiator temperature Temperature_IPM	-	Universal	Decimal	°C	16 Bit

U0-33 201E-21	Monitoring name	Range	Category	Panel display	Unit	Data type
	Instantaneous output power OutputPowerInst	-	Universal	Decimal	W	16 Bit

U0-34 201E-22	Monitoring name	Range	Category	Panel display	Unit	Data type
	Average output power OutputPowerAverage	-	Universal	Decimal	W	16 Bit

U0-35 201E-23	Monitoring name	Range	Category	Panel display	Unit	Data type
	Total operation time (hour)	-	Universal	Decimal	h	16 Bit

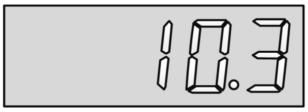
	HourTotalRun					

U0-37 201E-25	Monitoring name	Range	Category	Panel display	Unit	Data type
	Total operation time (minute) MinTotalRun	-	Universal	Decimal	min	16 Bit

U0-38 201E-26	Monitoring name	Range	Category	Panel display	Unit	Data type
	Total operation time (second) SecTotalRun	-	Universal	Decimal	s	16 Bit

U0-39 201E-27	Monitoring name	Range	Category	Panel display	Unit	Data type
	Load torque percentage ToqOutRate	-	Universal	Decimal	%	16 Bit

Display current load torque percentage. If the current load torque percentage is 10.3%, the panel of servo drive is displayed as below.



U0-40 201E-28	Monitoring name	Range	Category	Panel display	Unit	Data type
	Current operation time (hour) HourCurrentRun	-	Universal	Decimal	h	16 Bit

U0-42 201E-2A	Monitoring name	Range	Category	Panel display	Unit	Data type
	Current operation time (minute) MinCurrentRun	-	Universal	Decimal	min	16 Bit

U0-43	Monitoring	Range	Category	Panel	Unit	Data type

201E-2B	name			display		
	Current operation time (second) SecCurrentRun	-	Universal	Decimal	s	16 Bit

U0-44 201E-2C	Monitoring name	Range	Category	Panel display	Unit	Data type
	Instantaneous braking resistor power DisPwrInst	-	Universal	Decimal	W	16 Bit

U0-46 201E-2E	Monitoring name	Range	Category	Panel display	Unit	Data type
	Average braking resistor power DisPwrAvg	-	Universal	Decimal	W	16 Bit

U0-48 201E-30	Monitoring name	Range	Category	Panel display	Unit	Data type
	Power-on times PwrUpCount	-	Universal	Decimal	Times	16 Bit

U0-49 201E-31	Monitoring name	Range	Category	Panel display	Unit	Data type
	Overload times MotorOverLoadCount	-	Universal	Decimal	0.01%	16 Bit

U0-50 201E-32	Monitoring name	Range	Category	Panel display	Unit	Data type
	Motor cumulative number of circles (Low 32 bits) MotoTotal_Low	0~ (2^{32}-1)	Universal	Decimal	Circle	32 Bit

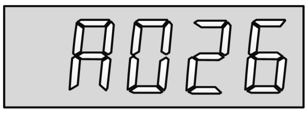
	Word					
Displays the cumulative number of revolutions of the motor. It is used with U0-13 cooperatively.						

U0-51 201E-33	Monitoring name	Range	Category	Panel display	Unit	Data type
	Motor cumulative number of circles (High 32 bits) MotoTotal_High Word	0~ (2^{32}-1)	Universal	Decimal	Circle	32 Bit

U0-52 201E-34	Monitoring name	Range	Category	Panel display	Unit	Data type
	Encoder bits EncoderBit	17 to 23	Universal	Decimal	Bit	16 Bit

U0-53 201E-35	Monitoring name	Range	Category	Panel display	Unit	Data type
	Motor model code MotoModel	-	Universal	Hexadeci mal	-	16 Bit

Displays the Motor Code of the current servo drive connected motor. Taking WD80M-07530S-A1F (A026) as an example, the description panel is displayed as below:



U0-54 201E-36	Monitoring name	Range	Category	Panel display	Unit	Data type
	Absolute encoder position in 1 lap AbsEncIn1Cycle	0~(2^{32}-1)	Universal	Decimal	Encoder unit	32 Bit

Display the single turn position feedback value of absolute encoder

U0-55 201E-37	Monitoring name	Range	Category	Panel display	Unit	Data type
	Absolute encoder number of circles AbsEncMultiTurn	0 to 65535	Universal	Decimal	Circle	32 Bit
Circle numbers of multi-turn absolute encoder						

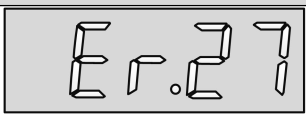
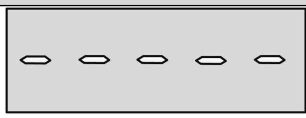
U0-56 201E-38	Monitoring name	Range	Category	Panel display	Unit	Data type
	Current position of the multi-turn absolute encoder (Low 32 bits) EncTotal_CmdUnit	-2^{31}~2^{31}	Universal	Decimal	Instruction unit	32-bit
Display the absolute position of the current motor (Instruction unit). It is only valid in multi-turn absolute encoder motor.						

U0-57 201E-39	Monitoring name	Range	Category	Panel display	Unit	Data type
	Current position of the multi-turn absolute encoder (High 32 bits) EncTotal_CmdUnit	-2^{31}~2^{31}	Universal	Decimal	Instruction unit	32-bit
Display the absolute position of the current motor (Instruction unit). It is only valid in multi-turn absolute encoder motor.						

Group 201Fh: Warning Monitoring

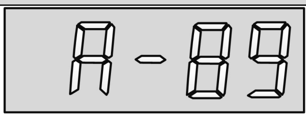
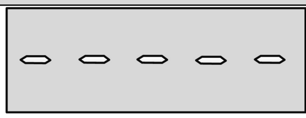
U1-01 201F-01	Monitoring name	Range	Category	Panel display	Unit	Data type
	Current error code NowErrorCode	-	Warning	-	-	16 Bit

If there is fault in servo drive, it would display the corresponding fault. If not, the panel displays "---", Taking the failure of "encoder disconnection" as an example, the panel of servo drive is displayed as below.

Servo drive has a fault "encoder disconnection"	Servo drive has no fault
	

U1-02 201F-02	Monitoring name	Range	Category	Panel display	Unit	Data type
	Current warning code NowWarmCode	-	Warning	-	-	16 Bit

If there is warning in servo drive, it would display the corresponding warning. If not, the panel displays "---". Taking the warning of "duplicate DI port configuration" as an example, the panel is displayed as below.

Servo drive has a warning "duplicate DI port configuration"	Servo drive has no warning
	

U1-03 201F-03	Monitoring name	Range	Category	Panel display	Unit	Data type
	U phase current when faults occur IuWarmOccur	-	Warning	Decimal	A	16 Bit

U1-04 201F-04	Monitoring name	Range	Category	Panel display	Unit	Data type
	V phase current when faults occurmalfunction IvWarmOccur	-	Warning	Decimal	A	16 Bit

U1-05 201F-05	Monitoring name	Range	Category	Panel display	Unit	Data type
	Bus voltage when faults occur UdcWarmOccur	-	Warning	Decimal	V	16 Bit

U1-06 201F-06	Monitoring name	Range	Category	Panel display	Unit	Data type
	IGBT temperature when faults occur T_IPMWarmOccur	-	Warning	Decimal	°C	16 Bit

U1-07 201F-07	Monitoring name	Range	Category	Panel display	Unit	Data type
	Torque component when faults occur IqWarmOccur	-	Warning	Decimal	%	16 Bit

U1-08 201F-08	Monitoring name	Range	Category	Panel display	Unit	Data type
	Excitation component when faults occur IdWarmOccur	-	Warning	Decimal	%	16 Bit

U1-09 201F-09	Monitoring name	Range	Category	Panel display	Unit	Data type
	Position deviation when faults occur PosErrWarmOccur	-	Warning	Decimal	Encoder unit	32 Bit

U1-10 201F-0A	Monitoring name	Range	Category	Panel display	Unit	Data type
	Speed value when faults occur SpdWarmOccur	-	Warning	Decimal	rpm	16 Bit

U1-11 201F-0B	Monitoring name	Range	Category	Panel display	Unit	Data type
	Time when the fault occurred Time 1WarmOccur	-	Warning	Decimal	s	16 Bit

U1-12 201F-0C	Monitoring name	Range	Category	Panel display	Unit	Data type
	Number of faults during current operation ErrCntCurRun	-	Warning	Decimal	-	16 Bit

U1-13 201F-0D	Monitoring name	Range	Category	Panel display	Unit	Data type
	Number of warnings during current operation WarmCntCurRun	-	Warning	Decimal	-	16 Bit

U1-14 201F-0E	Monitoring name	Range	Category	Panel display	Unit	Data type
	Total number of historical faults ErrorTotalCnt	-	Warning	Decimal	-	16 Bit

U1-15 201F-0F	Monitoring name	Range	Category	Panel display	Unit	Data type
	Total number of historical warnings	-	Warning	Decimal	-	16 Bit

	WarmTotalCnt					

U1-16 201F-10	Monitoring name	Range	Category	Panel display	Unit	Data type
	Latest 1st fault code ErrCodeLast1st	-	Warning	-	-	16 Bit
Display the 1st fault code of the most recent of servo drive						

U1-17 201F-11	Monitoring name	Range	Category	Panel display	Unit	Data type
	Latest 2nd fault code ErrCodeLast2nd	-	Warning	-	-	16 Bit

U1-18 201F-12	Monitoring name	Range	Category	Panel display	Unit	Data type
	Latest 3rd fault code ErrCodeLast 3rd	-	Warning	-	-	16 Bit

U1-19 201F-13	Monitoring name	Range	Category	Panel display	Unit	Data type
	Latest 4th fault code ErrCodeLast 4th	-	Warning	-	-	16 Bit

U1-20 201F-14	Monitoring name	Range	Category	Panel display	Unit	Data type
	Latest 5th fault code ErrCodeLast 5th	-	Warning	-	-	16 Bit

U1-21 201F-15	Monitoring name	Range	Category	Panel display	Unit	Data type
	Latest 1st warning code	-	Warning	-	-	16 Bit

	WarmCodeLast1st					
Display the 1st warning code of the most recent of servo drive						

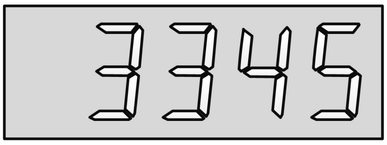
U1-22 201F-16	**Monitoring name**	**Range**	**Category**	**Panel display**	**Unit**	**Data type**
	Latest 2nd warning code WarmCodeLast 2 nd	-	Warning	-	-	16 Bit

U1-23 201F-17	**Monitoring name**	**Range**	**Category**	**Panel display**	**Unit**	**Data type**
	Latest 3rd warning code WarmCodeLast 3 rd	-	Warning	-	-	16 Bit

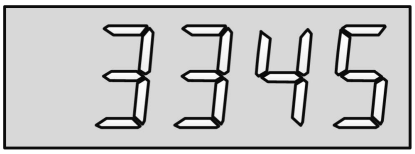
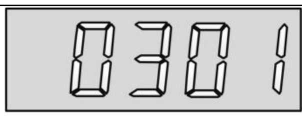
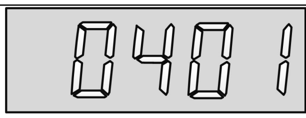
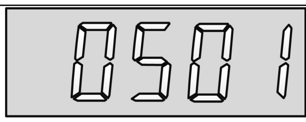
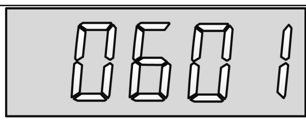
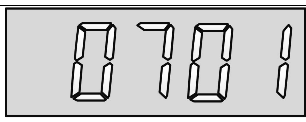
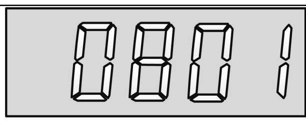
U1-24 201F-18	**Monitoring name**	**Range**	**Category**	**Panel display**	**Unit**	**Data type**
	Latest 4th warning code WarmCodeLast 4 th	-	Warning	-	-	16 Bit

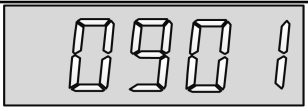
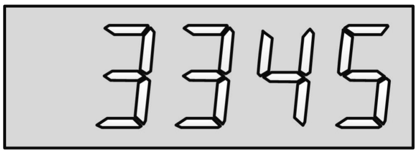
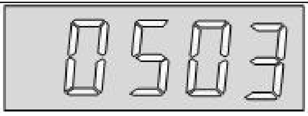
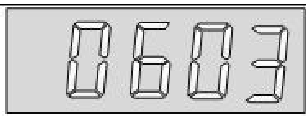
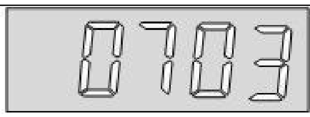
U1-25 201F-19	**Monitoring name**	**Range**	**Category**	**Panel display**	**Unit**	**Data type**
	Latest 5th warning code WarmCodeLast 5 th	-	Warning	-	-	16 Bit

Group 2020h: Device Monitoring

<table>
<tr><th rowspan="2">U2-01
2020-01</th><th>Monitoring name</th><th>Range</th><th>Category</th><th>Panel display</th><th>Unit</th><th>Data type</th></tr>
<tr><td>Product series
ProductSer</td><td>-</td><td>Device</td><td>Hexadecimal</td><td>-</td><td>16 Bit</td></tr>
<tr><td colspan="7">Display the product series code of servo drive.
The VD3E servo drive code is 0x3345. The panel is displayed as below:
</td></tr>
</table>

<table>
<tr><th rowspan="2">U2-02
2020-02</th><th>Monitoring name</th><th>Range</th><th>Category</th><th>Panel display</th><th>Unit</th><th>Data type</th></tr>
<tr><td>Model
Model1</td><td>-</td><td>Device</td><td>Hexadecimal</td><td>-</td><td>16 Bit</td></tr>
<tr><td colspan="7">Display the servo drive model.</td></tr>
</table>

<table>
<tr><th>U2-01 display</th><th>U2-02 display</th><th>Model</th></tr>
<tr><td rowspan="7"></td><td></td><td>VD3E-003SA1G</td></tr>
<tr><td></td><td>VD3E-010SA1G</td></tr>
<tr><td></td><td>VD3E-014SA1G</td></tr>
<tr><td></td><td>VD3E-016SA1G</td></tr>
<tr><td></td><td>VD3E-019SA1G</td></tr>
<tr><td></td><td>VD3E-021SA1G</td></tr>
<tr><td></td><td>VD3E-025SA1G</td></tr>
</table>

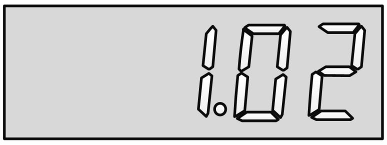
			VD3E-030SA1G	
			VD3E-016TA1G	
			VD3E-019TA1G	
			VD3E-021TA1G	

U2-03 2020-03	Monitoring name	Range	Category	Panel display	Unit	Data type
	Model Model2	-	Device	Hexadecimal	-	16 Bit

U2-04 2020-04	Monitoring name	Range	Category	Panel display	Unit	Data type
	Firmware version FirewareVer	-	Device	Decimal	-	16 Bit

Display the firmware version.

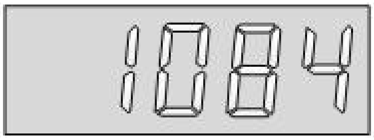
Display format: X.YY. For example, 1.02. The panel is displayed as below.



U2-05 2020-05	Monitoring name	Range	Category	Panel display	Unit	Data type
	cm firmware version CM FireWave	-	Device	Decimal	-	16 Bit

Display the Servo Hardware (FPGA) version.

Display format: X. YY, 2 decimal places. For example 1.00, the servo drive panel is displayed as follows:



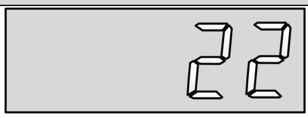
U2-06 2020-06	Monitoring name	Range	Category	Panel display	Unit	Data type
	Firmware time (year) ExFactoryYear	-	Device	Decimal	Year	16 Bit

U2-07 2020-07	Monitoring name	Range	Category	Panel display	Unit	Data type
	Firmware time (month) ExFactoryMonth	-	Device	Decimal	Month	16 Bit

U2-08 2020-08	Monitoring name	Range	Category	Panel display	Unit	Data type
	Firmware Date (Day) ExFactoryDay	-	Device	Decimal	Day	16 Bit

Display the production date of display firmware.

Taking the “VD3E-014SA1G_V1. 03 firmware production date is January 10, 2022” as an example, the drive panel is displayed as below:

U2-06	U2-07	U2-08
		

U2-09 2020-09	Monitoring name	Range	Category	Panel display	Unit	Data type
	Device serial number 1 DeviceSerNum1	-	Device	Decimal	-	16 Bit

U2-10 2020-0A	Monitoring name	Range	Category	Panel display	Unit	Data type
	Device serial number 2 DeviceSerNum2	-	Device	Decimal	-	16 Bit

U2-11 2020-0B	Monitoring name	Range	Category	Panel display	Unit	Data type
	Device serial number 3 DeviceSerNum3	-	Device	Decimal	-	16 Bit

U2-12 2020-0C	Monitoring name	Range	Category	Panel display	Unit	Data type
	EtherCAT XML Version number	-	Device	Decimal	-	16 Bit

U2-13 2020-0D	Monitoring name	Range	Category	Panel display	Unit	Data type
	Chip model (high byte)	-	Device	Decimal	-	16 Bit

U2-14 2020-0E	Monitoring name	Range	Category	Panel display	Unit	Data type
	Chip model (low byte)	-	Device	Decimal	-	16 Bit

U2-15 2020-0F	Monitoring name	Range	Category	Panel display	Unit	Data type
	CPU ID (high byte)	-	Device	Decimal	-	16 Bit

U2-16 2020-10	Monitoring name	Range	Category	Panel display	Unit	Data type
	CPU ID (low byte)	-	Device	Decimal	-	16 Bit

8.4 Standard Equipment Sub-protocol Area (6000h to 6FFFh)

603F	Parameter name	Accessibility	Mapped or not	Setting in force	Range	Default value	Correlation mode	Data type	Unit
	Error Code	RO	TPDO	-	0 to 65535	-	ALL	16-bit	-

When a drive fault alarm occurs, 603F represents the corresponding servo internal fault alarm code. For example: When the drive has an encoder disconnection fault, 603F is 27.

6040	Parameter name	Accessibility	Mapped or not	Setting in force	Range	Default value	Correlation pattern	Data Type	Unit
	Control Word	RW	RPDO	Run setting stop takes effect	0 to 65535	0	ALL 16 bits		-

Used to set control instructions. It is meaningless to assign each bit of a control word separately, and it must be combined with other bits to form a certain control instruction.
bit0 ~ bit3 have the same meaning in each control mode of servo drive, and commands must be sent in sequence before the servo drive can be switched according to CiA402 state machine.

Bit	Name	Description
0	Servo operation can be started	0: Invalid
		1: Valid
1	Connect the main circuit	0: Invalid
		1: Valid
2	Quick stop	0: Valid
		1: Invalid
3	Servo running	0: Invalid
		1: Valid
4 to 6	Operation mode	It is related to the operation mode of servo driver
7	Fault reset	Used to clear resettable faults. The rising edge of bit7 is valid; bit7 is kept as1, and other control instructions are invalid.
8	Pause	Please query the Object Dictionary for the pause mode in each mode 605D

9	Reserved	Undefined
10	Reserved	Undefined
11~15	Manufacturer customized	Manufacturer customized

6041	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Status Word (Status Word)	RO	TPDO	-	0 ~65535	0	ALL	16 bit	-

Used to display servo drive status.

Bit	Name	Description
0	Servo ready	0: Invalid
		1: Valid
1	Servo operation can be started	0: Invalid
		1: Valid
2	Servo operation	0: Invalid
		1: Valid
3	fault	0: Invalid
		1: Valid
4	Electrical connection of main circuit	0: Invalid
		1: Valid
5	Quick shutdown	0: Invalid
		1: Valid
6	Servo is not operational	0: Invalid
		1: Valid
7	Warning	0: Invalid
		1: Valid
8	-	-
9	Remote control	0: Invalid
		1: Valid
10	Target arrival	0: Invalid
		1: Valid

Bit 0 to bit 9 have the same meaning in all control modes of servo drive. After the control word 6040h sends commands in sequence, the servo feeds back the determined state.

Setting value (binary number)	Description
xxxx xxxx x0xx 0000	Servo is not ready
xxxx xxxx x1xx 0000	Startup failure
xxxx xxxx x01x 0001	Servo ready
xxxx xxxx x01x 0011	Start up
xxxx xxxx x01x 0111	Servo enable
xxxx xxxx x00x 0111	Malfunction shutdown valid

	xxxx xxxx x0xx 1111	Fault response valid	
	xxxx xxxx x0xx 1000	Fault	

605A	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Quick stop option selection	RW	NO	-	0 to 7	2	ALL	16 bit	-
Used to set the quick stop mode.									

605B	Parameter name	Accessibility	Mapped or not	Setting in force	Range	Default value	Correlation mode	Data type	Unit
	Stop Option Code	RW	NO	-	0 to 1	0	ALL	16-bit	-

When the servo state machine executes the Shutdown instruction from the Operational state, the servo stops according to the stop mode defined by 605Bh.

Setting value	Name
0	Drive enter OFF Status, drive is free stop. The motor axis remains free.
1	With6084 After decelerating and stopping,The motor axis remains free.

605C	Parameter name	Accessibility	Mapped or not	Setting in force	Range	Default value	Correlation mode	Data type	Unit
	Servo OFF shutdown mode selection (Disable Operation Option Code)	RW	NO	-	0 to 1	0	ALL	16-bit	-

Used to set the shutdown mode after shutdown is enabled.

Setting value	Name
0	Drive enter OFF Status, drive is free stop. The motor axis remains free.

1	With6084 After decelerating and stopping,The motor axis remains free.

605D	Parameter name	Accessibility	Mapped or not	Setting in force	Range	Default value	Correlation mode	Data type	Unit
	Pause shutdown mode selection (Halt option code)	RW	NO	-	1 to 3	1	ALL	16-bit	-

Used to set the shutdown mode for pause.

605E	Parameter name	Accessibility	Mapped or not	Setting in force	Range	Default value	Correlation mode	Data type	Unit
	Fault shutdown mode selection (Fault ReactionOption Code)	RW	NO	-	0 to 3	0	ALL	16-bit	-

Used to set the shutdown mode in case of failure.

Setting value	Name
0	Category 3 failed drive free stop. The motor axis remains free.
1	The motor axis remains free after the machine is stopped at 6084 deceleration for category 3 faults.
2	The motor axis remains free after the machine is stopped at 6085 deceleration for category 3 faults.
3	The motor axis remains free after shutdown with emergency shutdown torque reduction for category 3 faults.

✎**Note:** VD3E'sClass 1/2 fault stop mode only supports free stop.

6060	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Servo mode selection (Modes of operation)	RW	RPDO	Set value takes effect at the time of shutdown	0 ~ 10	0	ALL	8 bit	-

Used to set the operation mode of servo drive.

Setting value	Name	Remarks
1	Contour position control mode	-
3	Contour speed control mode	-
4	Contour torque control mode	Please refer to "7.7 Profile torque Mode" for details
6	Origin return mode	Please refer to "7.8 Homing Mode" for details
7	Interpolation mode	-
8	Cyclic Synchronous Position mode	Please refer to "7.4 Cyclic Synchronous Position mode (CSP)" for details
9	Periodic synchronous speed mode	Please refer to "7.5 Cyclic Synchronous Velocity mode (CSV)" for details
10	Periodic synchronous torque mode	Please refer to "7.6 Cyclic Synchronous Torque mode (CST)" for details

6061	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Run mode display (Mode operation)	RO	TPDO	-	0 ~ 10	0	ALL	8 bit	-

Used to display the current operation mode of servo drive.

Setting value	Name	Remarks
1	Contour position control mode	-
3	Contour speed	-

		control mode	
	4	Contour torque control mode	Please refer to "7.7 Profile Torque mode" for details
	6	Origin return mode	Please refer to "7.8 Homing Mode" for details
	7	Interpolation mode	-
	8	Cyclic Synchronous Position mode	Please refer to "7.4 Cyclic Synchronous Position mode (CSP)" for details
	9	Periodic synchronous speed mode	Please refer to "7.5 Cyclic Synchronous Velocity mode (CSV)" for details
	10	Periodic synchronous torque mode	Please refer to "7.6 Cyclic Synchronous Torque mode (CST)" for details

6062	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	position command (Position demand value)	RO	TPDO	-	-	0	CSP HM PP	32 bit	Instruction unit
It is used to reflect the position command (command unit) that has been input by the servo in the enabled state.									

6063	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Position feedback (Position actual value)	RO	TPDO	-	-	0	ALL	32 bit	Instruction unit
Used to reflect the absolute position of motor.									

606	Paramete	Accessibilit	Data mappin	Set to	Data displa	Defaul	Correlatio	Dat a	Unit

4	r name	y	g	take effec t	y range	t	n mode	typ e	
	Position feedback (Position actual value)	RO	TPDO	-	-	0	ALL	32 bit	Instructio n unit

Used to reflect real-time absolute position.

"Position Feedback 6064h" * "Gear Ratio 6091h" = "Position Feedback 6063h"

606 5	Paramet er name	Accessibili ty	Data mappin g	Set to take effect	Data displa y range	Defaul t	Correlatio n mode	Dat a typ e	Unit
	Threshol d of excessive position deviation (Followin g error window)	RW	RPDO	Set value takes effect at the time of shutdow n	0 ~ $(2^{31}-1)$	52428 8	CSP HM PP	32 bit	Instructio n unit

Used to set the position deviation excess threshold.

When the position deviation exceeds the set value of 6065h, Er.36 (excessive position deviation) will occur in servo.

6067	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode
	Position arrival threshold (Position window)	RW	RPDO	Set value takes effect at the time of shutdown	0 ~ $(2^{32}-1)$	1000	CSP HM PP

Used to set the threshold value for position arrival.

When the position deviation is within the set value of ±6067h, the position is determined to have arrived.

In position mode, bit10=1 for status word 6041

6068	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Position window time (Position window time)	RW	RPDO	Set value takes effect at the time of shutdown	0 ~65535	100	PP HM CSP	16 bit	Ms
Used to set the position window time of the servo drive under the position mode.									

606C	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Actual velocity (Velocity actual value)	RO	TPDO	-	-	-	ALL	32 bit	Instruction unit/s
Used to display the actual rotating speed of the servo drive.									

606D	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Velocity arrival threshold (Velocity window)	RW	RPDO	Set value takes effect at the time of shutdown	0 ~65535	30	PV	16 bit	Instruction unit/s
Used to set the velocity arrival threshold of servo drive under the velocity mode.									

606E	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Velocity window time (Velocity window time)	RW	RPDO	Set value takes effect at the time of shutdown	0 ~65535	10	PV	16 bit	ms
Used to set the velocity window time of servo drive under the velocity mode.									

6071	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Target torque (Target torque)	RW	RPDO	Set value takes effect at the time of shutdown	-3000~3000	0	PT CST	16 bit	0.1 %
Used to set the target torque of servo drive under the torque mode.									

6072	Parameter name	Accessibility	Data mapping	Setting in force	Data display range	Default value	Correlation mode	Data type	Unit
	Maximum torque Instruction (Max torque)	RW	RPDO	Operation setting Effective immediately	0~3000	3000	ALL	16-bit	0.1 %
Used to set the maximum torque instruction of the servo drive in PT/CST mode.									

6077	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Actual torque (Torque actual value)	RO	TPDO	-	-3000~3000	0	PT CST	16 bit	0.1 %
Used to display the actual torque value of servo drive under the torque mode.									

607A	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Target location (target position)	RW	RPDO	Set value takes effect at the time of shutdown	(-2^{31}) ~ $(2^{31}-1)$	0	CSP HM PP	32 bit	Instruction unit
Used to set the servo target position of the servo drive in the periodic synchronous mode (CSP).									

607C	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Home offset (Home offset)	RW	RPDO	Set value takes effect at the time of shutdown	(-2^{31}) ~ $(2^{31}-1)$	0	HM	32 bit	Instruction unit
Used to set the physical position of the mechanical Origin return mode from the motor origin in home return mode. This object dictionary only takes effect when the servo is powered on, the origin return operation is completed, and the status word 6041 is bit15=1.									

607F	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Maximum profile velocity (Max profile velocity)	RW	RPDO	Set value takes effect at the time of shutdown	0 ~ $(2^{31}-1)$	0	ALL	32 bit	Instruction unit/s
Set the maximum operating speed of user. The set value takes effect when the velocity instruction of slave station changes.									

6081	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Profile velocity (Profile velocity)	RW	RPDO	Set value takes effect at the time of shutdown	0 ~ (2^{31}-1)	218453	PP	32 bit	Instruction unit/s
Set the constant operating speed of the shift instruction under the profile position mode. The set value takes effect after the salve station receives the shift instruction.									

6083	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Profile acceleration (Profile acceleration)	RW	RPDO	Set value takes effect at the time of shutdown	0 ~ (2^{32}-1)	13107200	PP PV	32 bit	Instruction unit/s^2
Set the acceleration under the profile position mode and profile velocity mode. Under the profile position mode, the set value takes effect after the position command is triggered. The minimum value of the periodic position command increment of each position loop is 1. Under the profile velocity mode, the operation takes effect. If the parameter value is set to be 0, it will be converted to 1 compulsorily.									

6084	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Profile deceleration (Profile deceleration)	RW	RPDO	Set value takes effect at the time of shutdown	0 ~ (2^{31}-1)	13107200	PP PV CSP CSV	32 bit	Instruction unit/s^2

Set the deceleration under the profile position mode and profile velocity mode.
Under the profile position mode, the set value takes effect after the position command is triggered.
Under the profile velocity mode, the operation takes effect.
Under PP CSV PV mode, the quick-stop option code (605A) is equal to 1 or 5, the deceleration of slope shutdown takes effect when the quick-stop command is valid;
Under PP CSV PV mode, the halt option code (605D) is equal to 1, the deceleration of slope shutdown takes effect when halt command is valid.

6085	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Quick stop deceleration (Quick stop deceleration)	RW	RPDO	Set value takes effect at the time of shutdown	0 ~ (2^{31}-1)	100	PP PV HM CSP CSV	32 bit	Instruction unit/s^2

Under PP CSV PV HM mode, the quick-stop option code (605A) is equal to 2 or 6, the deceleration of slope shutdown takes effect when the quick-stop command is valid.
Under PP CSV PV HM mode, the halt option code (605D) is equal to 2, the deceleration of slope shutdown takes effect when the halt command is valid.

6086	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Motion profile type (Motion profile type)	RW	RPDO	Set value takes effect at the time of shutdown	2^{15}~ (2^{15}-1)	0	-	16 bit	-

Set the profile type of the motor position command or velocity command.
0: linear
For now, only “0” is supported.

6087	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data tyoe	Unit
	Torque slope (Torque slope)	RW	RPDO	Set value takes effect at the time of shutdown	0 ~ (231-1)	100	PT CST	32 bit	0.1%/s

Set the torque command acceleration under the profile torque mode, which means the torque command increment per second.

6091	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Gear Ratio	-	-	-	-	-	CSP HM PP PV CSV	-	-

Set range of electronic gear ratio: "0.001* encoder resolution/10000, 4000* encoder resolution/10000"

Beyond this set range, Er.35 (electronic gear ratio overrun) will occur in servo drive.

01h	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Dtaa type	Unit
	Electronic gear ratio numerator (Motor revolutions)	RW	RPDO	Set value takes effect at the time of shutdown	1 ~ (2^{32}-1)	1	-	32 bit	-

Used to set the motor resolution.

02h	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Electronic gear ratio denominator (Shaft revision)	RW	RPDO	Set value takes effect at the time of shutdown	1 ~ (2^{32}-1)	1	-	32 bit	-

Used to set the load shaft resolution.

6098	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Zero return mode (Homing method)	RW	RPDO	Set value takes effect at the time of shutdown	1 ~ 35	1	HM	8 bit	-

Used to select homing method.

method	Deceleration point	Origin	method	Deceleration point	Origin
1	Reverse overtravel switch	Motor Z signal	19	Origin switch	Origin switch
2	Forward overtravel switch	Motor Z signal	20	Origin switch	Origin switch
3	Origin switch	Motor Z signal	21	Origin switch	Origin switch
4	Origin switch	Motor Z signal	22	Origin switch	Origin switch
5	Origin switch	Motor Z signal	23	Origin switch	Origin switch
6	Origin switch	Motor Z signal	24	Origin switch	Origin switch
7	Origin switch	Motor Z signal	25	Origin switch	Origin switch
8	Origin switch	Motor Z signal	26	Origin switch	Origin switch
9	Origin switch	Motor Z signal	27	Origin switch	Origin switch
10	Origin switch	Motor Z signal	28	Origin switch	Origin switch
11	Origin switch	Motor Z signal	29	Origin switch	Origin switch
12	Origin switch	Motor Z signal	30	Origin switch	Origin switch
13	Origin switch	Motor Z signal	33	None	Motor Z signal
14	Origin switch	Motor Z signal	34	None	Motor Z signal
17	Reverse overtravel switch	Reverse overtravel switch	35	-	Current position
18	Forward overtravel	Forward overtravel			

	switch	switch			

6099	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Homing speed (Homing speeds)	-	-	-	-	-	HM	-	-
Used to set two speed values in homing mode									
01	**Parameter name**	**Accessibility**	**Data mapping**	**Set to take effect**	**Data display range**	**Default**	**Correlation mode**	**Data type**	**Unit**
	Speed during search for switch (Speed during search for switch)	RW	RPDO	Set value takes effect at the time of shutdown	0 ~ $(2^{32}-1)$	100	HM	32 bit	Instruction unit/s
Used to set the speed of searching deceleration point signal. It is recommended to set the speed to a higher value to prevent Er.44 (back-to-original timeout fault) caused by too long zero return time									
02	**Parameter name**	**Accessibility**	**Data mapping**	**Set to take effect**	**Data display range**	**Default**	**Correlation mode**	**Data type**	**Unit**
	Speed during search for zero (Speed during search for zero)	RW	RPDO	Set value takes effect at the time of shutdown	10 ~ $(2^{32}-1)$	100	HM	32 bit	Instscution unit/s
Used to set the speed of searching origin signal. It is recommended to be set to a lower value to prevent overshoot caused by high-speed stop.									

	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
609A	Home acceleration (Home acceleration)	RW	RPDO	Set value takes effect at the time of shutdown	0 ~ (2^{32}-1)	655360	HM	32 bit	Instruction unit/s

Used to set the acceleration in homing mode. When the origin zero return operation is started, the set value takes effect.

Home acceleration refers to the increment of position command (command unit) per second.

	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
60B0	Position offset (Position offset)	RW	RPDO	Set value takes effect at the time of shutdown	(-2^{31}) ~ (2^{31}-1)	0	CSP	32 bit	Instruction unit

Used to set the servo position command offset amount in the Cyclic Synchronous Position mode (CSP).

After offset, servo target position = 607A (target position) + 60B0 (position offset).

	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
60B2	Torque offset (Torque offset)	RW	RPDO	Set value takes effect at the time of shutdown	(-2^{31}) ~ (2^{31}-1)	0	CST	32 bit	0.1 %

Used to set the servo torque command offset in the cycle synchronous torque mode (CST). The actual target torque command of the servo after offset = 6071 (target torque) + 60B2 (torque offset).

	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
60B8	Touch probe function (Touch probe function)	RW	RPDO	Set value takes effect at the time of shutdown	0~65535	0	-	16 bit	-
Used to set the function of probe 1 and probe 2.									

	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
60B9	Touch probe status (Touch probe status)	RO	TPDO	-	0~65535	0	-	16 bit	-
Used to read the status of probe 1 and probe 2.									

	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
60BA	Probe 1 rising edge position value (Touch Probe Pos1 Pos Value)	RO	TPDO	-	(-2^{31}) ~ $(2^{31}-1)$	0	-	32 bit	Instruction unit
Used to display the rising edge and position value of probe 1 signal (instruction unit).									

60BB	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Probe 1 falling edge position value (Touch Probe Pos1 Neg Value)	RO	TPDO	-	(-2^{31}) ~ $(2^{31}-1)$	0	-	32 bit	Instruction unit
Used to display the falling edge and position value of probe 1 signal (command unit).									

60BC	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Probe 2 rising edge position value (Touch Probe Pos2 Pos Value)	RO	TPDO	-	(-2^{31}) ~ $(2^{31}-1)$	0	-	32 bit	Insturction unit
Used to display the rising edge and position value of probe 2 signal (Instruction unit).									

60BD	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Probe 2 falling edge position value (Touch Probe Pos2 Neg Value)	RO	TPDO	-	(-2^{31}) ~ $(2^{31}-1)$	0	-	32 bti	Instruction unit
Used to display the falling edge and position value of probe 2 signal (command unit).									

60C5	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Maximum acceleration (Max profile accelaration)	RO	TPDO	-	0 ~ $(2^{31}-1)$	0	ALL	32 bti	Instruction unit/s^2

Set the maximum acceleration allowed in the acceleration segment in the profile position mode and profile velocity mode.

60C6	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Maximum deceleration (Max profile decelaration)	RO	TPDO	-	0 ~ $(2^{31}-1)$	0	ALL	32 bti	Instruction/s^2

Set the maximum acceleration allowed in the deceleration segment in the profile position mode and profile velocity mode

60E0	Parameter name	Accessibility	Data mapping	Setting in force	Data display range	Default value	Correlation mode	Data type	Unit
	Forward direction maximum torque limit	RW	RPDO	Operation setting Effective immediately	0 to 3000	3000	ALL	16-bit	0.1%

Set the positive maximum torque limit of the servo.
✎**Note: It takes effect when the parameter P1-14=2.**

60E1	Parameter name	Accessibility	Data mapping	Setting in force	Data display range	Default value	Correlation mode	Data type	Unit
	Reverse direction maximum torque limit	RW	RPDO	Operation setting Effective immediately	0 to 3000	3000	ALL	16-bit	0.1%
Set the negative maximum torque limit of the servo. ✎**Note: It takes effect when the parameter P1-14=2.**									

60F4	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Position deviation (Following error actual value)	RO	TPDO	-	-	-	PP HM CSP	32 bit	Instruction unit
Used to display following error actual value (command unit).									

60FC	Parameter name	Accessibility	Mapped or not	Setting in force	Range	Default value	Correlation mode	Data type	Unit
	Position instruction (Position demand value)	RO	TPDO	-	-	-	PP HM CSP	32-bit	Encoder unit
Used to display the position demand value (encoder unit). When the servo is enabled, if there is no warning, the relationship between the position demand value (encoder unit) and position demand value (command unit) is shown as follows: Position demand value 60FCh (encoder unit) = position demand value 6062h (command unit) * gear ratio (6091h).									

60FD	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	DI status (Digital Input)	RO	TPDO	-	-	-	ALL	32-bit	-
Used to reflect the current DI terminal logic of drive:									

method	Deceleration point	Origin	method	Deceleration point	Origin
0	Reverse overrun switch	0: Invalid	19	DI4	0: Invalid
		1: Valid			1: Valid
1	Forward overrun switch	0: Invalid	20	DI5	0: Invalid
		1: Valid			1: Valid
2	Homing switch	0: Invalid	21	DI6	0: Invalid
		1: Valid			1: Valid
3-15	NA	0: Invalid	22	NA	0: Invalid
		1: Valid			1: Valid
16	DI1	0: Invalid	23	DI8	0: Invalid
		1: Valid			1: Valid
17	DI2	0: Invalid	24	DI9	0: Invalid
		1: Valid			1: Valid
18	SI3	0: Invalid	25-31	NA	0: Invalid
		1: Valid			1: Valid

60FE	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode
	Digital Output Dictionary DigitalDoOutput	RW	RPDO	Operation setting Effective immediately	0~ 65535	0	ALL

60EF-01		
bit	name	description
0-15	retain	-
16	DO_1	0： Forced output OFF
		1: Forced output ON
17	DO_2	0： Forced output OFF
		1: Forced output ON
18	DO_3	0： Forced output OFF
		1: Forced

60EF-02		
bit	name	description
0-15	retain	-
16	DO_1	0： Forced output OFF
		1: Forced output ON
17	DO_2	0： Forced output OFF
		1: Forced output ON
18	DO_3	0： Forced output OFF
		1: Forced

		output ON			output ON
19-31	retain	-	19-31	retain	-

60F4	Parameter name	Accessibility	Data mapping	Set to take effect	Data display range	Default	Correlation mode	Data type	Unit
	Profile velocity	RW	RPDO	-	(-2^{31}) ~ $(2^{31}-1)$	0	PP CSV	32 bit	unit/s
Set the user speed command in the profile speed mode and cycle synchronous speed mode.									

6502	Parameter name	Accessibility	Mapped or not	Setting in force	Range	Default value	Correlation mode	Data type	Unit
	Support servo operation mode (Supported drive modes)	RO	TPDO	-	-	-	-	32-bit	-

Reflect the servo operation mode supported by the drive.

Bit	Description	Support or not 0-Not supported 1-Support
0	Profile Position Mode (PP)	1
1	NA	0
2	Profile Velocity Mode (PV)	1
3	Profile Torque Mode (PT)	1
4	NA	0
5	Homing mode (HM)	1
6	Interpolation mode	0
7	Periodic Synchronous Position Pattern (CSP)	1
8	Cycle Synchronous Speed Mode (CSV)	1

	9	Periodic Synchronous Torque mode (CST)	1	
	10~31	Manufacturer customized	Reserved	

Chapter 9 Adjustments

9.1 Overview

The servo drive needs to make the motor work without delay as much as possible in accordance with the instructions issued by the host controller. In order to make the motor run based on command as much as possible and maximize the mechanical performance, it is necessary to adjust the gain. The flow of gain adjustment is as shown in Figure 9-1.

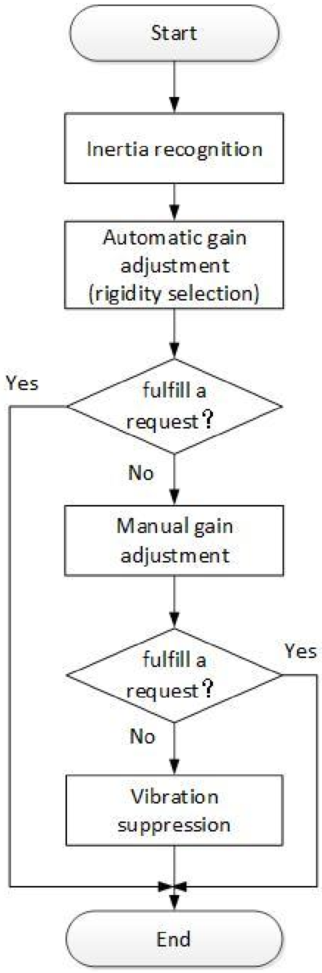


Figure 9-1 Gain adjustment process

The servo gain is composed of multiple sets of parameters such as position loop, speed loop, filter, load inertia ratio, etc., and they affect each other. In the process of setting the servo gain, the balance between the setting values of each parameter must be considered.

Notice
Before adjusting the gain, it is recommended to carry out inching test run first! Ensure that the servo motor can operate normally!

The gain adjustment process description is shown in Table 9-1.

Table 9-1 Gain adjustment process description

Gain adjustment process			Function	Detailed chapter
1	Inertia identification		Automatic load inertia ratio identification is carried out by using the upper computer debugging platform software matched with the drive.	9.2
2	Automatic gain adjustment		On the premise of setting the inertia ratio correctly, the drive automatically adjusts a set of matching gain parameters.	9.3.1
3	Manual gain adjustment	Basic gain	On the basis of automatic gain adjustment, if the expected effect is not achieved, manually fine-tune the gain to optimize the effect.	9.3.2
		Feedforward gain	The feedforward function is enabled to improve the followability.	9.3.3
4	Vibration suppression	Mechanical resonance	The notch filter function is enabled to suppress mechanical resonance.	9.4.1

9.2 Inertia identification

Load inertia ratio "2003-01" refers to:

$$\text{Load inertia ratio} = \frac{\text{Total moment of inertia of mechanical load}}{\text{Moment of inertia of the motor}}$$

Load inertia ratio is an important parameter of servo system. Correct setting of load inertia ratio is helpful to complete debugging quickly.

Notice

Before performing online load inertia identification, the following conditions should be met:

The maximum speed of the motor should be greater than 300rpm;

The actual load inertia ratio is 0.00~Between 100.00;

The load torque is relatively stable, and the load cannot change drastically during the measurement process;

The backlash of the load transmission mechanism is within a certain range;

The motor's movable stroke should meet following two requirements:

There is a movable stroke of more than 1 circle in both forward and reverse directions between the mechanical limit switches. Before performing online inertia identification, please make sure that the limit switch has been installed on the machine, and the motor has a movable stroke of more than 1 circle respectively in the forward and reverse directions to prevent overtravel during the inertia identification process, which may cause accidents.

Meet the requirements of inertia identification turns [2003-05]; make sure that the motor's movable stroke at the stop position is greater than the set value of the number of inertia identification circles [2003-05], otherwise the maximum speed of inertia identification [2003-06] should be appropriately reduced.

During the automatic load inertia identification process, if vibration occurs, the load inertia identification should be stopped immediately.

Related function codes are shown in Table 9-2.

Table 9-2 Details of inertia identification related parameters

Function code	Name	Setting method	valid time	Default	Range	Definition	Unit
2003-01	Load inertia ratio	OperationSetting	valid immediately	300	100~10000	Set load inertia ratio, 0.00~100.00 times	0.01
2003-05	Inertia identificationcircles	Shutdown Setting	valid immediately	2	1~20	Offline load inertia identification process, motor rotation number setting	Circle
2003-06	Maximum speed of inertia identification	Shutdown Setting	valid immediately	1000	300~2000	Set the allowable maximum motor speed instruction in offline inertia identification mode. The faster the speed during inertia identification is, the more accurate the identification result	rpm

Function code	Name	Setting method	valid time	Default	Range	Definition	Unit
						will be. Generally, keep the default value.	
2003-07	Parameter identification of rotation direction	Shutdown Setting	valid immediately	0	0 to 2	0: Forward and reverse reciprocating rotation 1: Forward one-way rotation 2: Reverse one-way rotation	-

9.3 Gain Adjustment

In order to optimize the responsiveness of the servo drive, the gain set in the servo drive needs to be adjusted. Servo gain needs to set multiple parameter combinations, which will affect each other. Therefore, the adjustment of servo gain must consider the relationship between each parameter. Under normal circumstances, high-rigidity machinery can improve the response performance by increasing the servo gain. But for machines with lower rigidity, when the servo gain is increased, vibration may occur, which will affect the increase in gain. Therefore, selecting appropriate servo gain parameters can achieve higher response and stable performance.
The servo supports automatic gain adjustment and manual gain adjustment. It is recommended to use automatic gain adjustment first.

9.3.1 Automatic Gain Adjustment

Automatic gain adjustment means that through the rigidity level selection function [2003-02], the servo drive will automatically generate a set of matching gain parameters to meet the requirements of rapidity and stability.
The rigidity of the servo refers to the ability of the motor rotor to resist load inertia, that is, the self-locking ability of the motor rotor. The stronger the servo rigidity is, the greater the corresponding position loop gain and speed loop gain can achieve, and the faster the response speed of the system will be.

Notice
Before adjusting the rigidity grade, set the appropriate load inertia ratio correctly [2003-01].

The value range of rigidity grade is between 0~ 31. The value range of the rigidity grade is between 0 and 31. Grade 0 corresponds to the weakest rigidity and minimum gain, and grade 31 corresponds to the strongest rigidity and maximum gain. According to different load types,Table 9-3 Empirical values can be used for reference.

Table 9-3 Experience reference of rigidity grade

Rigidity grade	Load mechanism type
Grade 4 to 8	Some large machinery
Grade 8 to 15	Low rigidity applications such as belts
Grade 15 to 20	High rigidity applications such as ball screw and direct connection

When the function code [2003-03] is set to 0, the gain parameters are stored in the first gain by modifying the rigidity grade.
When debugging with the upper computer debugging software, automatic rigidity level measurement can be carried out, which is used to select a set of appropriate rigidity grades as operating parameters. The operation steps are as follows:
Step 1 Confirm that the servo is in the ready state, the panel displays “ry”, and the communication line is connected;
Step 2 Open the servo drive debugging software, enter the trial run interface, set the corresponding parameters, and click "Servo on";

Step 3 Click the “forward" or “reverse" button to confirm the travel range of the servo operation;
Step 4 After the "Start Identification" of inertia identification lights up, click "Start Identification" to start inertia identification to measure the load inertia.
Step 5 After the inertia identification test is completed, click "Save inertia value";
Step 6 Click "Next" at the bottom right to go to the parameter adjustment interface, click "Parameter Measurement" to start parameter measurement.
Step 7 After the parameter measurement is completed, the servo drive debugging software will pop up a confirmation window for parameter writing and saving.

There may be a short mechanical whistling sound during the test. Generally, the servo will automatically stop the test. If it does not stop automatically or in other abnormal situations, you can click the "Servo Off" button on the interface to turn off the servo, or power off the machine! For the detailed operation of the upper computer debugging software, please refer to "Wecon SCTool Software User Manual".

Table 9-4 Self-tuning mode selection parameter details

Index code	Name	Setting method	Valid time	Default	Range	Definition	Unit
2003-03	Self-adjusting mode selection	OperationSetting	Valid immediately	0	0 to 2	0: Rigidity grade self-adjusting mode. Position loop gain, speed loop gain, speed loop integral time constant, torque filter parameter settings are automatically adjusted according to the rigidity grade setting. 1: Manual setting. Users need to manually set the position loop gain, speed loop gain, speed loop integral time	-

Index code	Name	Setting method	Valid time	Default	Range	Definition	Unit
						constant, and torque filter parameter setting 2: Online automatic parameter self-adjusting mode (Not implemented yet)	

9.3.2 Manual Gain Adjustment

When the servo automatic gain adjustment fails to achieve the desired result, you can manually fine-tune the gain to achieve better results.
The servo system consists of three control loops, from the outside to the inside are the position loop, the speed loop and the current loop. The basic control block diagram is shown as below.

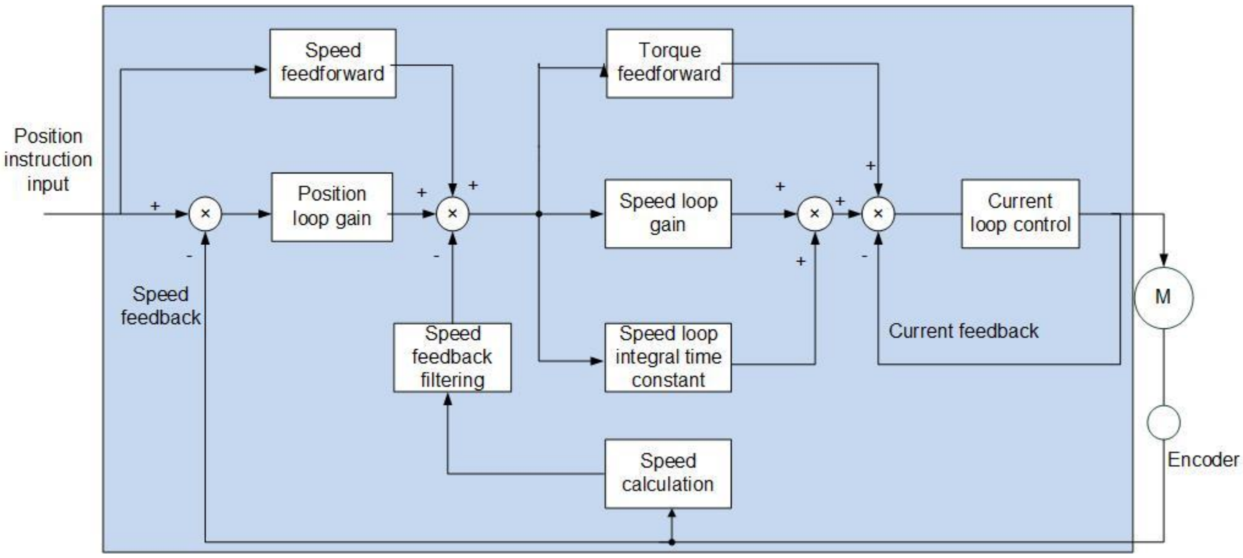


Figure 9-2 Basic block diagram of servo loop gain

The more the inner loop is, the higher the responsiveness is required. Failure to comply with this principle may lead to system instability!
The default current loop gain of the servo drive has ensured sufficient responsiveness, generally no adjustment is required, only the position loop gain, speed loop gain and other auxiliary gains need to be adjusted.

(1) Speed loop gain

The speed loop gain determines the highest frequency of the changing speed command that the speed loop can follow.
In the case of no vibration or noise in the mechanical system, the larger the speed loop gain setting value is, the better the response of servo system and the better the speed followability can achieve.

When noise occurs in the system, reduce the speed loop gain. Related function codes are shown in Table 9-5.

Table 9-5 Details of speed loop gain parameters

Index code	Name	Setting method	Valid time	Default	Range	Definition	Unit
2002-02	1st speed loop gain	OperationSetting	Valid immediately	65	0~35000	Set the speed loop proportional gain to determine the responsiveness of the speed loop.	0.1Hz

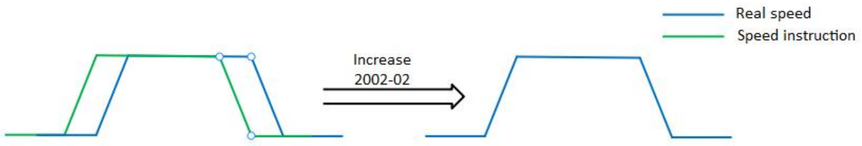


Figure 9-3 Gain Effect Schematic Diagram of Velocity Loop

(2) Speed loop integral time constant

The speed loop integral time constant is used to eliminate the speed loop deviation. Decreasing the integral time constant of the speed loop can increase the speed of the speed following. If the set value is too small, is will easily cause speed overshoot or vibration. When the setting value of time constant is too large, the integral action will be weakened, resulting in a deviation of the speed loop. Related function codes are shown in Table 9-6.

Table 9-6 Details of speed loop integral time constant parameters

Index code	Name	Setting method	Valid time	Default	Range	Definition	Unit
2002-03	speed loop 1st integral time	OperationSetting	Valid immediately	1000	100~65535	Set the speed loop integral constant. The smaller the set value is, the stronger the integral effect will be.	0.1ms

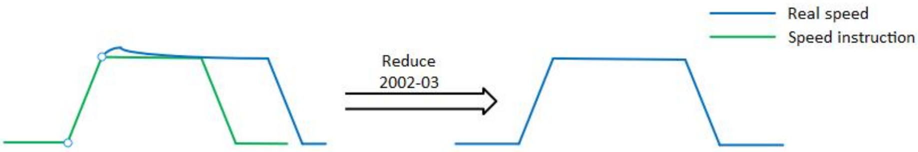


Figure 9-4 Sketch for the effect of integrating time constant of velocity loop

(3) Position loop gain

Determine the highest frequency of the position command that the position loop can follow the change. Increasing this parameter can speed up the positioning time and improve the ability of the motor to resist external disturbances when the motor is stationary. However, if the setting value is too large, the system may be unstable and disrupted. Related function codes are shown in Table 9-7.

Table 9-7 Details of position loop gain parameters

Index code	Name	Setting method	Valid time	Default	Range	Definition	Unit
2002-01	1st position loop gain	OperationSetting	Valid immediately	400	0~6200	Set the position loop proportional gain to determine the responsiveness of the position control system.	0.1Hz

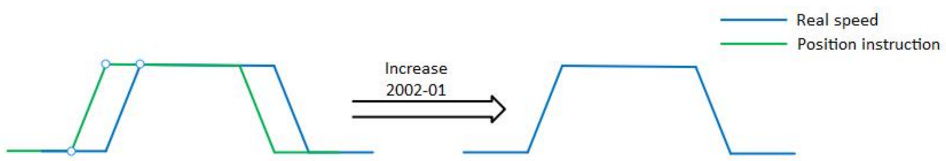


Figure 9-5 Gain effect schematic diagram of position loop

(4) Torque instruction filter time

Selecting an appropriate torque filter time constant could suppress mechanical resonance. The larger the value of this parameter, the stronger the suppression ability. If the setting value is too large, it will decrease the current loop response frequency and cause needle movement. Related function codes are shown in Table 9-8.

Table 9-8 Details of torque filter time constant parameters

Index code	Name	Setting method	Valid time	Default	Range	Definition	Unit
2004-04	Torque filtering time constant	Operation Setting	Valid immediately	50	10~2500	This parameter is automatically set when "Self-adusting Mode Selection" is selected as 0	0.01ms

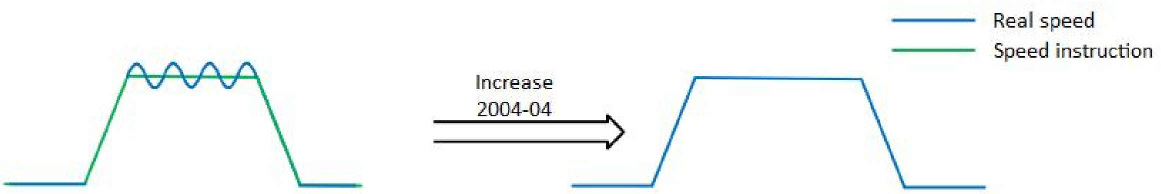


Figure 9-6 Time Constant Effect Schematic Diagram of Torque Filtering

9.3.3 Feedforward Gain

Speed feedforward could be used in position control mode and full closed-loop function. It could improve the response to the speed instruction and reduce the position deviation with fixed speed. Speed feedforward parameters are shown inTable 9-9. See Table 9-10 for details of torque feedforward parameters.

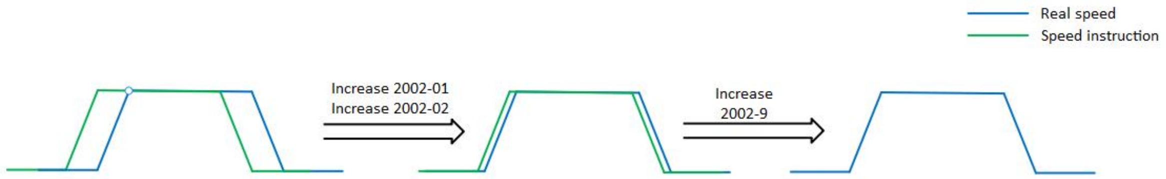


Figure 9-7 Effect schematic of speed feedforward parameters

Table 9-9 Speed feedforward parameters

Index code	Name	Adjustment description
2002-09	Speed feedforward gain	When the speed feedforward filter is set to 50 (0.5 ms), gradually increase the speed feedforward gain, and the speed feedforward will take effect. The position deviation during operation at a constant speed becomes smaller according to the value of the speed feedforward gain as shown in the following formula. Position deviation (pulse instruction) = instruction speed [instruction unit/s] ÷position loop gain [1/s] × (100 — speed feedforward gain [%]) ÷100
2002-0A	Speed feedforward filtering time constant	

Torque feedforward can improve torque command response and reduce position deviation during fixed acceleration and deceleration.

Table 9-10 Torque feedforward parameters

Index code	Name	Adjustment description
2002-0B	Torque feedforward gain	Increase the torque feedforward gain, because the position deviation during certain acceleration and deceleration can be close to 0, so under the ideal condition that the torque does not act when the external disturbance occurs, when driving under the trapezoidal speed model, the position deviation can be made in the entire action range close to 0. In fact, there must be external disturbance torque, so the position deviation cannot be 0. In addition, like the speed feedforward, the larger the constant of the torque feedforward filter is, the smaller the action will be, with greater positional deviation of the acceleration change point.
2002-0C	Torque feedforward filter time constant	

9.3.4 Model tracking control function

Model tracking control is suitable for position control mode. A model loop is added in addition to the three loops. In the model loop, new control quantities such as position instruction, speed feedforward and torque feedforward are generated according to the user's response requirements to the system and the ideal motor control model. Applying these control variables to the actual control loop can significantly improve the response performance and positioning performance of position control. The design block diagram is as follows.

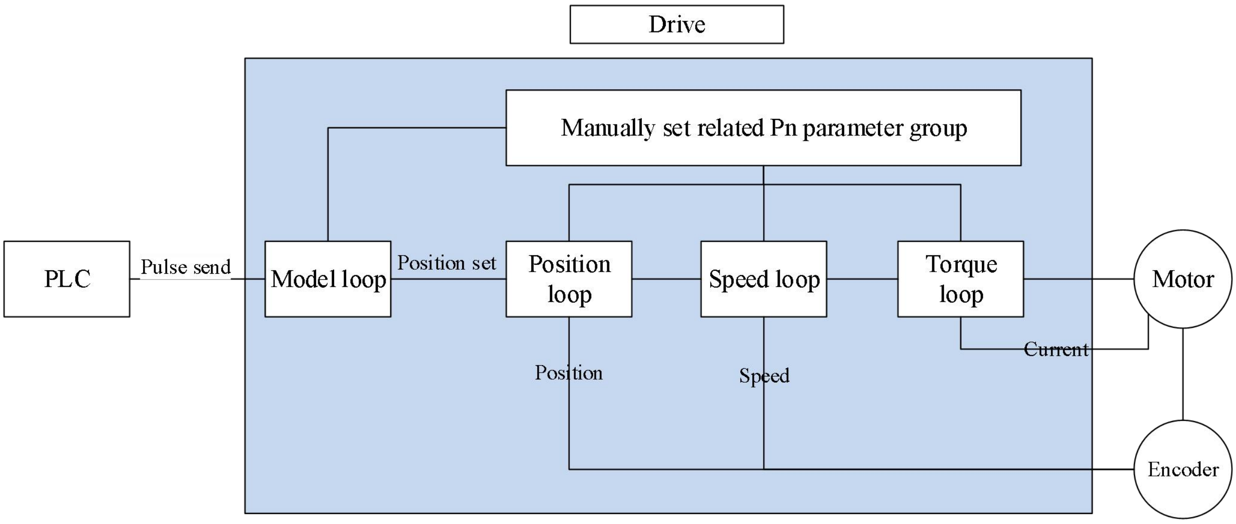


Figure 9-8 Block diagram of model tracking control design

Use methods and conditions of model tracking control:

① Correctly set the inertia ratio P3-1 of the system, which can be obtained by monitoring the real-time load inertia ratio U0-20;

② Set the load rigidity level P3-2 and set an appropriate value. There is no need to set a high rigidity level (the recommended value with rigid load is 17-21);

③ Set P2-20=1 to turn on the function of model tracking control;

④ Adjust the tracking control gain of P2-21 model from small to large, which can be gradually increased according to the step amount of 1000 until the responsiveness of the system meets the actual demand. The responsiveness of the system is mainly determined by this parameter;

⑤ After the responsiveness meets the requirements, appropriate adjustments can be made to improve the load rigidity level P3-2.

Note: Model tracing control is only available in position mode and not available in other modes.

Index code	Name	Setting method	Effective time	Default	Range	Definition	Unit
2002-14	Model tracking control enabled	Stop settings	Immediately	0	0 to 1	Set 1 to enable model tracking control features	--
2002-15	Model tracking control gain	Stop settings	Immediately	1000	200 to 20000	Increasing the model tracking control gain can improve the position response performance of the model loop. Too high gain may cause overshoot behavior. Gain compensation affects the damping ratio of the model loop, and the damping ratio becomes larger with the increase of gain compensation.	0.1/s
2002-16	Model tracking control gain compensation	Stop settings	Immediately	1000	500 to 2000		0.10%
2002-17	Model tracking control forward direction offset	Operation settings	Immediately	1000	0 to 10000	Magnitude of torque feedforward in forward and reverse directions in model tracking control	0.10%
2002-18	Model tracking control reverse direction offset	Operation settings	Immediately	1000	0 to 10000		0.10%
2002-19	Model tracking control speed feedforward compensation	Operation settings	Immediately	1000	0 to 10000	Velocity feedforward magnitude under model tracking control	0.10%

Please refer to the following table for examples of steps for adjusting servo gain.

Step	Content
1	Please try to set the correct load inertia ratio parameter P3-1.
2	If the automatic adjustment mode is adopted (P3-3 is set to 0), please set the basic rigidity level parameter P3-2;

Step	Content
	If the mode is adjusted manually (P3-3 is set to 1), please set the gain related to the position loop and the speed loop P2-1~P2-3 and torque filtering time constant P4-4. The setting principle is mainly non-vibration and overshoot.
3	Turn on the model tracking function P2-20 and set it to 1.
4	In the range where overshoot and vibration do not occur, improve the model tracking gain P2-21.
5	If the rigidity level of step 2 is relatively low, the rigidity level P3-2 can be appropriately increased.
6	When overshoot occurs, or when the responses of forward and reverse are different, fine-tuning is performed by model tracking control forward direction offset P2-23, model tracking control reverse direction offset P2-24, and model tracking control speed feedforward compensation P2-25.

9.3.5 Gain switching

Gain switching function:

① It can be switched to a lower gain when the motor is stationary (servo enabled) to suppress vibration;

② It can be switched to higher gain when the motor is stationary to shorten the positioning time;

③ It can be switched to higher gain in the running state of the motor to obtain better instruction tracking performance;

④ Different gain settings can be switched through external signals according to load equipment conditions, etc.

(1) Gain switching parameter setting

① When P02-07=0

Fixed to the first gain (i.e. using P02-01 to P02-03), P/PI (proportional/proportional integral) control switching can be realized through DI function 10 (GAIN-SEL, gain switching).

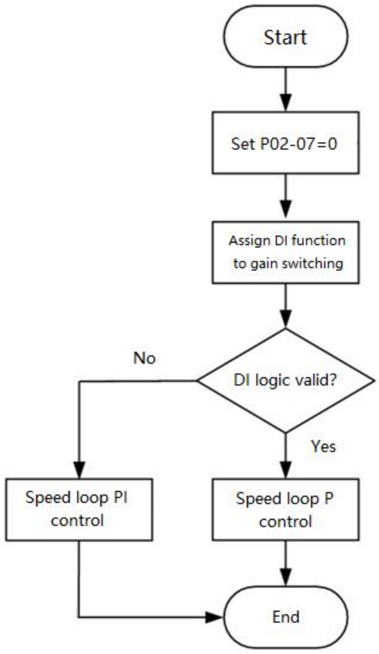


Figure 9-9 Gain switching flowchart when P02-07=0

② When P02-07=1

Achieve the first gain (P02-01 to P02-03) and second gain (P02-04 to P02-06), the switching condition can be set by parameter P02-08.

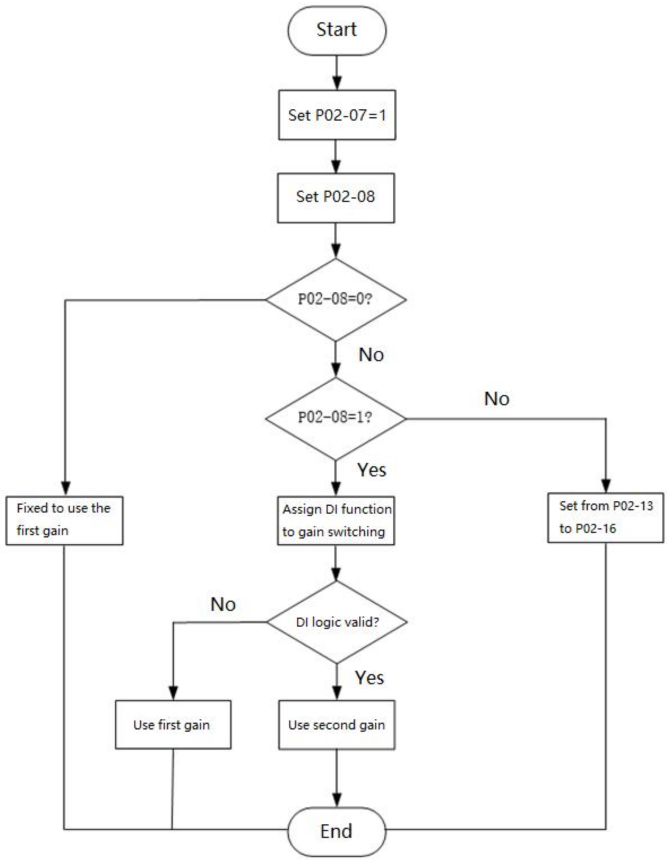
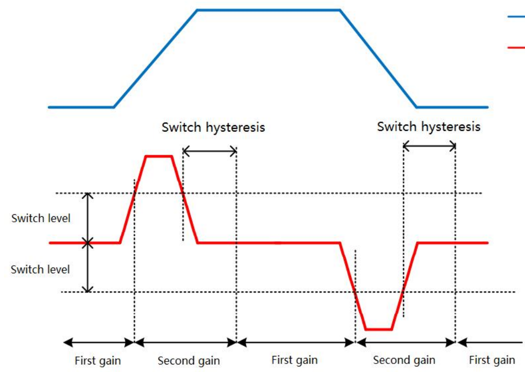
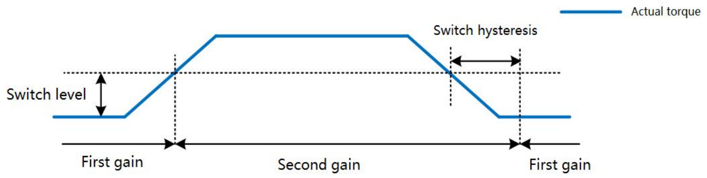
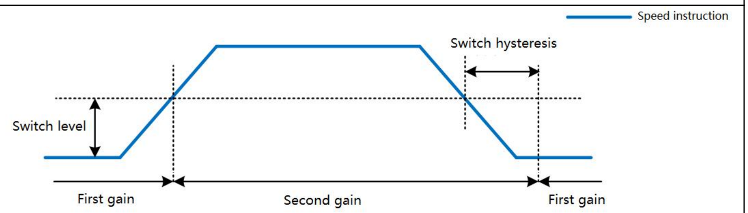
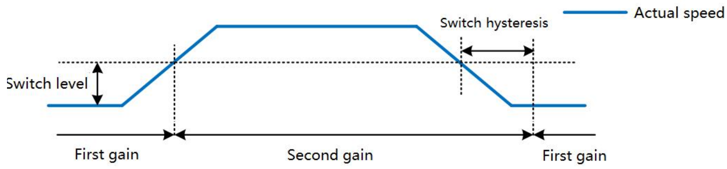
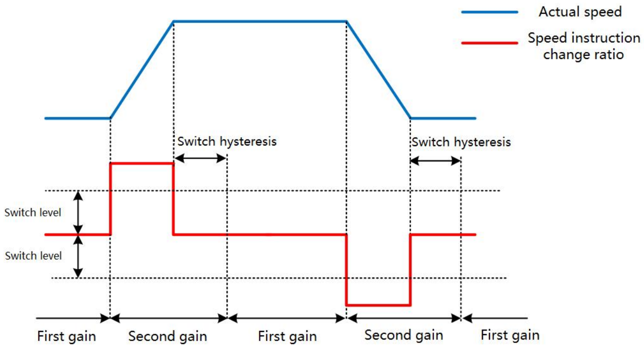
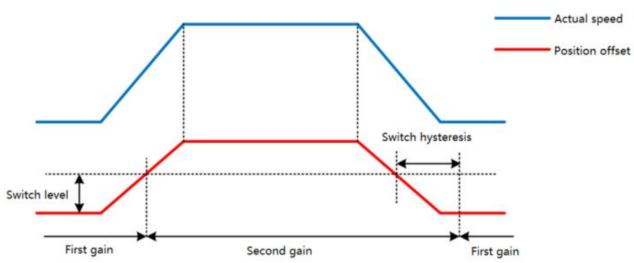
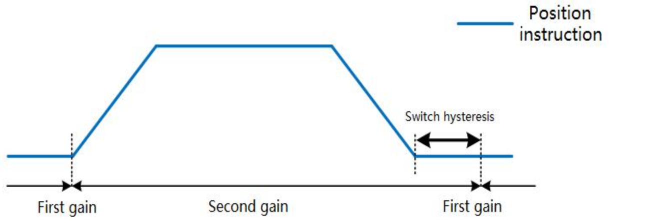
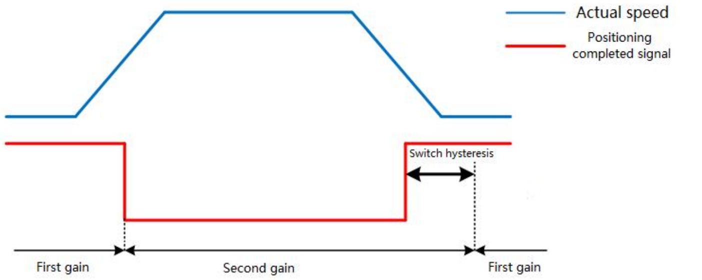
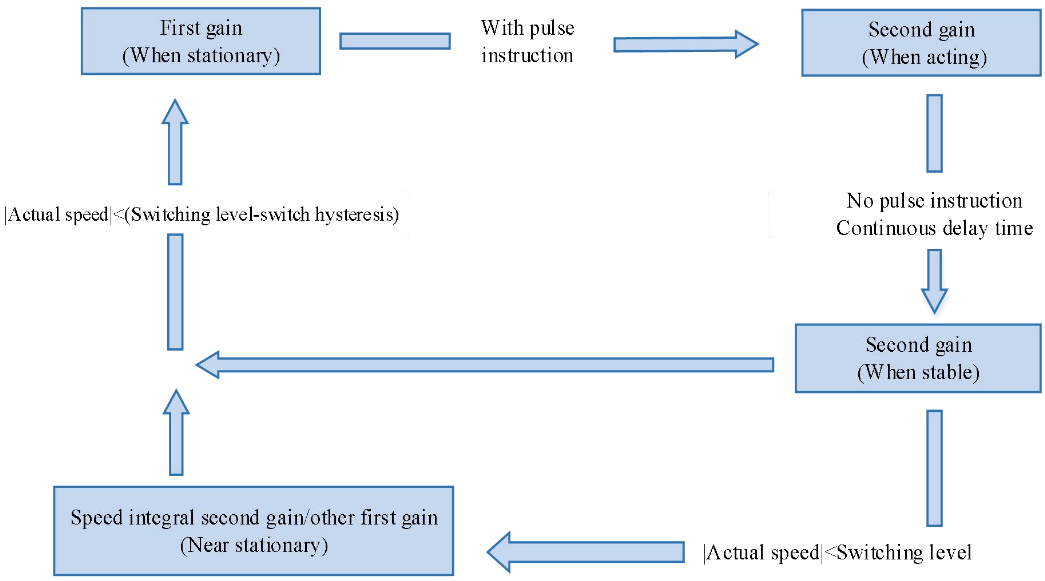


Figure 9-10 Flowchart of gain switching when P02-07=1

P02-08	Content	Schematic diagram
0	Fixedly used first gain	--
1	Switching with DI	--
2	When torque instruction is larger	
3	When actual torque is larger	
4	When speed instruction is larger	
5	When actual speed is larger	
6	When speed instruction change rate is larger	
7	When position deviation is larger	

P02-08	Content	Schematic diagram
8	There is a position instruction	
9	Positioning completed	
10	With position instruction+actual speed	The description is made with reference to figure 7-10. In the previous first gain, if the position Instruction is not 0, switching to the second gain; In the previous second gain, if the status in which the position instruction is 0 continues during the delay time, keeping the second gain; When the delay time reaches, if the absolute value of the current actual speed is less than (level), the speed integration time constant is fixed at the second integration time constant, and the rest are returned to the first gain. If the absolute value of the actual speed is less than (level-hysteresis), all are returned to the first gain.



(2) Description of relevant parameters

2002-07	Parameter name	Setting method	Effective time	Default	Range	Application category	Unit
	2nd gain switching mode	Operation setting	Effective immediately	1	0 to 1	Gain control	

The switching mode of the second gain is set.

Setting value	Function
0	First gain fixed Use DI function 10 (GAIN-SEL, gain switching) to switch. DI logic invalid: PI control; DI logic valid: P Control.
1	The first gain and the second gain are switched by the set value of P02-08.

2002-08	Parameter name	Setting method	Effective time	Default	Range	Application category	Unit
	Gain switching condition selection	Operation setting	Effective immediately	0	0 to 10	Gain control	

Set the conditions for gain switching.

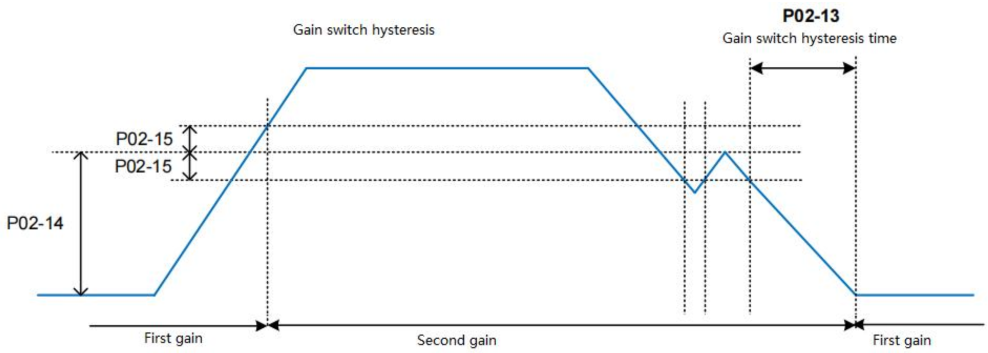
Setting value	Gain switching condition	Details
0	First gain fixed	First gain fixed
1	Switch by DI terminal	Use DI function 10 (GAIN-SEL, gain switching). DI logic invalid: First gain (P02-01-P02-03); DI logic valid: Second gain (P02-04-P02-06).
2	Larger torque instruction	In the previous first gain, when the absolute value of the torque instruction exceeds (level+hysteresis), switching to the second gain; In the previous second gain, when a status in which the absolute value of the torque instruction is less than (level-hysteresis) continues during the delay time, the second gain is returned to the first gain.

3	When actual torque is larger	In the previous first gain, when the absolute value of the actual torque exceeds (level+hysteresis), switching to the second gain; In the second gain of the previous time, when a state in which the absolute value of the actual torque is less than (level-hysteresis) continues during the delay time, the second gain is returned to the first gain.
4	When speed instruction is larger.	In the previous first gain, when the absolute value of the speed command exceeds (level+hysteresis), switching to the second gain; When the state where the absolute value of the speed instruction is less than (level-hysteresis) in the previous second gain continues during the delay time, the gain returns to the first gain.
5	When actual speed is larger	In the previous first gain, when the absolute value of the actual speed exceeds (level+hysteresis), switching to the second gain; In the second gain of the previous time, when a status in which the absolute value of the actual speed is less than (level-hysteresis) continues during the delay time, the first gain is returned to the first gain.
6	When speed instruction change rate is larger.	In the previous first gain, when the absolute value of the speed command change rate exceeds (level+hysteresis), switching to the second gain; In the previous second gain, when a status in which the absolute value of the speed command change rate is less than (level-hysteresis) continues during the delay time, the gain is returned to the first gain.
7	When position deviation is larger	In the previous first gain, when the absolute value of the position deviation exceeds (level+hysteresis), switching to the second gain; In the previous second gain, when a status in which the absolute value of the position deviation is less than (level-hysteresis) continues during the delay time, the gain is returned to the first gain.
8	There is a position instruction	In the previous first gain, if the position Instruction is not 0, switching to the second gain; If the state where the position instruction is 0 continues during the delay time in the previous second gain, the

		gain returns to the first gain.
9	Positioning completed	In the previous first gain, if the positioning is not complete, switching to the second gain; In the second gain of the previous time, if the positioning incomplete status persists during the delay time, the first gain is returned.
10	With position instruction+actual speed	In the previous first gain, if the position Instruction is not 0, switching to the second gain; In the previous second gain, if the state in which the position instruction is 0 continues during the delay time, maintaining the second gain; When the delay time reaches, if the absolute value of the current actual speed is less than (level), the speed integration time constant is fixed at the second integration time constant, and the rest are returned to the first gain. If the absolute value of the actual speed is less than (level-hysteresis), all are returned to the first gain.

2002-0C	Parameter name	Setting method	Effective time	Default	Range	Application category	Unit
	Gain switching delay time	Operation setting	Effective immediately	20	0 to 10000	Gain control	0.1ms

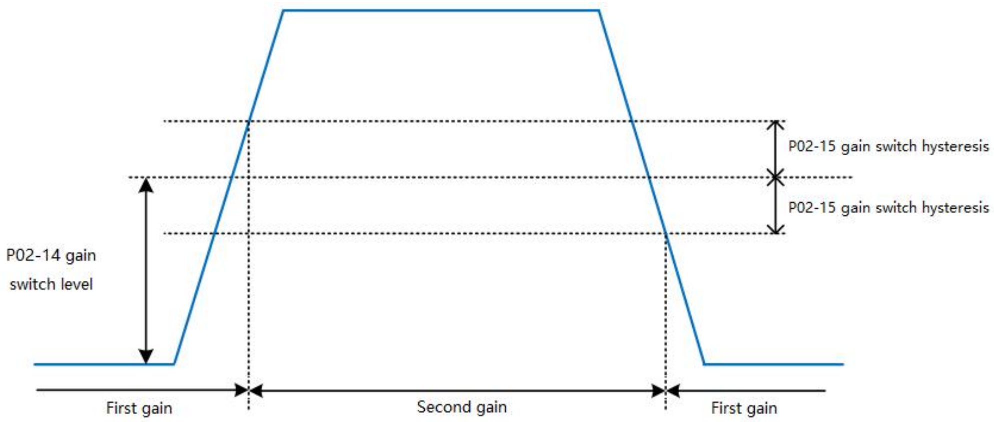
When the second gain is set to switch back to the first gain, the time switching condition needs to last.



✎**Note:** This parameter is valid only when the second gain is switched back to the first gain.

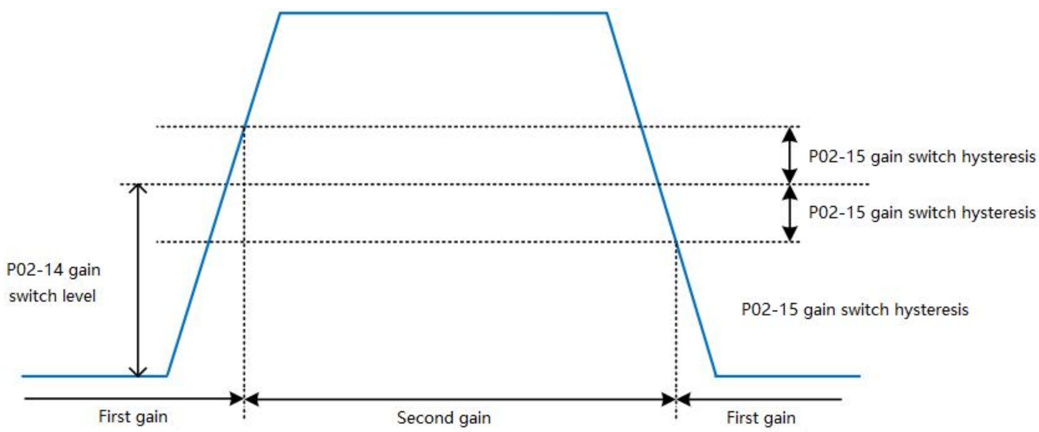
2002-0D	Parameter name	Setting method	Effective time	Default	Range	Application category	Unit
	Gain switching level	Operation setting	Effective immediately	50	0 to 20000	Gain control	According to the switching condition

Set the level of the gain condition. The actual switching action is affected by two conditions: level and hysteresis.



2002-0E	Parameter name	Setting method	Effective time	Default	Range	Application category	Unit
	Gain switching hysteresis	Operation setting	Effective immediately	20	0 to 20000	Gain control	According to the switching condition

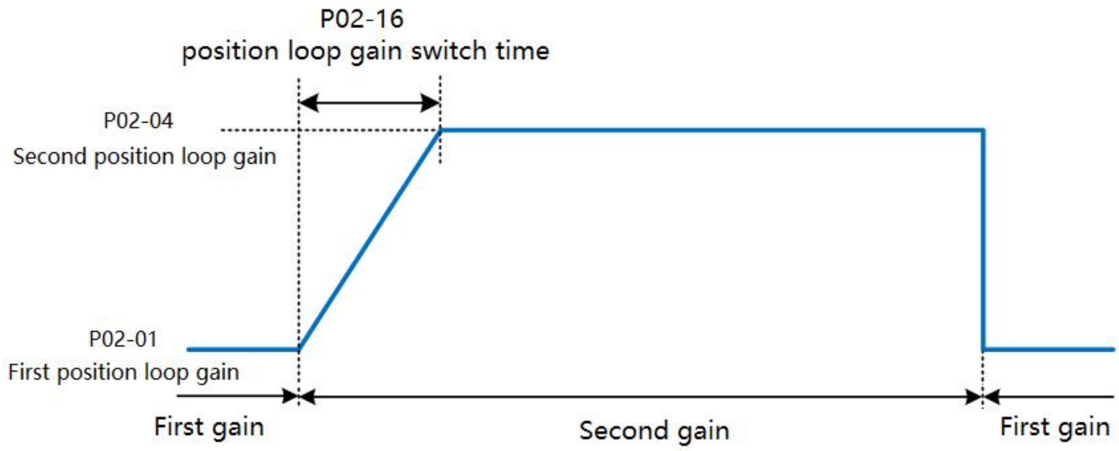
Set the hysteresis that satisfies the gain switching condition.



2002-10	Parameter name	Setting method	Effective time	Default	Range	Application category	Unit
	Position	Operation	Effective	30	0 to	Gain	0.1ms

	gain switching time	setting	immediately		10000	control	

The time is set at which the first position loop (P02-01) is switched to the second position loop (P02-04) in the position control mode.



If P02-04≤P02-01, this parameter is invalid and immediately switches to the second gain.

9.4 Mechanical Resonance Suppression

9.4.1 Mechanical Resonance Suppression Methods

When the mechanical rigidity is low, vibration and noise may occur due to resonance caused by shaft twisting, and it may not be possible to increase the gain setting. In this case, by using a notch filter to reduce the gain at a specific frequency, the servo gain can continue to increase after the resonance is validly suppressed. There are 2 methods to suppress mechanical resonance.

(1) Torque instruction filter

By setting the filter time constant, the torque instruction is attenuated in the high frequency range above the cutoff frequency, so as to achieve the expectation of suppressing mechanical resonance. The cut-off frequency of the torque instruction filter could be calculated by the following formula:

$$\text{Filter cutoff frequency} fc(Hz) = \frac{1}{2\,\pi\ * \text{Set parameter value} * 0.001}$$

(2) Notch filter

The notch filter can achieve the expectation of suppressing mechanical resonance by reducing the gain at a specific frequency. When setting the notch filter correctly, the vibration can be validly suppressed. You can try to increase the servo gain. The principle of notch filter is shown in Figure Figure 9-8.

9.4.2 Notch Filter

VD3E Ethernet servo drivehave 2 sets of notch filters, each of which has 3 parameters, namely notch frequency, width grade and depth grade.

(1) Width grade of notch filter

The notch width grade is used to express the ratio of the notch width to the center frequency of the notch:

$$\text{Notch filter width grade} = \frac{f_H - f_L}{f_T} \qquad (9\text{-}1)$$

In formula (9-1), f_TIt is the center frequency of notch filter, that is, the mechanical resonance frequency; $f_H - f_L$is the width of notch filter, which represents the frequency bandwidth with an amplitude attenuation rate of -3dB relative to the center frequency of notch filter.

(2) Depth grade of notch filter

The depth grade of notch filter represents the ratio relationship between input and output at center frequency.

When the depth level of notch filter is 0, the input is completely suppressed at the center frequency; When the notch filter depth level is 100, the input is completely passable at the center frequency. Therefore, the smaller the the notch filter depth grade is set, the deeper the the notch filter depth will be, and the stronger the suppression of mechanical resonance can achieve, but it may lead to system instability, so attention should be paid when using it. Specific relationships are shown in Figure 9-9.

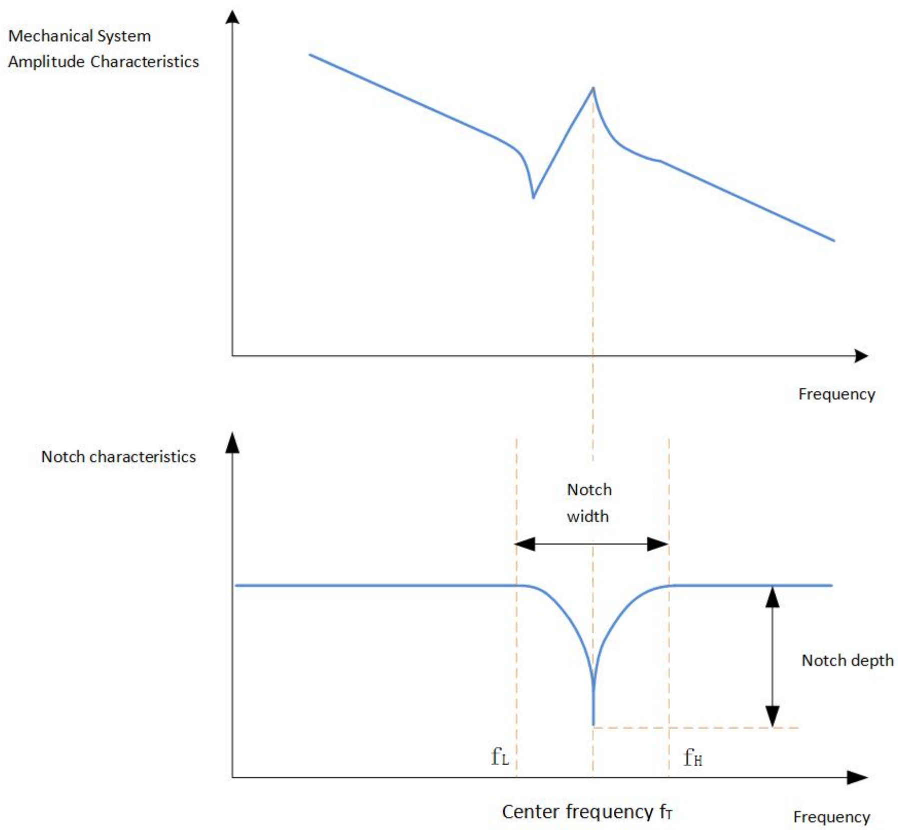


Figure 9-8 Notch characteristics, notch width and notch depth

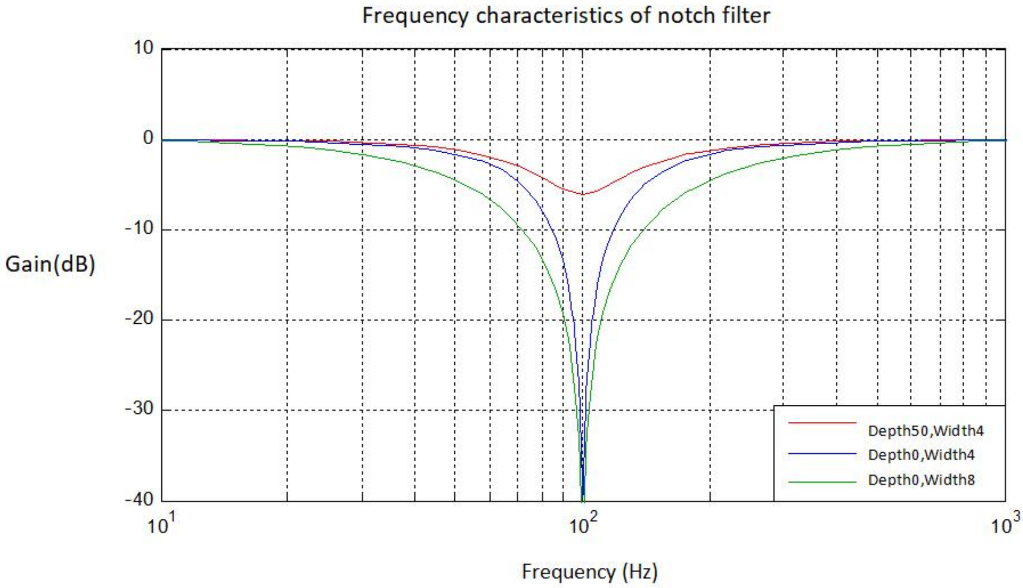


Figure 9-9 Frequency characteristics of notch filter

Table 9-11 Details of notch filter function code parameters

Index code	Name	Setting method	Valid time	Default	Range	Definition	Unit
2004-05	1st notch filter frequency	Operation Setting	Valid immediately	300	250~5000	Set the center frequency of the 1st notch filter. When the set value is 5000, the function of the notch filter is invalid.	Hz
2004-06	1st notch filter depth	Operation Setting	Valid immediately	100	0~100	0: all truncated 100: All passed	-
2004-07	1st notch filter width	Operation Setting	Valid immediately	4	0~12	0: 0.5 times the bandwidth 4: 1 time the bandwidth 8: 2 times the bandwidth 12: 4 times the bandwidth	-
2004-08	2nd notch filter frequency	Operation Setting	Valid immediately	500	250~5000	Set the center frequency of the 2nd notch filter. When the set value is	Hz

						5000, the function of the notch filter is invalid.	
2004-09	2nd notch filter depth	Operation Setting	Valid immediately	100	0~100	0: All truncated 100: All passed	-
2004-0A	2nd notch filter width	Operation Setting	Valid immediately	4	0~12	0: 0.5 times the bandwidth 4: 1 time the bandwidth 8: 2 times the bandwidth 12: 4 times the bandwidth	-

Chapter 10 Malfunctions

10.1 Faults and Warnings Handling at Startup

<table>
<tr><th>Boot process</th><th>Fault phenomenon</th><th>Reason</th><th>Confirmation method</th></tr>
<tr><td rowspan="4">Power supply (L1, L3)</td><td rowspan="2">① Digital tube is not bright
② Not display "ry"</td><td>① The power terminal is disconnected</td><td>☆Rewiring</td></tr>
<tr><td>② Servo drive failure</td><td>☆Contact technician for repair</td></tr>
<tr><td>Panel display "Er.xx"</td><td colspan="2">Refer to"10.2 Faults and warnings handling during operation" to find the cause and troubleshoot</td></tr>
<tr><td colspan="3">After troubleshooting, the servo drive panel should display"ry"</td></tr>
</table>

10.2 Faults and Warnings Handling During Operation

10.2.1 Overview

The faults and warnings of Wecon VD3E series servo drives are graded according to their severity, which can be divided into four grades: Category 1, Category 2, Category 3, Category 4.

Severity level: Category 1> Category 2> Category 3 > Category 4. The specific types are as follows:

Category 2: non-clearable faults;

Category 2: clearable faults;

Category 3: clearable faults;

Category 4: clearable warning.

Among them, "clearable" means that the panel stops the fault display state by giving a "clear signal". The specific operations are as follows:

① Set the parameters 200A-03=1 (fault clearing) or use DI function 02 (02-A-CLR, fault and warning clearing) and set it to logic valid, which can stop the fault display on the panel.

② The clearing method of category 2 and category 3 clearable faults: first turn off the servo enable signal (set S-ON to OFF), then set P10-03=1 or use DI function 2.

③ The clearing method of category 4 of clearable warnings: set 200A-03=1 or use DI function 2.

Notice
For some faults and warnings, please change the settings to eliminate the causes before they can be cleared, but clearing does not mean that the changes take effect. For the changes that need the device to be re-powered to take effect, the device must be re-powered; for the changes that need to stop the device to take effect, the servo must be disabled. After the changes take effect, the servo drive is running normally.

Associated function code:

Function code	Name	Setting method	Valid time	Default	Range	Definition
200A-03=1	Fault clearing	Operation Setting	Valid immediately	0	0 to 1	0: No operation 1: For clearable faults, after the cause of fault is removed, and write 1 to the function code, the drive will stop the fault display and enter the Rdy (or RUN) state again. ✎**Note: If the servo S-ON is valid, when the fault is removed and cleared, the servo will directly enter the Run state. When performing fault clearing actions, be sure to stop sending control instructions such as pulses to ensure personal safety.**

Associated function number:

Number	Name	Function name	Function
2	A-CLR	Fault and warning clear	Invalid, does not reset faults and warnings valid, reset faults and warnings

Wecon VD3E series bus servo drives have a fault recording function, which could record the latest 5 faults and the latest 5 warning names and the status parameters of servo drive when the fault or warning occurs. After the fault or warning is cleared, the fault record will still save the fault and warning.

The current fault code could be viewed through the monitoring parameter U1-01, and the current warning code could be viewed through U1-02. The monitoring U1-16 to U1-25 could display the latest 5 fault codes and warning codes. Please refer to "201Fh Group: warning monitoring".

10.2.2 Fault and warning code тable

Category	Fault/warning name	Fault code	Can it be cleared
Category 1	Parameter damage	Er.01	No
Category 1	Parameter storage error	Er.02	No
Category 1	ADC reference source error	Er.03	No
Category 1	AD current sampling conversion error	Er.04	No
Category 1	Abnormal FPGA communication	Er.05	No
Category 1	Wrong FPGA program version	Er.06	No
Category 1	Clock abnormal	Er.07	No
Category 1	ADC conversion undone	Er.60	No
Category 1	Internal software fault	Er.61	No
Category 1	Internal software fault	Er.62	No
Category 1	Internal software fault	Er.63	No
Category 1	Internal software fault	Er.64	No
Category 1	Internal software fault	Er.65	No
Category 1	Wrong motor model	Er.26	No
Category 1	Encoder Z pulse lost	Er.28	No
Category 1	Encoder UVW signal error	Er.30	No
Category 1	Exceeding motor maximum speed	Er.32	No
Category 1	Overcurrent	Er.20	No
Category 1	The braking resistor is turned on abnormally	Er.24	No
Category 1	Encoder disconnected	Er.27	Yes
Category 2	Main power supply overvoltage	Er.22	Yes
Category 2	Power line disconnected	Er.31	Yes

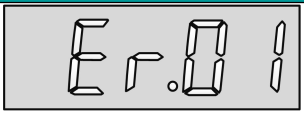
Category	Fault/warning name	Fault code	Can it be cleared
Category 2	Abnormal Internet status switching	Er.09	Yes
Category 2	Synchronization loss	Er.10	Yes
Category 2	Unburned XML configuration file	Er.11	Yes
Category 2	Network initialization failed	Er.12	Yes
Category 2	Synchronization period setting error	Er.13	Yes
Category 2	Synchronization period error is too large	Er.14	Yes
Category 3	Main power supply is undervoltage	Er.21	Yes
Category 3	Braking resistor is not connected	Er.23	Yes
Category 3	The resistance of the brake resistor is excessive.	Er.25	Yes
Category 3	Power module is over temperature	Er.33	Yes
Category 3	Motor overload protection	Er.34	Yes
Category 3	Electronic gear ratio exceeds limit	Er.35	Yes
Category 3	Excessive position deviation	Er.36	Yes
Category 3	Abnormal torque saturation	Er.37	Yes
Category 3	Main circuit electrical phase loss	Er.38	Yes
Category 3	Emergency stop	Er.39	Yes
Category 3	Encoder battery failure	Er.40	Yes
Category 3	Motor (encoder) over temperature	Er.41	Yes
Category 3	Encoder write failure	Er.42	Yes
Category 3	Homing timeout fault	Er.44	Yes
Category 3	Drive stall over temperature	Er.45	Yes
Category 4	Over speed alarm	A-81	Yes
Category 4	Overload	A-82	Yes

Category	Fault/warning name	Fault code	Can it be cleared
Category 4	Braking resistor is over temperature or overload	A-83	Yes
Category 4	Parameter modification that needs to be powered on again	A-84	Yes
Category 4	Main circuit instantaneous power failure	A-88	Yes
Category 4	Duplicate DI port configuration	A-89	Yes
Category 4	Duplicate DO port configuration	A-90	Yes
Category 4	Frequent parameter modification	A-91	Yes
Category 4	Encoder battery voltage low warning	A-92	Yes
Category 4	Frequent encoder read-write verification exception	A-93	Yes

10.2.3 Troubleshooting

Er.01 Parameter damage

(1) Fault phenomenon

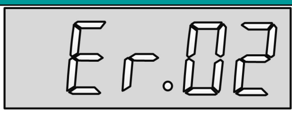
Servo drive panel display	Fault name
	Parameter damage

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
EEPROM could not be read and written	Restore factory setting [200A-02=1] and power on again. If the servo drive still alarms after multiple operations, it is faulty.	■ Contact the manufacturer's technician personnel for maintenance.

Er.02 Parameter storage error

(1) Fault phenomenon

Servo drive panel display	Fault name
	Parameter storage error

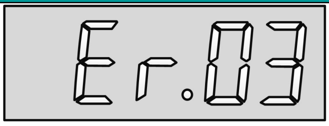
Reason: The total number of function codes or content transmission changes. It usually occurs after firmware upgrade.

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Firmware upgraded	●Check whether the program has been upgraded.	■Repower the servo drive.
Parameter read and write exceptions	●After a parameter is changed, power it on again and check whether the parameter is saved	■ If the parameters are not saved and the problem persists after multiple power-on, contact the manufacturer's technical personnel for repair.
	●Restore factory setting [200A-02=1] and power on again. If the servo drive still alarms after multiple operations, it is faulty.	■ Contact the manufacturer's technician personnel for maintenance.

Er.03 ADC reference source error

(1) Fault phenomenon

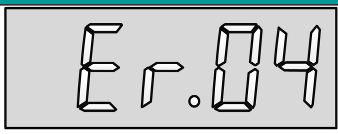
Servo drive panel display	Fault name
	ADC reference source error

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
The internal analog reference source of the drive is not accurate	Restore factory setting [200A-02=1] and power on again. If the servo drive still alarms after multiple operations, it is faulty.	■ If servo still have alarm after powering on several times, contact the manufacturer's technicians for maintenance.

Er.04 AD current sampling conversion error

(1) Fault phenomenon

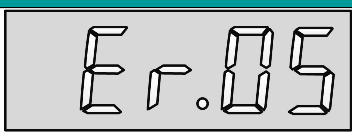
Servo drive panel display	Fault name
	AD current sampling conversion error

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Current sampling timeout	Restore factory setting [200A-02=1] and power on again. If the servo drive still alarms after multiple operations, it is faulty.	■ If servo still have alarm after powering on several times, contact the manufacturer's technicians for maintenance.
Current sensor error		

Er.05 Abnormal FPGA communication

(1) Fault phenomenon

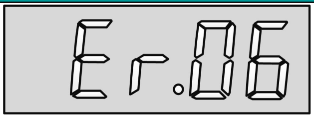
Servo drive panel display	Fault name
	Abnormal FPGA communication

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Abnormal FPGA communication	Restore factory setting [200A-02=1] and power on again. If the servo drive still alarms after multiple operations, it is faulty.	■ If servo still have alarm after powering on several times, contact the manufacturer's technicians for maintenance.

Er.06 Wrong FPGA program version

(1) Fault phenomenon

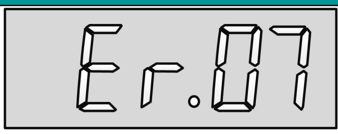
Servo drive panel display	Fault name
	Wrong FPGA program version

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
The FPGA program version does not match firmware version	●Check whether the servo drive monitoring quantities 2020-04 (firmware version) and 2020-05 (hardware version) conform to the corresponding relationship.	■ Contact the manufacturer's technician to upgrade FPGA (hardware version).
Servo drive fault	Restore factory setting [200A-02=1] and power on again.If the servo drive still alarms after multiple operations, it is faulty.	■ If servo still have alarm after powering on several times, contact the manufacturer's technicians for maintenance.

Er.07 Clock abnormality

(1) Fault phenomenon

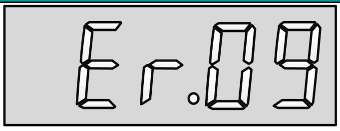
Servo drive panel display	Fault name
	Clock abnormality

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
External interference	●Check whether there are strong magnetic fields nearby	■ Eliminate the interference of strong magnetic field nearby.
	●Check whether there are sources of interference such as power supply inverter equipment nearby	■ Try to separate the strong and weak currents in the wiring, ensure that the motor and the servo drive are well grounded, and keep away from the power cables.
Servo drive fault	●Restore factory setting [200A-02=1] and power on again.If the servo drive still alarms after multiple operations, it is faulty.	■ If servo still have alarm after powering on several times, contact the manufacturer's technicians for maintenance.

Er.09 Abnormal network status switching

(1) Fault phenomenon

Servo drive panel display	Fault name
	Abnormal network status switching

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Master station operation error	●Check whether the master station switches the network status when the servo drive is enabled.	■ Correct the upper computer network switching program.
Communication cable connection error	●Check whether the communication cable is properly connected.	■ Correctly connect the communication cable.

Er.10 Loss of synchronization

(1) Fault phenomenon

Servo drive panel display	Fault name
	Loss of synchronization

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Communication is disturbed	●Check whether the servo drive network port is damaged. (Displayed by the first digital tube from the left of the servo drive panel)	■ If damaged, contact the manufacturer's technician for repair.
	●Check whether the communication cable is damaged.	■ If damaged, replace a reliable communication cable, it is recommended to use twisted-pair shielded cable with shielding function.
	●Check whether the servo drive is well grounded.	■The servo drive is well grounded.
Communication wiring error	●Check whether the communication connection follows the sequence of CN5 port in and CN6 port out to connect each slave station.	■ Correctly connect the communication cable.
Master station configuration error	●Cross-verification, using normal PLC for comparative test.	■ If it is determined that the configuration of the master station is wrong, correct the relevant

Reason	Troubleshooting methods	Handling
		procedures of the master station configuration.
The upper computer is shut down or stuck	●Check whether the upper computer is shut down or stuck.	■Restart the upper computer.
Upper computer synchronization clock is not in effect	●Measure the synchronization period by oscilloscope.	■ If the synchronization period is 0, first check whether the communication cable connection mode is correct, and then restart the network. ■If the synchronization period is not 0, contact the manufacturer's technician.
Servo drive fault	●None of the above methods can solve the fault.	■ If damaged, contact the manufacturer's technician for repair.

Er.11 Unburned XML configuration file

(1) Fault phenomenon

Servo drive panel display	Fault name
Er.11	Unburned XML configuration file

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Unburned device configuration file (XML file)	● After the upper computer scans the slave station, check whether the slave station ID is empty.	Contact the manufacturer's technician to burn the device file.
Servo drive fault	●After burning the configuration file, the fault still not be solved.	■ Contact the manufacturer's technician personnel for maintenance.

Er.12 Network initialization failed

(1) Fault phenomenon

Servo drive panel display	Fault name
Er.12	Network initialization failed

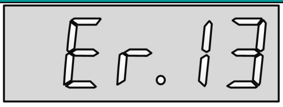
(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Unburned device configuration file (XML file)	●After the upper computer scans the slave station, check whether the slave station ID is empty.	Contact the manufacturer's technician to burn the device file.

Servo drive fault	●After burning the configuration file, the fault still not be solved.	■ Contact the manufacturer's technician personnel for maintenance.

Er.13 Synchronization period setting error

(1) Fault phenomenon

Servo drive panel display	Fault name
	Synchronization period setting error

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
The synchronization period is not an integer multiple of 125us or 250us	●Check the setting value of synchronization period.	■ Modify the synchronization period to an integer multiple of 125us or 250us.

Er.14 Synchronization period error is too large

(1) Fault phenomenon

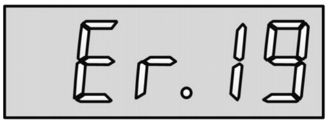
Servo drive panel display	Fault name
	Synchronization period error is too large

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Device profile mismatch	●Check whether this fault occurs every time, the device profile does not match.	■ Contact the manufacturer technician to update the device configuration file (XML file) inside the servo drive to the latest version.
The synchronization period error of the controller is large	●Check whether this fault is accidental.	■Check the upper computer.

Er.19 Software Overcurrent

(1) Phenomenon

Servo drive panel display	Fault name
	Software overcurrent

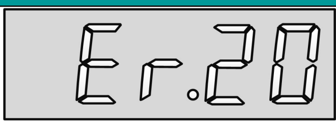
(2) Troubleshooting methods

Cause	Troubleshooting	Treatment
UVW phase sequence of motor power cable is incorrect.	●Check whether the phase sequence of the motor power cable on the servo driver side and motor side corresponds to each other.	Connect correctly as per driver side and motor side UVW.
Motor power lines are short-circuited.	●Check whether power line UVW is short-circuited to PE	Replace the power cable.
The motor power line wiring port is poorly contacted.	Check whether the motor power line connection port is connected reliably	Tighten the fixing screw on the wiring port of the motor power wire.
Braking resistor abnormal	● Wrong wiring using internal brake resistor: Check whether the short connection cap is connected between C and D and whether the contact is normal.	Reliable connect short cap or short wiring between C and D.
	●External braking resistor wiring error: Check whether the external resistor is connected reliably between P+ and C.	The external braking resistor is reliably connected in series between P+ and C.
	● Built-in brake resistor short circuit: Check the built-in brake resistor for short circuit.	Remove the short-circuit cap between C and D, and reliably connect the external braking resistor of equal resistance between P+ and C. Contact the manufacturer to replace the internal brake resistor.
	● The resistance of external braking resistor is too small: Test the resistance value of the actually selected external braking resistor, compare it with the recommended braking resistor, and confirm whether the resistance value of the actually selected resistor is too small.	Select the appropriate external brake resistor.
Encoder wiring error; loose plug	● Check whether the encoder cable port (CN1) connection is reliable.	Tighten the fixing screw for CN1 port.
	● Check whether the servo driveCN1 port jack is deformed.	If deformed, replace the cable or cable port.

Cause	Troubleshooting	Treatment
	●Check whether both ends of the rectangular connector are reliably connected	Ensure that both ends of the rectangular connection port are reliably connected; Replace it with an encoder cable with higher connection reliability.
Improper parameter setting	● Inspect 2003-01load inertia ratio and whether the setting of 2003-02 (load rigidity level) is reasonable.	Set 2003-01 (Load Inertia Ratio) to a reasonable value and adjust 2003-02 (Load Rigidity Rating) settings appropriately.
	●Check whether the gain parameters are set properly	Reasonably adjust the gain parameters.
Frequent acceleration and deceleration	●Check overload characteristics of motor or servo drive	Appropriately extend the acceleration and deceleration time.
Internal servo drive fault	●Cross-verification. Use the normal motor, encoder cable to connect to the servo drive, only connect the encoder cable. If the servo drive still alarm, it is failure.	Contact the technicians for maintenance.

Er.20 Overcurrent

(1) Fault phenomenon

Servo drive panel display	Fault name
	Overcurrent

(2) Troubleshooting methods

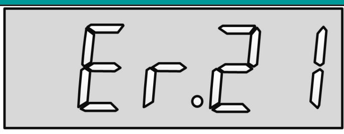
Reason	Troubleshooting methods	Handling
Motor power cable UVW phase sequence is wrong	●Check whether the phase sequence of the motor power cable on the servo drive side and motor side corresponds to each other.	■ According to the drive side UVW, connect the motor side UVW correctly.
Motor power line short circuit	●Check whether power line UVW is short-circuited to PE	■Replace the power cable.
Poor connection of motor power line terminal	●Check whether the motor power line connection port is connected reliably	■ Tighten the fixing screws at the connection port of the motor power wire.

Reason	Troubleshooting methods	Handling
Abnormal braking resistance	●Internal brake resistance wiring error: check whether C, D are connected to the shorting cap and the contact is normal	■ Ensure reliable connection between C and D shorting cap or short wiring.
	●External braking resistor wiring error: Check whether the external resistor is connected reliably between P+ and C.	■ The external braking resistor is reliably connecting between P + and C.
	●Short-circuit of the built-in brake resistance: Check whether the built-in brake resistance is short-circuited.	■Remove the shorting cap between C and D, and connect the external braking resistors with equal resistance between P + and C. ■ Contact the manufacturer's technician to replace the internal braking resistor.
	●The resistance value of the external braking resistor is too small: Test the resistance value of the external braking resistor actually selected and compare it with the recommended braking resistor to confirm whether the resistance value of the actual resistor is too small	■ Select the appropriate external braking resistor.
Encoder wiring error; loose plug	●Check whether the cable port (CN2) of the encoder is properly connected	■Tighten the fixing screws for CN2 port.
	●Check whether the servo drive CN2 port jack is deformed	■Replace the cable or cable port if deformed.
	●Check whether both ends of the rectangular connector are reliably connected	■Ensure reliable connection at both ends of rectangular connection port; ■Replace with an encoder cable with higher connection reliability.
Improper parameter setting	●Check whether 2003-02 (load rigidity level) is set properly	■Appropriately increase the setting value of 2003-02 (load rigidity level).
	●Check whether the gain parameters are set properly, resulting in overshoot	■ Reasonably adjust the gain parameters.
Frequent acceleration and deceleration	●Check whether frequent acceleration and deceleration are performed and whether the	■ Appropriately extend the acceleration and deceleration time.

Reason	Troubleshooting methods	Handling
	acceleration and deceleration time is too short.	
Internal servo drive fault	●Cross-verification. Use the normal motor, encoder cable to connect to the servo drive, only connect the encoder cable. If the servo drive still alarm, it is failure.	■ Contact the manufacturer's technician personnel for maintenance.

Er.21 Main power supply undervoltage

(1) Fault phenomenon

Servo drive panel display	Fault name
	Main power supply is undervoltage

Reason: DC bus voltage is lower than the fault value.

○220V drive: The normal value of DC bus voltage is 310V, and the fault value of DC bus voltage is 200V;

○380V drive: The normal value of DC bus voltage is 540V, and the fault value of DC bus voltage is 420V.

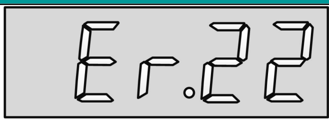
(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Power-off when VD3E drive is enabled	●Check whether the servo drive is power off when logic is valid and the S-ON function is enabled in the 2006 Group “DIDO Function configuration parameter”.	■It is servo internal software logic, and the alarm will be automatically released after the indicator light of servo drive panel is off.
The power supply is unstable or off	●Observe whether the monitoring quantity 201E-1f (bus voltage) is in the following range: 220V drive: 201E-1F less than 200V; 380V drive: 201E-1F less than 420V.	■Run servo after the power supply is stable; ■Increase power capacity.
The voltage drops during operation of the servo drive	●Check whether the servo drive shares the same power supply with other high loads	■Turn off other loads of the same main circuit power supply; ■ Servo drive uses a separate power supply
Phase loss (three phase power is running on single phase power)	●Check if the main circuit wiring is correct VD3E A: single-phase 220V input	■ Correctly connect the main circuit wiring.

	connected to L1, L3; VD3E B: single-phase 220V input connected to L1, L3; three-phase 220V input connected to L1, L2, L3.	

Er.22 Main power supply overvoltage

(1) Fault phenomenon

Servo drive panel display	Fault name
	Main power supply is overvoltage

Reason: DC bus voltage is higher than the fault value.

○220V drive: The normal value of DC bus voltage is 310V, and the fault value of DC bus voltage is 390V;

○380V drive: The normal value of DC bus voltage is 540V, and the fault value of DC bus voltage is 670V.

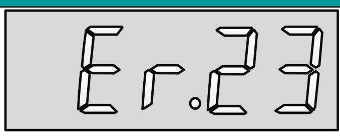
(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
The input voltage is too high	●Check that the drive input power specifications meet the specifications: 220V drive: valid value: 198V ~ 242V; 380V drive: valid values: 342V ~ 418V.	■ Change or adjust the power supply.
The power supply is not stable or struck by lightning	●Check whether the input power supply of the servo drive meets the specifications and monitor whether it has been struck by lightning.	■Run servo after the power supply is stable; ■ Connect the surge suppressor, please contact the technical personnel of the manufacturer for the specific connection method.
Abnormal braking resistance	●Internal briking resistor wiring error: check whether C, D are connected to the shorting cap and the connection is normal	■ Reliable connection between C and D shorting cap or short wiring.
	●External braking resistor wiring error: Check whether the external resistor is connected reliably between P+ and C.	■ The external braking resistor is reliably connected between P + and C.
	●Short-circuit of the built-in braking resistor: Check whether	■Remove the shorting cap between C and D, and reliably connect the

Reason	Troubleshooting methods	Handling
	the built-in braking resistor suffers from short-circuit.	external braking resistors with equal resistance between P + and C. ■ Contact the manufacturer's technician to replace the internal braking resistor.
	●The resistance value of the external braking resistor is too large: Check the resistance value of the external braking resistor actually selected and compare it with the recommended braking resistor to confirm whether the resistance value of the actual resistor is too large.	■ Select the appropriate external braking resistor.
The motor is in a state of rapid acceleration and deceleration motion	●Monitor the servo drive monitoring quantity 201E-1F (bus voltage) to confirm whether the voltage exceeds the fault value when the motor is in the deceleration section.	■ Ensure that the input voltage is within the specification range and increase the acceleration and deceleration time.
Internal servo drive fault	●The servo drive is still faulty after power on again	■ Servo drive may be damaged, contact the manufacturer's technician for repair.

Er.23 Braking resistor is not connected

(1) Fault phenomenon

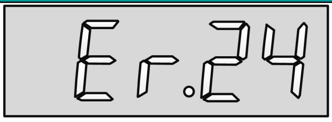
Servo drive panel display	Fault name
	Braking resistor is not connected

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Internal braking resistor wiring error	●Check whether C, D are connected to the shorting cap and the connection is normal	■ When internal braking resistors are used, ensure the shorting caps or short wires are reliably connected between C and D.
External braking resistor wiring error	●Check whether the external resistor is connected reliably between P+ and C.	■ When external braking resistors are used, ensure the external resistors are reliably strung between P + and C.
Internal braking resistor damaged	●The servo drive is powered off. Detect whether the resistance between P+ and D is 50Ω	■ Contact the manufacturer's technician to replace the internal braking resistor. ■Use the external braking resistor and change the relevant parameters in servo drive 2000 group "basic settings".

Er.24 Braking resistor turns on abnormally

(1) Fault phenomenon

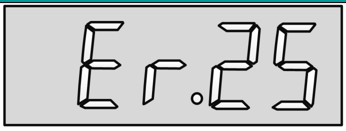
Servo drive panel display	Fault name
	The braking resistor is turned on abnormally

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Internal hardware of servo drive damaged	●The servo drive is still faulty after power on again	■ Contact the manufacturer's technician for maintenance.

Er.25 Braking resistor resistance is too large

(1) Fault phenomenon

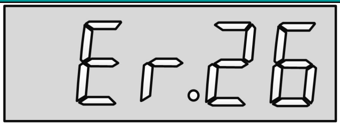
Servo drive panel display	Fault name
	Braking resitor resistance is too large

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
The resistance value of the external braking resistor is large	●Check the resistance value of the external braking resistor actually selected and compare it with the recommended braking resistor to confirm whether the resistance value of the actual resistor is too large.	■ Use an appropriate external braking resistor.
Improper parameter setting	●Check whether the value of servo drive 2000-0A (external brake resistance) is set too high	■ Reasonably set the parameter value of 2000-0A (external braking resistance value).

Er.26 Wrong motor model

(1) Fault phenomenon

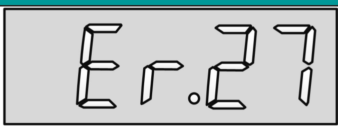
Servo drive panel display	Fault name
	Wrong motor model

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
The motor is not supported by the servo drive	●Check whether the servo drive model supports the motor	■ Contact the manufacturer's technician to obtain the appropriate servo drive model and motor model.
Wrong motor model	●Check whether the Motor Code is consistent with the motor nameplate	■Contact technician to record the motor Motor Code

Er.27 Encoder disconnection

(1) Fault phenomenon

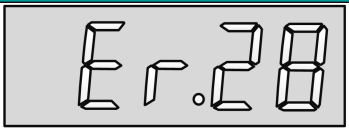
Servo drive panel display	Fault name
	Encoder is disconnected

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Poor contact on CN2 port	●Check whether the cable port (CN2) of the encoder is properly connected	■Tighten the fixing screws for CN2 port.
	●Check whether the servo drive CN2 port jack is deformed	■Replace the cable or cable port if deformed.
Poor contact on adapter port (Rectangular connection cable)	●Check whether both ends of the rectangular connector are reliably connected	■ Ensure reliable connection at both ends of rectangular connection port; ■ Replace with an encoder cable with higher connection reliability.
Wrong encoder cable wiring	●Check whether the both ends of the encoder cable are correctly connected	■ Adjust the wiring according to the corresponding relationship of pins; ■ Preferably use the standard encoder cable of the manufacturer.

Er.28 Encoder Z pulse lost

(1) Fault phenomenon

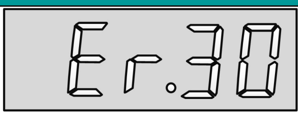
Servo drive panel display	Fault name
	Encoder Z pulse is lost

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Wrong motor model	●Check whether the servo drive model supports the motor	■ Contact the manufacturer's technician to obtain the appropriate servo drive model and motor model.
External interference	●Check whether there are strong magnetic fields nearby	■ Eliminate the interference of strong magnetic field nearby.
	●Check whether there are sources of interference such as power supply inverter equipment nearby	■ Try to separate the strong and weak currents in the wiring, ensure that the motor and the servo drive are well grounded, and keep away from the power cables.
Encoder fault	●Manually rotate the motor shaft counterclockwise or clockwise to observe whether the monitoring quantity U0-30 (electrical angle) changes regularly	■ If the value of U0-30 (electric angle) changes abruptly or does not change, there may be a problem with the encoder itself. Please replace the motor or encoder.

Er.30 Encoder UVW signal error

(1) Fault phenomenon

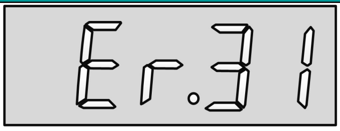
Servo drive panel display	Fault name
	Encoder UVW signal error

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
External interference	●Check that the motor and servo drive are well grounded	■ Ensure the motor and servo drive are well grounded.
Encoder cable fault	●Cross-verification. Use the normal motor, encoder cable to connect to the servo drive.	■Replace with an encoder cable with higher connection reliability.
Servo drive fault	●The servo drive is still faulty after power on again	■ Contact the manufacturer's technician for maintenance.

Er.31 Power line disconnection

(1) Fault phenomenon

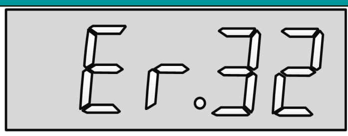
Servo drive panel display	Fault name
	Power line disconnection

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Poor contact of motor power wiring port	●Check whether the motor power wiring port is connected reliably	■ Tighten the fixing screws at the wiring port of the motor power wire.
Power line disconnection	●Check whether both ends of the power cable are disconnected	■ Replace the power cable and repower
Poor contact on adapter port (rectangular connection cable)	●Check whether both ends of the rectangular connector are reliably connected	■Ensure reliable connection at both ends of rectangular connection port; ■Replace with a power cable with higher connection reliability.

Er.32 Exceeding motor maximum speed

(1) Fault phenomenon

Servo drive panel display	Fault name
	Exceeding motor maximum speed

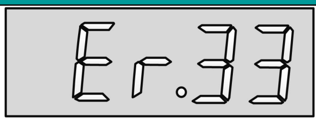
(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Motor power cable UVW phase sequence error	●Check whether the phase sequence of the motor power cable on the servo drive side and motor side corresponds to each other.	■According to the drive side UVW, the motor side UVW is connected correctly.
2001-0A parameter setting is not proper	●Check that the parameter value of 2001-0A (maximum speed threshold) is less than the maximum speed required for the actual operation of the motor	■Reset 2001-0A (maximum speed threshold) according to mechanical requirements.
	●Check whether the motor rotating speed corresponding to the input command exceeds 2001-0A (maximum speed threshold)	

Reason	Troubleshooting methods	Handling
Motor speed overshoot	●Check whether the gain parameters are set properly, resulting in overshoot	■ Reasonably adjust the gain parameters.
Servo drive fault	●The servo drive is still faulty after power on again	■ Servo drive may be damaged, replace servo drive.

Er.33 Power module over temperature

(1) Fault phenomenon

Servo drive panel display	Fault name
	Power module is over temperature

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Ambient temperature is too high	●Measure the ambient temperature.	■Reduce the ambient temperature of the servo drive.
Servo drive fan failure	●Check whether the servo drive fan is blocked or damaged	■ Contact the manufacturer's technician to repair or replace the fan.
The servo drive is mounted in an unreasonable orientation or the spacing between the servo drives is unreasonable	●Check whether the servo drive installation is reasonable	■ Contact the manufacturer's technician to obtain the servo drive installation standard.
Servo drive fault	●Fault is still reported when restarting after ten minutes of power cutoff	■ Servo drive may be damaged, contact the manufacturer's technician for repair.

Er.34 Motor overload protection

(1) Fault phenomenon

Servo drive panel display	Fault name
Er.34	Motor overload protection

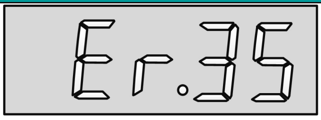
(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Motor power cable, encoder cable wiring error	●Check whether the motor power cable and encoder cable wiring are correct.	■Connect according to the correct connection method; ■Preferably use the motor power lines and encoder cables standard by manufacturers.
The load is too large	●Check overload characteristics of motor or servo drive	■Reduce the load; ■Contact the manufacturer's technician to obtain the drive and motor model with appropriate capacity.
Frequent acceleration and deceleration	●Check whether frequent acceleration and deceleration are performed and whether the acceleration and deceleration time is too short.	■Appropriately extend the acceleration and deceleration time.
Motor model and servo drive do not match	●Check the monitoring quantity 201E-35 (motor model code).	■Contact the manufacturer's technician to obtain the matching motor model.
Unreasonable parameters	●Use Wecon SCTools to obtain the actual torque waveform and observe whether overshoot is obvious	■ Set the appropriate loop gain parameters.
	●Observe whether the motor vibrates during operation	■Set the appropriate rigidity level.
	●Check whether 200A-04 (motor overload protection time coefficient) parameter is reasonable	■Increase 200A-04 (motor overload protection time coefficient) under the premise that the motor will not burn out.
The motor is locked	●Check whether the brake output function is enabled by mistake, resulting in the motor locking.	■ Disable the brake output function.
Servo drive fault	●The servo drive is still faulty after power on again	■Servo drive may be damaged, contact the manufacturer's

		technician for repair.

Er.35 Electronic gear ratio exceeds limit

(1) Fault phenomenon

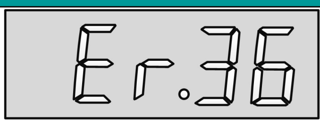
Servo drive panel display	Fault name
	Electronic gear ratio exceeds limit

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
The electronic gear ratio setting is greater than the settable range	Check whether the ratio of object dictionaries 6091: 01 to 6091: 02 is within the following range: ●The upper limit of 17bit absolute value encoder can be set to 52428; ●The upper limit of 23bit absolute value encoder can be set to 3355443.	■ After modifying the corresponding function code according to the settable range, set 200A-03 (fault clearing) to 1
The electronic gear ratio setting is less than the settable range	Check whether the ratio of object dictionaries 6091: 01 to 6091: 02 is within the following range: ●The lower limit of 17bit absolute value encoder can be set to 0.01; ●The lower limit of 23bit absolute value encoder can be set to 0.83.	

Er.36 Position deviation is too large

(1) Fault phenomenon

Servo drive panel display	Fault name
	Position deviation is too large

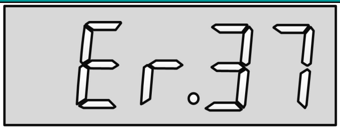
(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Cable problem	●Check whether the phase sequence of the motor power cable on the servo drive side and motor side corresponds to each other.	■According to the drive side UVW, connect the motor side UVW correctly.
	●Check whether both ends of power cable are disconnected	■ Replace the power cable and repower
Improper parameter	●Check whether 2003-02 (load	■ Appropriately increase the

Reason	Troubleshooting methods	Handling
setting	rigidity level) is set properly	setting value of 2003-02 (load rigidity level).
	●Check whether the gain parameters are set properly; if not, it may result in overshoot	■ Reasonably adjust the gain parameters.
	●Check whether 6065 (position deviation threshold) is set properly	■ Appropriately increase the setting value of 6065 (excessive position deviation threshold)
	●Use Wecon SCTools to obtain the equivalent speed of the position command and check whether the speed is greater than the motor rotating speed limit	■ Increase the setting values of 2001-0C (forward speed threshold) and 2001-0D (reverse speed threshold) according to mechanical requirements.
Motor is locked	●Check whether motor is locked due to mechanical jamming	■ Solve the problem of mechanicam jamming.
Brake is not opened	●Check whether the brake device is opened normally, and check whether the output voltage of the brake is 24V	■ Check the logic of brake power supply or brake output signal.
Position command equivalent speed changes too quickly	●Check whether the position command equivalent speed changes too quickly	■ Properly increase the acceleration and deceleration time and reduce the change rate of the rotating speed.

Er.37 Abnormal torque saturation

(1) Fault phenomenon

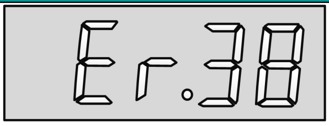
Servo drive panel display	Fault name
	Abnormal torque saturation

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Motor power cable UVW phase sequence error	●Check whether the phase sequence of the motor power cable on the servo drive side and motor side corresponds to each other.	■According to the drive side UVW, connect the motor side UVW correctly.
Improper parameter setting	●Check whether 2001-13 (torque saturation timeout) is set properly	■ Appropriately increase the setting value of 2001-13 (torque saturation timeout time).
	Check whether 2001-0F (forward torque limit) and 2001-10 (reverse torque limit) are set reasonably	■ Appropriately increase the setting values of 2001-0F (positive torque limit) and 2001-10 (reverse torque limit).
	●Check whether the gain parameters are set properly	■ Reasonably adjust the gain parameters.
	●Check whether the acceleration and deceleration time are set properly	■ Appropriately increase the acceleration and deceleration time.
The load is too large	●Check whether the load is too large	■Reduce the load.
Motor is locked	●Check whether the motor is locked due to mechanical jamming of the load.	■Solve the problem of mechanical jamming.
Limit switches are mounted beyond the travel	●Check whether the limit switch is installed beyond the travel	■Adjust the installation position of the limit switch.
The brake is not opened	●Check whether the brake device is opened normally, and check whether the output voltage of the brake is 24V	■ Check the logic of brake power supply or brake output signal.

Er.38 Main circuit electrical phase loss

(1) Fault phenomenon

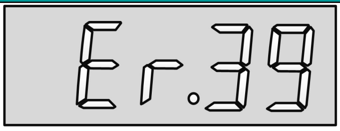
Servo drive panel display	Fault name
	Main circuit electrical phase loss

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Cable problem	●Check whether the motor power wiring port is connected reliably	■ Tighten the fixing screws at the wiring port of the motor power wire.
	●Check whether both ends of the power cable are disconnected	■ Replace the power cable and repower
Three-phase specification drives run on single-phase power supplies	●Check whether the three-phase drive has a single-phase power supply	■ Re-connect the three-phase power supply according to the power supply specifications.
The power supply is unstable or off	●Check that the drive input power specifications meet the specifications: 220V drive: valid value: 198V ~ 242V; 380V drive: valid value: 342V ~ 418V.	■Run servo after the power supply is stable.
Servo drive fault	●The servo drive is still faulty after power on again	■ Servo drive may be damaged, contact the manufacturer's technician for repair.

Er.39 Emergency stop

(1) Fault phenomenon

Servo drive panel display	Fault name
	Emergency stop

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Servo drive receives emergency stop instructions	●Check whether emergency stop protection is triggered manually	■Repower the servo drive.
	●Check whether the servo drive has mistakenly triggered the emergency stop signal. Check whether function 08 (E-STOP) is configured in "DI "port function selection" of the 2006 group "DIDO configuration" function code group and whether the DI port wiring is normal.	■Reasonably wire the DI port.

Er.40 Encoder battery failure

(1) Fault phenomenon

Servo drive panel display	Fault name
Er.40	Encoder battery failure

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Multi-turn absolute encoder is not connected to the battery when the servo drive is power off	●Check if the encoder is connected to the battery during the power off of the servo	■Set 200A-03 (fault clearing) to 1.
The voltage of multi-turn absolute encoder battery is low	●Measure battery voltage	■ Contact the manufacturer's technician to replace the new encoder battery.

Er.41 Motor (encoder) over temperature

(1) Fault phenomenon

Servo drive panel display	Fault name
Er.41	Motor (encoder) over temperature

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
The motor is overloaded	●Check whether the motor is overloaded	■Reduce the load.

Er.42 Encoder write fault

(1) Fault phenomenon

Servo drive panel display	Fault name
Er.42	Encoder write fault

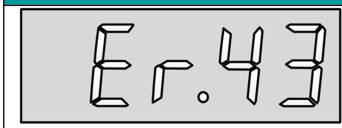
(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Poor contact on CN1 port	●Check whether the cable port (CN1) of the encoder is properly connected	■Tighten the fixing screws for CN2 port.
	●Check whether the servo drive CN1 port jack is deformed	■Replace the cable or cable port if deformed.
Poor contact on adapter port (rectangular	●Check whether both ends of the rectangular connector are	■Ensure reliable connection at both ends of rectangular connection port;

connection cable)	reliably connected	■ Replace with an encoder cable with higher connection reliability.
External interference	●Check whether there are strong magnetic fields nearby	■ Eliminate the interference of strong magnetic field nearby.
	●Check whether there are sources of interference such as power supply inverter equipment nearby	■ Try to separate the strong and weak currents in the wiring, ensure that the motor and the servo drive are well grounded, and keep away from the power cables.
Servo drive fault	●The servo drive is still faulty after power on again	■ Servo drive may be damaged, contact the manufacturer's technician for repair.

Er.43 Drive overload fault

Fault

Servo drive panel	Fault name
	Drive overload fault

Troubleshooting

Reason	Troubleshooting	Handling
The average output power of U0-34 exceeds the limit power (110% overload) for more than 20 minutes.	■ Whether the average output power of U0-34 often exceeds the limit (110% overload) Check whether the drive meets the requirements.	■ It can be observed whether the U0-34 is often greater than the servo limit power (110% overload) when servo is running. When ER.43 alarm is found in the process of machine adjustment, please check whether the servo power is suitable. It is recommended to replace the drive model with higher power.
Servo drive fault	■ The servo drive is still fault after power on again	■ Servo drive may be damaged. Please contact the manufacturer's technician for repair.

Servo drive model	Rated power /W	Limited power/W (110% overload)
VD3E-003SA1G	100	110
VD3E-010SA1G	400	440
VD3E-014SA1G	750	825
VD3E-016SA1G	1500	1650

Servo drive model	Rated power /W	Limited power/W (110% overload)
VD3E-019/021 SA1G	2300	2530
VD3E-025/030 SA1G	2600	2860
VD3E-016TA1G	1500	1650
VD3E-019TA1G	2000	2200
VD3E-021TA1G	3000	3300

Er.44 Homing timeout fault

(1) Fault phenomenon

Servo drive panel display	Fault name
Er.44	Homing timeout fault

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Fault of homing switch	Check whether homing is always in a high-speed search instead of a low-speed search. Check whether homing high-speed search has been in the reverse low-speed search process.	■ First confirm whether the DI function 26 is set in group 2006, and then check the connection of the DI terminal. When manually changing the logic of the DI terminal, check whether the servo drive receives the corresponding DI level signal through 201E-11. If not, it means that the DI wiring is wrong, please wire correctly. ■Manually make DI terminal logic change, if received level signal, indicating the homing operation is wrong, please operate correctly.
The speed of searching the home switch signal at high speed is too small	●Check whether the 6099: 01h setting value is too small.	■ Increase the 6099: 01h setting value.
Hardware switch setting is unreasonable	●Confirm whether the limit switch signals on both sides are valid at the same time. ●Confirm whether a limit switch signal and the deceleration point signal or origin signal are valid at the same time	■Set the hardware switch position reasonably.

Er.45 Drive stall and Overtemperature Protection

（1） Fault phenomenon

Servo drive panel display	Fault name
Er.45	Drive Stall Overtemperature Protection

（2） Troubleshooting

Cause	Troubleshooting	Treatment
Controlled by parameter P10-11 motor stall and over-temperature function. When P10-11=0, the motor is stalled, the actual speed of the motor is less than 10rpm, the torque instruction exceeds the rated torque of the motor, and the duration reaches the motor overheating protection time at the corresponding torque, ER.45 fault will be reported and the machine will be shut down immediately.	Check the waveform of the oscilloscope. The actual speed of the motor is less than 10rpm, and the torque instruction exceeds the rated torque of the motor. Observe whether the mechanical structure is jammed.	View oscilloscope waveforms. The actual speed of the motor is less than 10rpm, and the torque instruction exceeds the rated torque of the motor. Observe whether the motor is stuck by the mechanical structure. A temporary solution. P10-11=1 When the motor is stalled, the torque will become 70% of the rated torque. (Not recommended) Note: The shielded drive stall and over-temperature protection function is likely to cause motor and mechanical failure. Please use it carefully!

Er.60 ADC conversion is not completed

(1) Fault phenomenon

Servo drive panel display	Fault name
Er.60	ADC conversion is not completed

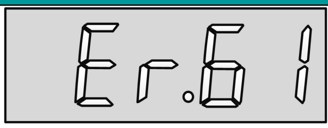
(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
External interference	●Check whether there are strong magnetic fields nearby	■ Eliminate the interference of strong magnetic field nearby.

	●Check whether there are sources of interference such as power supply inverter equipment nearby	■ Try to separate the strong and weak currents in the wiring, ensure that the motor and the servo drive are well grounded, and keep away from the power cables.
Servo drive fault	●Restore factory setting [200A-02=1] and power on again. If the servo drive still alarms after multiple operations, it is faulty.	■ If servo still give alarm after powering on several times, contact the manufacturer's technicians for maintenance.

Er.61 Internal software fault

(1) Fault phenomenon

Servo drive panel display	Fault name
	Internal software fault

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Servo drive fault	●Restore factory setting [200A-02=1] and power on again. If the servo drive still alarms after multiple operations, it is faulty.	■ If servo still give alarm after powering on several times, contact the manufacturer's technicians for maintenance.

Er.62 Internal software fault

(1) Fault phenomenon

Servo drive panel display	Fault name
Er.62	Internal software fault

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Servo drive fault	●Restore factory setting [200A-02=1] and power on again. If the servo drive still alarms after multiple operations, it is faulty.	■ If servo still give alarm after powering on several times, contact the manufacturer's technicians for maintenance.

Er.63 Internal software fault

(1) Fault phenomenon

Servo drive panel display	Fault name
Er.63	Internal software fault

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Servo drive fault	●Restore factory setting [200A-02=1] and power on again. If the servo drive still alarms after multiple operations, it is faulty.	■ If servo still give alarm after powering on several times, contact the manufacturer's technicians for maintenance.

Er.64 Internal software fault

(1) Fault phenomenon

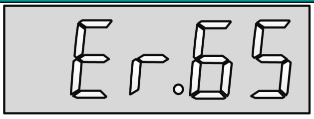
Servo drive panel display	Fault name
Er.64	Internal software fault

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Servo drive fault	●Restore factory setting [200A-02=1] and power on again. If the servo drive still alarms after multiple operations, it is faulty.	■ If servo still give alarm after powering on several times, contact the manufacturer's technicians for maintenance.

Er.65 Internal software fault

(1) Fault phenomenon

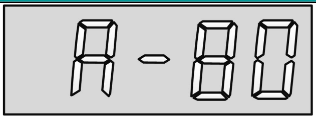
Servo drive panel display	Fault name
	Internal software fault

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Servo drive fault	●Restore factory setting [200A-02=1] and power on again. If the servo drive still alarms after multiple operations, it is faulty.	■ If servo still give alarm after powering on several times, contact the manufacturer's technicians for maintenance.

A-80 power limit alarm

(1) Fault

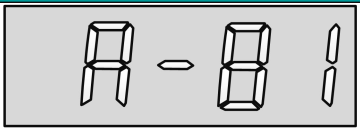
Servo drive panel	Alarm name
	Drive overpower alarming

(2) Troubleshooting

Reason	Troubleshooting	Handling
When the average output power of U0-34 exceeds the limit power of the drive (110% overload) for more than 5 seconds, there is drive overpower alarming.	■ Check whether the average output power of U0-34 exceeds the limit (110% overload) for more than 5 seconds.	■ Check whether the power of U0-34 exceeds 110% of the rated power of the drive. When A80 alarm is reported in the adjustment process, please check whether the servo power is suitable.

A-81 Overspeed alarm

(1) Fault phenomenon

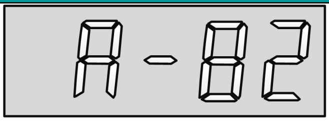
Servo drive panel display	Warning name
	Overspeed alarm

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Motor power cable UVW phase sequence error	●Check whether the phase sequence of the motor power cable on the servo drive side and motor side corresponds to each other.	■ According to the drive side UVW, connect the motor side UVW correctly.
2001-0B parameter setting is not proper	●Check whether the value of 2001-0B (warning speed threshold) is less than the max speed required for the operation of motor	■ Reset 2001-0B (warning speed threshold) according to mechanical requirements.
Input speed instruction is too high	●Check whether the motor speed corresponding to the input command exceeds 2001-0B (warning speed threshold)	■Reduce the input speed command while ensuring mechanical requirements; ■ Reasonably increase 2001-0B (warning speed threshold).

A-82 Overload

(1) Fault phenomenon

Servo drive panel display	Warning name
	Overload

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Motor power cable, encoder cable wiring error	●Check whether the motor power cable and encoder cable wiring are correct.	■Complete wiring according to the correct wiring method; ■ Preferably use the standard motor power lines and encoder cables provided by manufacturers.
The load is too large	●Perform inertia identification and check the inertia ratio.	■Reduce the load; ■ Contact the manufacturer's technician to obtain the drive and motor model with appropriate capacity.
Frequent acceleration and deceleration	●Check whether frequent acceleration and deceleration are performed and whether the acceleration and deceleration time is too short.	■ Appropriately extend the acceleration and deceleration time.
Motor model and servo drive do not match	●Check the monitoring quantity 201E-35 (motor model code).	■ Contact the manufacturer's technician to obtain the matching motor model.
Unreasonable parameters	●Use Wecon SCTools to obtain the actual torque waveform and observe whether overshoot is obvious	■ Set the appropriate loop gain parameters.
	●Observe whether the motor vibrates during operation	■Set the appropriate rigidity level.

A-83 Braking resistor is over temperature or overloaded

(1) Fault phenomenon

Servo drive panel display	Warning name
A-83	Braking resistor is over temperature or overloaded

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Improper wiring of internal braking resistor	●Check whether C, D are connected to the shorting cap and the contact is normal	■ When internal braking resistors are used, ensure the shorting caps or short wires are reliably connected between C and D.
Improper wiring of external braking resistor	●Remove the external braking resistor and measure whether the resistance value is "∞"(Infinity).	■ Replace with a new external braking resistor, after ensuring that the resistance value of the resistor is consistent with the nominal value, connect it in series between P+ and C.
The resistance value of the external braking resistor is too large	●Test the actual external braking resistor resistance and compare it with the recommended braking resistor to make sure the actual resistance is not too large.	■ Use an appropriate external braking resistor.
Improper parameter setting	When using an external braking resistor, check the following parameters. Whether the value of 2000-09 (brake setting) is reasonable Whether the value of 2000-10 (resistance value of external braking resistor) is reasonable.	■ Reasonably set the parameter value of 2000-09 (brake setting setting): 2000-09=1 (external braking resistor is used, natural cooling) 2000-09=3 (no braking resistor is used, and all are absorbed by capacitance) ■The parameter value of 2000-0A (external braking resistor) should be the same as the actual external braking resistance.

A-84 Parameter modification that needs device to be powered on again

(1) Fault phenomenon

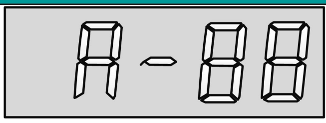
Servo drive panel display	Warning name
A-84	Parameter modification that needs device to be powered on again

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Modified the valid timing parameter to "power on again".	●Check whether the servo drive has modified the valid timing parameter to "power on again".	■Power it on again.

A-88 Main circuit instantaneous power failure

(1) Fault phenomenon

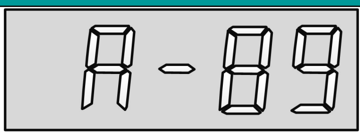
Servo drive panel display	Warning name
	Main circuit instantaneous power failure

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
Power failure	●Check that the drive input power specifications meet the specifications: 220V drive: valid value : 198V ~ 242V;; 380V drive: valid values : 342V ~ 418V.	■If the mains input has no voltage or is unstable, wait for the power supply to stabilize before use.
Servo drive fault	When the mains power is confirmed to be normal, the servo drive is still faulty after power on again	■ Servo drive may be damaged, please contact the manufacturer's technician.

A-89 Duplicate DI port configuration

(1) Fault phenomenon

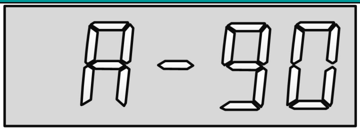
Servo drive panel display	Fault name
	Duplicate DI port configuration

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
The same non-zero DI function is assigned to multiple DI ports	Check whether the "DI port function selection" of the "DIDO Configuration" function code group of the 2006 group is configured with the same DI function	■ Set different DI functions for different DI port, and repower the servo; ■Configure the function of unnecessary DI port to 0 (off), and repower servo; ■Restore parameters to factory settings through setting 200A-02 as 1, and power it on again.

A-90 Duplicate DO port configuration

(1) Fault phenomenon

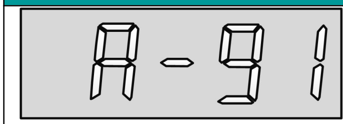
Servo drive panel display	Fault name
	Duplicate DO port configuration

(2) Troubleshooting methods

Reason	Troubleshooting methods	Handling
The same non-zero DO function is assigned to multiple DO ports	Check whether the “DO port function selection" of the "DIDO Configuration" function code group of the 2006 group is configured with the same DO function.	■ Set different DO functions for different DO port; ■ Configure the function of unnecessary DO port to 128 (off); ■ Restore parameters to factory settings through setting 200A-02 as 1, and power it on again.

A-91 parameter modification is too frequent.

(1) Fault

Servo drive panel	Fault name
	Parameter modification is too frequent (Allowable modification frequency of the function code): 150 times/ 4 hours ✎**Note: 32-bit function code is recorded as 2 times)**

(2) Troubleshooting

Reason	Troubleshooting	Handling
Parameter modification is too frequent	●Check whether the host computer modifies the writing parameters frequently; (Allowable modification frequency of the function code): 150 times/ 4 hours) ✎**Note: 32-bit function code is recorded as 2 times**	(1) During the adjustment, A91 alarming (150 times/4 hours) caused by frequently manual modification of function codes can be cleared through P10-03. In other cases, please check the PLC program; (2) If A91 alarming appears in the normal working mode of the machine, please check whether the PLC program frequently modifies the function code.

A-92 Low encoder battery voltage warning

(1) Fault

Servo drive panel display	Fault name
A-92	Low encoder battery voltage warning

(2) Troubleshooting

Reason	Troubleshooting methods	Handling
Encoder battery voltage is less than 3.1V	●Measure encoder battery voltage	■ Contact the manufacturer's technician to replace the new encoder battery.

A-93 encoder read-write verification exception is too frequent.

(1) Fault

Servo drive panel	Fault name
A-93	Encoder read-write verification exception is too frequent.

(2) Troubleshooting

Reason	Troubleshooting	Handling
External interference	■ Check for strong magnetic fields nearby	■ Eliminate the interference of strong magnetic field nearby.
	■ Check whether there are sources of interference such as power supply inverter equipment nearby	■ Try to separate the strong and weak currents in the wiring. Make sure the motor and drive are well grounded and keep away from the power cables.
	■ Increase P0-31: Encoder read-write verification excepti on threshold setting	■ Eliminate the A93 alarming by increasing the exception threshold is regarded as a temporary solution. The disadvantage is that the motor may run in an unstable state.
Encoder fault	■Manually rotate the motor axis counterclockwise or clockwise to observe whether the monitoring value 201E-1E (electrical angle) changes regularly	■ If the value of 201E-1E (electric angle) changes abruptly or does not change, there may be a problem with the encoder itself. Please replace the motor or encoder.
Servo drive fault	■ Cross-verification: Use the normal motor and encoder cables to connect to the servo drive. If the servo drive still alarms, it is a servo drive fault.	■ Servo drive may be damaged, please contact the manufacturer's technician.

If P6-14 and P6-17 are set to other functions, such as instruction reversal or other DI functions, the use of touch probe function will not be affected. That is, when DI5 or DI6 is enabled, the touch probe function and the corresponding function code function will take effect together and do not affect each other.

Chapter 11 Appendix

11.1 Object Dictionary List

Group 1000

Object dictionary (Hex)	Name	Accessibility	Data mapping	Default	Data range	Unit	Data Type	Page number
1000	Device type	RO	No	0x00020192	-	-	UDINT	112
1001	Error record	RO	No	0x00	-	-	USINT	112
1008	Device name	RO	No	-	-	-	STRING	112
1009	Manufacturer's hardware equipment	RO	No	-	-	-	STRING	112
100A	Manufacturer software version	RO	No	-	-	-	STRING	112
1018: 01	Vendor ID	RO	No	0x00000EFF	-	-	UDINT	112
1018: 02	Product code	RO	No	0x10003101	-	-	UDINT	112
1018: 03	Revision number	RO	No	0x00000001	-	-	UDINT	112
1018: 04	Serial number	RO	No	0x00001419	-	-	UDINT	112
1600: 01	First mapping object	RW	RPDO	0x60400010	-	-	UDINT	113
1600: 02	Second mapping object	RW	RPDO	0x607A0020	-	-	UDINT	113
1600: 03	Third mapping object	RW	RPDO	0x60B80010	-	-	UDINT	113
1600: 04	Fourth mapping object	RW	RPDO	0X60600008			UDINT	113
1701: 01	First mapping object	RW	RPDO	0x60400010	-	-	UDINT	113
1701: 02	Second mapping	RW	RPDO	0x607A0020	-	-	UDINT	113

Object dictionary (Hex)	Name	Accessibility	Data mapping	Default	Data range	Unit	Data Type	Page number
	object							
1701: 03	Third mapping object	RW	RPDO	0x60B80010	-	-	UDINT	113
1701: 04	Fourth mapping object	RW	RPDO	0x60600008	-	-	UDINT	113
1702: 01	First mapping object	RW	RPDO	0x60400010	-	-	UDINT	114
1702: 02	Second mapping object	RW	RPDO	0x607A0020	-	-	UDINT	114
1702: 03	Third mapping object	RW	RPDO	0x60FF0020	-	-	UDINT	114
1702: 04	Fourth mapping object	RW	RPDO	0x60710010	-	-	UDINT	114
1702: 05	Fifth mapping object	RW	RPDO	0x60600008	-	-	UDINT	114
1702: 06	Sixth mapping object	RW	RPDO	0x60B80010	-	-	UDINT	114
1702: 07	Seventh mapping object	RW	RPDO	0x607F0020	-	-	UDINT	114
1A00: 01	First mapping object	RW	TPDO	0x60410010	-	-	UDINT	114
1A00: 02	Second mapping object	RW	TPDO	0x60640020	-	-	UDINT	114
1A00: 03	Third mapping object	RW	TPDO	0x60B90010	-	-	UDINT	114
1A00: 04	Fourth mapping object	RW	TPDO	0x60BA0020	-	-	UDINT	114
1A00: 05	Fifth mapping	RW	TPDO	0x60BC0020	-	-	UDINT	114

Object dictionary (Hex)	Name	Accessibility	Data mapping	Default	Data range	Unit	Data Type	Page number
	object							
1A00: 06	Sixth mapping object	RW	TPDO	0x603F0010	-	-	UDINT	114
1A00: 07	Seventh mapping object	RW	TPDO	0x60610008	-	-	UDINT	114
1B01: 01	First mapping object	RO	TPDO	0x603F0010	-	-	UDINT	115
1B01: 02	Second mapping object	RO	TPDO	0x60410010	-	-	UDINT	115
1B01: 03	Third mapping object	RO	TPDO	0x60640020	-	-	UDINT	115
1B01: 04	Fourth mapping object	RO	TPDO	0x60770010	-	-	UDINT	115
1B01: 05	Fifth mapping object	RO	TPDO	0x60F40020	-	-	UDINT	115
1B01: 06	Sixth mapping object	RO	TPDO	0x60610008	-	-	UDINT	115
1C12: 01	Index of objects allocated by RPDO	RW	RPDO	0x1701	-	-	ARR	115
1C13: 01	Index of objects assigned by TPDO	RW	No	0x0001	-	-	ARR	115
1C32: 01	Synchronization type	RW	No	0x0002	-	-	UINT	116
1C32: 04	Synchronization types supported	RO	No	0x0005	-	-	UDINT	116
1C32: 05	Minimum cycle time	RO	No	0x0001E848	-	-	UINT	116
1C33: 01	Synchronizati	RW	No	0x0002	-	-	UINT	116

Object dictionary (Hex)	Name	Accessibility	Data mapping	Default	Data range	Unit	Data Type	Page number
	on type							
1C33: 04	Synchronization types supported	RO	No	0x0005	-	-	UDINT	116
1C33: 05	Minimum cycle time	RO	No	0x0001E848	-	-	UINT	116

Group 2000

Object dictionary (Hex)		Function code (Dec)	Name	Setting method	Valid time	Default	Range	Unit	Data type
Index	Sub-index								
2000	04	P00-04	Rotation direction	Shutdown setting	Valid immediately	0	0 to 1	-	16 Bit
2000	09	P00-09	Braking resistance setting	Operation setting	Valid immediately	0	0 to 3	-	16 Bit
2000	0A	P00-10	External braking resistor resistance	Operation setting	Valid immediately	50	0~65535	Ω	16 Bit
2000	0B	P00-11	External braking resistor power	Operation setting	Valid immediately	100	0~65535	W	16 Bit
2000	1E	P00-30	Shield multi-turn absolute encoder battery fault	Operation setting	Power-on again	0	0 to 1	-	16 Bit

Group 2001

Object dictionary (Hex)		Function code (Dec)	Name	Setting method	Valid time	Default	Range	Unit	Data type
Index	Sub-index								
2001	0A	P01-10	MaxSpeedLimit	Operation setting	Valid immediately	3600	0~5000	rpm	16 Bit
2001	0B	P01-11	WarmSpeedTh	Operation setting	Valid immediately	3300	0~5000	rpm	16 Bit

Object dictionary (Hex)		Function code (Dec)	Name	Setting method	Valid time	Default	Range	Unit	Data type
Index	Sub-index								
2001	0C	P01-12	PosSpeedTh	Operation setting	Valid immediately	3000	0~5000	rpm	16 Bit
2001	0D	P01-13	NegSpeedTh	Operation setting	Valid immediately	3000	0~5000	rpm	16 Bit
2001	0E	P01-14	ToqLimitSrc	Shutdown setting	Valid immediately	0	0 to 1	-	16 Bit
2001	0F	P01-15	PToqLim	Operation setting	Valid immediately	3000	0~3000	0.1%	16 Bit
2001	10	P01-16	NToqLim	Operation setting	Valid immediately	3000	0~3000	0.1%	16 Bit
2001	13	P01-19	ToqLimTime	Operation setting	Valid immediately	1000	0~65535	ms	16 Bit
2001	14	P01-20	SoftOverCurrentDt	Operation setting	Valid immediately	8	0~65535	-	16 Bit
2001	1E	P01-30	Delay from brake output ON to instruction reception	Operation setting	Valid immediately	250	0~500	ms	16 Bit
2001	1F	P01-31	In the static state, delay from the “brake output is OFF to the motor is not energized”.	Operation setting	Valid immediately	150	1~1000	ms	16 Bit
2001	20	P01-32	Rotation status, when the brake output is OFF, the speed threshold.	Operation setting	Valid immediately	30	0~3000	rpm	16 Bit

Object dictionary (Hex)		Function code (Dec)	Name	Setting method	Valid time	Default	Range	Unit	Data type
Index	Sub-index								
2001	21	P01-33	Rotation status, delay from servo enable OFF to brake output OFF	Operation setting	Valid immediately	500	1~1000	ms	16 Bit

Group 2002

Object dictionary (Hex)		Function code (Dec)	Name	Setting method	Valid time	Default	Range	Unit	Data type
Index	Sub-index								
2002	01	P02-01	PosLoop1stGain	Operation setting	Valid immediately	400	0~6200	0.1Hz	16 Bit
2002	02	P02-02	SpdLoop1stGain	Operation setting	Valid immediately	65	0~35000	0.1Hz	16 Bit
2002	03	P02-03	SpdLoop1stIntgTime	Operation setting	Valid immediately	1000	100~65535	0.1ms	16 Bit
2002	09	P02-09	SpdFeedForwardGain	Operation setting	Valid immediately	0	0~1000	0.1%	16 Bit
2002	0A	P02-10	SpdFeedForwardFilter	Operation setting	Valid immediately	50	0~10000	0.01 ms	16 Bit
2002	0B	P02-11	ToqFeedForwardGain	Operation setting	Valid immediately	0	0~2000	0.1%	16 Bit
2002	0C	P02-12	ToqFeedForwardFilter	Operation setting	Valid immediately	50	0~10000	0.01 ms	16 Bit

Group 2003

Object dictionary (Hex)		Function code (Dec)	Name	Setting method	Valid time	Default	Range	Unit	Data type
Index	Sub-index								
2003	01	P03-01	Load InerRatio	Operation setting	Valid immediately	300	100~10000	0.01	16 Bit
2003	02	P03-02	RigiditySel	Operation setting	Valid immediately	14	0~31	-	16 Bit
2003	03	P03-03	SelfAdjustMode	Operation setting	Valid immediately	0	0 to 2	-	16 Bit
2003	04	P03-04	InerIdOnline	Operation setting	Valid immediately	0	0 to 2	-	16 Bit
2003	05	P03-05	InerIdCircle	Shutdown setting	Valid immediately	2	1 to 20	Circle	16 Bit
2003	06	P03-06	InerIdMaxSpd	Shutdown setting	Valid immediately	1000	300 to 2000	rpm	16 Bit
2003	07	P03-07	InerIdRollMode	Shutdown setting	Valid immediately	0	0 to 2	-	16 Bit
2003	08	P03-08	InerIdWaitTime	Shutdown setting	Valid immediately	1000	300 to 10000	ms	16 Bit

Group 2004

Object dictionary (Hex)		Function code (Dec)	Name	Setting method	Valid time	Default	Range	Unit	Data type
Index	Sub-index								
2004	01	P04-01	PulseFilterType	Shutdown	Valid immediat	0	0 to 1	-	16 Bit

Object dictionary (Hex)		Function code (Dec)	Name	Setting method	Valid time	Default	Range	Unit	Data type
Index	Sub-index								
				setting	ely				
2004	02	P04-02	LowpassFilterTime	Shutdown setting	Valid immediately	0	0~1000	ms	16 Bit
2004	03	P04-03	AveragingFilterTime	Shutdown setting	Valid immediately	0	0 to 128	ms	16 Bit
2004	04	P04-04	TogFilterTime	Operation setting	Valid immediately	50	10~2500	0.01 ms	16 Bit
2004	05	P04-05	NotchFilter1_Freq	Operation setting	Valid immediately	300	250 to 5000	Hz	16 Bit
2004	06	P04-06	NotchFilter1_Deep	Operation setting	valid immediately	100	0 to 100	-	16 Bit
2004	07	P04-07	NotchFilter1_Band	Operation setting	Valid immediately	4	0 to 12	-	16 Bit
2004	08	P04-08	NotchFilter2_Freq	Operation setting	Valid immediately	500	250 to 5000	Hz	16 Bit
2004	09	P04-09	NotchFilter2_Deep	Operation setting	Valid immediately	100	0 to 100	-	16 Bit
2004	0A	P04-10	NorthFilter2_Band	Operation setting	Valid immediately	4	0 to 12	-	16 Bit

Group 2005

Object dictionary (Hex)		Function code (Dec)	Name	Setting method	Valid time	Default	Range	Unit	Data type
Index	Sub-index								

Object dictionary (Hex)		Function code (Dec)	Name	Setting method	Valid time	Default	Range	Unit	Data type
Index	Sub-index								
2005	10	P05-16	RotateSpdDtTh	Operation setting	Valid immediately	20	0~1000	rpm	16 Bit
2005	13	P05-19	SpdZeroOutTh	Operation setting	Valid immediately	10	0~6000	rpm	16 Bit
2005	17	P05-23	Probe filter 1 time parameters	Operation setting	Valid immediately	200	0~500	10ns	16 Bit
2005	18	P05-24	Probe filter 2 time parameters	Operation setting	Valid immediately	200	0~500	10ns	16 Bit
2005	19	P05-19	TouchprobeDiOn CompensationTime	Operation setting	Valid immediately	500	-10000 to10000	10ns	16 Bit
2005	1A	P05-25	TouchprobeDiOff CompensationTime	Operation setting	Valid immediately	500	-10000 to10000	10ns	16 Bit

Group 2006

Object dictionary (Hex)		Function code (Dec)	Name	Setting method	Valid time	Default	Range	Unit	Data type
Index	Sub-index								
2006	02	P06-02	Di1FunSel	Operation setting	Power-on again	0	0~32	-	16 Bit
2006	03	P06-03	Di1LogSel	Operation setting	Valid immediately	0	0 to 1	-	16 Bit
2006	04	P06-04	Di1SrcSeL	Operation setting	Valid immediately	0	0 to 1	-	16 Bit

Object dictionary (Hex)		Function code (Dec)	Name	Setting method	Valid time	Default	Range	Unit	Data type
Index	Sub-index								
2006	05	P06-05	Di2FunSel	Operation setting	Power-on again	2	0~32	-	16 Bit
2006	06	P06-06	Di2LogSel	Operation setting	Valid immediately	0	0 to 1	-	16 Bit
2006	07	P06-07	Di2SrcSel	Operation setting	Valid immediately	0	0 to 1	-	16 Bit
2006	08	P06-08	Di3FunSel	Operation setting	Power-on again	3	0~32	-	16 Bit
2006	09	P06-09	Di3LogSel	Operation setting	Valid immediately	0	0 to 1	-	16 Bit
2006	0A	P06-10	Di3SrcSel	Operation setting	Valid immediately	0	0 to 1	-	16 Bit
2006	0B	P06-11	Di4FunSel	Operation setting	Power-on again	4	0~32	-	16 Bit
2006	0C	P06-12	Di4LogSel	Operation setting	Valid immediately	0	0 to 1	-	16 Bit
2006	0D	P06-13	Di4SrcSel	Operation setting	Valid immediately	0	0 to 1	-	16 Bit
2006	0E	P06-14	Di5FunSel	Operation setting	Power-on again	0	0~32	-	16 Bit
2006	0F	P06-15	Di5LogSel	Operation setting	Valid immediately	0	0 to 1	-	16 Bit
2006	10	P06-16	Di5SrcSel	Operation setting	Valid immediately	0	0 to 1	-	16 Bit
2006	11	P06-17	Di6FunSel	Operati	Power-on	0	0~32	-	16

Object dictionary (Hex)		Function code (Dec)	Name	Setting method	Valid time	Default	Range	Unit	Data type
Index	Sub-index								
				on setting	again				Bit
2006	12	P06-18	Di6LogSel	Operation setting	Valid immediately	0	0 to 1	-	16 Bit
2006	13	P06-19	Di6SrcSel	Operation setting	Valid immediately	0	0 to 1	-	16 Bit
2006	1A	P06-26	Do1FunSel	Operation setting	Valid immediately	132	128 ~ 148	-	16 Bit
2006	1B	P06-27	Do1LogSel	Operation setting	Valid immediately	0	0 to 1	-	16 Bit
2006	1C	P06-28	Do2FunSel	Operation setting	Valid immediately	130	128 ~ 148	-	16 Bit
2006	1D	P06-29	Do2LogSel	Operation setting	Valid immediately	0	0 to 1	-	16 Bit
2006	1E	P06-30	Do3FunSel	Operation setting	Valid immediately	129	128 ~ 148	-	16 Bit
2006	1F	P06-31	Do3LogSel	Operation setting	Valid immediately	0	0 to 1	-	16 Bit
2006	20	P06-34	ECAT forces DO to output state	Operation setting	Valid immediately	0	0 to 1	-	16 Bit

Group 200A

Object dictionary (Hex)	Function code (Dec)	Name	Setting method	Valid time	Default	Range	Unit	Data typ

Index	Sub-index								
200A	01	P10-01	SpdRefJOG	Operation setting	Valid immediately	100	0~3000	rpm	16 Bit
200A	02	P10-02	RstFuncFac	Shutdown setting	Valid immediately	0	0 to 1	-	16 Bit
200A	03	P10-03	ServoErrClear	Operation setting	Valid immediately	0	0 to 1	-	16 Bit
200A	04	P10-04	MotOLProtect_Coef	Operation setting	Valid immediately	100	0 to 800	%	16 Bit
200A	05	P10-05	Motor type	Operation setting	Power-on again	0	0 to 65535	-	16 Bit
200A	06	P10-06	AbsEncRst	Shutdown setting	Valid immediately	0	0 to 65535	-	16 Bit
200A	07	P10-07	Manual setting motor code	Operation setting	Power-on again	0	0 to 1	-	16 Bit
200A	08	P10-11	Motor stall over temperature enable	Operation setting	Valid immediately	0	0 to 1	-	16 Bit

Group 200D

Object dictionary (Hex)		Function code (Dec)	Name	Setting method	Valid time	Default	Range	Unit	Data type
Index	Sub-index								
200D	01	P13-01	CommVdi_1	Operation setting	Valid immediately	0	0 to 1	-	16 Bit
200D	02	P13-02	CommVdi_2	Operation setting	Valid immediately	0	0 to 1	-	16 Bit
200D	03	P13-03	CommVdi_3	Operatio	Valid immediatel	0	0 to 1	-	16

Object dictionary (Hex)		Function code (Dec)	Name	Setting method	Valid time	Default	Range	Unit	Data type
Index	Sub-index								
				n setting	y				Bit
200D	04	P13-04	CommVdi_4	Operation setting	Valid immediately	0	0 to 1	-	16 Bit
200D	05	P13-05	CommVdi_5	Operation setting	Valid immediately	0	0 to 1	-	16 Bit
200D	06	P13-06	CommVdi_6	Operation setting	Valid immediately	0	0 to 1	-	16 Bit
200D	0B	P13-11	CommVdo_1	Operation setting	Valid immediately	0	0 to 1	-	16 Bit
200D	0C	P13-12	CommVdo_2	Operation setting	Valid immediately	0	0 to 1	-	16 Bit
200D	0D	P13-13	CommVdo_3	Operation setting	Valid immediately	0	0 to 1	-	16 Bit

DI/DO channel function definition

DI channel function definition				
Channel function code	Name	Function name	Description	Remark
0	-	OFF (not used)	-	-
1	S-ON	Servo enabled	Invalid: Servo motor enabled function prohibited; Valid: Servo motor power-on enabled.	-
2	A-CLR	Fault and warning cleared	Invalid: Do not reset faults or warnings Valid: Reset fault or warning.	-
3	POT	Forward drive prohibited	Invalid: Forward drive allowed; Valid: Forward drive prohibited.	-
4	NOT	Reverse drive prohibited	Invalid: Reverse drive allowed; Valid: Reverse drive prohibited.	-
6	CL	Clear deviation counter	Invalid: The position deviation is not cleared; Valid: Position deviation is cleared.	-
8	E-STOP	Emergency stop	Invalid: Position lock after zero speed stop; Valid: Do not affect the current running state.	-
26	HOMEORG	Origin signal	Invalid: Do not affect the current operation of servo motor Valid: Servo motor implements origin regression mode.	-

DO channel function definition				
Channel function code	Name	Function name	Description	Remark
128	-	OFF (not used)	-	-
129	RDY	Servo ready	Servo is ready, and could receive S-ON signal. Invalid: Servo is not ready Valid: Servo is ready	-
130	ALM	Fault signal	Valid when the fault is detected	-
131	WARN	Warning signal	Valid when warning signals are output	-
132	TGON	Rotation detection	When the absolute value of servo motor speed is higher than 2005-10 set value: Invalid: The motor rotation detection signal is invalid Valid: The motor rotation detection signal is valid	-
133	ZSP	Zero speed signal	The signal output by the servo motor when it stops: Invalid: Motor zero speed signal is invalid Valid: Motor zero speed signal is valid	-
134	P-COIN	Positioning completed	In the position control mode, the absolute value of the position deviation meets the setting conditions of the object dictionary 6067h and 6068h, indicating that the servo positioning is completed.	-
137	V-NEAR	Speed approach	-	-
138	T-COIN	Torque arrival	Invalid: The absolute value of torque command is less than the set value Valid: The absolute value of torque command reaches the set value	-

DO channel function definition				
139	T-LIMIT	Torque limit	The confirmation signal of torque limit. Invalid: Motor torque is not limited Valid: Motor torque is limited	-
140	V-LIMIT	Speed limited	The confirmation signal of speed limit in torque mode. Invalid: Motor speed is not limited Valid: Motor speed is limited	-
141	BRK-OFF	Brake output	Outputting this signal indicates that the brake of the servo motor is released.	To use this DO function, you need to power it on again
142	SRV-ST	Servo start state Output	Invalid: servo drive is in non-running mode Valid: servo drive in running mode	-
145	COM_VDO1	Communication VDO1 output	Use communication VDO	-
146	COM_VDO2	Communication VDO2 output	Use communication VDO	
147	COM_VDO3	Communication VDO3 output	Use communication VDO	

Group 201E

Object dictionary (Hex)		Monitoring Quantity (Dec)	Monitoring name	Category	Unit	Data type
Index	Sub-index					
201E	01	U0-01	SrvStatus	Universal	-	16 Bit
201E	02	U0-02	SpeedDis	Universal	rpm	16 Bit
201E	03	U0-03	SpdCmd	Universal	rpm	16 Bit
201E	04	U0-04	PosCmdToSpd	Universal	rpm	16 Bit
201E	05	U0-05	PulsErr	Universal	Equivalent pulse unit	32 Bit
201E	09	U0-09	PulsTotal	Universal	Instruction unit	32 Bit

Object dictionary (Hex)		Monitoring Quantity (Dec)	Monitoring name	Category	Unit	Data type
Index	Sub-index					
201E	0D	U0-13	EncTotal_LowWord (Low 32 bits)	Universal	Encoder unit	32 Bit
201E	0F	U0-15	EncTotal_HighWord (High 32 bits)	Universal	Encoder unit	32 Bit
201E	11	U0-17	DiData1	Universal	-	16 Bit
201E	13	U0-19	DoData1	Universal	-	16 Bit
201E	14	U0-20	InerRatioReal	Universal	%	16 Bit
201E	17	U0-23	DisVibFreq	Universal	Hz	16 Bit
201E	18	U0-24	DisVibMag	Universal	rpm	16 Bit
201E	19	U0-25	PToqLimitDis	Universal	%	16 Bit
201E	1A	U0-26	NToqLimitDis	Universal	%	16 Bit
201E	1B	U0-27	PSpdLimitDis	Universal	rpm	16 Bit
201E	1C	U0-28	NSpdLimitDis	Universal	rpm	16 Bit
201E	1D	U0-29	MachineAngle	Universal	°	16 Bit
201E	1E	U0-30	ElecAngle	Universal	°	16 Bit
201E	1F	U0-31	DcBusVoltDisp	Universal	V	16 Bit
201E	20	U0-32	Temperature_IPM	Universal	°C	16 Bit
201E	21	U0-33	OutputPowerInst	Universal	W	16 Bit
201E	22	U0-34	OutputPowerAverage	Universal	W	16 Bit
201E	23	U0-35	HourTotalRun	Universal	h	16 Bit
201E	25	U0-37	MinTotalRun	Universal	min	16 Bit
201E	26	U0-38	SecTotalRun	Universal	s	16 Bit
201E	27	U0-39	ToqOutRate	Universal	%	16 Bit
201E	28	U0-40	HourCurrentRun	Universal	h	16 Bit
201E	2A	U0-42	MinCurrentRun	Universal	min	16 Bit
201E	2B	U0-43	SecCurrentRun	Universal	s	16 Bit

Object dictionary (Hex)		Monitoring Quantity (Dec)	Monitoring name	Category	Unit	Data type
Index	Sub-index					
201E	2C	U0-44	DisPwrInst	Universal	W	16 Bit
201E	2E	U0-46	DisPwrAvg	Universal	W	16 Bit
201E	30	U0-48	PwrUpCount	Universal	Times	16 Bit
201E	32	U0-50	MotoTotal_LowWord (lower 32 bits)	Universal	Circle	32 Bit
201E	33	U0-51	MotoTotal_HighWord (high 32 bits)	Universal	Circle	32 Bit
201E	35	U0-53	MotoModel	Universal	-	16 Bit
201E	36	U0-54	AbsEncIn1Cycle	Universal	Encoder unit	32 Bit
201E	37	U0-55	AbsEncMultiTurn	Universal	Circle	32 Bit
201E	38	U0-56	EncTotal_CmdUnit	Universal	Instruction unit	32 Bit

Group 201F

Object dictionary (Hex)		Monitoring Quantity (Dec)	Monitoring name	Category	Unit	Data type
Index	Sub-index					
201F	01	U1-01	NowErrorCode	Warning	-	16 Bit
201F	02	U1-02	NowWarmCode	Warning	-	16 Bit
201F	03	U1-03	IuWarmOccur	Warning	A	16 Bit
201F	04	U1-04	IvWarmOccur	Warning	A	16 Bit
201F	05	U1-05	UdcWarmOccur	Warning	V	16 Bit
201F	06	U1-06	T_IPMWarmOccur	Warning	°C	16 Bit
201F	07	U1-07	IqWarmOccur	Warning	%	16 Bit
201F	08	U1-08	IdWarmOccur	Warning	%	16 Bit
201F	09	U1-09	PosErrWarmOccur	Warning	Encoder Units	32 Bit
201F	0A	U1-10	SpdWarmOccur	Warning	rpm	16 Bit
201F	0B	U1-11	Time1WarmOccur	Warning	s	16 Bit
201F	0C	U1-12	ErrCntCurRun	Warning	-	16 Bit
201F	0D	U1-13	WarmCntCurRun	Warning	-	16 Bit
201F	0E	U1-14	ErrorTotalCnt	Warning	-	16 Bit
201F	0F	U1-15	WarmTotalCnt	Warning	-	16 Bit
201F	10	U1-16	ErrCodeLast1st	Warning	-	16 Bit
201F	11	U1-17	ErrCodeLast2nd	Warning	-	16 Bit
201F	12	U1-18	ErrCodeLast3rd	Warning	-	16 Bit
201F	13	U1-19	ErrCodeLast4th	Warning	-	16 Bit

Object dictionary (Hex)		Monitoring Quantity (Dec)	Monitoring name	Category	Unit	Data type
Index	Sub-index					
201F	14	U1-20	ErrCodeLast5th	Warning	-	16 Bit
201F	15	U1-21	WarmCodeLast1st	Warning	-	16 Bit
201F	16	U1-22	WarmCodeLast2nd	Warning	-	16 Bit
201F	17	U1-23	WarmCodeLast3rd	Warning	-	16 Bit
201F	18	U1-24	WarmCodeLast4th	Warning	-	16 Bit
201F	19	U1-25	WarmCodeLast5th	Warning	-	16 Bit

Group 2020

Object dictionary (Hex)		Monitoring Quantity (Dec)	Monitoring name	Category	Unit	Data type
Index	Sub-index					
2020	01	U2-01	ProductSer	Device	-	16 Bit
2020	02	U2-02	Model1	Device	-	16 Bit
2020	03	U2-03	Model2	Device	-	16 Bit
2020	04	U2-04	FirewareVer	Device	-	16 Bit
2020	05	U2-05	HardwareVer	Device	-	16 Bit
2020	06	U2-06	ExFactoryYear	Device	Year	16 Bit
2020	07	U2-07	ExFactoryMonth	Device	Month	16 Bit
2020	08	U2-08	ExFactoryDay	Device	Day	16 Bit
2020	09	U2-09	DeviceSerNum1	Device	-	16 Bit
2020	0A	U2-10	DeviceSerNum2	Device	-	16 Bit
2020	0B	U2-11	DeviceSerNum3	Device	-	16 Bit
2020	0C	U2-12	EtherCAT XML version number	Device	-	16 Bit

Object dictionary (Hex)		Monitoring Quantity (Dec)	Monitoring name	Category	Unit	Data type
Index	Sub-index					
2020	0D	U2-13	Chip model (high byte)	Device	-	16 Bit
2020	0E	U2-14	Chip model (low byte)	Device	-	16 Bit
2020	0F	U2-15	CPU ID (high byte)	Device	-	16 Bit
2020	10	U2-16	CPU ID (low byte)	Device	-	16 Bit

Group 6000

Object dictionary (Hex)	Name	Accessibility	Data mapping	Default	Data range	Unit	Data type
603F	Error code	RO	TPDO	0	0~65535	-	16 Bit
6040	Control word	RW	TPDO	0	0~65535	-	16 Bit
6041	Status word	RO	TPDO	0	0~65535	-	16 Bit
605A	Quick-stop option code	RW	No	2	0 to 7	-	16 Bit
605D	Halt option code	RW	No	1	1 to 3	-	16 Bit
6060	Modes of servo operation	RW	RPDO	0	0 ~ 10	-	8 bit
6061	Modes operation	RO	TPDO	0	0 ~ 10	-	8 bit
6062	Position demand value	RO	TPDO	0	-	Instruction unit	32 Bit
6063	Position actual value	RO	TPDO	0	-	Encoder Units	32 Bit
6064	Position actual value	RO	TPDO	0	-	Instruction unit	32 Bit
6065	Following error window	RW	RPDO	524288	1 to $(2^{32}-1)$	Instruction unit	32 Bit
6067	Position window	RW	RPDO	0	0 to 2^{32}	Encoder	32

Object dictionary (Hex)	Name	Accessibility	Data mapping	Default	Data range	Unit	Data type
						Units	Bit
6068	Position window time	RW	RPDO	0	0~65535	1ms	16 Bit
606C	Velocity actual value	RW	TPDO	0	-	Instruction unit/s	32 Bit
606D	Velocity window	RW	RPDO	10	0~65535	rpm	16 Bit
606E	Velocity window time	RW	RPDO	0	0~65535	ms	16 Bit
6071	Target torque	RW	RPDO	0	-5000~5000	0.1%	16 Bit
6072	Max torque	RW	RPDO	5000	0~5000	0.1%	16 Bit
6074	Torque demand	RO	TPDO	0	-5000~5000	0.1%	16 Bit
6077	Torque actual value	RO	TPDO	0	-5000~5000	0.1%	16 Bit
607A	Target position	RW	RPDO	0	-2^{31} to $(2^{31}-1)$	Instruction unit	32 Bit
607C	Home offset	RW	RPDO	0	-2^{31} to $(2^{31}-1)$	Instruction unit	32 Bit
607D: 01	Min position limit	RW	RPDO	-2^{31}	-2^{31} to $(2^{31}-1)$	User position unit	32 Bit
607D: 02	Max position limit	RW	RPDO	$-2^{31}-1$	-2^{31} to $(2^{31}-1)$	User position unit	32 Bit
607E	Command polarity	RW	RPDO	0	0 ~ 255	-	8 bit
607F	Max profile velocity	RW	RPDO		0 to $(2^{32}-1)$	Instruction unit/s	32 Bit
6081	Profile velocity	RW	RPDO	0	0 to $(2^{32}-1)$	User position speed unit	32 Bit
6083	Profile acceleration	RW	RPDO	100	0 to	Instruction on	32

Object dictionary (Hex)	Name	Accessibility	Data mapping	Default	Data range	Unit	Data type
					$(2^{32}-1)$	unit/s^2	Bit
6084	Profile deceleration	RW	RPDO	100	0 to $(2^{32}-1)$	Instruction unit/s^2	32 Bit
6085	Quick stop deceleration	RW	RPDO	100	0 to $(2^{32}-1)$	User acceleration unit	32 Bit
6086	Motion profile type	RW	RPDO	0	-2^{15} to $(2^{15}-1)$	-	16 Bit
6087	Torque slope	RW	RPDO	$2^{32}-1$	0 to $(2^{32}-1)$	0.1%/s	32 Bit
6091: 01	Gear ratio	RW	RPDO	1	1 to $(2^{32}-1)$	-	32 Bit
6091: 02	Motor revolutions	RW	RPDO	1	1 to $(2^{32}-1)$	-	32 Bit
6098	Homing method	RW	RPDO	1	1 to 35	-	8 bit
6099: 01	Speed during search for switch	RW	RPDO	100	0 to $(2^{32}-1)$	Instruction unit/s	32 Bit
6099: 02	Speed during search for zero	RW	RPDO	100	0 to $(2^{32}-1)$	Instruction unit/s	32 Bit
609A	Home acceleration	RW	RPDO	100	0 to $(2^{32}-1)$	Instruction unit/s^2	32 Bit
60B0	Position offset	RW	RPDO	0	-2^{31} to $(2^{31}-1)$	Instruction unit	32 Bit
60B1	Velocity offset	RW	RPDO	0	-2^{31} to $(2^{31}-1)$	Instruction unit/s	32 Bit
60B2	Torque offset	RW	RPDO	0	-5000~5000	0.1%	16 Bit
60B8	Touch probe function	RW	RPDO	0	0~65535	-	16 Bit
60B9	Touch probe status	RO	TPDO	0	0~65535	-	16 Bit
60BA	Touch probe Pos1 Pos Value	RO	TPDO	0	-2^{31} to $(2^{31}-1)$	Instruction unit	32 Bit

Object dictionary (Hex)	Name	Accessibility	Data mapping	Default	Data range	Unit	Data type
60BB	Touch Probe Pos1 Neg Value	RO	TPDO	0	-2^{31} to $(2^{31}-1)$	Instruction unit	32 Bit
60BC	Touch Probe Pos2 Pos Value	RO	TPDO	0	-2^{31} to $(2^{31}-1)$	Instruction unit	32 Bit
60BD	Touch Probe Pos2 Neg Value	RO	TPDO	0	-2^{31} to $(2^{31}-1)$	Instruction unit	32 Bit
60E0	Forward Direction Torque Limit Value	RW	RPDO	5000	0~5000	0.1%	16 Bit
60E1	Reverse Direction Torque Limit Value	RW	RPDO	5000	0~5000	0.1%	16 Bit
60F4	Following error actual value	RO	RPDO	-	-	Instruction unit	32 Bit
60FC	Position demand value	RO	TPDO	-	-	Encoder Units	32 Bit
60FD	Digital Input	RO	PDO	-	0 to 2^{32}	-	32 Bit
60FE:01	Digital Output Dictionary	RW	RPDO	0	0~65535	-	32 Bit
60FE:02	Digital Output Dictionary	RW	RPDO	0	0~65535	-	32 Bit
60FF	Profile velocity	RW	RPDO	0	-	Instruction unit/s	32 Bit
6502	Support servo operation mode	RO	TPDO	-	-	-	32 Bit

11.2 List of Fault and Warning Codes

Clearable: the panel can stop the fault display state by giving a "clear signal".
Stop immediately: The control action state stops immediately.

Code	Content	Cleanable	Immediately Stop
Er.01	Parameter damage		○
Er.02	Parameter storage error		○
Er.03	ADC reference source error		○
Er.04	AD current sampling conversion error		○
Er.05	Abnormal FPGA communication		○
Er.06	Wrong FPGA program version		○
Er.07	Clock exception		○
Er.09	Abnormal network status switching	✔	○
Er.10	Loss of synchronization	✔	○
Er.11	Unburned XML configuration file	✔	○
Er.12	Network initialization failed	✔	○
Er.34	Motor overload protection	✔	○
Er.35	Electronic gear ratio exceeds limit	✔	○
Er.36	Position deviation is too large	✔	○
Er.37	Abnormal torque saturation	✔	○
Er.38	Main circuit electrical phase loss	✔	○
Er.39	Emergency stop	✔	○
Er.40	Encoder battery failure	✔	○
Er.41	Motor (encoder) over temperature	✔	○
Er.42	Encoder write failure	✔	○
Er.44	Back to original timeout fault	✔	○
Er.60	ADC conversion is not completed		○

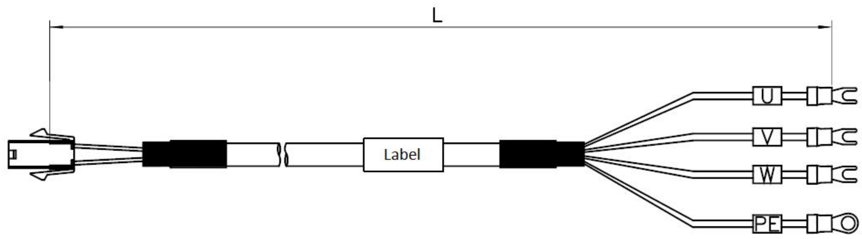
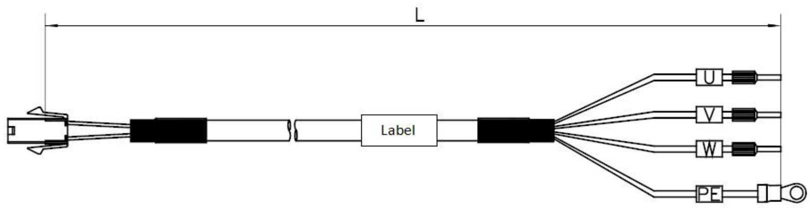
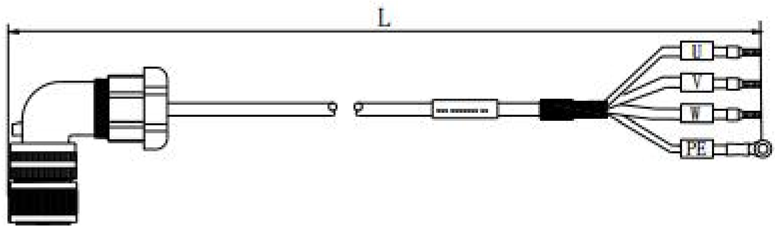
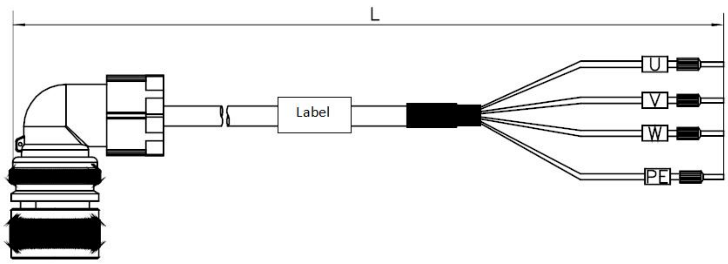
Code	Content	Cleanable	Immediately Stop
Er.13	Synchronization period setting error	✔	○
Er.14	Synchronization period error is too large	✔	
Er.20	Overcurrent		○
Er.21	Main power supply is undervoltage	✔	○
Er.22	Main power supply is overvoltage	✔	○
Er.23	Braking resistor is not connected	✔	○
Er.24	The braking resistor is turned on abnormally		○
Er.25	Wrong motor model	✔	○
Er.26	Wrong motor model		○
Er.27	Encoder is disconnected	✔	○
Er.28	Encoder Z pulse is lost		○
Er.61	Internal software fault		○
Er.62	Internal software fault		○
Er.63	Internal software fault		○
Er.64	Internal software fault		○
Er.65	Internal software fault		○
A-81	Over speed alarm	✔	
A-82	Overload	✔	
A-83	Braking resistor is over temperature or overload	✔	
A-84	Parameter modification that needs to be powered on again	✔	
A-88	Main circuit instantaneous power failure	✔	
A-89	Duplicate DI port configuration	✔	

Code	Content	Cleanable	Immediately Stop
Er.30	Encoder UVW signal error		○
Er.31	Power line disconnection	✔	○
Er.32	Exceeding motor maximum speed		○
Er.33	Power module is over temperature	✔	○

Code	Content	Cleanable	Immediately Stop
A-90	Duplicate DO port configuration	✔	
A-91	Parameter modification is too frequent	✔	
A-92	Encoder battery voltage low warning	✔	
A-93	Encoder read and write check is abnormal and frequency is too high	✔	

11.3 Wire

Table 11-1 Appearance of servo motor power cable

<table>
<tr><th>Wire type</th><th>Cable length L</th><th>Appearance drawing of cable</th></tr>
<tr><td>P-Z3O1-R4M-3MX4</td><td>3 meters</td><td rowspan="3">
Suitable for [VD3E type A drive], which can connect [60/80 flange conductor motor]</td></tr>
<tr><td>P-Z3O1-R4M-5MX4</td><td>5 meters</td></tr>
<tr><td>P-Z3O1-R4M-10MX4</td><td>10 meters</td></tr>
<tr><td>P-U3O1-R4M-3MX4</td><td>3 meters</td><td rowspan="3">
Suitable for [VD3E type B drive], which can connect [80 flange conductor motor]</td></tr>
<tr><td>P-U3O1-R4M-5MX4</td><td>5 meters</td></tr>
<tr><td>P-U3O1-R4M-10MX4</td><td>10 meters</td></tr>
<tr><td>P-Z3O1-H28J4M-3MX4</td><td>3 meters</td><td rowspan="3">
Suitable for [VD3E type A drive], which can connect [110/130 flange conductor motor]</td></tr>
<tr><td>P-Z3O1-H28J4M-5MX4</td><td>5 meters</td></tr>
<tr><td>P-Z3O1-H28J4M-10MX4</td><td>10 meters</td></tr>
<tr><td>P-U3O1-H28J4M-3MX4</td><td>3 meters</td><td rowspan="3">
Suitable for [VD3E type B drive], which can connect [110/130</td></tr>
<tr><td>P-U3O1-H28J4M-5MX4</td><td>5 meters</td></tr>
<tr><td>P-U3O1-H28J4M-10MX4</td><td>10 meters</td></tr>
</table>

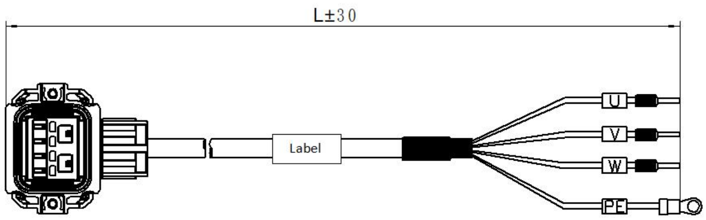
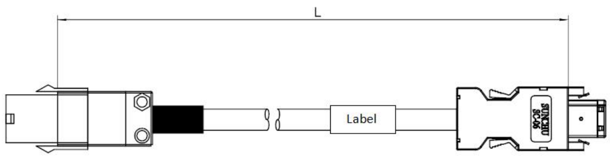
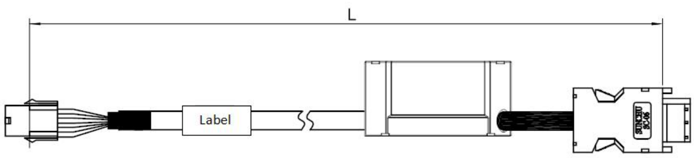
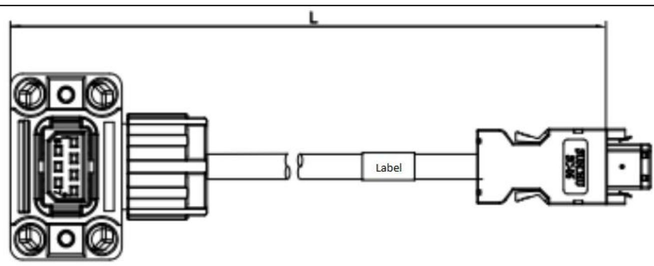
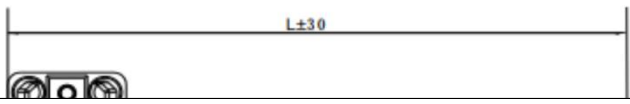
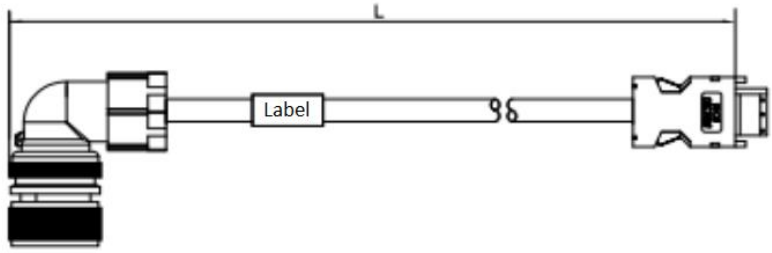
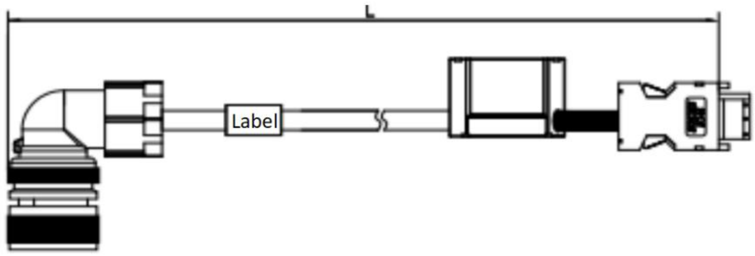
		flange conductor motor]
P-Z3O1-MC4S-3MX4	3 meters	 Suitable for [VD3E type A drive], which can connect [60/80 flange conductor motor]
P-Z3O1-MC4S-5MX4	5 meters	
P-Z3O1-MC4S-10MX4	10 meters	
E-J1394-R9M-3MX5-A	3 meters	 Suitable for [VD3E series drive], which can connect [60/80 flange conductor motor (single-turn encoder)]
E-J1394-R9M-5MX5-A	5 meters	
E-J1394-R9M-10MX5-A	10 meters	

Table 11-2 Appearance diagram of servo encoder cable

Wire type	Cable length L	Appearance drawing of cable
E-J1394-R9M-3MX7-A1	3 meters	 Suitable for [VD3E series drive], which can connect [60/80 flange conductor motor (multi-turn encoder)]
E-J1394-R9M-5MX7-A1	5 meters	
E-J1394-R9M-10MX7-A1	10 meters	
E-J1394-MC7S-3MX5-A	3 meters	 Suitable for [VD3E series drive], which can connect [60/80 flange connector motor (single-turn encoder)]
E-J1394-MC7S-5MX5-A	5 meters	
E-J1394-MC7S-10MX5-A	10 meters	
E-J1394-MC7S-3MX7-A1	3 meters	

E-J1394-MC7S-5MX7-A1	5 meters	Suitable for [VD3E series drive], which can connect [60/80 flange connector motor (multi-turn encoder)]
E-J1394-MC7S-10MX7-A1	10 meters	
E-J1394-H28K7M-3MX5-A	3 meters	 Suitable for [VD3E series drive], which can connect [110/130 flange motor (single-turn encoder)]
E-J1394-H28K7M-5MX5-A	5 meters	
E-J1394-H28K7M-10MX5-A	10 meters	
E-J1394-H28K7M-3MX7-A1	3 meters	 Suitable for [VD3E series drive], which can connect [110/130 flange motor (multi-turn encoder)]
E-J1394-H28K7M-5MX7-A1	5 meters	
E-J1394-H28K7M-10MX7-A1	10 meters	

11.4 Correspondence of International Standards

The products meet the requirements of EMC standards:

Certification information

Certification name	Certification symbol	Instruction Name		Standards	
CE certification	CE	EMC Directive	2014/30/EU	Servo drive Servo motor	EN 61800-3 C2

The VD3E series drives comply with European EMC Directive 2014/30/EU and meet the requirements of EN 61800-3 C2 under the following conditions.

The recommended external EMC filter should be installed at the input terminal of the drive, and the shielded wire should be selected at the output terminal. Ensure the reliable grounding of the filter and 360° overlapping grounding of output line shielding. For the selection of EMC filters, check "11.4.1 Hardware Requirements (1) EMC Filter Recommendations" below Table 11-3 Recommended Manufacturers and Models of EMC Input Filters"";

The input terminal needs to be equipped with AC inductors that meet the requirements;

Shielded cable shall be used for driving cable between drive and motor. Please refer to below for cable selection and installation: "11.4.1 Hardware Requirements"[(3) Cable requirements and wiring]";

Install the drive and wiring according to the recommended cable wiring method as below: "11.4.1 Hardware Requirements"[(3) Cable requirements and wiring]";

Install a common mode filter if necessary.

11.4.1 Hardware requirements

(1) EMC filter recommendation

Recommended model: SCHAFFNER models are recommended as shown in the following table:

Table 11-3 Recommended manufacturers and models of EMC input filters

Series	Drive model	Rated input current	Filter model
		IN	SCHAFFNER
VD3E-0xxSA1G			
Single-phase 220V	VD3E-003SA1G	0.9	FN 2090-1-06
	VD3E-010SA1G	3.6	FN 2090-4-06
	VD3E-014SA1G	6.7	FN 2090-8-06
	VD3E-016SA1G	13.4	FN 2090-16-06
	VD3E-021SA1G	20	FN 2090-20-06
Three-phase 220V	VD3E-016SA1G	7.7	FN 3258-16-44
	VD3E-021SA1G	11.9	FN 3258-16-44
	VD3E-030SA1G	13.4	FN 3258-16-44
VD3E-0xxTA1G			

Three-phase 380V	VD3E-021TA1G	8.6	FN 3258-16-44

Applicable to European EMC directives.
Servo drives and motors cannot be used in ordinary families or connected to low-voltage public communication circuits. The drive may send radio frequency if the similar loops above is connected.
For its application to EMC directives, please use noise filters and surge absorbers and ferrite magnetic rings. As for the EMC Directive's applies on machinery and equipment, and the final mechanical equipment for assembling drives and motors must be confirmed.

(2) Requirements for AC input inductors

The AC input inductor is mainly used to reduce the filtering in the input current. As an optional accessory, it should be external connect when the application environment has high harmonic requirements.

(3) Cable requirements and wiring

① Cable requirements
In order to meet the EMC requirements of CE marking, shielding lines with shielding layer must be used. Shielding line has three phase conductors and four phase conductors. If the conductivity of the shielding line layer cannot meet the requirements, a separate PE wire needs to be added. Or shielding line with four phase conductors, one of which is PE wire. In order to effectively suppress the emission and conduction of radio frequency interference, the shielding layer of shielding wire is composed of coaxial copper braided tape. In order to increase shielding effectiveness and electrical conductivity, the braiding density of shielding layer should be greater than 90%.
② Wiring requirements
Motor cables and their PE shielded wire (twister shield) should be as short as possible to reduce electromagnetic radiation and stray current and capacitive current outside the cable. If the length of motor cable exceeds 100m, it is required to install output filter or dv/dt inductor. It is recommended that all control cables should be shielding lines. Motor cable wiring must be far away from other cable wiring. Motor cables of several drives can be wired side by side. It is recommended to put the motor cable, input power cables and control cables respectively distributed in different troughs. In order to avoid electromagnetic interference caused by rapid changes in the output voltage of the drive, long-distance side-by-side routing of motor cables and other cables should be avoided.
When the control cable must pass through the power cable, ensure that the included angle between the two cables is kept at 90 degrees as much as possible. Do not put other cables through the drive. The power input and output lines of the drive and weak current signal lines (such as control lines) should not be arranged in parallel as far as possible, but vertically when conditions permit. Cable troughs must be well connected and well grounded. Aluminum trough can be used to improve equipotential. Filters, drives and motors should be well overlapped with the system (machinery or device), and spraying protection should be done in the installation part, and conductive metals should be fully contacted.

(3) Leakage current suppression

Because the output of the drive is a high-speed pulse voltage, high-frequency leakage current will be generated. Drive equipment will generate DC leakage current in protective conductor, and B-type (delay type) leakage protection circuit breaker must be used. If it’s necessary to install multiple drives, each drive shall be provided with a leakage protection circuit breaker.

11.4.2 Recommendations for common EMC issues

Drive products belong to strong interference equipment. When there are problems in wiring and grounding during use, interference may still occur. When interference with other equipment occurs, the following methods can be adopted for rectification.

Table 11-4 Common EMC interference problems and rectification methods

Interference states	Rectification method
Switch trip of leakage protection circuit breaker	◆Reduce the carrier frequency without affecting the performance; ◆Reduce the length of driving line; ◆Add a magnet ring to the input drive; ◆If the power-on trips instantly, it is necessary to disconnect the large ground current at the input terminal; (Disconnect the ground of the external or internal filter and the ground terminal of the input port to the ground y capacitor) ◆In case of running or enabling trip, leakage current suppression measures should be installed at the input terminal. (Leakage current filter, safety capacitor and magnet ring, magnet ring)
Interference caused by drive running	◆The motor shell is connected to the PE end of the drive; ◆The PE terminal of the drive is connected to the power grid PE; ◆Add a magnet ring to input power; ◆Power supply or magnet ring is added to the interfered signal port; ◆Add additional common ground connection between devices.
Communication interference	◆Connect the motor shell to the PE end of the drive; ◆Connect the PE terminal of the drive to the power grid PE; ◆Add a magnet ring to input power line; ◆Add matching resistors to the communication line source and load terminal; ◆Differential line of communication line adds external communication common ground line; ◆Shielded wires for communication lines, and the shielding layer is connected to the communication common place; ◆Multi-node communication wiring needs daisy chain, and the length of branch line is less than 30cm.

Interference states	Rectification method
I/O interference	◆Low-speed DI increases capacitance filtering, and the maximum value is recommended to 0.1 uF; ◆AI increases capacitance filtering, and the recommended maximum value is 0.22 uF.

Notice

◆This series of products should strictly comply with EMC-related electrical installation requirements in the manual to meet EMC certification standards;

◆When the CE marking is attached to the equipment or device with this series of products, please confirm whether the final equipment or device meets the European unified standard, and the relevant responsibility shall be borne by the customer of the final assembled product;

◆For more product certification information, please consult our agent or sales person in charge.