



User Guide

HVAC Drive H300

Standard and High IP

Model Sizes 3 to 12

Universal Variable Speed AC drive for induction and permanent magnet motors



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Compliance Information

Manufacturer: Nidec Control Techniques Limited ("we", "our")

Registered office: The Gro, Newtown, Powys, SY16 3BE United Kingdom

Registered in: England and Wales, company registration number 01236886

Manufacturer's EU Authorised Representative: Nidec Netherlands B.V., Kubus 155, 3364 DG Slidrecht, the Netherlands, registered at the Dutch Trade Register under number 33213151; Tel. +31 (0)184 420 555, info.nl@mail.nidec.com

Original instructions

With reference to the UK Supply of Machinery (Safety) Regulations 2008 and the EU Machinery Directive 2006/42/EC, the English version of this Manual constitutes the original instructions. Manuals published in other languages are translations of the original instructions and the English language version of this Manual prevails over any other language version in the event of inconsistency.

Documentation and user software tools

Manuals, datasheets and software that we make available to users of our products can be downloaded from: <http://www.controltechniques.com/support>.

Manuals may be accompanied by an Errata list. This will be located alongside the manuals if applicable.

Warranty and liability

The contents of this Manual are presented for information purposes only, and while every effort has been made to ensure their accuracy, they are not to be construed as warranties or guarantees, express or implied, regarding the products or services described herein or their use or applicability. All sales are governed by our terms and conditions, which are available on request. We reserve the right to modify or improve the designs, specifications or performance of our products at any time without notice. For full details of the warranty terms applicable to the product, contact the supplier of the product.

In no event and under no circumstances shall we be liable for damages and failures due to misuse, abuse, improper installation, or abnormal conditions of temperature, dust, or corrosion, or failures due to operation outside the published ratings for the product, nor shall we be liable for consequential and incidental damages of any kind.

Environmental management

We operate an Environmental Management System which complies with the requirements of ISO 14001:2015. Further information on our Environmental Statement can be found at: <http://www.controltechniques.com/environment>.

Restriction and control of hazardous substances

The products covered by this Manual comply with the following legislation and regulations on the restriction and control of hazardous substances:

UK Restriction of the Use of Certain Hazardous Substances in Electrical and Electronic Equipment Regulations 2012

UK REACH etc. (Amendment etc.) (EU Exit) Regulations 2020, European Union REACH Regulation EC 1907/2006

EU restriction of the Use of certain Hazardous Substances in Electrical and Electronic Equipment (RoHS) - Directive 2011/65/EU

EC Regulation 1907/2006 on the Registration, Evaluation, authorisation, and restriction of Chemicals (REACH)

Chinese Administrative Measures for Restriction of Hazardous Substances in Electrical and Electronic Products 2016/07/01

U.S. Environmental Protection Agency ("EPA") regulations under the Toxic Substances Control Act ("TSCA")

MEPC 68/21 / Add.1, Annex 17, Resolution MEPC.269(68) 2015 Guidelines for the development of the inventory of hazardous materials

The products covered by this Manual do not contain asbestos.

Further information on REACH and RoHS can be found at: <http://www.controltechniques.com/environment>.

Conflict minerals

With reference to the Conflict Minerals (Compliance) (Northern Ireland) (EU Exit) Regulations 2020, the U.S. Dodd-Frank Wall Street Reform and Consumer Protection Act and Regulation (EU) 2017/821 of the European Parliament and of the European Council:

We have implemented due diligence measures for responsible sourcing, we conduct conflict minerals surveys of relevant suppliers, we continually review due diligence information received from suppliers against company expectations and our review process includes corrective action management. We are not required to file an annual conflict minerals disclosure. Nidec Control Techniques Limited is not an issuer as defined by the U.S. SEC.

Disposal and recycling (WEEE)



The products covered by this Manual fall within the scope of the UK Waste Electrical and Electronic Equipment Regulations 2013, EU Directive 2012/19/EU amended by EU Directive 2018/849 (EU) on Waste Electrical and Electronic Equipment (WEEE).

When electronic products reach the end of their useful life, they must not be disposed of along with domestic waste but should be recycled by a specialist recycler of electronic equipment. Our products are designed to be easily dismantled into their major component parts for efficient recycling. Most materials used in our products are suitable for recycling.

Our product packaging is of good quality and can be re-used. Smaller products are packaged in strong cardboard cartons which have a high recycled fibre content. Cartons can be re-used and recycled. Polythene, used in protective film and bags for the ground screws, can be recycled. When preparing to recycle or dispose of any product or packaging, please observe local legislation and best practice.

Copyright and trade marks

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No part of this Manual may be reproduced or transmitted in any form or by any means including by photocopying, recording or by an information storage or retrieval system, without our permission in writing.

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How to use this guide

This user guide provides complete information for installing the drive.

The information is in logical order, taking the reader from receiving the drive through to installation.

NOTE

There are specific safety warnings throughout this guide, located in the relevant sections. In addition, Chapter 1 *Safety information* contains general safety information. It is essential that the warnings are observed and the information considered when working with or designing a system using the drive.

This map of the user guide helps to find the right sections for the task you wish to complete, but for specific information, refer to the table of contents overleaf.

	Quick Start / bench testing	Familiarisation	System design	Programming and commissioning	Troubleshooting
1 Safety information	●	●	●	●	●
2 Product information		●	●		
3 Mechanical installation			●		
4 Electrical installation			●		
5 Getting started		●	●		
6 Basic parameters		●	●	●	
7 Running the motor	●	●	●	●	
8 Optimization			●	●	
9 NV media card operation			●	●	
10 Building automation			●	●	
11 Advanced parameters			●	●	
12 Technical data		●	●	●	
13 Diagnostics					●
14 UL listing information			●	●	

UK Declaration of Conformity

1. Product range

Unidrive-M, Commander, Digitax HD and derivative products, variable speed AC motor drive.

2. Name and address of the manufacturer

Nidec Control Techniques Ltd
The Gro
Pool Road
Newtown
Powys
SY16 3BE
UK

Registered in England and Wales. Company
Reg. No. 01236886
Telephone: 00 44 1686 612000
E mail: cthoadmin@mail.nidec.com
Web: www.controltechniques.com

3. Responsibility

This declaration is issued under the sole responsibility of the manufacturer.

4. Object of the declaration

Model number	Interpretation	Nomenclature aaaa - bbc dddde
aaaa	Basic series	C200, C300, M100, M101, M200, M201, M300, M400, M600, M608, M700, M701, M702, M708, M709, M750, M751, M753, M754, M880, M881, M882, M888, M889, E300, E301, F300, F600, H300, HS30, HS70, HS71, HS72, M000, RECT
bb	Frame size	01, 02, 03, 04, 05, 06, 07, 08, 09, 10, 11, 12
c	Voltage rating	1 = 100 V, 2 = 200 V, 4 = 400 V, 5 = 575 V, 6 = 690 V
dddd	Current rating	Example 01000 = 100 A
e	Drive format	A = 6P Rectifier + Inverter with internal choke, D = Inverter, E = 6P Rectifier + Inverter, T = 12P Rectifier + Inverter

The model number may be followed by additional characters that do not affect the ratings.

Accessories (may not be suitable for every drive listed above)

Model No.	Model number
Option modules	SI-Applications Compact, SI-Applications Plus, SI-BACnet IP, SI-CANopen V2, SI-CiA417, SI-DeviceNet, SI-DCP, SI-Encoder V2, SI-EtherCAT, SI-Ethernet, SI-Interbus 500kBd, SI-Interbus 2MBd, SI-IO, SI-IO 24 Plus, SI-Powerlink, SI-PROFIBUS, SI-PROFINET V2, SI-PROFINET RT, SI-Option mounting kit, SI-Universal Encoder, Encoder breakout kit, PTi210, PTi210 V2, SI-Safety, SI-SLM, SI-Varan, MCI200, MCI200 V2, MCI210, MCI210 V2, MiS210, MiS250, KI-485 Adaptor, AI-485 Adaptor, AI-485 Adaptor 24V, AI-Backup adaptor, AI-Smart adaptor
Control pods	Mxxx-STANDARD011100A0100, Mxxx-MASTER11100A0100, M000-FOLLOWER011100A0100 Where Mxxx denotes M600, M700, M701, M702, HS70, HS71 or HS72
Displays, keypads and other accessories	KI-Keypad, KI-Keypad RTC, KI-HOA keypad RTC, KI-Compact Display, KI-Compact 485 adaptor, Remote Keypad (LCD), Remote Keypad RTC, CI-Keypad, CI-485 Adaptor, Capacitor module M75C, External DC cable connection kit, Multi axis kit (standard - with and without SI option mounting kit fitted), Cable grommet kit, External EMC filter, Fan replacement kit, Input inductor, Vent kit, Compact brake resistor kit, External brake resistor 20/40 or 80 ohm, Digitax HD to Uni M panel mounted & through hole mounted DC bus paralleling kits

5. Declaration

The object of the declaration is in conformity with the relevant UK statutory requirements:

UK Regulations
Electrical Equipment (Safety) Regulations 2016
Electromagnetic Compatibility Regulations 2016
The Restriction of the Use of Certain Hazardous Substances in Electrical and Electronic Equipment Regulations 2012
The Ecodesign for Energy-Related Products Regulations 2021 No. 745

6. References to the relevant designated British standards

The variable speed drive products listed above have been designed and manufactured in accordance with the following designated British standards:

EN 61800-5-1:2007 + A1:2017 + A11: 2021	Adjustable speed electrical power drive systems - Part 5-1: Safety requirements - Electrical, thermal and energy
BS EN 61800-3: 2018	Adjustable speed electrical power drive systems - Part 3: EMC requirements and specific test methods
BS EN 61000-6-2: 2019	Electromagnetic compatibility (EMC) - Part 6-2: Generic standards - Immunity for industrial environments
BS EN 61000-6-4: 2019	Electromagnetic compatibility (EMC) - Part 6-4: Generic standards - Emission standard for industrial environments
BS EN 61000-3-2:2019+A1:2021	Electromagnetic compatibility (EMC) - Part 3-2: Limits for harmonic current emissions (equipment input current \leq 16 A per phase)
EN 61000-3-3: 2013+A1:2019 + A2:2021	Electromagnetic compatibility (EMC) - Part 3-3: Limitation of voltage changes, voltage fluctuations and flicker in public, low voltage supply systems, for equipment with rated current \leq 16 A per phase and not subject to conditional connection
EN 61000-3-12: 2011	Electromagnetic compatibility (EMC) - Part 3-12: Limits. Limits for harmonic currents produced by equipment connected to public low-voltage systems with input current $>$ 16 A and \leq 75 A per phase.

7. Responsible person



Jon Holman-White
Vice President of Research and Development
Nidec Control Techniques Ltd
Date: 13th February 2025
Newtown, Powys, UK.

These electronic drive products are intended to be used with appropriate motors, controllers, electrical protection components and other equipment to form complete end products or systems. Compliance with safety and EMC regulations depends upon installing and configuring drives correctly, including using the specified input filters.

The drives must be installed only by professional installers who are familiar with requirements for safety and EMC. Refer to the Product Documentation. An EMC data sheet is available giving detailed information. The assembler is responsible for ensuring that the product or system complies with all the relevant laws in the country where it is to be used.

1-000-022-213 Rev.00.30

EU Declaration of Conformity - Machinery Directive

1. Product model

Unidrive-M, Digitax HD and derivative products incorporating a Safe Torque Off (STO) function used as a safety component of a machine. Only the Safe Torque Off function may be used as a safety component of a machine.

2. Name and address of the manufacturer and authorised representative

Manufacturer:

Nidec Control Techniques Ltd
The Gro
Newtown
Powys
UK
SY16 3BE

Authorised representative:

Nidec Netherlands B.V.
Kubus 155
3364 DG Sliedrecht
Netherlands.

Registered in England and Wales. Company Reg. No. 01236886

Telephone: 00 44 1686 612000

E mail: cthoadmin@mail.nidec.com

Web: www.controltechniques.com

3. Responsibility

This declaration is issued under the sole responsibility of the manufacturer.

4. Object of the declaration

Model number	Interpretation	Nomenclature aaaa - bbc ddddde
aaaa	Basic series	M600, M700, M701, M702, M608, M708, M709, CSD1, HS70, HS71, HS72, E200, E300, E301, M880, M881, M882, M889, F300, F600, H300, M751, M753, M750, M754
bb	Frame size	01, 02, 03, 04, 05, 06, 07, 08, 09, 10, 11, 12
c	Voltage rating	1 = 100 V, 2 = 200 V, 4 = 400 V, 5 = 575 V, 6 = 690 V
dddd	Current rating	Example 01000 = 100 A
e	Drive format	A = 6P Rectifier + Inverter (internal choke), D = Inverter, E = 6P Rectifier + Inverter (external choke), T = 12P Rectifier + Inverter (external choke)

The model number may be followed by additional characters that do not affect the ratings.

(Refer to the TUV Revision List: 01_205(U)_5270_0x_2x_RL_2025_01_09).

5. Declaration

The safety function STO within the above drive series fulfils the requirements of SIL 3 of EN 61800-5-2 / EN 61508 and Cat 4 / PLe of EN ISO 1384901 and can be used in safety related applications up to these safety levels and in the application area of EN IEC 62061:2021.

Further it can be used for electric passenger and goods lifts within the scope of EN 81-20, clause 5.9.2.5.4 d) as a SIL 3 drive control featuring a defined interface for stopping of the drive by a means of static elements.

The object of the declaration is in conformity with the following European Union harmonisation legislation:

Machinery Directive (2006/42/EC)

Electromagnetic Compatibility Directive (2014/30/EU)

Type examination has been carried out by the following notified body:

TUV Rheinland Industrie Service GmbH, Am Grauen Stein, D-51105 Köln, Germany

Notified body identification number: 0035

EC type-examination certificate number: 01/205/5270.03/22 dated 2022-08-26, valid until 2027-08-26.

6. References to the relevant harmonised standards used

The variable speed drive products listed above have been designed and manufactured in accordance with the following European harmonized standards:

EN 61800-5-2:2017	Adjustable speed electrical power drive systems - Part 5-2: Safety requirements - Functional
EN 61800-5-1:2007 + A1: 2017 + A11: 2021, 4.3, 5.2.3.8, 5.2.6	Adjustable speed electrical power drive systems - Part 5-1: Safety requirements - Electrical, thermal and energy
EN ISO 13849-1:2015	Safety of Machinery, Safety-related parts of control systems, General principles for design
EN 61508 Parts 1 - 7:2010	Functional safety of electrical/ electronic/programmable electronic safety-related systems

7. Signed for and on behalf of:

Person authorised to complete the technical file:

Authorised representative (see details above)



DoC authorised by:

Jon Holman-White, Vice President, Research and Development

Date:

24th July 2025, Newtown, Powys, UK

IMPORTANT NOTICE

These electronic drive products are intended to be used with appropriate motors, controllers, electrical protection components and other equipment to form complete power drive system (PDS).

It is the responsibility of the installer to ensure that the design of the system and machine, including its safety-related control system, is carried out in accordance with the requirements of the Machinery Directive and any other relevant legislation.

The use of a safety component does not ensure the safety of the machine.

Compliance with safety and EMC regulations depends upon installing and configuring drives correctly, including using the specified input filters.

The drive must be installed only by professional installers who are familiar with requirements for safety and EMC.

The assembler is responsible for ensuring that the final product or system complies with all relevant laws in the country where it is to be used. For more information regarding Safe Torque Off, refer to the Product Documentation.

EU Declaration of Conformity

1. Product range

Unidrive-M, Commander, Digitax HD and derivative products. Adjustable speed AC motor drives, including option modules and accessories.

2. Name and address of the manufacturer and authorised representative

Manufacturer

Nidec Control Techniques Ltd
The Gro
Newtown
Powys
UK
SY16 3BE

Authorised representative:

Nidec Netherlands B.V.
Kubus 155
3364 DG Slidrecht
Netherlands.

Registered in England and Wales. Company Reg. No. 01236886
Telephone: 00 44 1686 612000
E mail: cthoadmin@mail.nidec.com
Web: www.controltechniques.com

3. Responsibility

This declaration is issued under the sole responsibility of the manufacturer.

4. Object of the declaration

Variable speed drives

Model number	Interpretation	Model Number nomenclature aaaa - bbc ddddde
aaaa	Basic series	C200, C300, M100, M101, M200, M201, M300, M400, M600, M608, M700, M701, M702, M708, M709, M750, M751, M753, M754, M880, M881, M882, M888, M889, E300, E301, F300, F600, H300, HS30, HS70, HS71, HS72, M000, RECT
bb	Frame size	01, 02, 03, 04, 05, 06, 07, 08, 09, 10, 11, 12
c	Voltage rating	1 = 100 V, 2 = 200 V, 4 = 400 V, 5 = 575 V, 6 = 690 V
dddd	Current rating	Example 01000 = 100 A
e	Drive format	A = 6P Rectifier + Inverter with internal choke, D = Inverter, E = 6P Rectifier + Inverter, T = 12P Rectifier + Inverter

The model number may be followed by additional characters that do not affect the ratings.

Accessories (may not be suitable for every drive listed above)

Category	Description
Option modules	SI-Applications Compact, SI-Applications Plus, SI-BACnet IP, SI-CANopen V2, SI-CiA417, SI-DeviceNet, SI-DCP, SI-Encoder V2, SI-EtherCAT, SI-Ethernet, SI-Interbus 500kBd, SI-Interbus 2MBd, SI-IO, SI-IO 24 Plus, SI-Powerlink, SI-PROFIBUS, SI-PROFINET V2, SI-PROFINET RT, SI-Option mounting kit, SI-Universal Encoder, Encoder breakout kit, PTi210, PTi210 V2, SI-Safety, SI-SLM, SI-Varan, MCI200, MCI200 V2, MCI210, MCI210 V2, MiS210, MiS250, KI-485 Adaptor, AI-485 Adaptor, AI-485 Adaptor 24V, AI-Backup adaptor, AI-Smart adaptor
Control pods	Mxxx-STANDARD011100A0100, Mxxx-MASTER11100A0100, M000-FOLLOWER011100A0100 (where Mxxx denotes M600, M700, M701, M702, HS70, HS71 or HS72)
Displays, keypads, other accessories	KI-Keypad, KI-Keypad RTC, KI-HOA keypad RTC, KI-Compact Display, KI-Compact 485 adaptor, Remote Keypad (LCD), Remote Keypad RTC, CI-Keypad, CI-485 Adaptor, Capacitor module M75C, External DC cable connection kit, Multi axis kit (standard - with and without SI option mounting kit fitted), Cable grommet kit, External EMC filter, Fan replacement kit, Input inductor, Vent kit, Compact brake resistor kit, External brake resistor 20/40 or 80 ohm, Digitax HD to Uni M panel mounted & through hole mounted DC bus paralleling kits

5. Declaration: The object of the declaration is in conformity with the relevant European Union harmonisation legislation.

Low Voltage Directive (2014/35/EU)

Electromagnetic Compatibility Directive (2014/30/EU)

Restriction of Hazardous Substances Directive (2011/65/EU and 2015/863/EU)

Regulation 2019/1781 of directive 2009/125/EC (Energy related products).

6. References to the relevant harmonised EN standard

The variable speed drive products listed above have been designed and manufactured in accordance with the following European harmonised standards.

EN 61800-5-1:2007 + A1:2017 + A11: 2021	Adjustable speed electrical power drive systems - Part 5-1: Safety requirements - Electrical, thermal and energy
EN 61800-3: 2018	Adjustable speed electrical power drive systems - Part 3: EMC requirements and specific test methods
EN 61000-6-2: 2019	Electromagnetic compatibility (EMC) - Part 6-2: Generic standards - Immunity for industrial environments
EN 61000-6-4: 2019	Electromagnetic compatibility (EMC) - Part 6-4: Generic standards - Emission standard for industrial environments
EN 61000-3-2:2019+A1:2021	Electromagnetic compatibility (EMC) - Part 3-2: Limits for harmonic current emissions (equipment input current ≤ 16 A per phase)
EN 61000-3-3:2013+A1:2019 + A2:2021	Electromagnetic compatibility (EMC) - Part 3-3: Limitation of voltage changes, voltage fluctuations and flicker in public, low voltage supply systems, for equipment with rated current ≥ 16 A per phase and not subject to conditional connection
EN 61000-3-12: 2011	Electromagnetic compatibility (EMC) - Part 3-12: Limits. Limits for harmonic currents produced by equipment connected to public low-voltage systems with input current > 16 A and ≤ 75 A per phase.

7. Responsible person



Jon Holman-White
Vice President, Research and Development
Nidec Control Techniques Ltd
Date: 13th February 2025
Newtown, Powys, UK.

IMPORTANT NOTE

These products are Basic Drive Modules, intended to be used with motors, controllers, electrical protection components and other equipment to form Power Drive Systems. Compliance with safety and EMC regulations depends upon installing and configuring the drive modules correctly.

The drives must be installed only by professional installers who are familiar with requirements for safety and EMC. Refer to the Safety information and Installation instructions supplied with the drive. The installer is responsible for ensuring that the Power Drive System complies with all applicable laws in the country where it is to be used.

1 Safety information

1.1 Warnings, Cautions and Notes



A Warning contains information which is essential for avoiding a safety hazard.

WARNING



A Caution contains information which is necessary for avoiding a risk of damage to the product or other equipment.

CAUTION

NOTE

A Note contains information which helps to ensure correct operation of the product.

1.2 Important safety information. Hazards. Competence of designers and installers

This guide applies to products which control electric motors either directly (drives) or indirectly (controllers, option modules and other auxiliary equipment and accessories). In all cases the hazards associated with powerful electrical drives are present, and all safety information relating to drives and associated equipment must be observed.

Specific warnings are given at the relevant places in this guide.

Drives and controllers are intended as components for professional incorporation into complete systems. If installed incorrectly they may present a safety hazard. The drive uses high voltages and currents, carries a high level of stored electrical energy, and is used to control equipment which can cause injury. Close attention is required to the electrical installation and the system design to avoid hazards either in normal operation or in the event of equipment malfunction. System design, installation, commissioning/start-up and maintenance must be carried out by personnel who have the necessary training and competence. They must read this safety information and this guide carefully.

1.3 Responsibility

It is the responsibility of the installer to ensure that the equipment is installed correctly with regard to all instructions given in this guide. They must give due consideration to the safety of the complete system, so as to avoid the risk of injury both in normal operation and in the event of a fault or of reasonably foreseeable misuse.

The manufacturer accepts no liability for any consequences resulting from inappropriate, negligent or incorrect installation of the equipment.

1.4 Compliance with regulations

The installer is responsible for complying with all relevant regulations, such as national wiring regulations, accident prevention regulations and electromagnetic compatibility (EMC) regulations. Particular attention must be given to the cross-sectional areas of conductors, the selection of fuses or other protection, and protective ground (earth) connections.

This guide contains instructions for achieving compliance with specific EMC standards.

All machinery to be supplied within the European Union in which this product is used must comply with the following directives:

2006/42/EC Safety of machinery.

2014/30/EU: Electromagnetic Compatibility.

1.5 Electrical hazards

The voltages used in the drive can cause severe electrical shock and/or burns, and could be lethal. Extreme care is necessary at all times when working with or adjacent to the drive. Hazardous voltage may be present in any of the following locations:

- AC and DC supply cables and connections
- Output cables and connections
- Many internal parts of the drive, and external option units

Unless otherwise indicated, control terminals are single insulated and must not be touched.

The supply must be disconnected by an approved electrical isolation device before gaining access to the electrical connections.

The STOP and Safe Torque Off functions of the drive do not isolate dangerous voltages from the output of the drive or from any external option unit.

The drive must be installed in accordance with the instructions given in this guide. Failure to observe the instructions could result in a fire hazard.

1.6 Stored electrical charge

The drive contains capacitors that remain charged to a potentially lethal voltage after the AC supply has been disconnected. If the drive has been energized, the AC supply must be isolated at least ten minutes before work may continue.

1.7 Mechanical hazards

Careful consideration must be given to the functions of the drive or controller which might result in a hazard, either through their intended behaviour or through incorrect operation due to a fault. In any application where a malfunction of the drive or its control system could lead to or allow damage, loss or injury, a risk analysis must be carried out, and where necessary, further measures taken to reduce the risk - for example, an over-speed protection device in case of failure of the speed control, or a fail-safe mechanical brake in case of loss of motor braking.

With the sole exception of the Safe Torque Off function, none of the drive functions must be used to ensure safety of personnel, i.e. they must not be used for safety-related functions.

The Safe Torque Off function may be used in a safety-related application. The system designer is responsible for ensuring that the complete system is safe and designed correctly according to the relevant safety standards.

The design of safety-related control systems must only be done by personnel with the required training and experience. The Safe Torque Off function will only ensure the safety of a machine if it is correctly incorporated into a complete safety system. The system must be subject to a risk assessment to confirm that the residual risk of an unsafe event is at an acceptable level for the application.

1.8 Access to equipment

Access must be restricted to authorized personnel only. Safety regulations which apply at the place of use must be complied with.

1.9 Environmental limits

Instructions in this guide regarding transport, storage, installation and use of the equipment must be complied with, including the specified environmental limits. This includes temperature, humidity, contamination, shock and vibration. Drives must not be subjected to excessive physical force.

1.10 Hazardous environments

The equipment must not be installed in a hazardous environment (i.e. a potentially explosive environment).

1.11 Motor

The safety of the motor under variable speed conditions must be ensured.

To avoid the risk of physical injury, do not exceed the maximum specified speed of the motor.

Low speeds may cause the motor to overheat because the cooling fan becomes less effective, causing a fire hazard. The motor should be installed with a protection thermistor. If necessary, an electric forced vent fan should be used.

The values of the motor parameters set in the drive affect the protection of the motor. The default values in the drive must not be relied upon. It is essential that the correct value is entered in the Motor Rated Current parameter.

1.12 Mechanical brake control

Any brake control functions are provided to allow well co-ordinated operation of an external brake with the drive. While both hardware and software are designed to high standards of quality and robustness, they are not intended for use as safety functions, i.e. where a fault or failure would result in a risk of injury. In any application where the incorrect operation of the brake release mechanism could result in injury, independent protection devices of proven integrity must also be incorporated.

1.13 Adjusting parameters

Some parameters have a profound effect on the operation of the drive. They must not be altered without careful consideration of the impact on the controlled system. Measures must be taken to prevent unwanted changes due to error or tampering.

1.14 Electromagnetic compatibility (EMC)

Installation instructions for a range of EMC environments are provided in the relevant Power Installation Guide. If the installation is poorly designed or other equipment does not comply with suitable standards for EMC, the product might cause or suffer from disturbance due to electromagnetic interaction with other equipment. It is the responsibility of the installer to ensure that the equipment or system into which the product is incorporated complies with the relevant EMC legislation in the place of use.

2 Product information

2.1 Drive firmware version

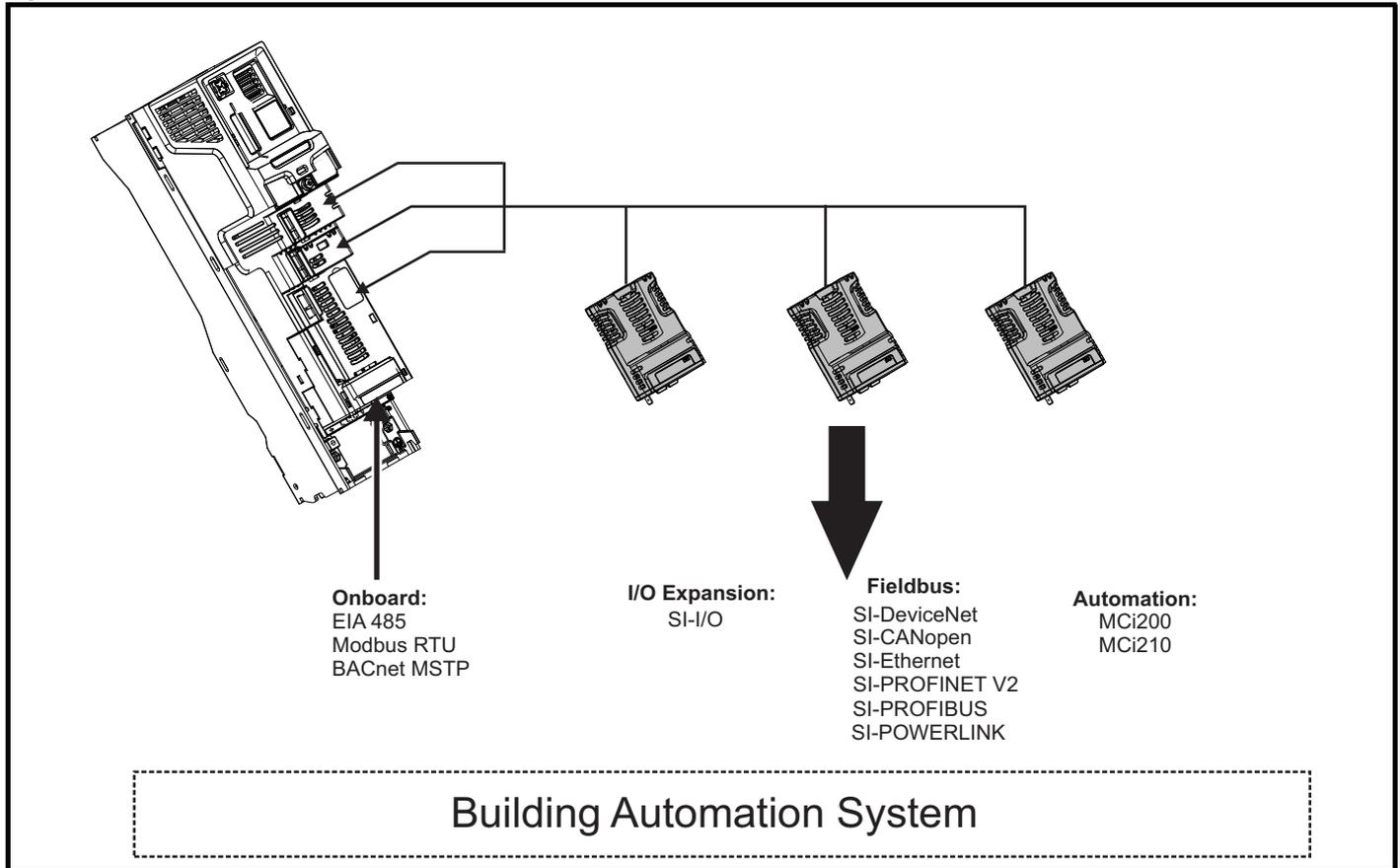
This product is supplied with the latest firmware version. If this drive is to be connected to an existing system or machine, all drive firmware versions should be verified to confirm the same functionality as drives of the same model already present. This may also apply to drives returned from an Nidec Industrial Automation Service Centre or Repair Centre. If there is any doubt please contact the supplier of the product.

The firmware version of the drive can be checked by looking at Pr **00.005** {11.029}.

2.2 AC drive for fans, pumps and compressors

The H300 is a high performance open loop AC drive specifically designed for use in building automation / Commercial HVAC/R applications. Figure 2-1 below indicates the key product features including built in connectivity to building automation systems. Each drive is equipped with three identical option slots for I/O and communications expansion.

Figure 2-1 Features



The H300 drive can be used as a stand alone motor controller or integrated into a building automation system using analog and digital I/O or serial communications. The base drive incorporates a EIA-485 serial communications port that is selectable between Modbus RTU or BACnet MSTP.

DeviceNet, CANopen, Ethernet and PROFIBUS connectivity is achieved with the addition of plug-in option modules

Key features:

- Universal high performance drive for induction and sensorless permanent magnet motors.
- Onboard IEC 61131-3 programmable automation
- Dual integrated form C relay outputs
- NV Media Card for parameter copying and data storage
- EIA-485 serial communications interface
- Single channel Safe Torque Off (STO) input

Fire mode

Fire Mode is a configurable override function that is used to alter the operation of the drive based upon external inputs, typically a discrete digital input from a Building Management Fire Protection system.



WARNING

Fire Mode - Important Warning

When Fire Mode is active the motor overload and thermal protection are disabled, as well as a number of drive protection functions. Fire Mode is provided for use only in emergency situations where the safety risk from disabling protection is less than the risk from the drive tripping - typically in smoke extraction operation to permit evacuation of a building. The use of Fire Mode itself causes a risk of fire from overloading of the motor or drive, so it must only be used after careful consideration of the balance of risks.

Care must be taken to prevent inadvertent activation or de-activation of Fire Mode. Fire Mode is indicated by a flashing display text warning "Fire mode active".

Care must be taken to ensure that parameters Pr **01.053** or Pr **01.054** are not inadvertently re-allocated to different inputs or variables. It should be noted that, by default, Pr **01.054** is controlled from digital input 4 and changing Pr **08.024** can re-allocate this digital input to another parameter. These parameters are at access level 2 in order to minimize the risk of inadvertent or unauthorized changes. It is recommended that User Security be applied to further reduce the risk (see section 5.9.1 *User Security Level / Access Level* on page 144). These parameters may also be changed via serial communications so adequate precautions should be taken if this functionality is utilized.

Real time clock

- An internal real time clock is available which is used for the timer functions and trip log.

Timer functions

- Two timers are available to switch an output on a routine basis.

Sleep / Wake mode

- Sleep / wake mode stops and starts the motor during periods of low demand to improve system efficiency.

Advanced Process PID

- Two PIDs are available which can operate independently or combine to provide more complex functionality.

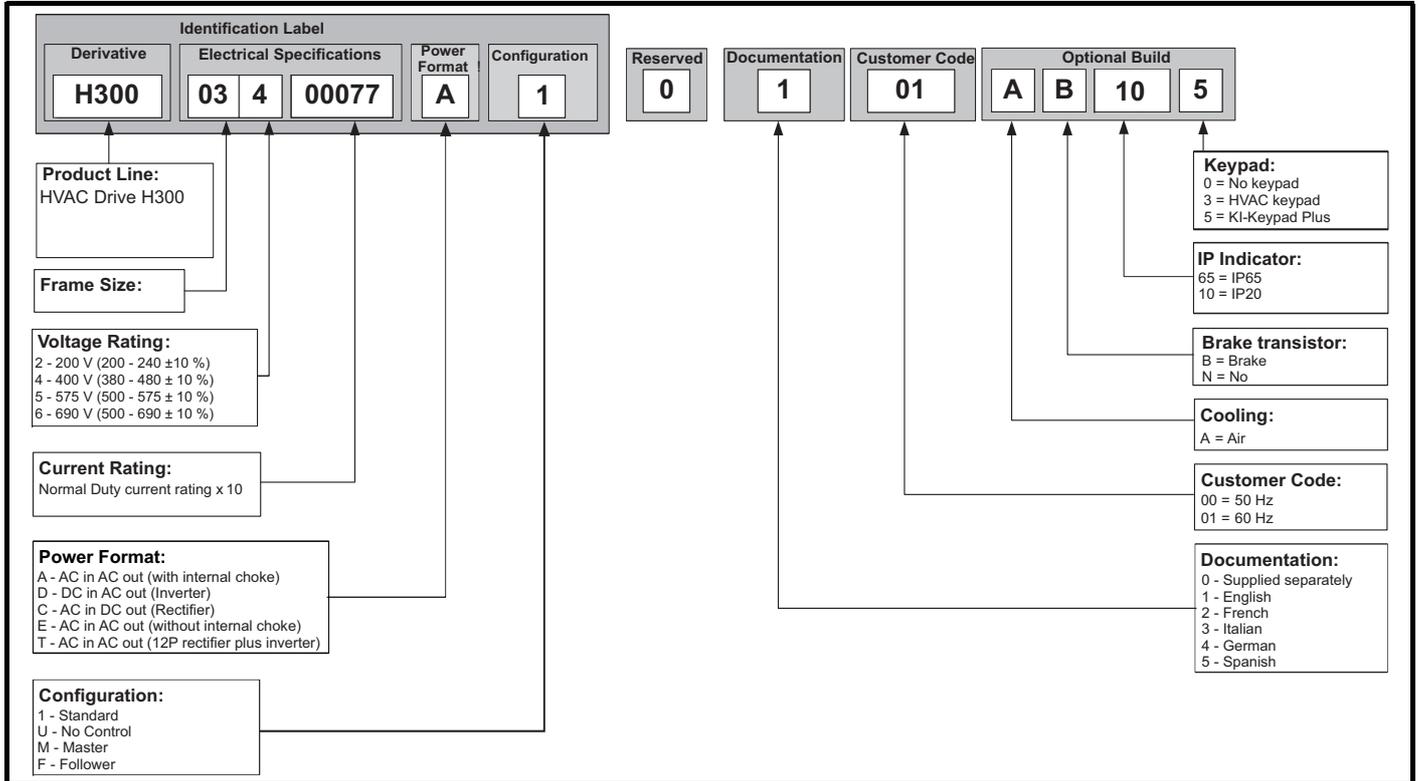
RTD's

- A PT1000 RTD temperature sensor input is available which can directly provide an analog input without a transducer for control of fans and pumps.
- Select up to three option modules.

2.3 Model number

The way in which the model numbers for the HVAC Drive H300 range are formed is illustrated below:

Figure 2-2 Model number



* Only shown on Frame 9 and above identification label.

** For further information on the D, C or T power format models, please refer to the *Modular Installation Guide*

NOTE

For simplicity, a Frame 9 drive with no internal choke (i.e. model 09xxxxxE) is referred to as a Frame 9E and a Frame 9 drive with an internal choke (i.e. model 09xxxxxA) is referred to as a Frame 9A. Any reference to Frame 9 is applicable to both sizes 9E and 9A. All Frame 10 and 11 drives are supplied with no internal choke.

2.4 Ratings

Normal Duty

The H300 is optimized for applications which use Self ventilated (TENV/TEFC) induction motors and require a low overload capability, and full torque at low speeds is not required (e.g. fans, pumps). Self ventilated (TENV/TEFC) induction motors require increased protection against overload due to the reduced cooling effect of the fan at low speed. To provide the correct level of protection the I^2t software operates at a level which is speed dependent. This is illustrated in the graph below.

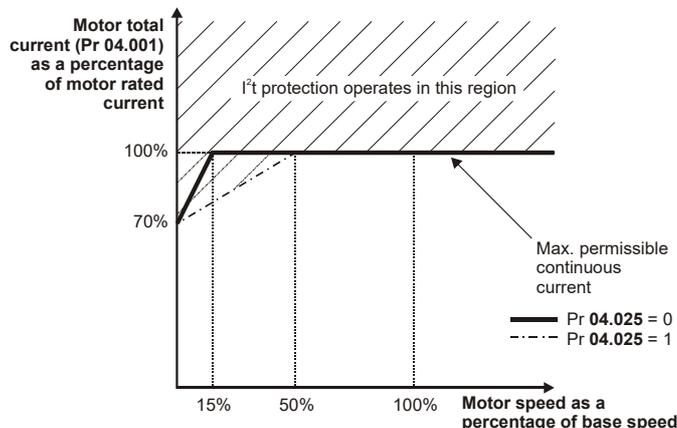
NOTE

The speed at which the low speed protection takes effect can be changed by the setting of *Low Speed Thermal Protection Mode* (04.025). The protection starts when the motor speed is below 15 % of base speed when Pr **04.025** = 0 (default) and below 50 % when Pr **04.025** = 1.

Operation of motor I^2t protection

Motor I^2t protection is fixed as shown below and is compatible with:

- Self ventilated (TENV/TEFC) induction motors



The continuous current ratings given are for maximum 40 °C (104 °F), 1000 m altitude and 3 kHz switching frequency. Derating is required for higher switching frequencies, ambient temperature >40 °C (104 °F) and high altitude. For further information, refer to Chapter 12 *Technical data* on page 279.

Table 2-1 200 V drive ratings (200 V to 240 V ±10 %)

Model		Normal Duty			
		Maximum continuous output current	Nominal power at 230 V	Motor power at 230 V	Peak current
		A	kW	hp	A
Frame size 3	03200066	6.6	1.1	1.5	7.2
	03200080	8	1.5	2	8.8
	03200110	11	2.2	3	12.1
	03200127	12.7	3	3	13.9
Frame size 4	04200180	18	4	5	19.8
	04200250	25	5.5	7.5	27.5
Frame size 5	05200300	30	7.5	10	33
Frame size 6	06200500	50	11	15	55
	06200580	58	15	20	63.8
Frame size 7	07200750	75	18.5	25	82.5
	07200940	94	22	30	103.4
	07201170	117	30	40	128.7
Frame size 8	08201490	149	37	50	163.9
	08201800	180	45	60	198
Frame size 9	09202160	216	55	75	237.6
	09202660	266	75	100	292.6
Frame size 10	10203250	325	90	125	357.5
	10203600	360	110	150	396

Table 2-2 High IP 200 V drive ratings (200 V to 240 V ±10 %)

Frame size	High IP Model	Normal Duty			
		Maximum continuous output current	Nominal power at 230 V	Motor power at 230 V	Peak current
		A	kW	hp	A
3	H300-03200066A10100AB653	6.6	1.1	1.5	7.2
	H300-03200080A10100AB653	8	1.5	2	8.8
	H300-03200110A10100AB653	11	2.2	3	12.1
	H300-03200127A10100AB653	12.7	3	3	13.9
4	H300-04200180A10100AB653	18	4	5	19.8
	H300-04200240A10100AB653	24	5.5	7.5	27.5
	H300-04200250A10100AB653	25	5.5	7.5	27.5
5	H300-05200300A10100AB653	30	7.5	10	33
6	H300-06200500A10100AB653	50	11	15	55

Table 2-3 400 V drive ratings (380 V to 480 V ±10 %)

Model		Normal Duty			
		Maximum continuous output current	Nominal power at 400 V	Motor power at 460 V	Peak current
		A	kW	hp	A
Frame size 3	03400034	3.4	1.1	1.5	3.7
	03400045	4.5	1.5	2.0	4.9
	03400062	6.2	2.2	3.0	6.8
	03400077	7.7	3.0	5.0	8.4
	03400104	10.4	4.0	5.0	11.4
	03400123	12.3	5.5	7.5	13.5
Frame size 4	04400185	18.5	7.5	10.0	20.3
	04400240	24.0	11.0	15.0	26.4
Frame size 5	05400300	30.0	15.0	20.0	33.0
Frame size 6	06400380	38.0	18.5	25.0	41.8
	06400480	48.0	22.0	30.0	52.8
	06400630	63.0	30.0	40.0	69.3
Frame size 7	07400790	79	37	50	86.9
	07400940	94	45	60	103.4
	07401120	112	55	75	123.2
Frame size 8	08401550	155	75	100	170.5
	08401840	184	90	125	202.4
Frame size 9	09402210	221	110	150	243.1
	09402660	266*	132	200	292.6
Frame size 10	10403200	320	160	250	352
	10403610	361	200	300	397.1
Frame size 11	11404370	437	225	350	480.7
	11404870	487*	250	400	535.7
	11405070	507*	280	450	557.7
Frame size 12	12404800	608	315	500	668
	12405660	660	355	550	726
	12406660	755	400	650	830.5
	12407200	865	500	700	951.5

* These ratings are for 2 kHz switching frequency. For ratings at 3 kHz switching frequency refer to Chapter 12.1.1 *Power and current ratings (Derating for switching frequency and temperature)* on page 279.

Table 2-4 400 V drive input current, fuse rating and cable size

Model	Maximum continuous input current	Fuse (6 per drive)				Nominal cable size (European) mm ²				Nominal cable size (USA)		
		IEC		UL/USA		Input 6 pulse	Input 12 pulse	Output	Cable type (input & output)	Input 6 pulse	Input 12 pulse	Output
		Nom	Class	Nom	Class							
		3 ph	A	A	A	mm ²	mm ²	mm ²	kcmil	kcmil	kcmil	
12404800T	720	550	aR	400	gR	4 x 120	2 x 120	3 x 150	XLPE/EPR	4 x 3/0 AWG (85 mm ²)	2 x 3/0 AWG (85 mm ²)	4 x 1/0 AWG (53.5 mm ²)
12405660T	777	550		450		4 x 150	2 x 150	4 x 120		4 x 3/0 AWG (85 mm ²)	2 x 3/0 AWG (85 mm ²)	4 x 2/0 AWG (67.4 mm ²)
12406600T	845	550		500				3 x 185		4 x 4/0 AWG (107.2 mm ²)	2 x 4/0 AWG (107.2 mm ²)	4 x 3/0 AWG (85 mm ²)
12407200T	995	550		550		4 x 185	2 x 185	4 x 185		4 x 250 Kcmil (127.2 mm ²)	2 x 250 Kcmil (127.2 mm ²)	4 x 4/0 AWG (107.2 mm ²)

Table 2-5 High IP 400 V drive ratings (380 V to 480 V ±10 %)

Frame size	H300 High IP Model	Normal Duty			
		Maximum continuous output current	Nominal power at 400 V	Motor power at 460 V	Peak current
		A	kW	hp	A
3	H300-03400034A10100AB653	3.4	1.1	1.5	3.7
	H300-03400045A10100AB653	4.5	1.5	2.0	4.9
	H300-03400062A10100AB653	6.2	2.2	3.0	6.8
	H300-03400077A10100AB653	7.7	3.0	5.0	8.4
	H300-03400104A10100AB653	10.4	4.0	5.0	11.4
	H300-03400123A10100AB653	12.3	5.5	7.5	13.5
4	H300-04400185A10100AB653	18.5	7.5	10.0	20.3
	H300-04400240A10100AB653	24.0	11.0	15.0	26.4
5	H300-05400300A10100AB653	30.0	15.0	20.0	33.0
	H300-05400310A10100AB653	31.0	15.0	20.0	33.0
6	H300-06400380A10100AB653	38.0	18.5	25.0	41.8
	H300-06400480A10100AB653	48.0	22	30.0	52.8

Table 2-6 575 V drive ratings (500 V to 575 V ±10 %)

Model		Normal Duty			
		Maximum continuous output current	Nominal power at 575 V	Motor power at 575 V	Peak current
		A	kW	hp	A
Frame size 5	05500039	3.9	2.2	3	4.3
	05500061	6.1	4	5	6.7
	05500100	10	5.5	7.5	11
Frame size 6	06500120	12	7.5	10	13.2
	06500170	17	11	15	18.7
	06500220	22	15	20	24.2
	06500270	27	18.5	25	29.7
	06500340	34	22	30	37.4
	06500430	43	30	40	47.3
Frame size 7	07500530	53	45	50	58.3
	07500730	73	55	60	80.3
Frame size 8	08500860	86	75	75	94.6
	08501080	108	90	100	118.8
Frame size 9	09501250	125	110	125	137.5
	09501500	150	110	150	165
Frame size 10	10502000	200	150	200	220
Frame size 11	11502480	248	185	250	272.8
	11502880	288*	225	300	316.8
	11503150	315*	250	350	346.5

* These ratings are for 2 kHz switching frequency. For ratings at 3 kHz switching frequency refer to Chapter 12.1.1 *Power and current ratings (Derating for switching frequency and temperature)* on page 279.

Table 2-7 High IP 575 V drive ratings (500 V to 575 V ±10 %)

Frame size	H300 Drive High IP Model	Normal Duty			
		Maximum continuous output current	Nominal power at 575 V	Motor power at 575 V	Peak current
		A	kW	hp	A
5	H300-05500039A10100AB653	3.9	2.2	3	4.3
	H300-05500061A10100AB653	6.1	4	5	6.7
	H300-05500100A10100AB653	10	5.5	7.5	11
6	H300-06500120A10100AB653	12	7.5	10	13.2
	H300-06500170A10100AB653	17	11	15	18.7
	H300-06500220A10100AB653	22	15	20	24.2
	H300-06500270A10100AB653	27	18.5	25	29.7
	H300-06500340A10100AB653	34	22	30	37.4

Table 2-8 690 V drive ratings (500 V to 690 V ±10 %)

Model		Normal Duty			
		Maximum continuous output current	Nominal power at 690 V	Motor power at 690 V	Peak current
		A	kW	hp	A
Frame size 7	07600230	23	18.5	25	25.3
	07600300	30	22	30	33
	07600360	36	30	40	39.6
	07600460	46	37	50	50.6
	07600520	52	45	60	57.2
	07600730	73	55	75	80.3
Frame size 8	08600860	86	75	100	94.6
	08601080	108	90	125	118.8
Frame size 9	09601250	125	110	150	137.5
	09601550	155	132	175	170.5
Frame size 10	10601720	172	160	200	189.2
	10601970	197	185	250	216.7
Frame size 11	11602250	225	200	250	247.5
	11602750	275*	250	300	302.5
	11603050	305*	280	400	335.5

* These ratings are for 2 kHz switching frequency. For ratings at 3 kHz switching frequency refer to Chapter 12.1.1 *Power and current ratings (Derating for switching frequency and temperature)* on page 279.

2.4.1 Typical short term overload limits

The maximum percentage overload limit changes depending on the selected motor. Variations in motor rated current, motor power factor and motor leakage inductance all result in changes in the maximum possible overload. The exact value for a specific motor can be calculated using the equations detailed in Menu 4 in the *Parameter Reference Guide*.

Typical values are shown in the table below for RFC (RFC-A or RFC-S) and open loop (OL) modes:

Table 2-9 Typical overload limits

Operating mode	RFC from cold	RFC from 100 %	Open loop from cold	Open loop from 100 %
Overload with motor rated current = drive rated current	110 % for 165 s	110 % for 9 s	110 % for 165 s	110 % for 9 s

Generally the drive rated current is higher than the matching motor rated current allowing a higher level of overload than the default setting. The time allowed in the overload region is proportionally reduced at very low output frequency on some drive ratings.

NOTE

The maximum overload level which can be attained is independent of the speed.

2.5 Operating modes

The drive is designed to operate in any of the following modes:

Open loop mode

- Open loop vector mode
- Fixed V/F mode (V/Hz)
- Quadratic V/F mode (V/Hz)

RFC - A

Without position feedback sensor (Sensorless)

RFC - S

Without position feedback sensor (Sensorless)

2.5.1 Open loop mode

The drive applies power to the motor at frequencies varied by the user. The motor speed is a result of the output frequency of the drive and slip due to the mechanical load. The drive can improve the speed control of the motor by applying slip compensation. The performance at low speed depends on whether V/F mode or open loop vector mode is selected.

Open loop vector mode

The voltage applied to the motor is directly proportional to the frequency except at low speed where the drive uses motor parameters to apply the correct voltage to keep the flux constant under varying load conditions.

Typically 100 % torque is available down to 1 Hz for a 50 Hz motor.

Fixed V/F mode

The voltage applied to the motor is directly proportional to the frequency except at low speed where a voltage boost is provided which is set by the user. This mode can be used for multi-motor applications.

Typically 100 % torque is available down to 4 Hz for a 50 Hz motor.

Quadratic V/F mode

The voltage applied to the motor is directly proportional to the square of the frequency except at low speed where a voltage boost is provided which is set by the user. This mode can be used for running fan or pump applications with quadratic load characteristics or for multi-motor applications. This mode is not suitable for applications requiring a high starting torque.

2.5.2 RFC-A Sensorless

Rotor Flux Control for Asynchronous (induction) motors (**RFC-A**) encompasses closed loop vector control without a position feedback device.

Sensorless mode provides closed loop control without the need for position feedback by using current, voltages and key operating motor parameters to estimate the motor speed. It can eliminate instability traditionally associated with open loop control such as operating large motors with light loads at low frequencies.

2.5.3 RFC- S Sensorless

Rotor Flux Control for Synchronous (permanent magnet brushless) motors (**RFC-S**) provides closed loop control without a position feedback device.

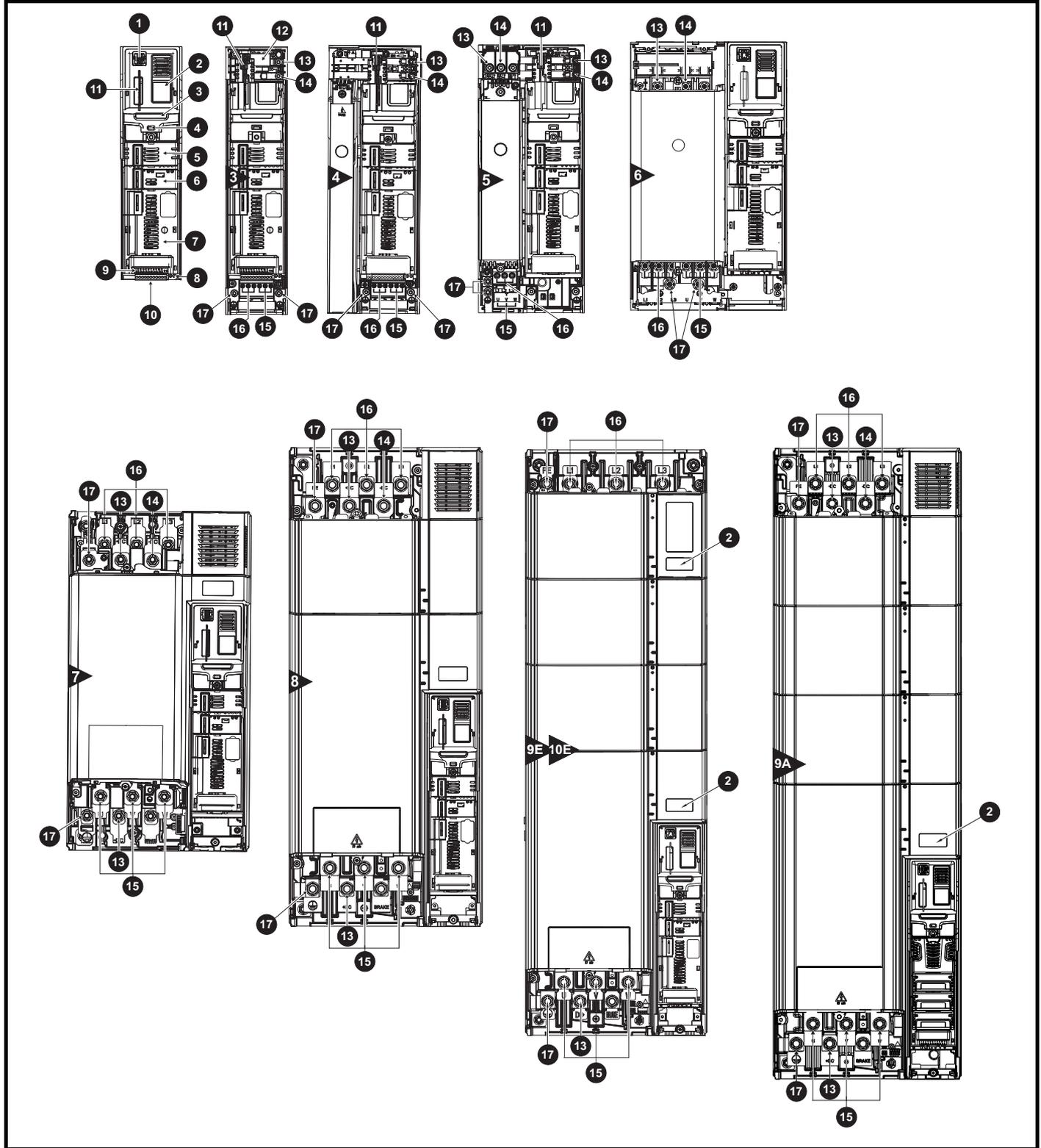
For use with permanent magnet brushless motors without a feedback device installed.

Flux control is not required because the motor is self excited by the permanent magnets which form part of the rotor.

Full torque is available all the way down to zero speed, with salient motors.

2.6 Drive features

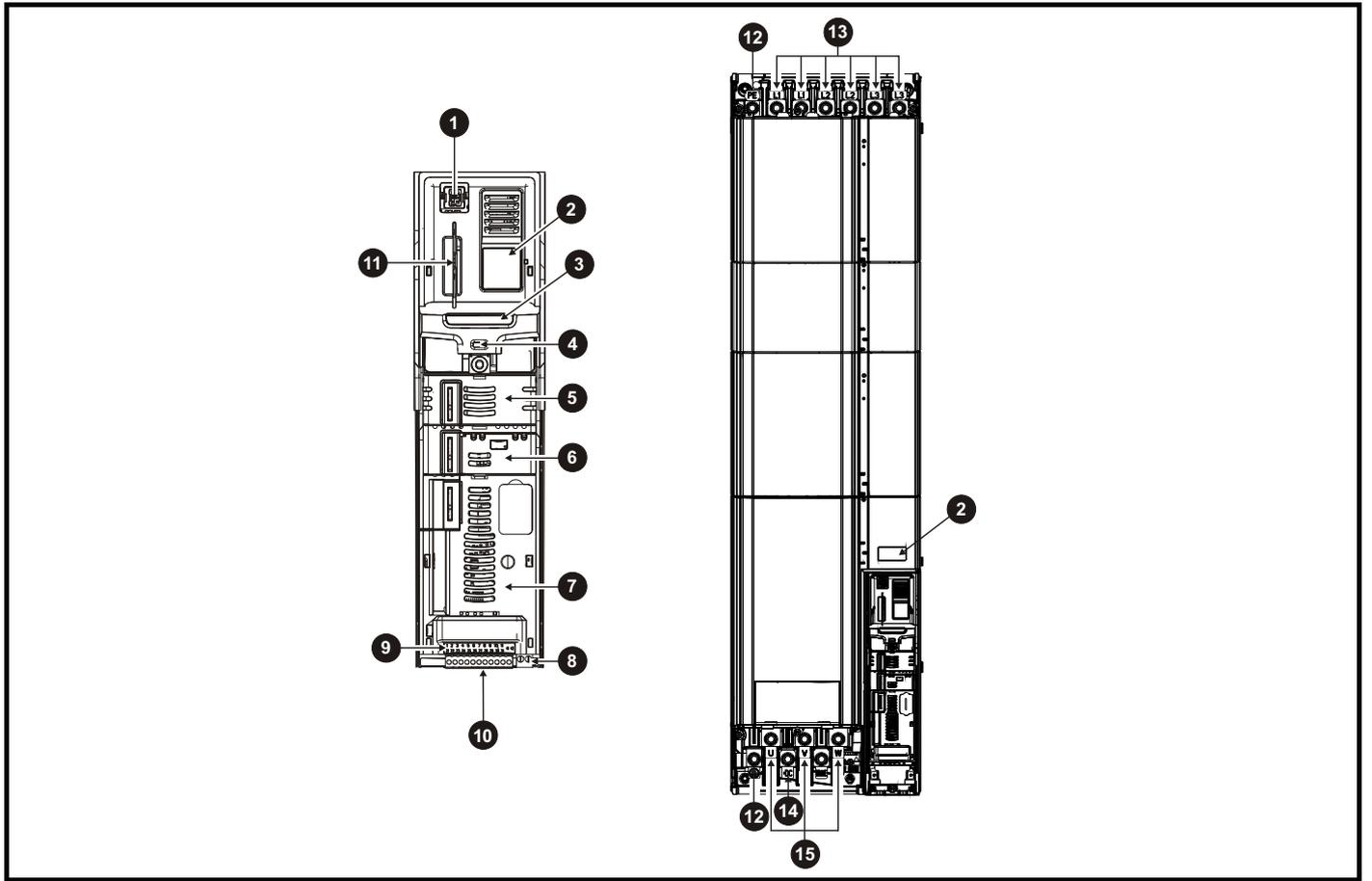
Figure 2-3 Features of the drive (size 3 to 10)



Key

- | | | | |
|-------------------------|-------------------------|-------------------------|---------------------------|
| 1. Keypad connection | 6. Option module slot 2 | 11. NV media card slot | 16. AC supply connections |
| 2. Rating label | 7. Option module slot 3 | 12. Internal EMC filter | 17. Ground connections |
| 3. Identification label | 8. Relay connections | 13. DC bus + | |
| 4. Status LED | 9. Control connections | 14. DC bus - | |
| 5. Option module slot 1 | 10. Communications port | 15. Motor connections | |

Figure 2-4 Features of the drive (size 11E)



- Key**
- | | | | |
|-------------------------|-------------------------|-------------------------|----------------------------|
| 1. Keypad connection | 5. Option module slot 1 | 9. Control connections | 13. AC supply connections* |
| 2. Rating label | 6. Option module slot 2 | 10. Communications port | 14. DC bus + |
| 3. Identification label | 7. Option module slot 3 | 11. NV media card slot | 15. Motor connections |
| 4. Status LED | 8. Relay connections | 12. Ground connections | |

* Common AC supply connections are internally linked on the 11E 6 pulse drive.

2.7 Nameplate description

See Figure 2-3 for location of rating labels.

Figure 2-5 Typical drive rating labels

The main nameplate contains the following information:

- Approvals:** CE, UK CA, RCM (triangle with checkmark), RoHS (circle with slash), UL (circle with 'UL' and 'US'), and LISTED8D14 E171230 Ind. Cont. Equipment.
- Technical Data:**

1.5kW				
IP 380-480V	50-60Hz	3ph	6.5A	
O/P 0-480V	0-550Hz	3ph	4.5A	
- Model and Date Code:** H300-034 00045 A, 2546
- Input/Output Voltage and Frequency:**

Input voltage	H300-034 00045 A	1.5kW	2546
	I/P 380-480V	50-60Hz	3ph 6.6A
Output voltage	O/P 0-480V	0-550Hz	3ph 4.5A
- Serial Number and IP Rating:** S/N: 300005001, IP20
- Manufacturer Information:** Control Techniques, The Gro.Pool Road, Newtown, Powys, United Kingdom, SY16 3BE. Made in U.K. Patents: www.ctpatents.info, Manuals: www.ctmanuals.info

The smaller label shows the model H300-034 00045 A and a warning symbol.

	CE approval	Europe
	RCM regulatory compliance mark	Australia
	UL / cUL approval	USA & Canada
	RoHS compliant	Europe
	Functional safety	USA & Canada
	UK Conformity Assessed	UK

* This label is only applicable to Size 7 and above.

Refer to Figure 2-2 *Model number* on page 16 for further information relating to the labels.

NOTE

Date code format

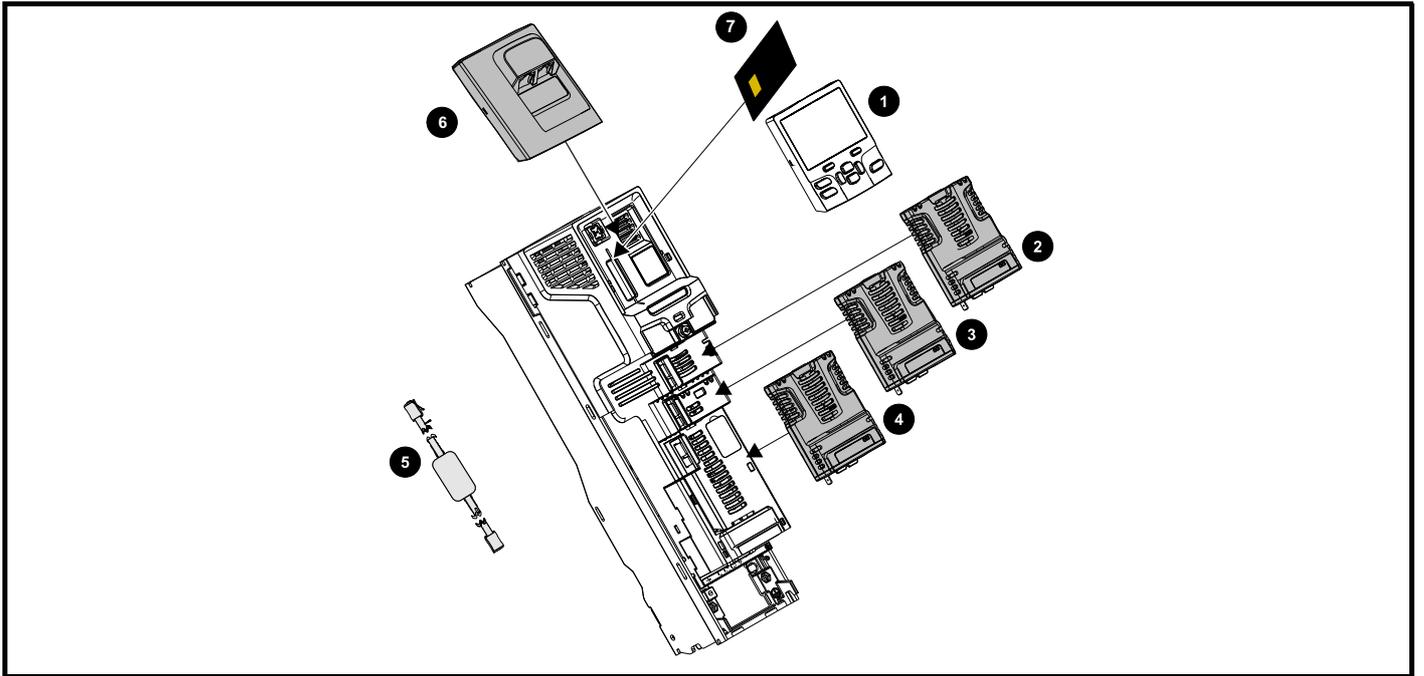
The date code is four numbers. The first two numbers indicate the year and the remaining numbers indicate the week of the year in which the drive was built.

Example:

A date code of 1710 would correspond to week 10 of year 2017.

2.8 Options

Figure 2-6 Options available with the drive



- | | |
|---------------------------|--------------------------|
| 1. Keypad / Remote keypad | 5. CT USB Comms cable |
| 2. Option module slot 1 | 6. KI-485 comms adaptor* |
| 3. Option module slot 2 | 7. NV media card** |
| 4. Option module slot 3 | |

* A KI-485 Adaptor is required for remote LCD keypad operation and connection to Connect software.

** For further information refer to section 9 *NV Media Card Operation* on page 193



Be aware of possible live terminals when inserting or removing the NV media card.

All standard option modules are color-coded in order to make identification easy. All modules have an identification label on top of the module. Standard option modules can be installed to any of the available option slots on the drive. The following tables shows the color-code key and gives further details on their function.

Table 2-10 Option module identification

Type	Option module	Color	Name	Further Details
Fieldbus		N/A	KI-485 Adaptor	485 Comms Adaptor 485 Comms adaptor provides EIA-485 communication interface. This adaptor supports 115 k Baud, node addresses between 1 to 16 and 8 1 NP M serial mode.
		Purple	SI-PROFIBUS	PROFIBUS option PROFIBUS adapter for communications with the drive
		Medium Grey	SI-DeviceNet	DeviceNet option DeviceNet adapter for communications with the drive
		Light Grey	SI-CANopen	CANopen option CANopen adapter for communications with the drive
		Beige	SI-Ethernet	External Ethernet module that supports EtherNet/IP, Modbus TCP/IP and RTMoE. The module can be used to provide high speed drive access, global connectivity and integration with IT network technologies, such as wireless networking
		Water Blue	SI-BACnet IP	BACnet IP option BACnet IP adapter for communication with the drive
		Yellow Green	SI-PROFINET V2	PROFINET V2 option PROFINET V2 adapter for communications with the drive
		Pale Blue	SI-POWERLINK	POWERLINK adapter for communications with the drive
Automation (I/O expansion)		Orange	SI-I/O	Extended I/O Increases the I/O capability by adding the following combinations: <ul style="list-style-type: none"> • Digital I/O • Digital Inputs • Analog Inputs (differential or single ended) • Analog Output • Relays
Automation (Applications)		Moss Green	MCi200	Machine Control Studio Compatible Applications Processor 2nd processor for running pre-defined and/or customer created application software.
		Moss Green	MCi210	Machine Control Studio Compatible Applications Processor (with Ethernet communications) 2nd processor for running pre-defined and/or customer created application software with Ethernet communications.
		Black	SI-Applications Plus	SyPTPro Compatible Applications Processor (with CNet) 2nd processor for running pre-defined and/or customer created application software with CNet support (can only be used on Slot 3).
		Black	SI-Applications Compact	SyPTPro Compatible Applications Processor (with CNet) 2nd processor for running pre-defined and/or customer created application software with CNet support (can be used in any slot).

Table 2-11 Keypad identification

Type	Keypad	Name	Further Details
Keypad		KI-HOA Keypad RTC	LCD keypad option Keypad with a LCD display and Hand / Off / Auto buttons and RTC
		HOA Remote keypad	Remote LCD keypad option Remotely mounted keypad with an LCD display, Hand / Off / Auto buttons and real time clock
		KI-Keypad Plus	Remote colour TFT keypad option with Bluetooth connectivity Remote multilingual keypad with a 2.8" colour TFT display, real time clock and Bluetooth connectivity.

Table 2-12 Additional options

Type	Option	Name	Further Details
Back-up		SD Card Adaptor	SD Card Adaptor Allows the drive to use an SD card for drive back-up
		SMARTCARD	SMARTCARD Used for parameter back-up with the drive

2.9 Items supplied with the drive

The drive is supplied with a copy of the *Getting Started Guide*, a safety information booklet, the Certificate of Quality and an accessory kit box including the items shown in Table 2-13.

Table 2-13 Parts supplied with the drive (size 3 to 8)

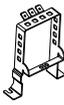
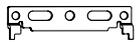
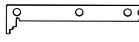
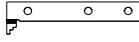
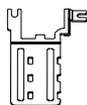
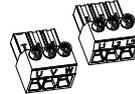
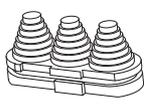
Description	Size 3	Size 4	Size 5	Size 6	Size 7	Size 8
Control connectors 1 to 9 and 21 to 29				 x 1	 x 1	
Communication connector				 x 1		
Relay connector				 x 1	 x 1	
24 V power supply connector					 x 1	
Grounding bracket				 x 1		
Surface mounting brackets	 x 2	 x 2	 x 2	 x 2	 x 2	 x 2
Grounding clamp	 x 1		 x 1	 x 1		
DC terminal cover grommets	 x 2					
Terminal nuts				 M6 x 11		
Supply and motor connector	 x 1		 x 1	 x 1		
Finger guard grommets			 x 3	 x 2		

Table 2-14 Parts supplied with the drive (size 9A, 9E, 10E and 11E)

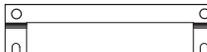
Description	Size 9A / 9E	Size 10E	Size 11E
Control connectors 1 to 9 and 21 to 29		 x 1	 x 1
Relay connector		 x 1	 x 1
24 V power supply connectors		 x 1	 x 1
Grounding bracket		 x 1	
Fan power supply connector		 x 1	
Surface mounting brackets	 x 2		 x 2  x 1

Table 2-15 Parts supplied with the High IP Drive

Description	Size 3	Size 4	Size 5	Size 6
Kit bag	3470-0201	3470-0200	3470-0203	3470-0205
	3470-0202	3470-0199	3470-0204	3470-0198

NOTE

For Frame 12 Drives please consult the Power Module Frame 12 Installation Guide.

3 Mechanical installation

This chapter describes how to use all mechanical details to install the drive. The drive is intended to be installed in an enclosure. Key features of this chapter include:

- Through-hole mounting
- High IP as standard or through-panel mounting
- Enclosure sizing and layout
- Option module installing
- Terminal location and torque settings

3.1 Safety information



Follow the instructions

The mechanical and electrical installation instructions must be adhered to. Any questions or doubt should be referred to the supplier of the equipment. It is the responsibility of the owner or user to ensure that the installation of the drive and any external option unit, and the way in which they are operated and maintained, comply with the requirements of the Health and Safety at Work Act in the United Kingdom or applicable legislation and regulations and codes of practice in the country in which the equipment is used.



Competence of the installer

The drive must be installed by professional assemblers who are familiar with the requirements for safety and EMC. The assembler is responsible for ensuring that the end product or system complies with all the relevant laws in the country where it is to be used.



Enclosure

The drive is intended to be mounted in an enclosure which prevents access except by trained and authorized personnel, and which prevents the ingress of contamination. It is designed for use in an environment classified as pollution degree 2 in accordance with IEC 60664-1. This means that only dry, non-conducting contamination is acceptable.

3.2 Planning the installation

The following considerations must be made when planning the installation:

3.2.1 Access

Access must be restricted to authorized personnel only. Safety regulations which apply at the place of use must be complied with.

The IP (Ingress Protection) rating of the drive is installation dependent. For further information, refer to section 3.9 *Enclosing standard drive for high environmental protection* on page 63.

3.2.2 Environmental protection

The drive must be protected from:

- Moisture, including dripping water or spraying water and condensation. An anti-condensation heater may be required, which must be switched off when the drive is running.
- Contamination with electrically conductive material
- Contamination with any form of dust which may restrict the fan, or impair airflow over various components
- Temperature beyond the specified operating and storage ranges
- Corrosive gasses

NOTE

During installation it is recommended that the vents on the drive are covered to prevent debris (e.g. wire off-cuts) from entering the drive.

3.2.3 Cooling

The heat produced by the drive must be removed without its specified operating temperature being exceeded. Note that a sealed enclosure gives much reduced cooling compared with a ventilated one, and may need to be larger and/or use internal air circulating fans.

For further information, refer to section 3.6 *Enclosure for standard drives* on page 59.

3.2.4 Electrical safety

The installation must be safe under normal and fault conditions. Electrical installation instructions are given in Chapter 4 *Electrical installation* on page 87.

3.2.5 Fire protection

The drive enclosure is not classified as a fire enclosure. A separate fire enclosure must be provided.

For installation in the USA, a NEMA 12 enclosure is suitable.

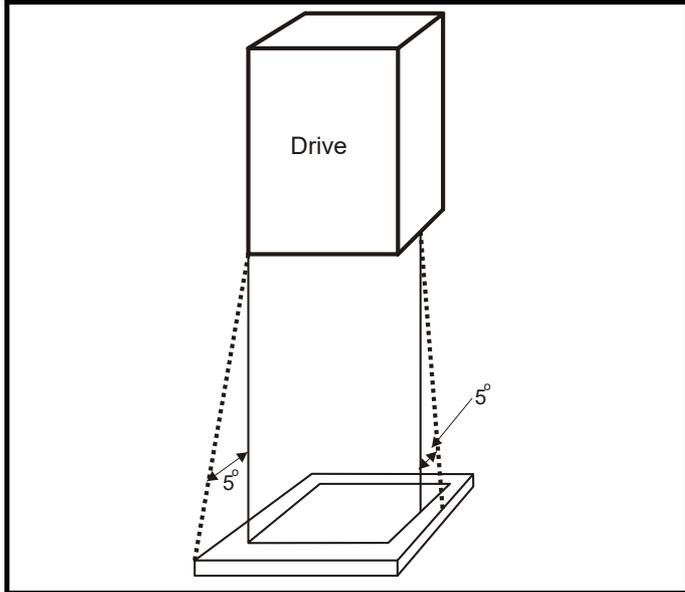
For installation outside the USA, the following (based on IEC 62109-1, standard for PV inverters) is recommended.

Enclosure can be metal and/or polymeric, polymer must meet requirements which can be summarized for larger enclosures as using materials meeting at least UL 94 class 5VB at the point of minimum thickness.

Air filter assemblies to be at least class V-2.

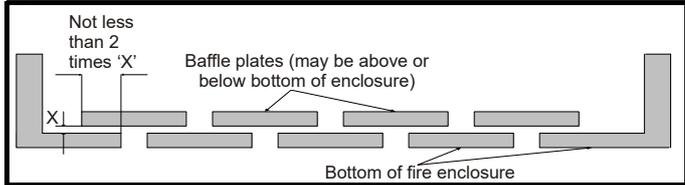
The location and size of the bottom shall cover the area shown in Figure 3-1. Any part of the side which is within the area traced out by the 5° angle is also considered to be part of the bottom of the fire enclosure.

Figure 3-1 Fire enclosure bottom layout



The bottom, including the part of the side considered to be part of the bottom, must be designed to prevent escape of burning material - either by having no openings or by having a baffle construction. This means that openings for cables etc. must be sealed with materials meeting the 5VB requirement, or else have a baffle above. See Figure 3-2 for acceptable baffle construction. This does not apply for mounting in an enclosed electrical operating area (restricted access) with concrete floor.

Figure 3-2 Fire enclosure baffle construction



3.2.6 Electromagnetic compatibility

Variable speed drives are powerful electronic circuits which can cause electromagnetic interference if not installed correctly with careful attention to the layout of the wiring.

Some simple routine precautions can prevent disturbance to typical industrial control equipment.

If it is necessary to meet strict emission limits, or if it is known that electromagnetically sensitive equipment is located nearby, then full precautions must be observed. In-built into the drive, is an internal EMC filter, which reduces emissions under certain conditions. If these conditions are exceeded, then the use of an external EMC filter may be required at the drive inputs, which must be located very close to the drives. Space must be made available for the filters and allowance made for carefully segregated wiring. Both levels of precautions are covered in section 4.11 *EMC (Electromagnetic compatibility)* on page 115.

3.2.7 Hazardous areas

The drive must not be located in a classified hazardous area unless it is installed in an approved enclosure and the installation is certified.

3.3 Terminal cover removal



Isolation device

The AC and / or DC power supply must be disconnected from the drive using an approved isolation device before any cover is removed from the drive or before any servicing work is performed.

WARNING



Stored charge

The drive contains capacitors that remain charged to a potentially lethal voltage after the AC and / or DC power supply has been disconnected. If the drive has been energized, the power supply must be isolated at least ten minutes before work may continue.

Normally, the capacitors are discharged by an internal resistor. Under certain, unusual fault conditions, it is possible that the capacitors may fail to discharge, or be prevented from being discharged by a voltage applied to the output terminals. If the drive has failed in a manner that causes the display to go blank immediately, it is possible the capacitors will not be discharged. In this case, consult Control Techniques or their authorized distributor.

WARNING

3.3.1 Removing the terminal covers

Figure 3-3 Location and identification of terminal covers (size 3 to 10)

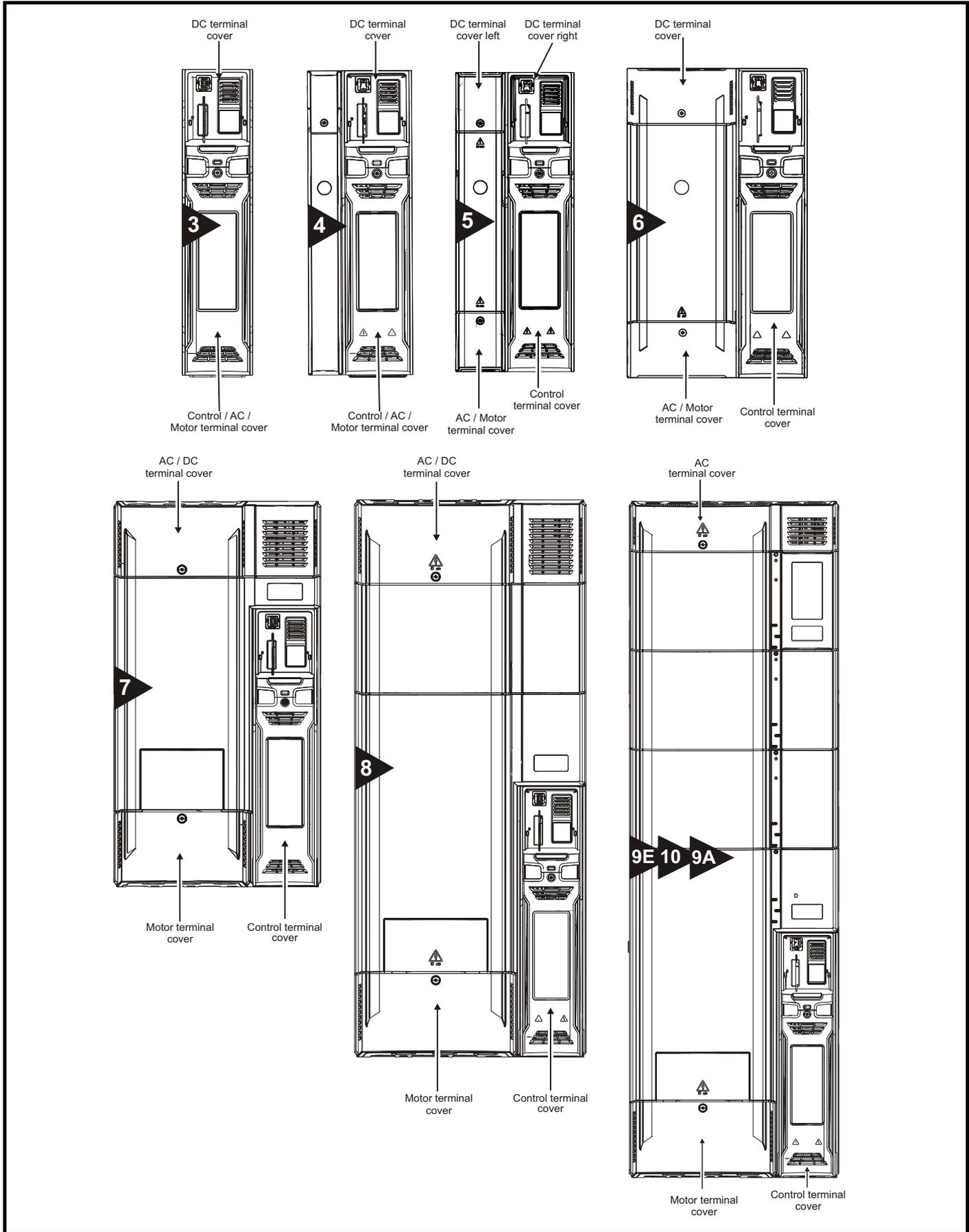


Figure 3-4 Location and identification of terminal covers (size 11)

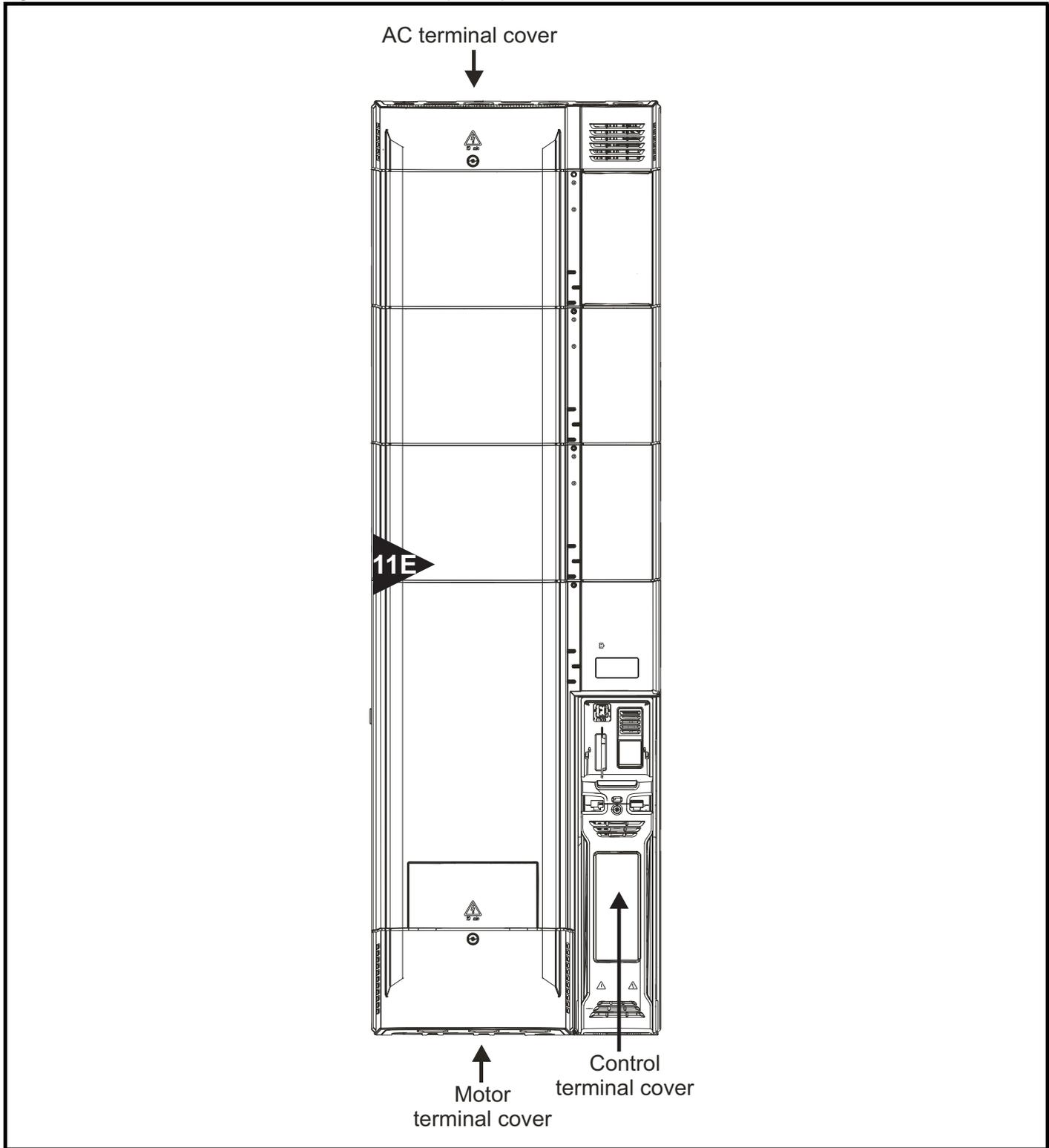
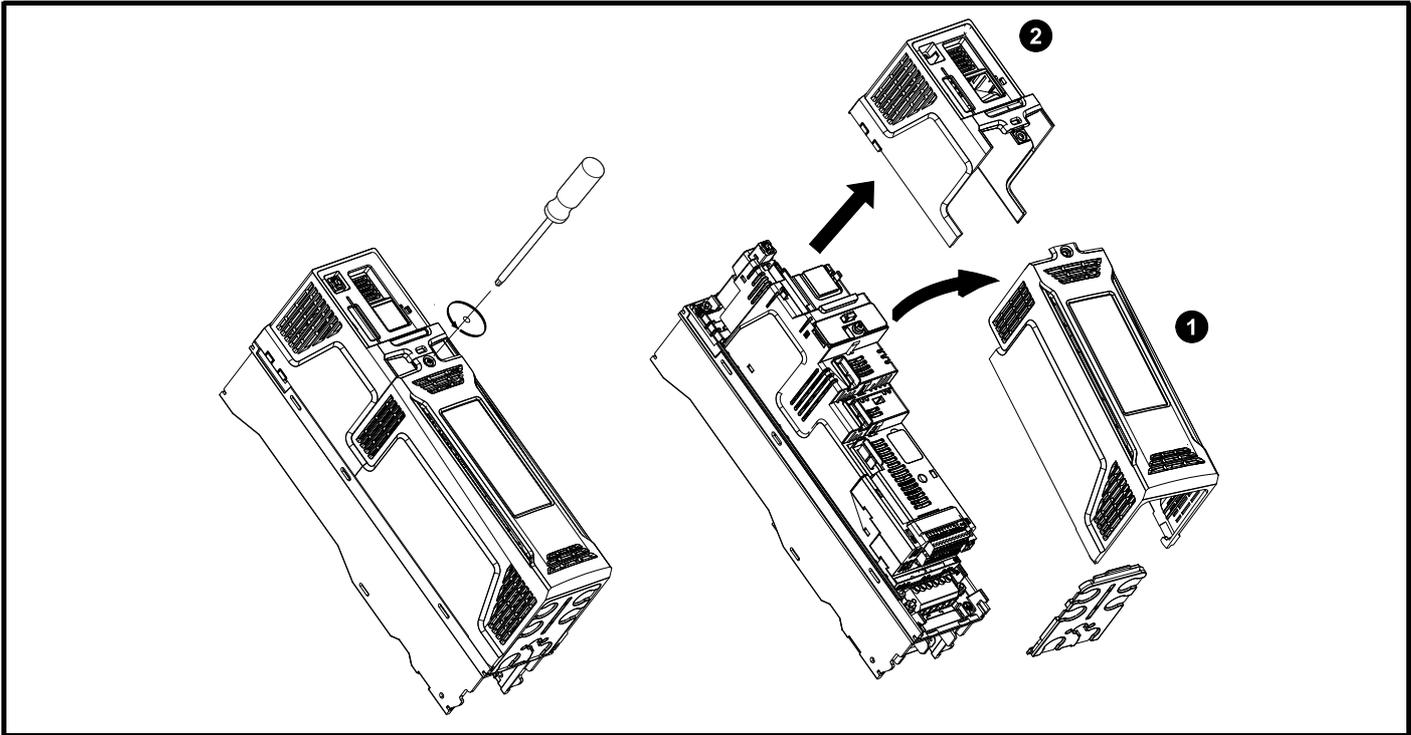


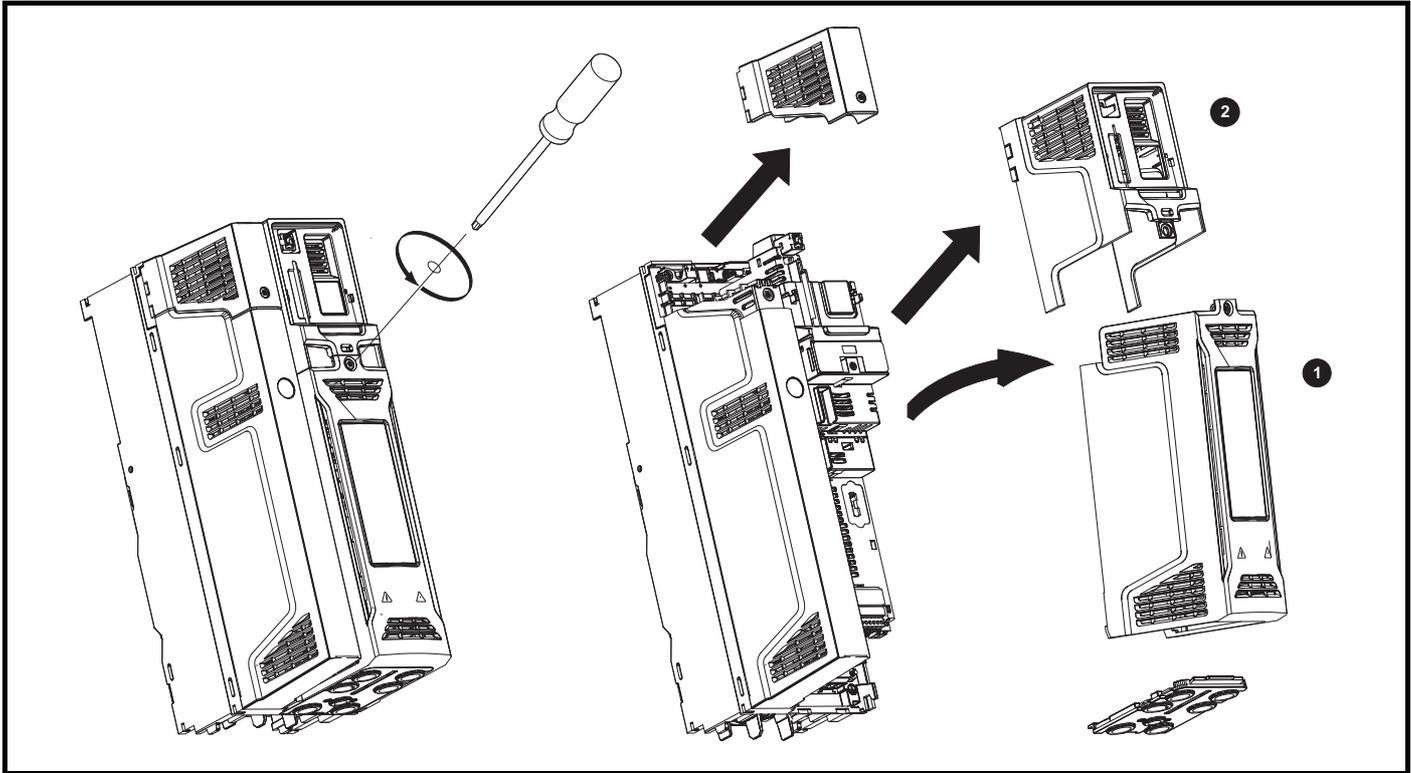
Figure 3-5 Removing the size 3 terminal covers



1. Control / AC / Motor terminal cover
2. DC cover

On size 3 drives, the Control / AC / Motor terminal cover must be removed before removal of the DC / Terminal cover. When replacing the terminal covers, the screws should be tightened to a maximum torque of 1 Nm (8.4 lb in).

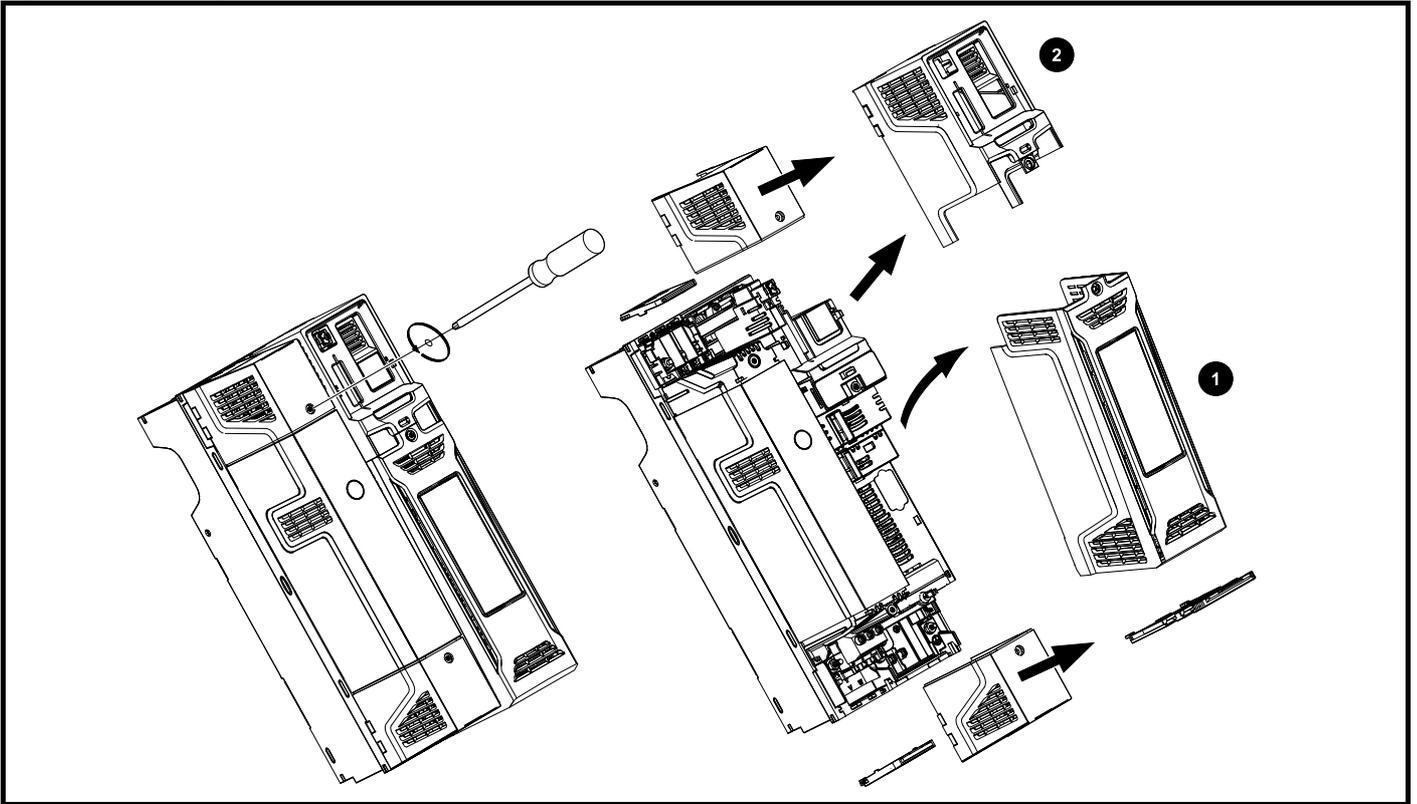
Figure 3-6 Removing the size 4 terminal covers



1. Control / AC / Motor terminal cover
2. DC cover

On size 4 drives, the Control / AC / Motor terminal cover must be removed before removal of the DC / Terminal cover. When replacing the terminal covers, the screws should be tightened to a maximum torque of 1 Nm (8.4 lb in).

Figure 3-7 Removing the size 5 terminal covers



1. Control terminal cover
2. DC cover

On size 5 drives, the Control terminal cover must be removed before removal of the DC / Terminal cover right. When replacing the terminal covers, the screws should be tightened to a maximum torque of 1 Nm (8.4 lb in).

Figure 3-8 Removing the size 6 terminal covers

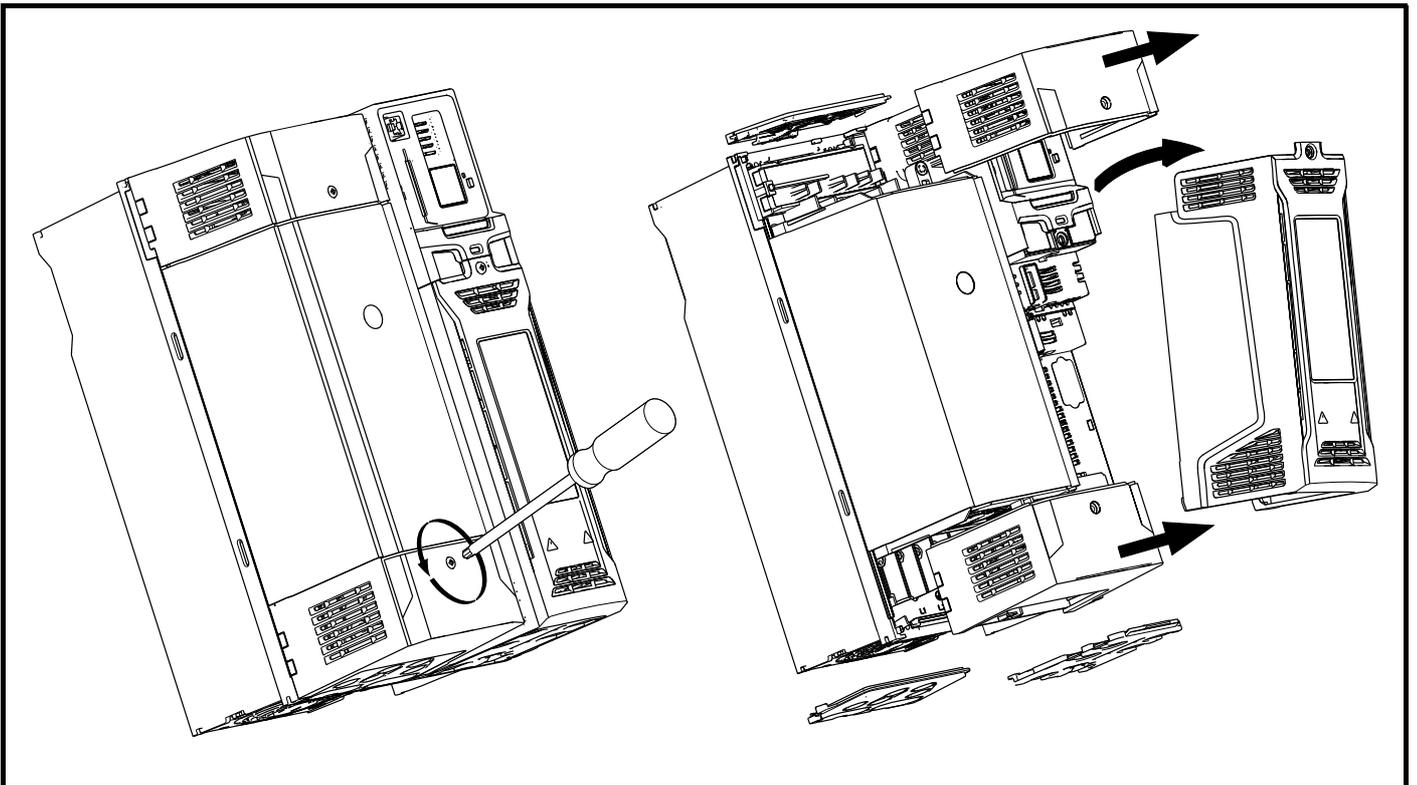
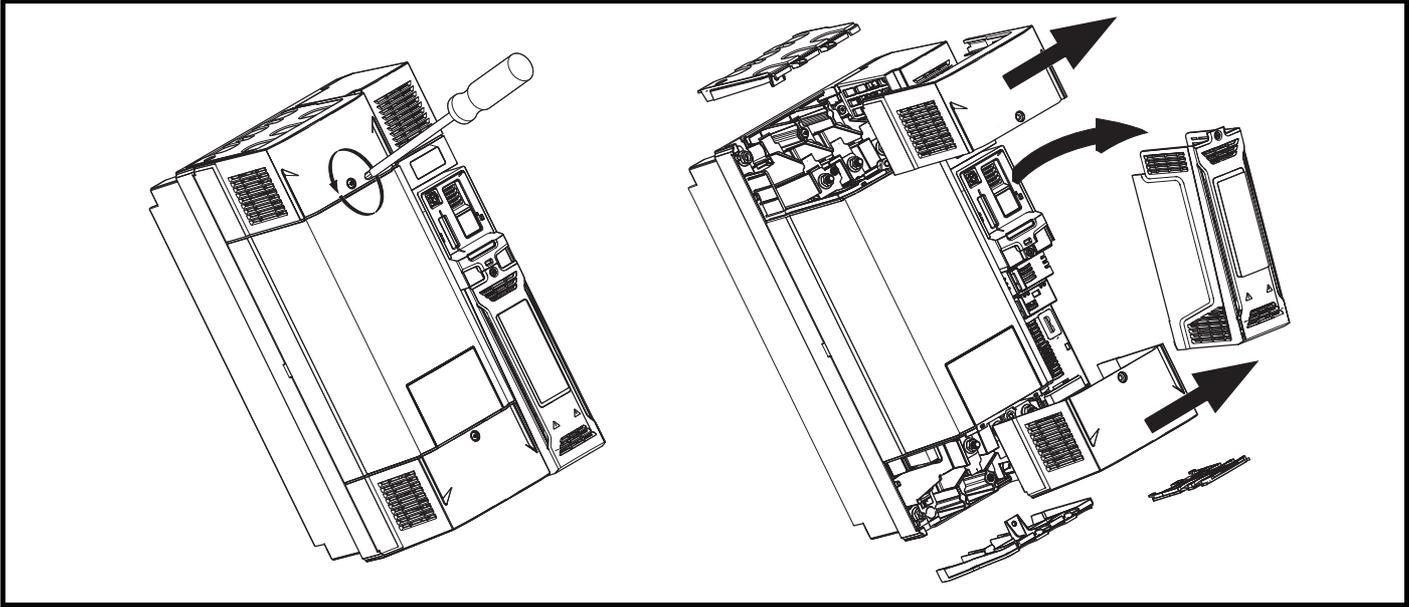
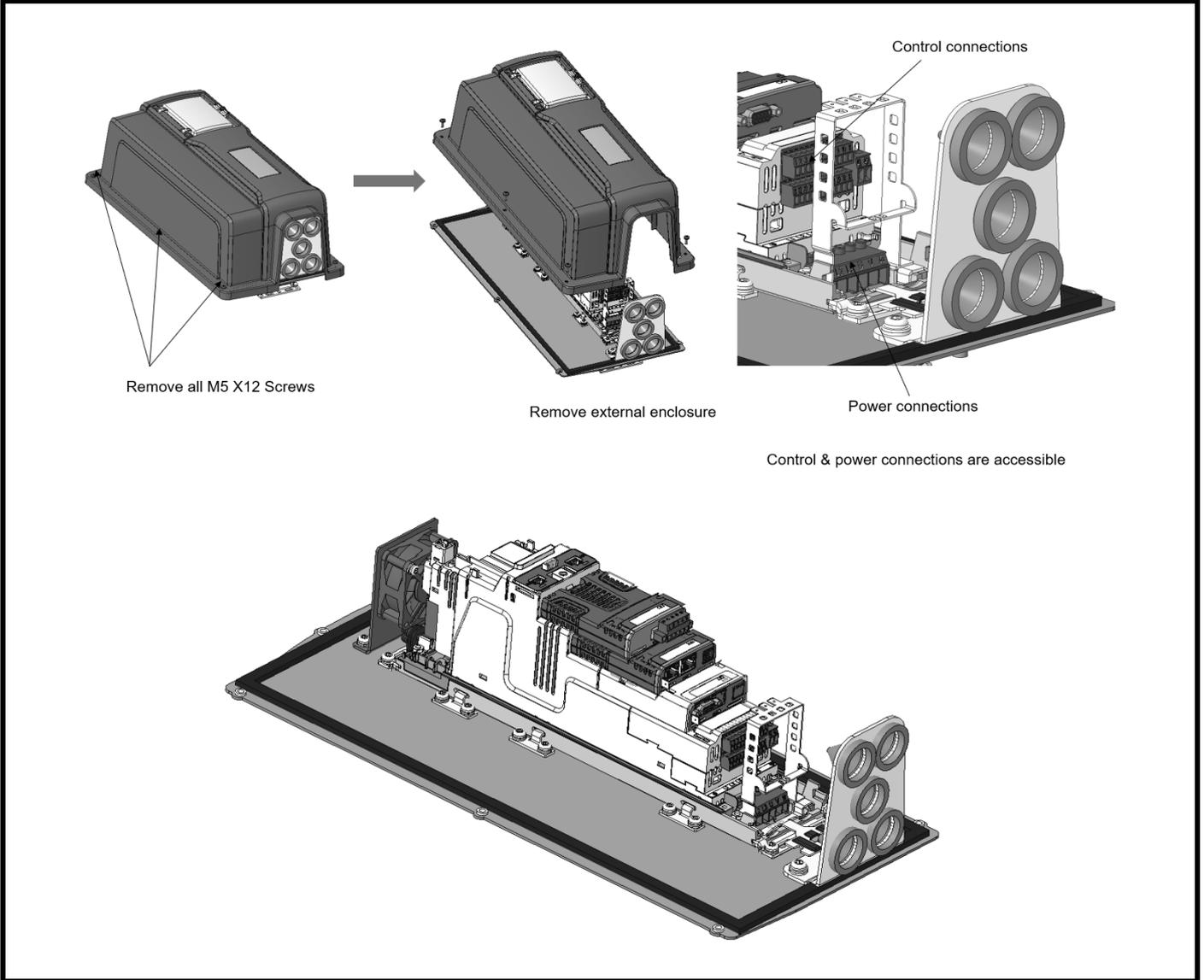


Figure 3-9 Removing the size 7 to 11 terminal covers (size 7 shown)



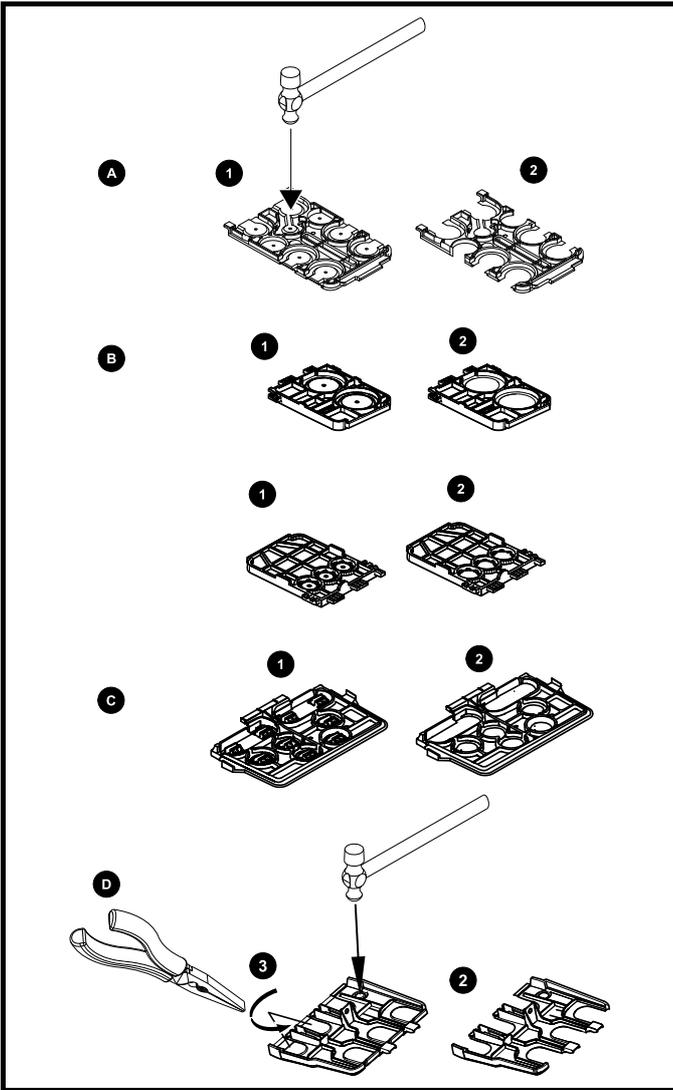
When replacing the terminal covers, the screws should be tightened to a maximum torque of 1 Nm (8.4 lb in).

Figure 3-10 High IP Access to control and power terminals



3.3.2 Removing the finger-guard and DC terminal cover break-outs

Figure 3-11 Removing the finger-guard break-outs



A: All sizes. B: Size 5 only. C: Size 6 only. D: Size 7 to 10.

Place finger-guard on a flat solid surface and hit relevant break-outs with hammer as shown (1). Continue until all required break-outs are removed (2). Remove any flash / sharp edges once the break-outs are removed.

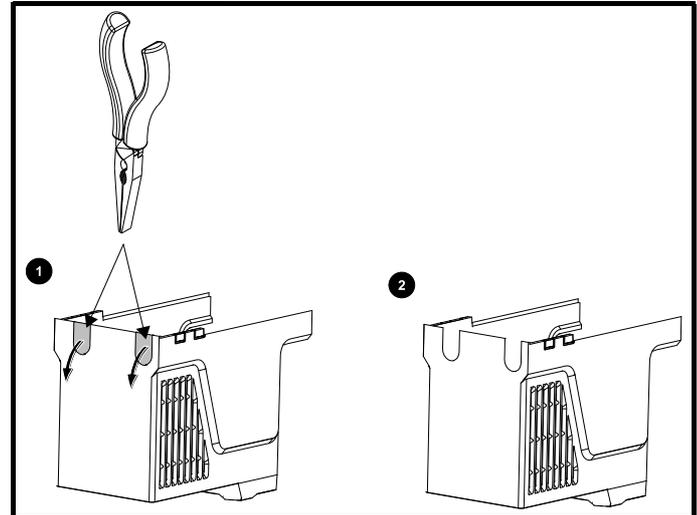
Grommet kits are available for size 7 to 10 finger guards. For size 8 to 10, two versions are available allowing for either single or double cable entries.

Table 3-1 Grommet kits

Drive size	Quantity of kits	Part number	Picture
Size 7 - Kit of 8 x single entry grommets	1	3470-0086	
Size 8 - Kit of 8 x single entry grommets	1	3470-0089	

Size 8 - Kit of 8 x double entry grommets	1	3470-0090	
Size 9 and 10 - Kit of 8 x double entry grommets	1	3470-0107	
Size 11 - kit of 8 x double entry grommets	2	3470-0107	

Figure 3-12 Removing the size 3 and 4 DC terminal cover break-outs



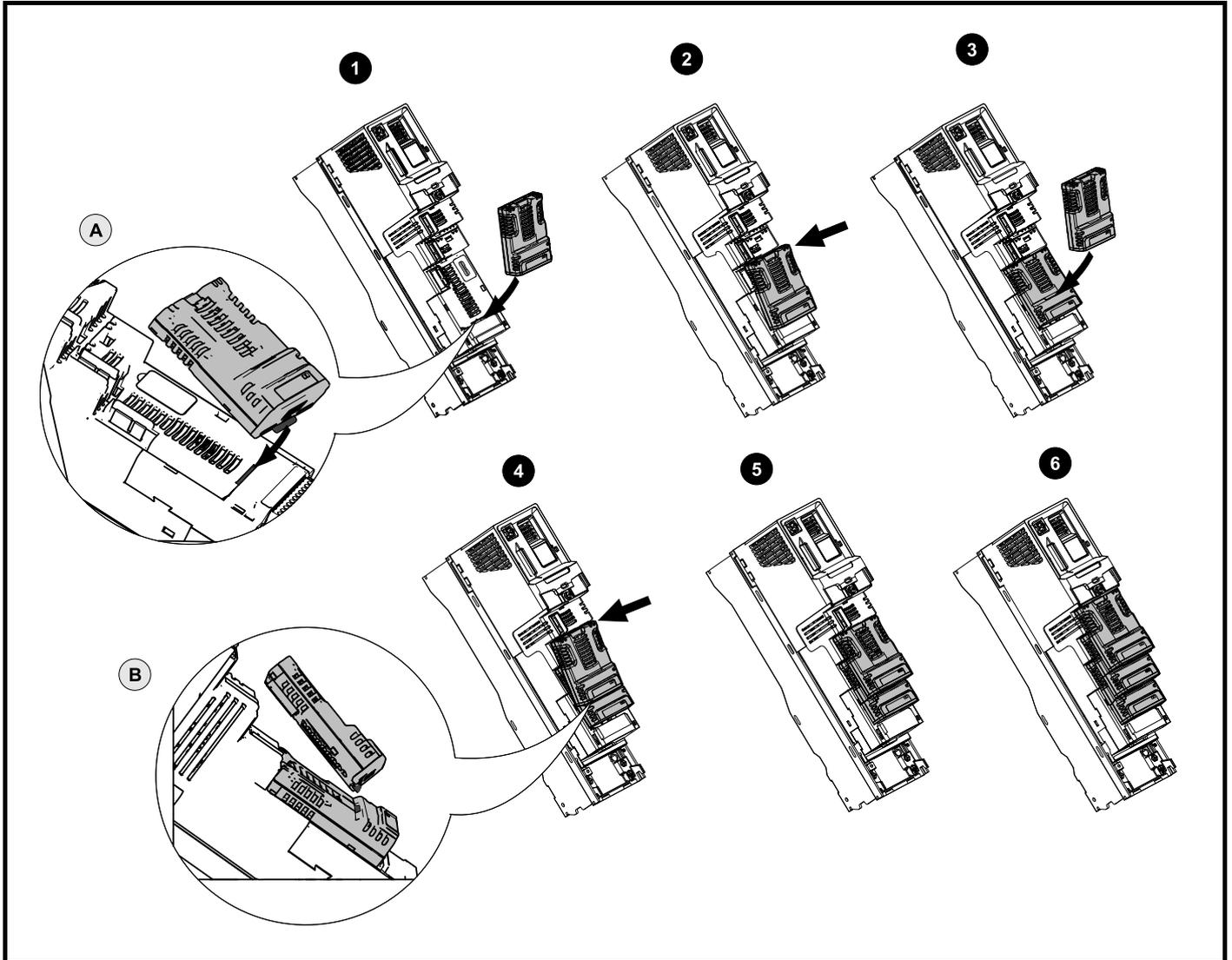
Grasp the DC terminal cover break-outs with pliers as shown (1) and pull down in the direction shown to remove. Continue until all required break-outs are removed (2). Remove any flash / sharp edges once the break-outs are removed. Use the DC terminal cover grommets supplied in the accessory box (Table 2-13 on page 29) to maintain the seal at the top of the drive.

3.4 Installing / removing option modules and keypads



Power down the drive before installing / removing the option module. Failure to do so may result in damage to the product.

Figure 3-13 Installation of a standard option module



Installing the first option module

NOTE

Option module slots must be used in the following order: slot 3, slot 2 and slot 1 (refer to Figure 2-3 *Features of the drive (size 3 to 10)* on page 23 for slot numbers).

- Move the option module in direction shown (1).
- Align and insert the option module tab in to the slot provided (2), this is highlighted in the detailed view (A).
- Press down on the option module until it clicks into place.

Installing the second option module

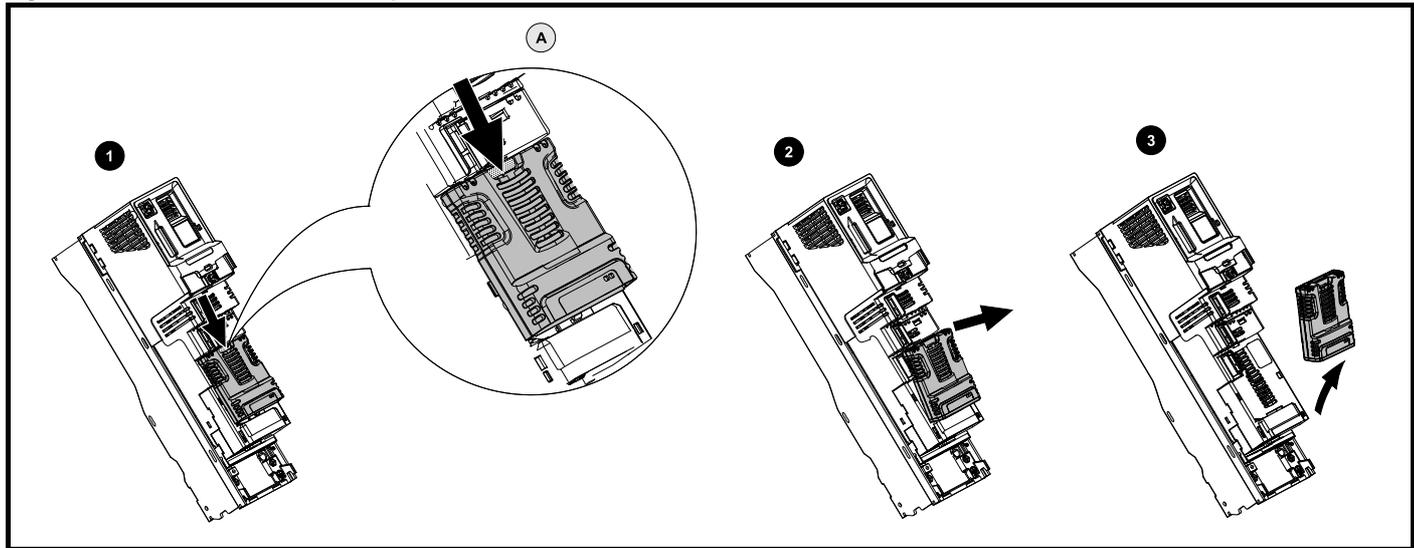
- Move the option module in direction shown (3).
- Align and insert the option module tab in to the slot provided on the already installed option module (4), this is highlighted in the detailed view (B).
- Press down on the option module until it clicks into place. Image (5) shows two option modules fully installed.

Installing the third option module

- Repeat the above process.

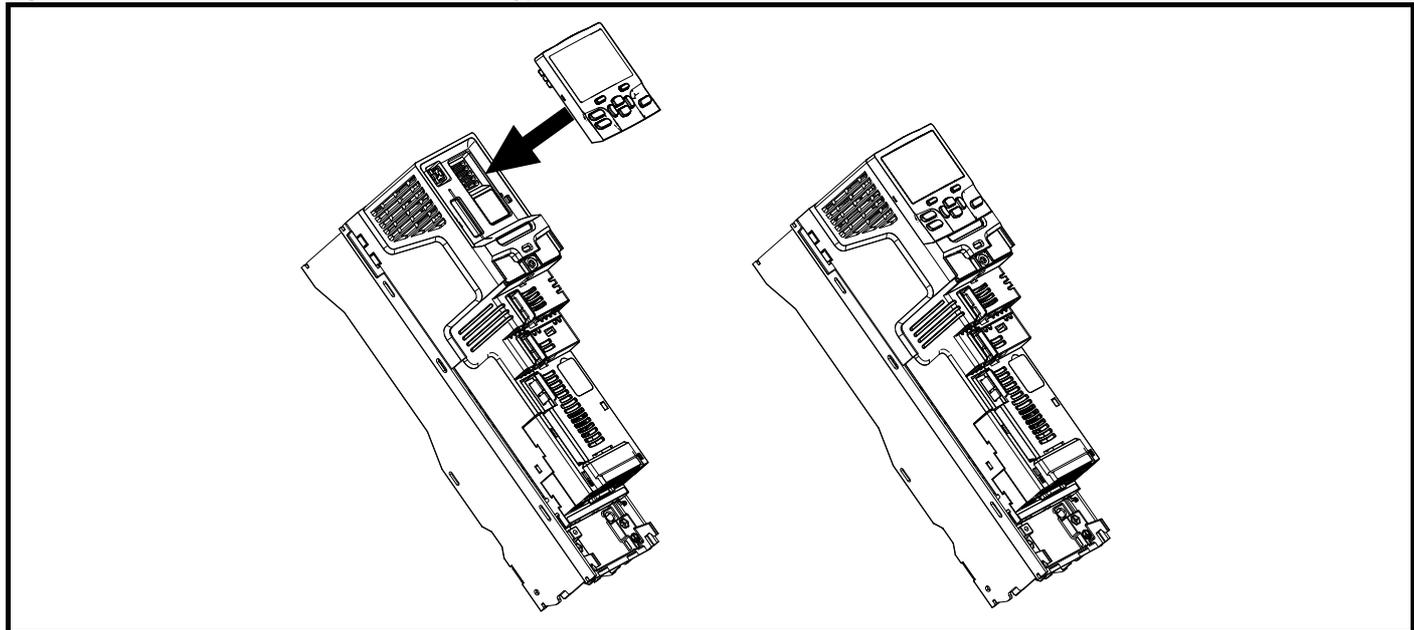
The drive has the facility for all three option module slots to be used at the same time, image (6) shows the three option modules installed.

Figure 3-14 Removal of a standard option module



- Press down on the tab (1) to release the option module from the drive housing, the tab is highlighted in the detailed view (A).
- Tilt the option module towards you as shown (2).
- Totally remove the option module in direction shown (3).

Figure 3-15 Installation and removal of the KI-Keypad



To install, align the keypad and press gently in the direction shown until it clicks into position.

To remove, reverse the installation instructions.

NOTE

The keypad can be installed / removed while the drive is powered up and running a motor, providing that the drive is not operating in keypad mode.

3.5 Dimensions and mounting methods

The drive can be either surface or through-panel mounted using the appropriate brackets. The following drawings show the dimensions of the drive and mounting holes for each method to allow a back plate to be prepared.

The Through-panel mounting kit is not supplied with the drive and can be purchased separately, below are the relevant part numbers:

Size	CT part number
3	3470-0053
4	3470-0056
5	3470-0067
6	3470-0055
7	3470-0079
8	3470-0083
9A	3470-0119
9E/10E	3470-0105
11E	3470-0126



If the drive has been used at high load levels for a period of time, the heatsink can reach temperatures in excess of 70 °C (158 °F). Human contact with the heatsink should be prevented.



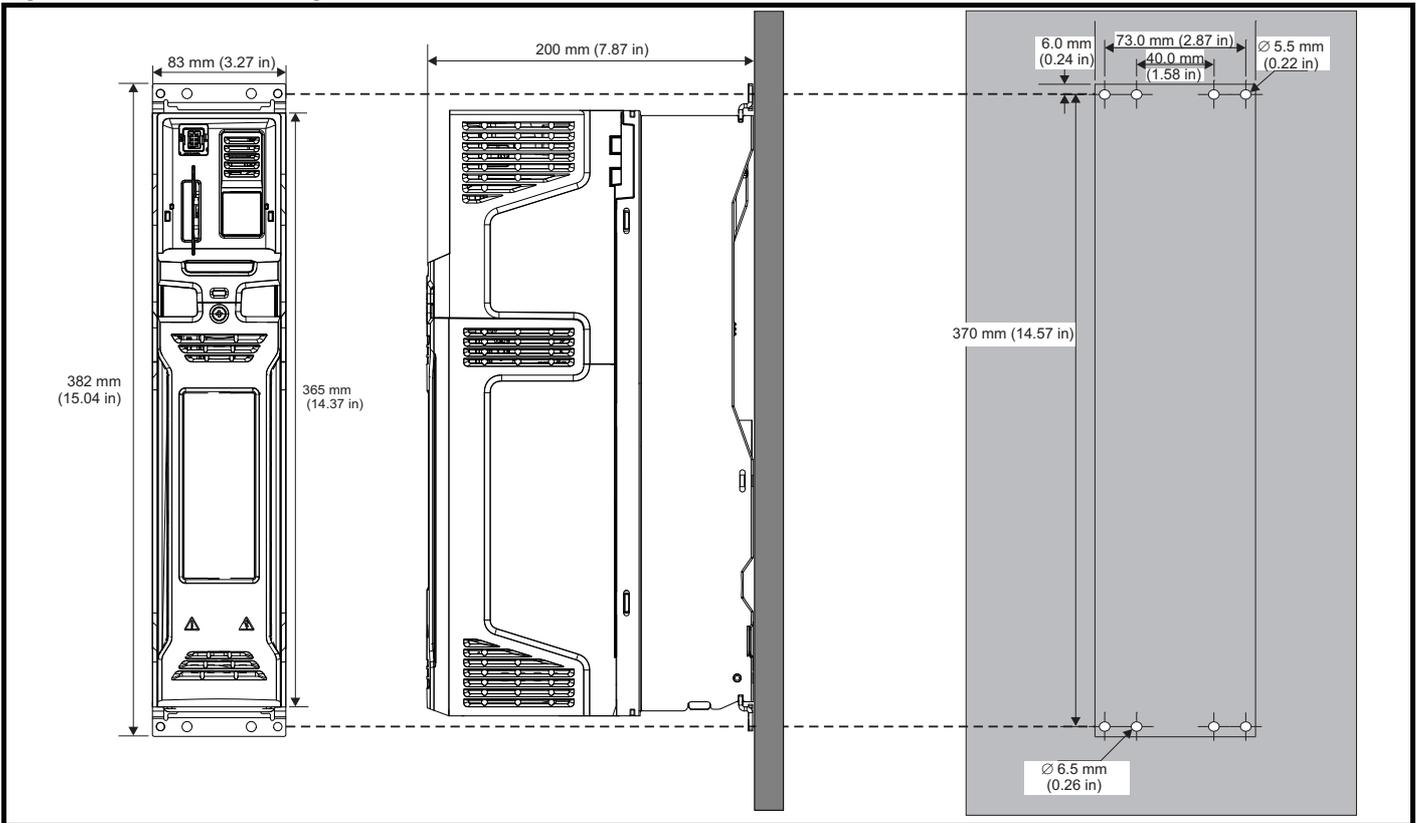
Many of the drives in this product range weigh in excess of 15 kg (33 lb). Use appropriate safeguards when lifting these models. A full list of drive weights can be found in section 12.1.19 *Weights* on page 292.

NOTE

For size 12 drives please refer to Unidrive M Power Module Frame 12 Installation Guide for information.

3.5.1 Surface mounting

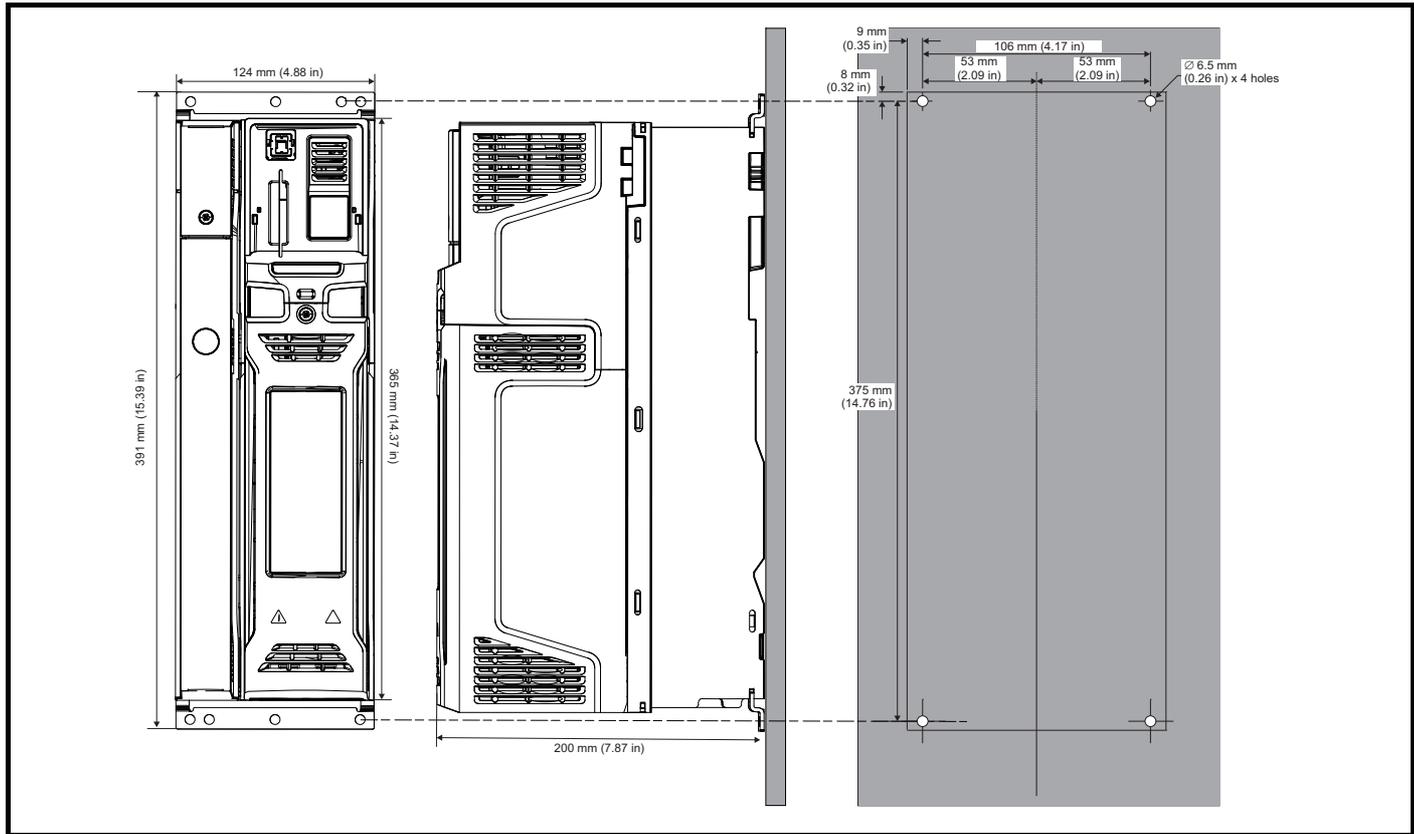
Figure 3-16 Surface mounting the size 3 drive



NOTE

Each mounting bracket contains 4 mounting holes, the outer holes (5.5 mm) x 2 should be used for mounting the drive to the backplate as this allows the heatsink fan to be replaced without removing the drive from the backplate. The inner holes (6.5 mm) x 2 are used for Unidrive SP size 1 retrofit applications. See Table 3-2 for further information.

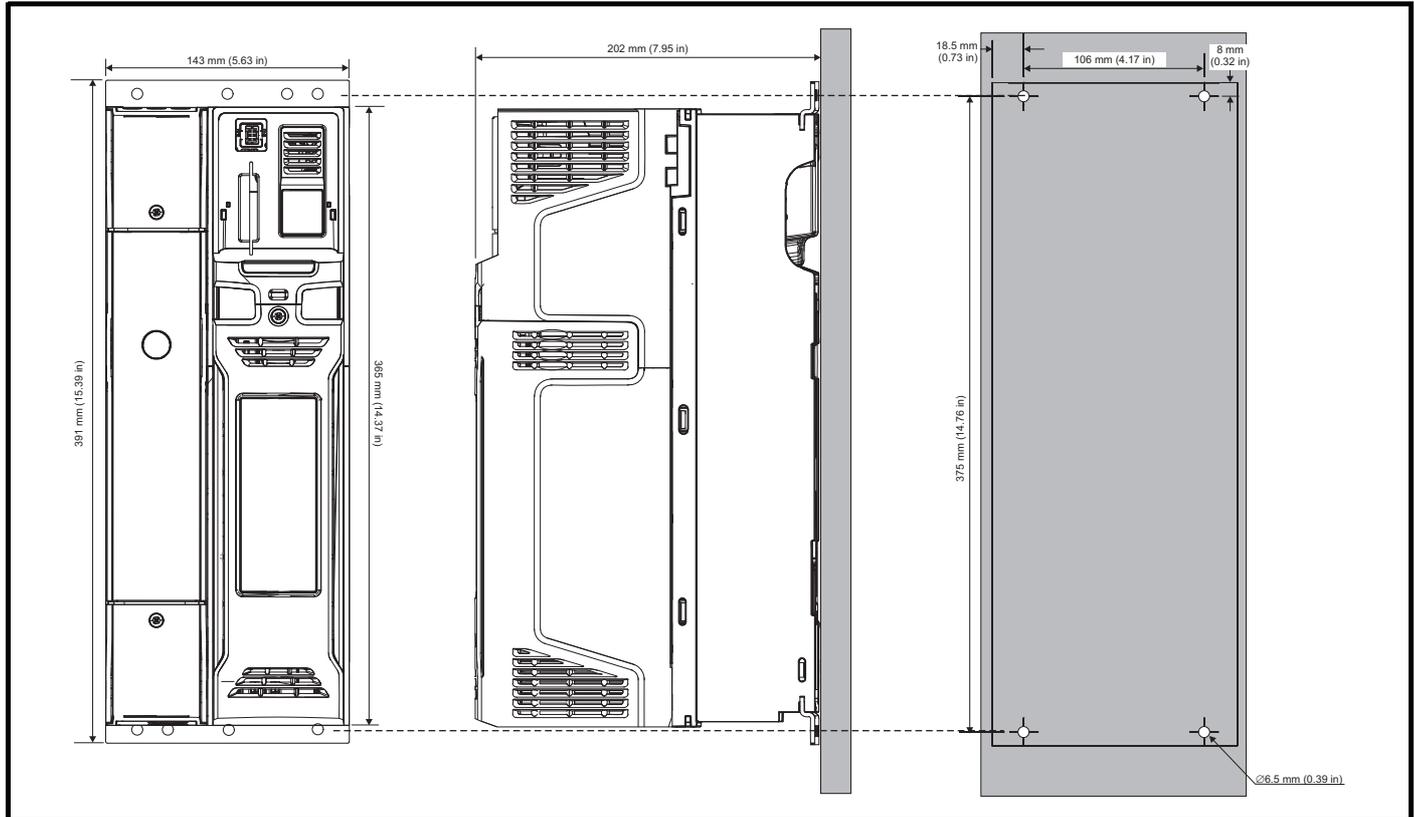
Figure 3-17 Surface mounting the size 4 drive



NOTE

The outer holes in the mounting bracket are to be used for surface mounting. See Table 3-2 for further information.

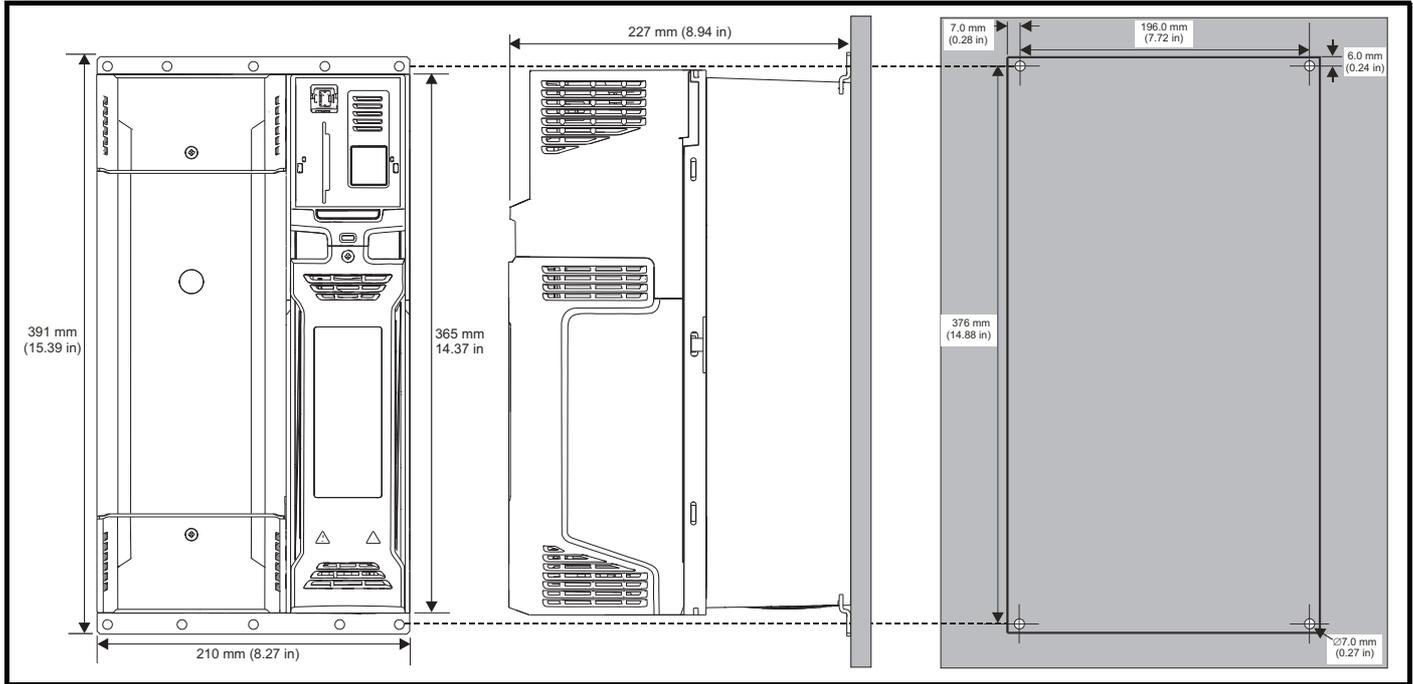
Figure 3-18 Surface mounting the size 5 drive



NOTE

The outer holes in the mounting bracket are to be used for surface mounting. See Table 3-2 for further information.

Figure 3-19 Surface mounting the size 6 drive



NOTE

The outer holes in the mounting bracket are to be used for surface mounting. See Table 3-2 for further information.

Figure 3-20 Surface mounting the size 7 drive

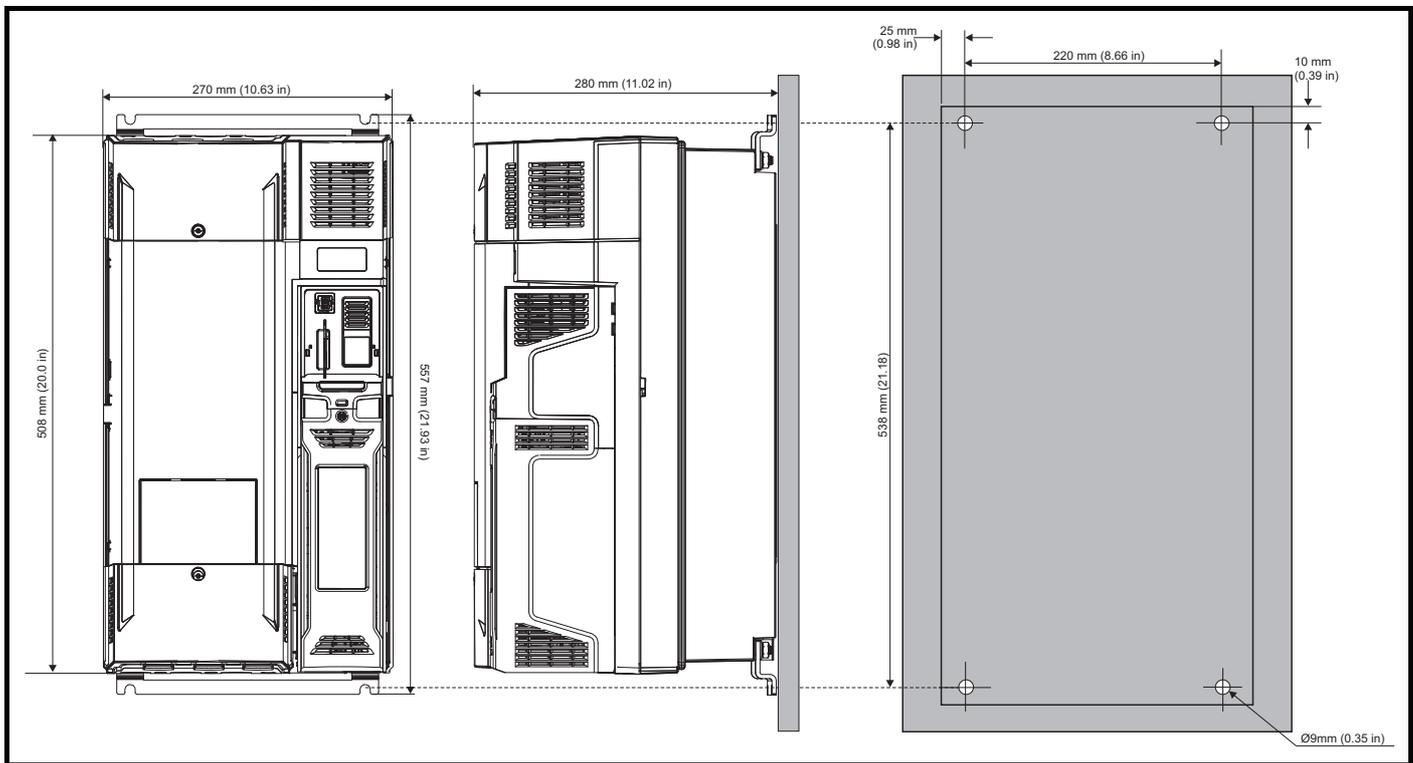


Figure 3-21 Surface mounting the size 8 drive

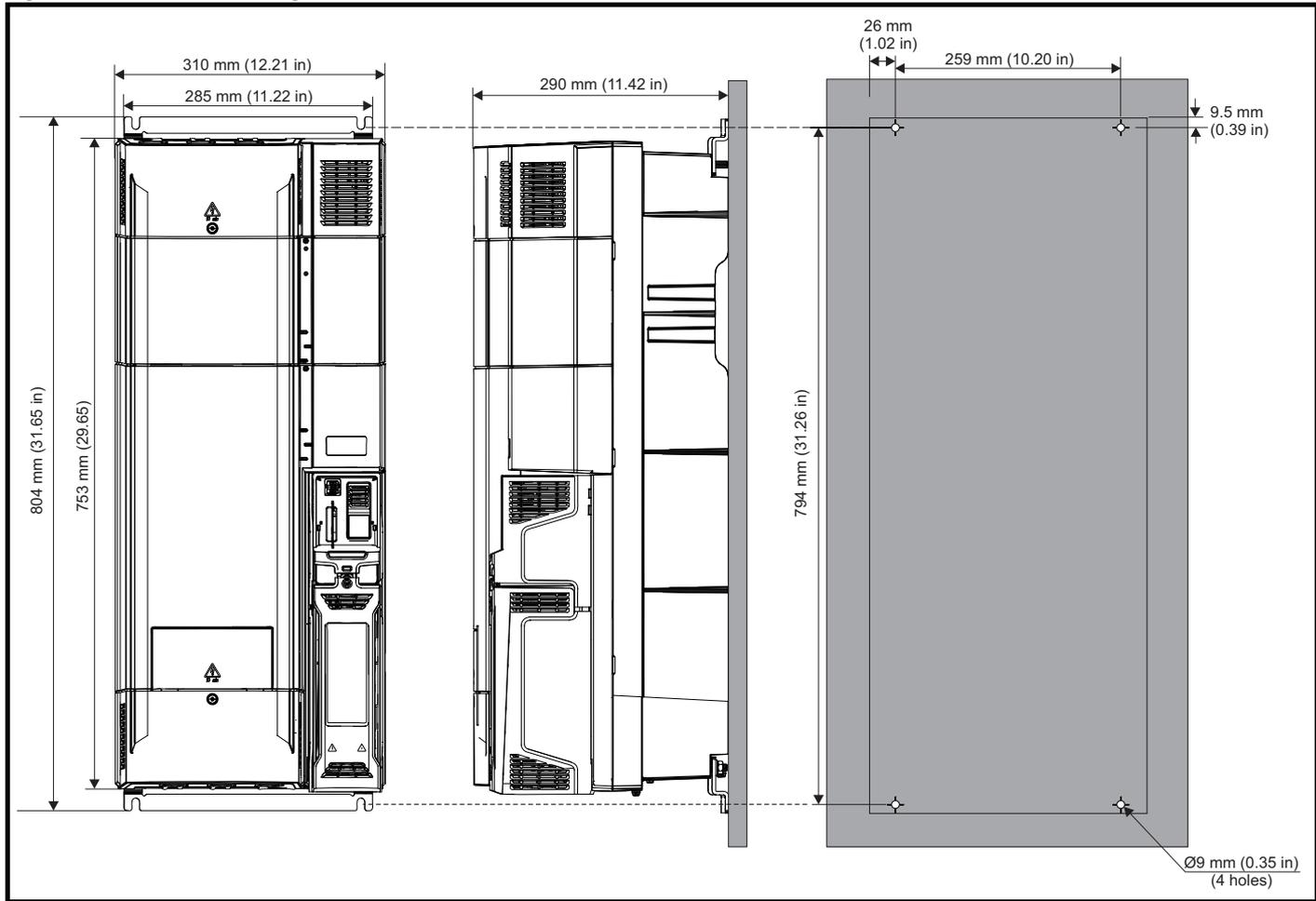


Figure 3-22 Surface mounting the size 9A

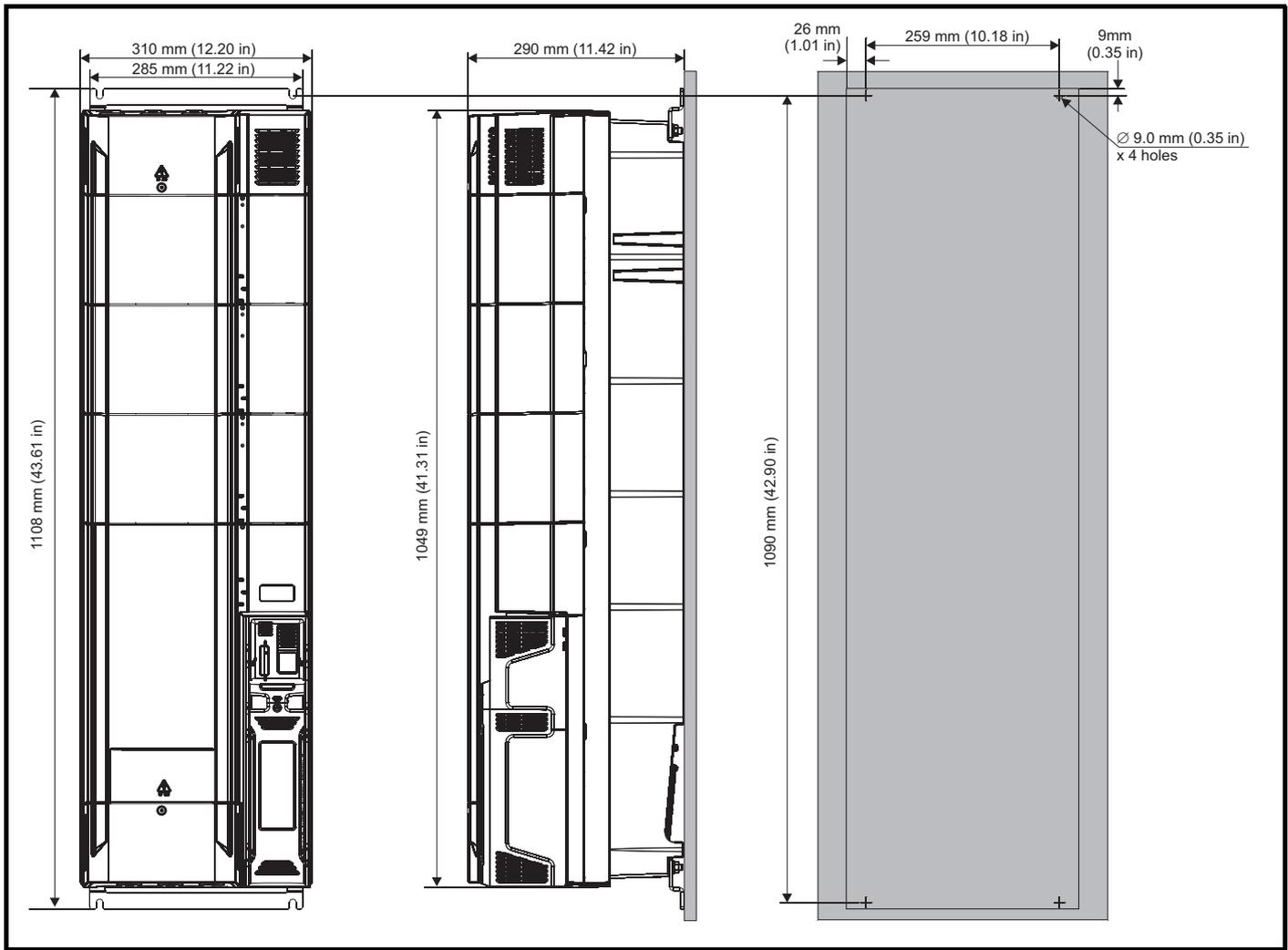


Figure 3-23 Surface mounting the size 9E and 10E

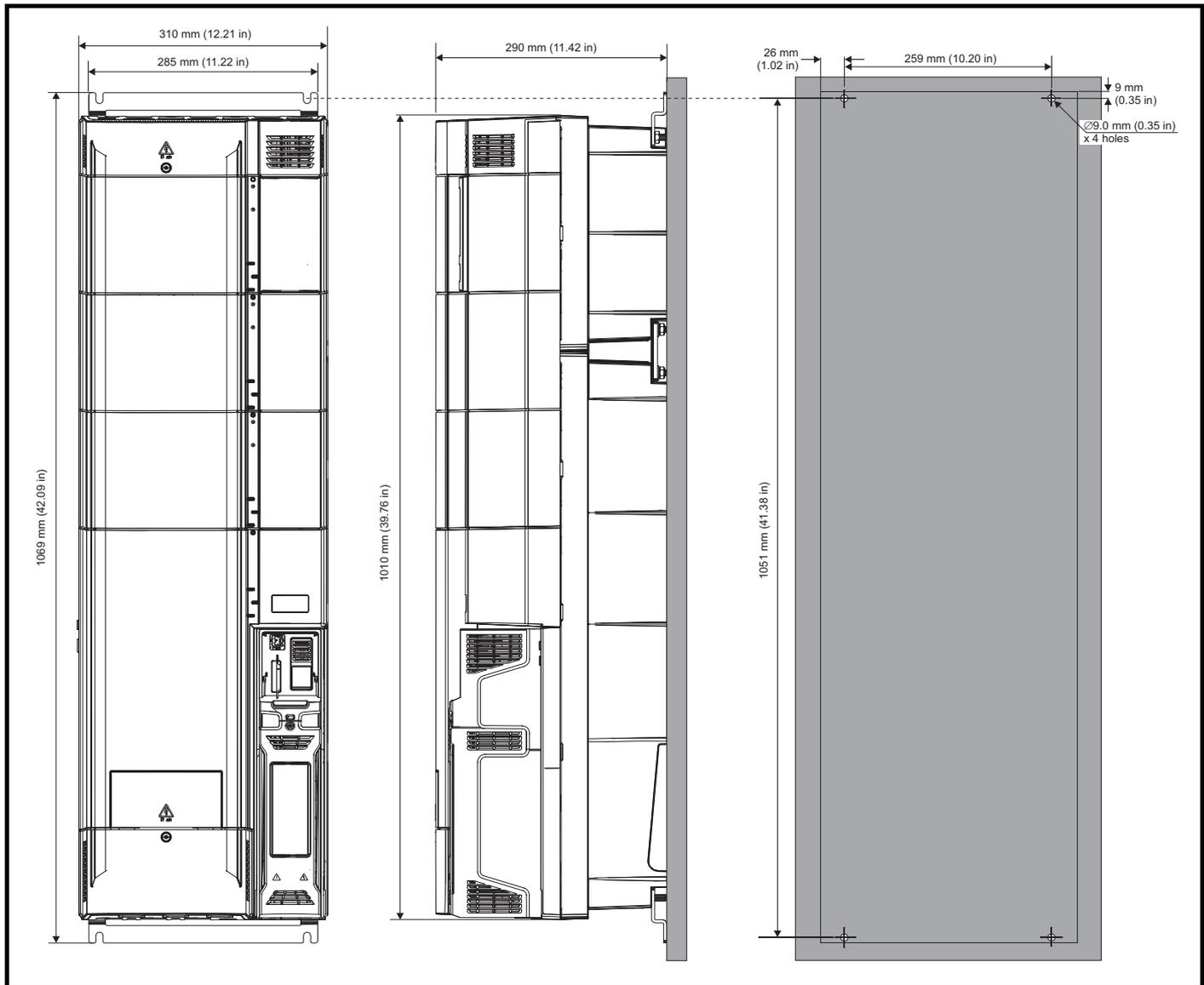
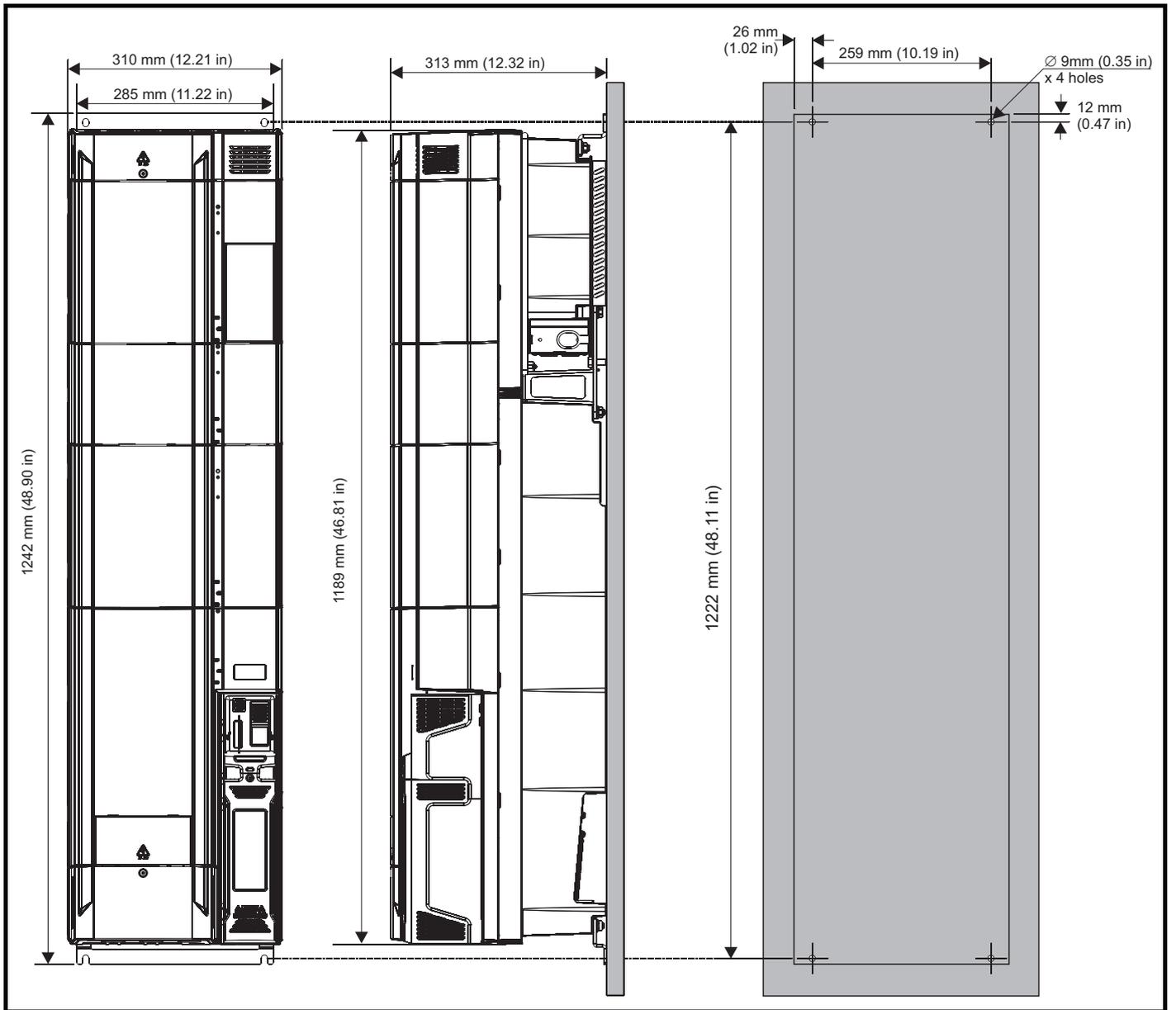


Figure 3-24 Surface mounting the size 11E



3.5.2 Through-panel mounting

Figure 3-25 Through-panel mounting the size 3 drive

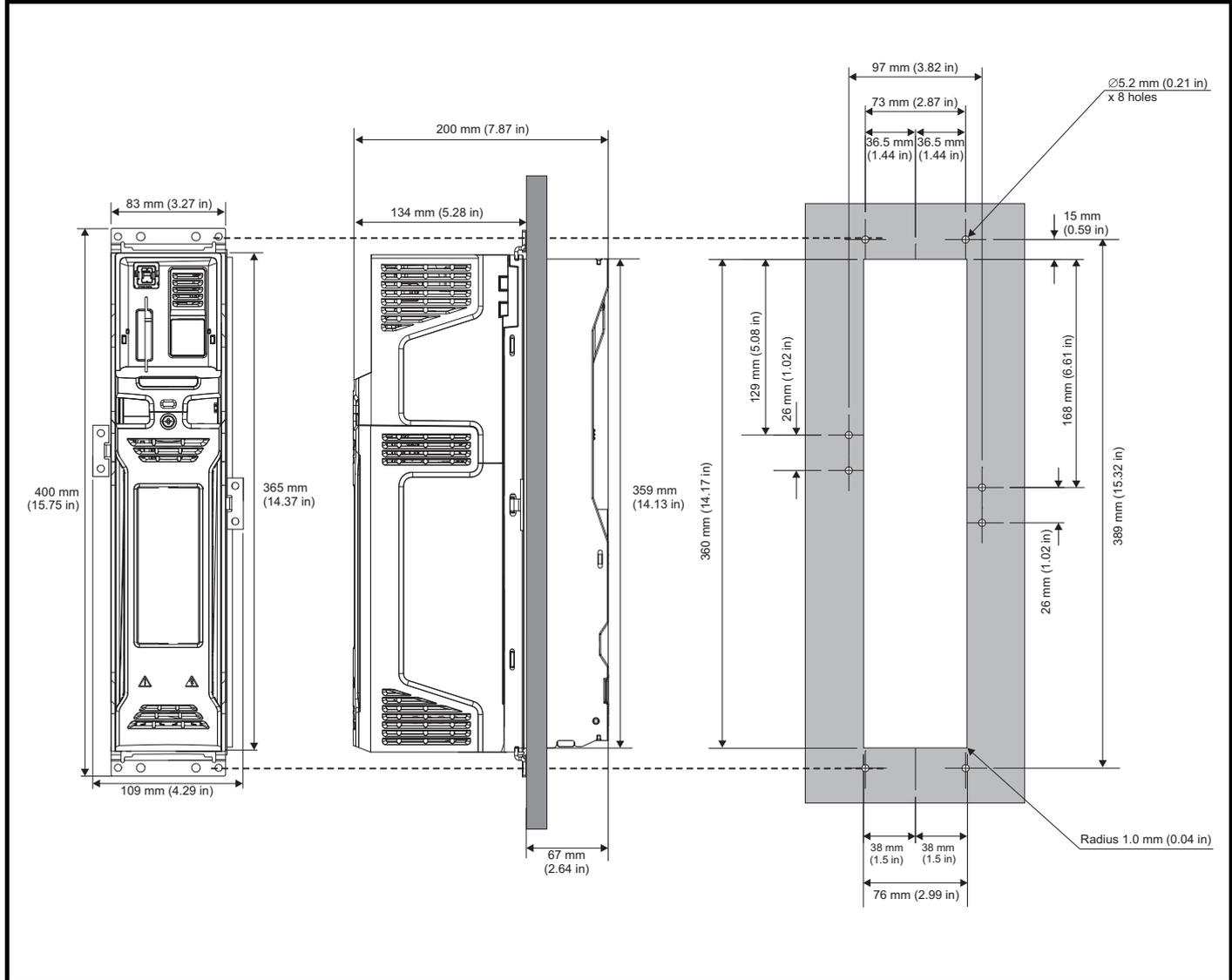


Figure 3-26 Through panel mounting the size 4 drive

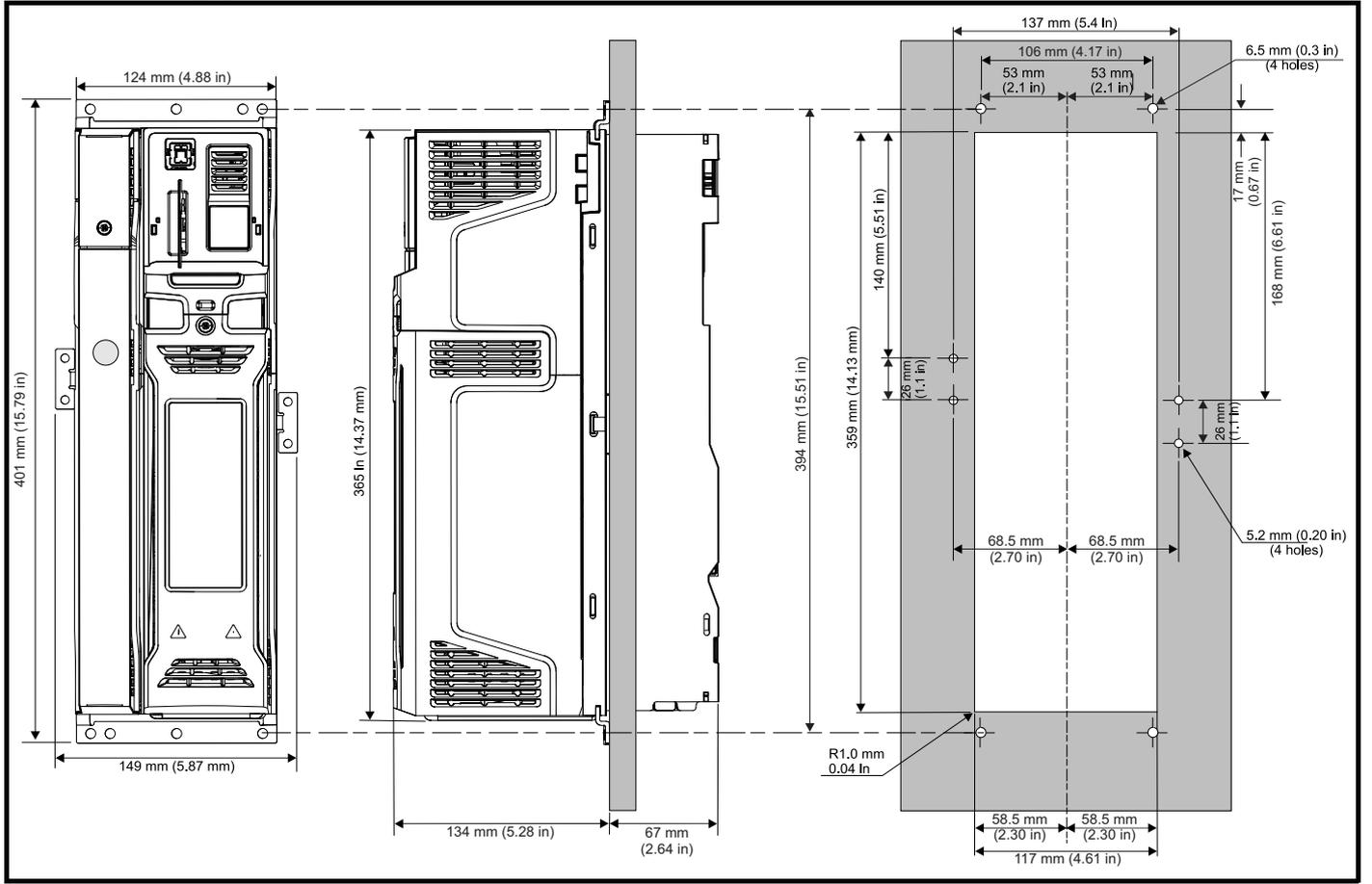


Figure 3-27 Through panel mounting the size 5 drive

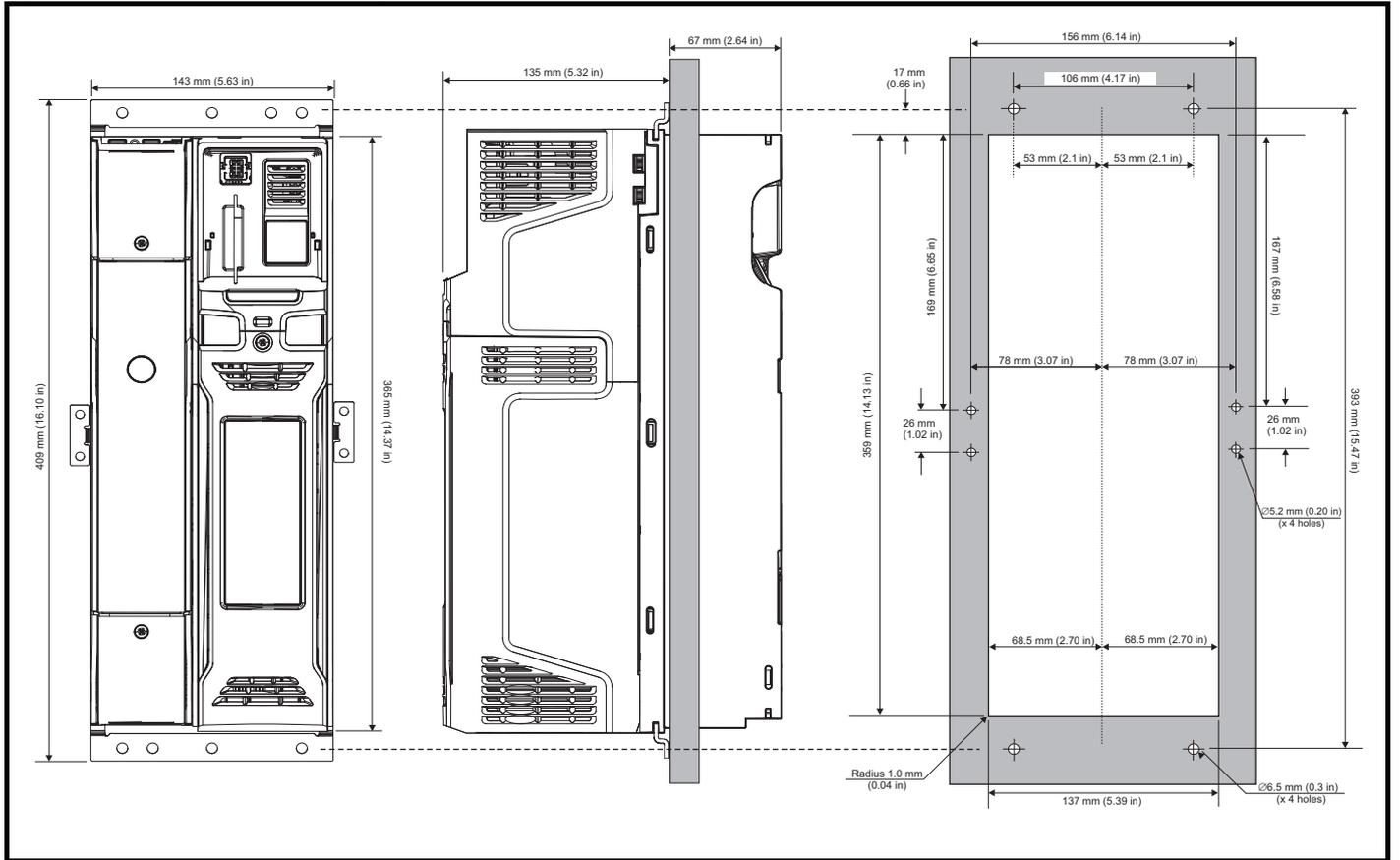


Figure 3-32 Through-panel mounting the size 9E and 10E

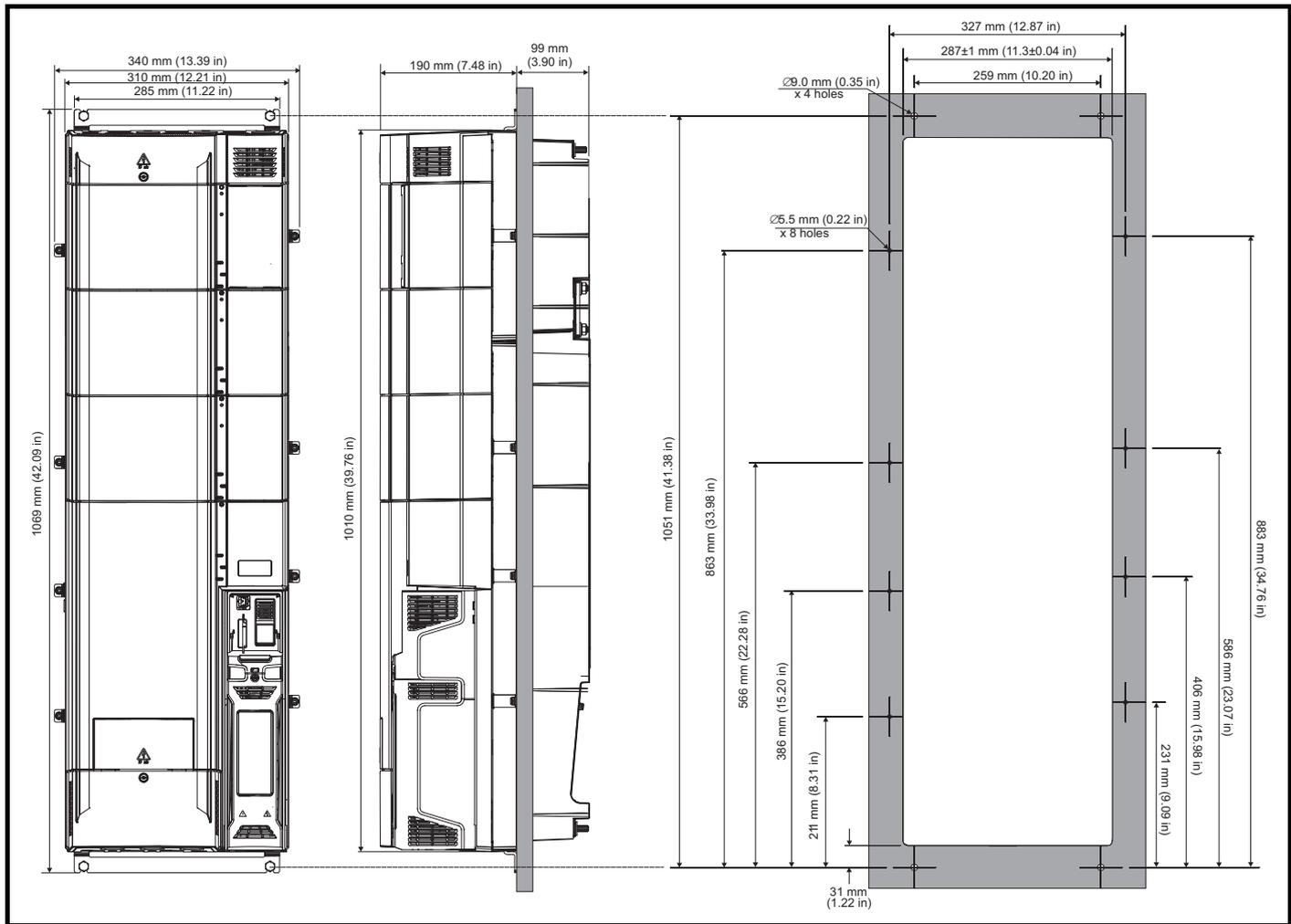


Figure 3-33 Through panel mounting the size 11E

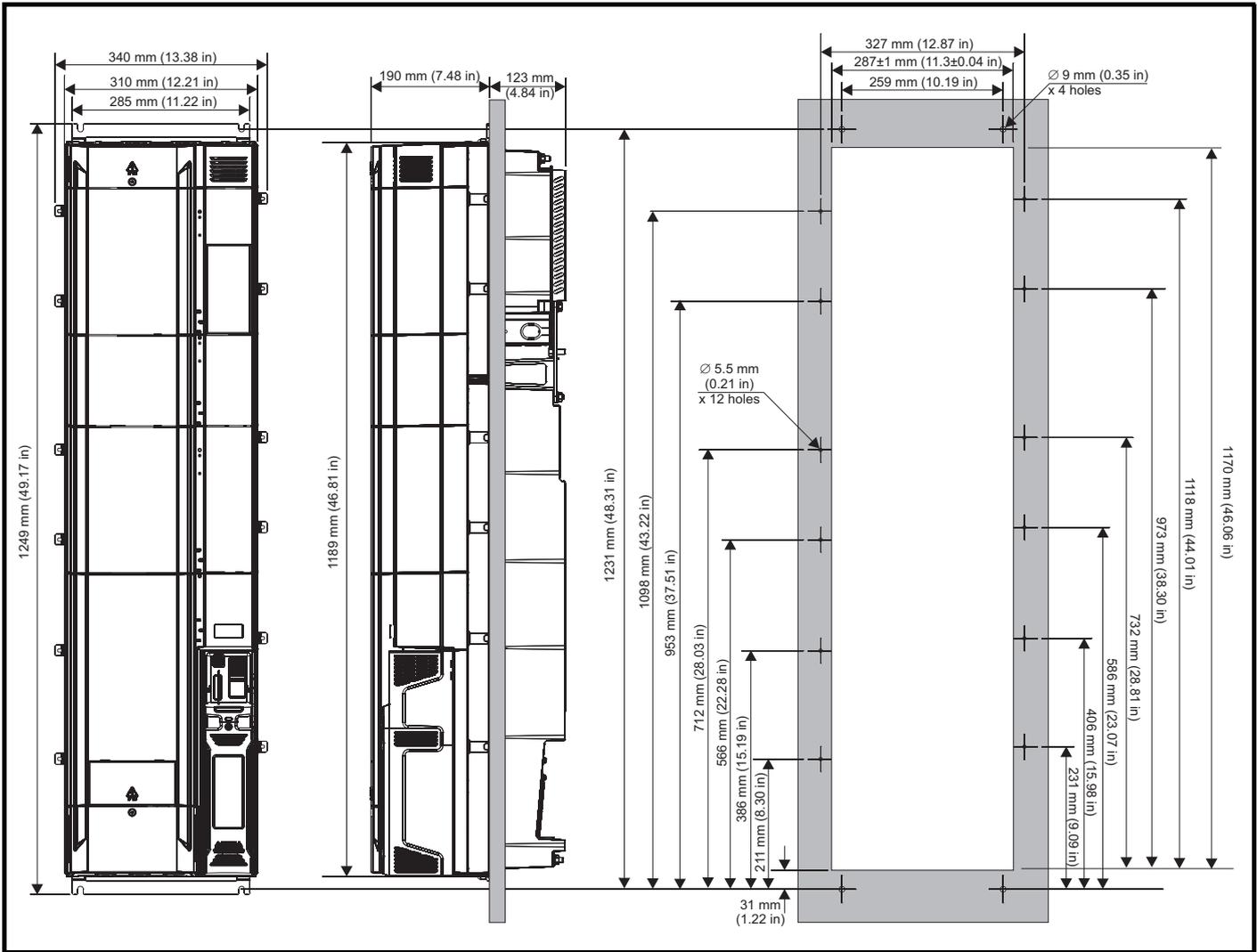


Figure 3-34 Size 3 High IP Drive and Mounting Hole Dimensions

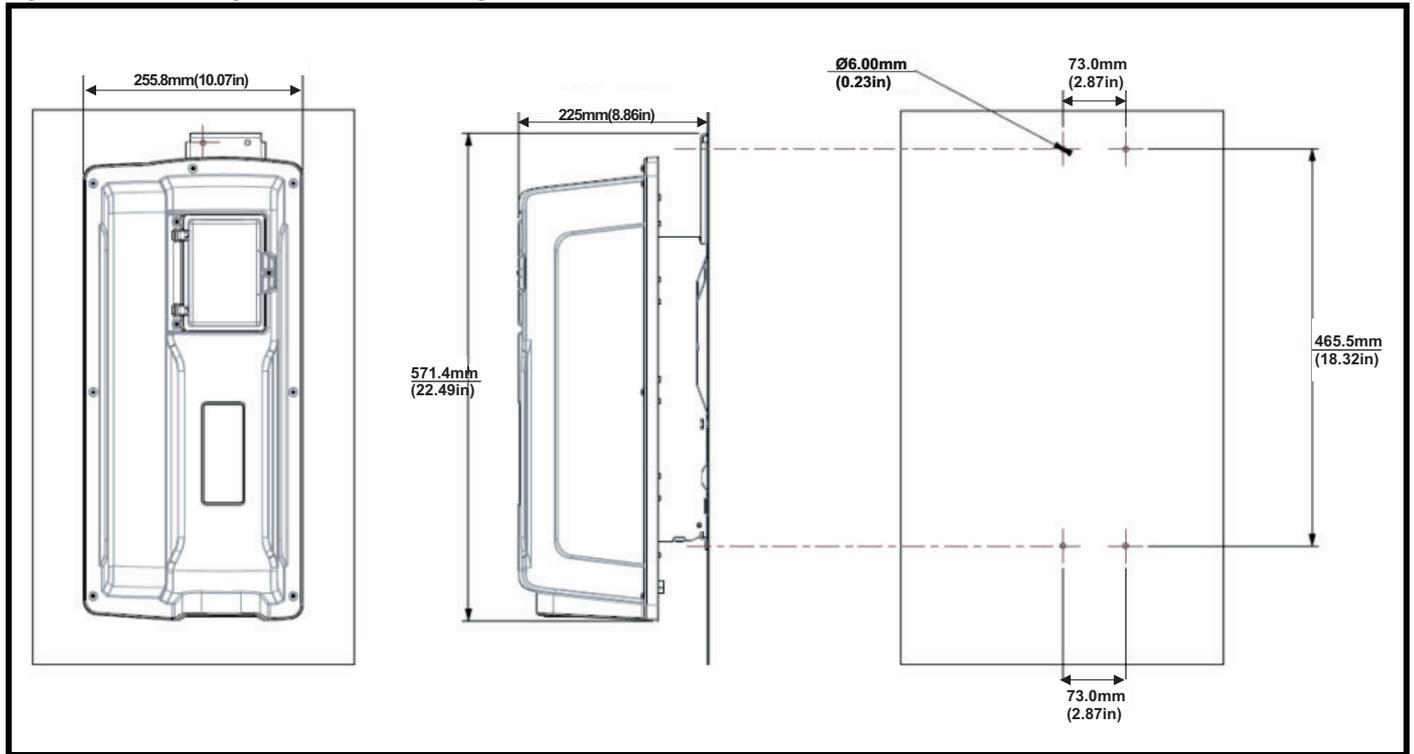


Figure 3-35 Size 4 High IP Drive and Mounting Hole Dimensions

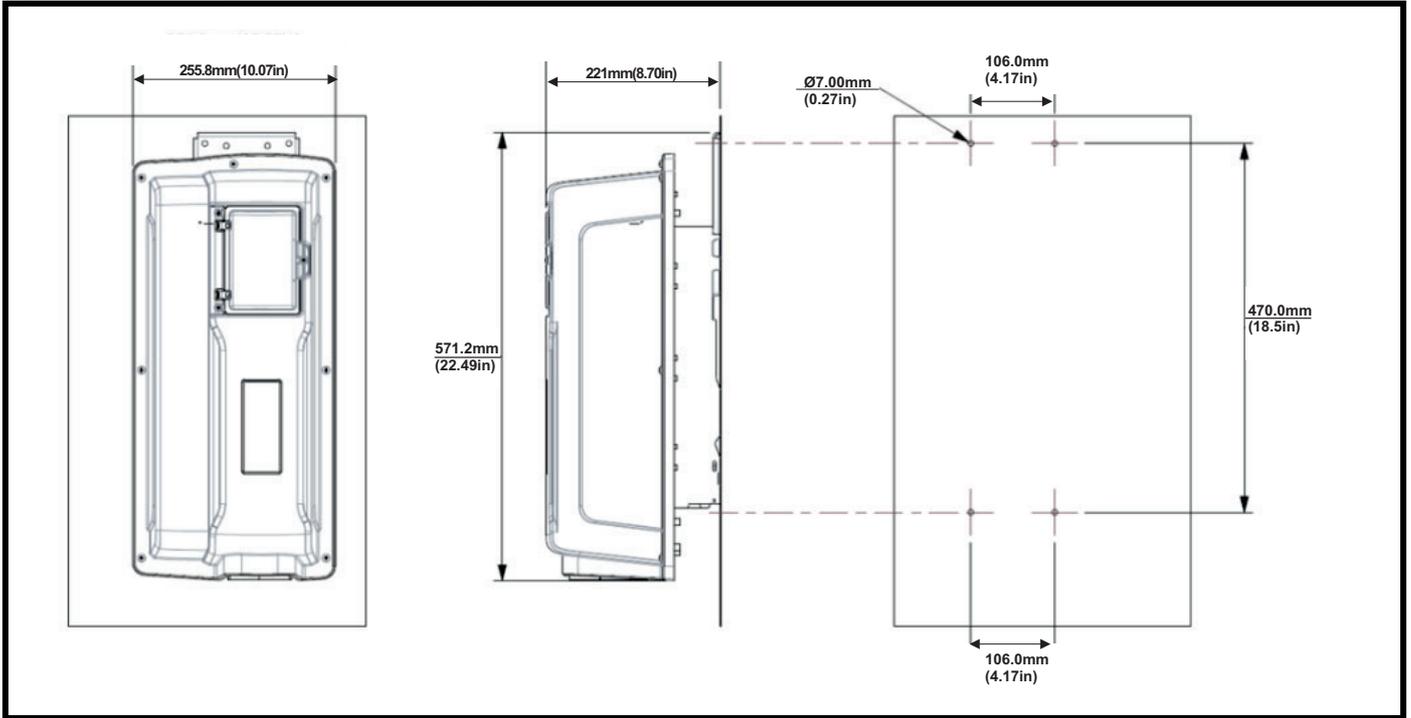


Figure 3-36 Size 5 High IP Drive and Mounting Hole Dimensions

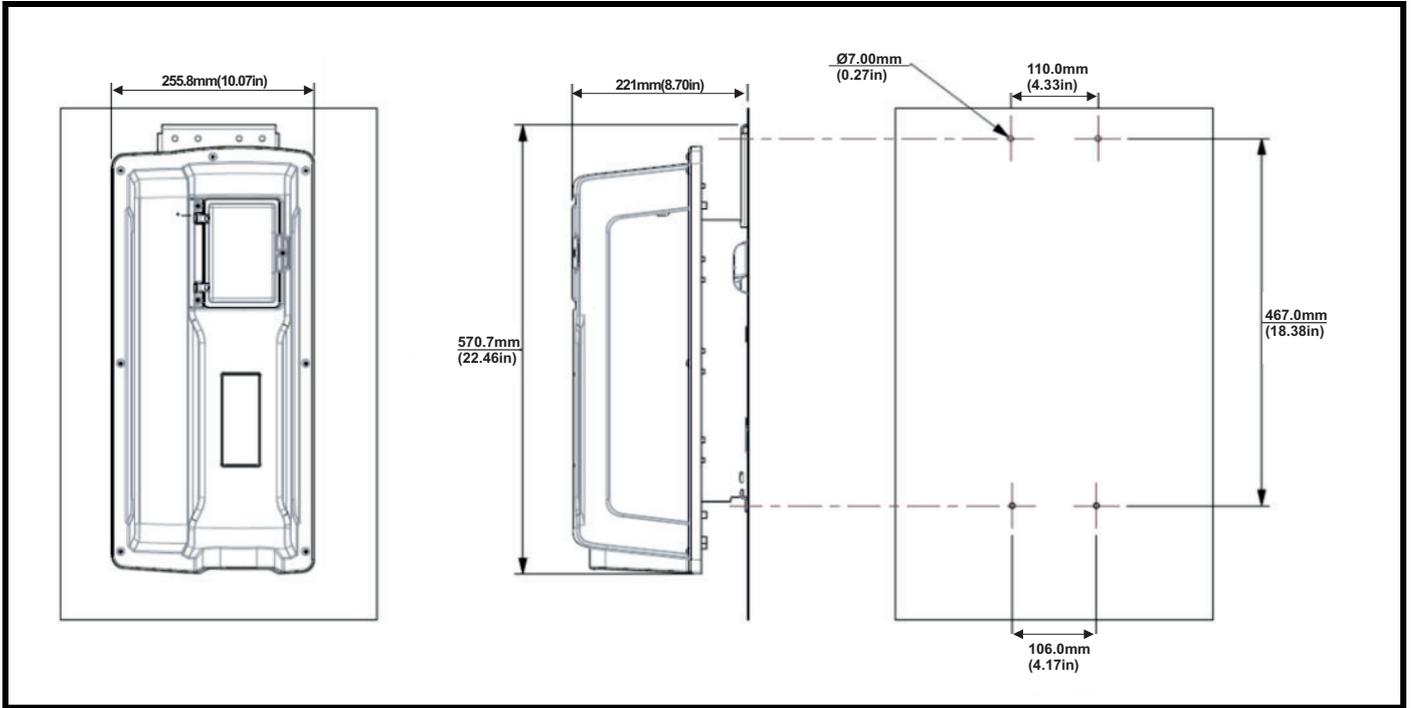
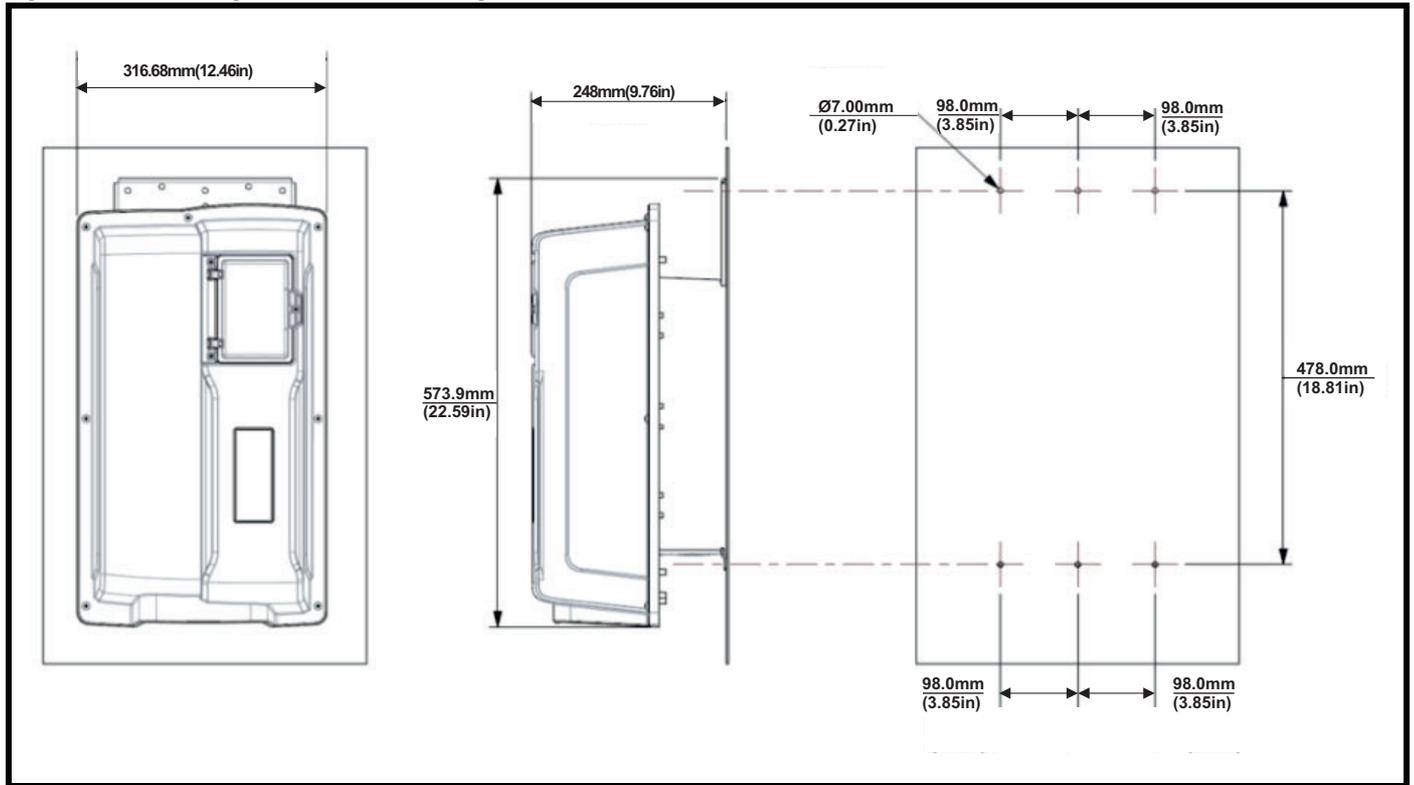
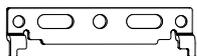
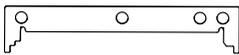
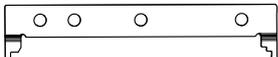
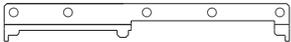
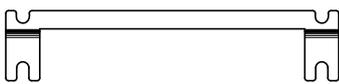
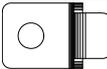
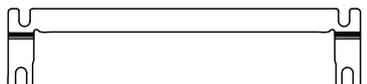
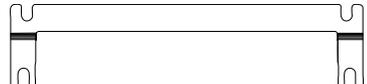


Figure 3-37 Size 6 High IP Drive and Mounting Hole Dimensions



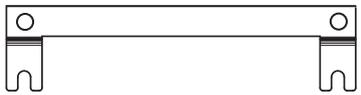
3.5.3 Mounting brackets

Table 3-2 Mounting brackets

Frame size	Surface mounting kit (supplied with drive)	Qty	Through-panel mounting kit (option)	Qty
3	 Outer hole size: 5.2 mm (0.20 in) Centre hole / slot size: 6.2 mm (0.24 in)	x 2*	 Hole size: 5.2 mm (0.21 in)	x 2
				x 1
4	 Hole size: 6.5 mm (0.26 in)	x 2*	 Hole size: 5.2 mm (0.21 in)	x 2
				x 1
5	 Hole size: 6.5 mm (0.26 in)	x 2*	 Hole size: 5.2 mm (0.21 in)	x 2
				x 1
6	 Hole size: 6.5 mm (0.26 in)	x 2*	 Hole size: 5.2 mm (0.21 in)	x 3
				x 1
7	 Hole size: 9 mm (0.35 in)	x 2*	 Hole size: 9 mm (0.35 in)	x 2
				x 1
8	 Hole size: 9 mm (0.35 in)	x 2*	 Hole size: 5.5 mm (0.22 in)	x 6
				x 1
9A, 9E and 10E	 Hole size: 9 mm (0.35 in)	x 2*	 Hole size: 5.5 mm (0.22 in)	x 8
				x 1

* Surface mounting brackets are also used when through-panel mounting.

Table 3-3 Mounting brackets (size 11)

Frame size	Surface mounting kit (supplied with drive)	Qty	Through-panel mounting kit (option)	Qty
11E	 Hole size: 9 mm (0.35 in)	x 2*	 Hole size: 5.5 mm (0.22 in)	x 12
	 Hole size: 9 mm (0.35 in)	x 1		x 1

* Surface mounting brackets are also used when through-panel mounting.

3.6 Enclosure for standard drives

3.6.1 Recommended spacing between the drives

Figure 3-38 Recommended spacing between the drives

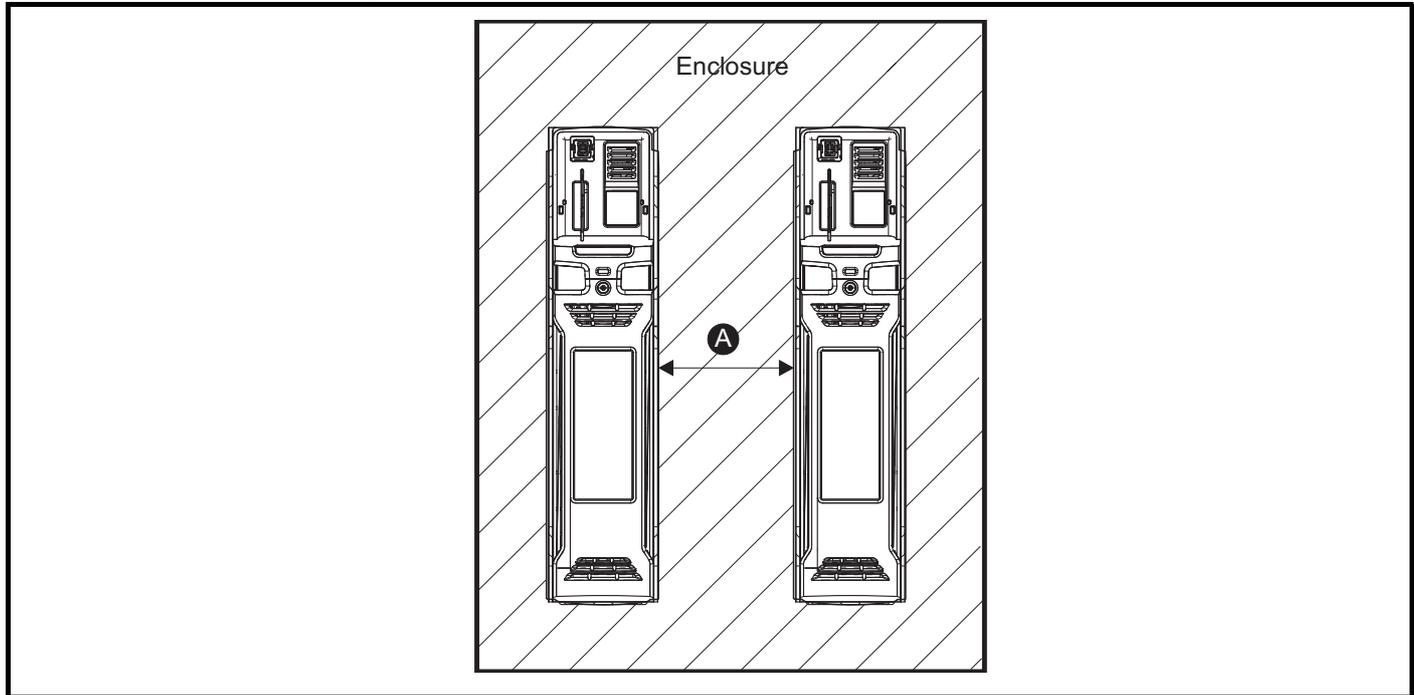


Table 3-4 Spacing required between the drives (without high IP bung)

Drive Size	Spacing (A)	
	40°C	50°C*
3	0 mm (0.00 in)	
4	0 mm (0.00 in)	
5	0 mm (0.00 in)	30 mm (1.18 in)
6	0 mm (0.00 in)	
7	30 mm (1.18 in)	
8	30 mm (1.18 in)	
9A / 9E	60 mm (2.37 in)	
10E / 11E		

* 50°C derating applies, refer to Table 12-3 *Maximum permissible continuous output current @ 50 °C (122 °F)* on page 283.

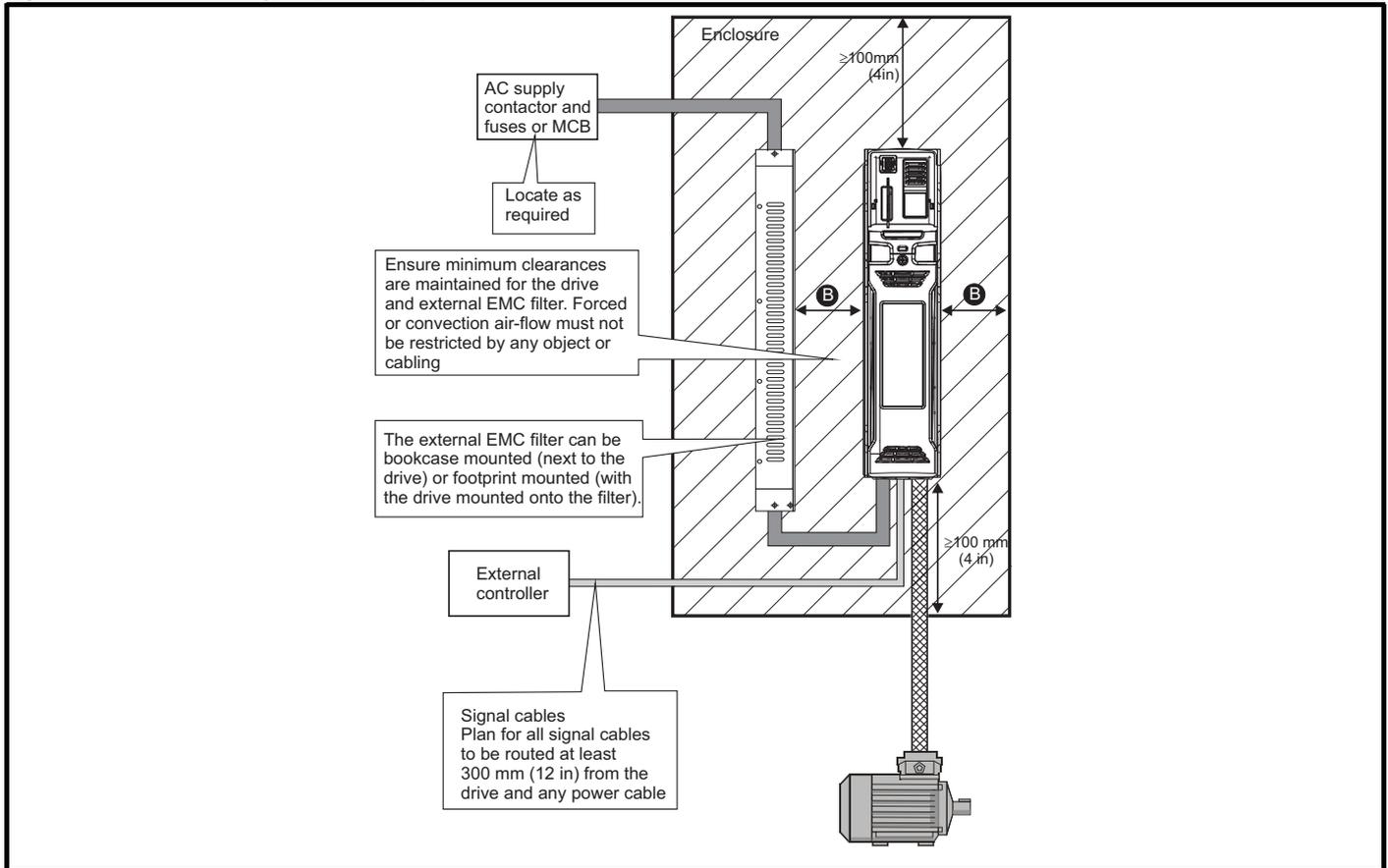
NOTE

When through-panel mounted, ideally drives should be spaced 45 mm (1.77 in) to maximize panel stiffness.

3.6.2 Enclosure layout

Please observe the clearances in the diagram below taking into account any appropriate notes for other devices / auxiliary equipment when planning the installation.

Figure 3-39 Enclosure layout (size 3 to 8)



NOTE

For EMC compliance:

1. When using an external EMC filter, one filter is required for each drive.
2. Power cabling must be at least 100 mm (4 in) from the drive in all directions

Table 3-5 Spacing required between drive / enclosure and drive / EMC filter (size 3 to 8)

Drive Size	Spacing (B)
3	0 mm (0.00 in)
4	30 mm (1.18 in)
5	
6	
7	
8	

NOTE

Drive sizes 3 to 5 can be tile mounted where limited mounting space is available. The tile mounting kit is not supplied with the drive, it can be purchased separately.

Figure 3-40 Enclosure layout (size 9 to 11)

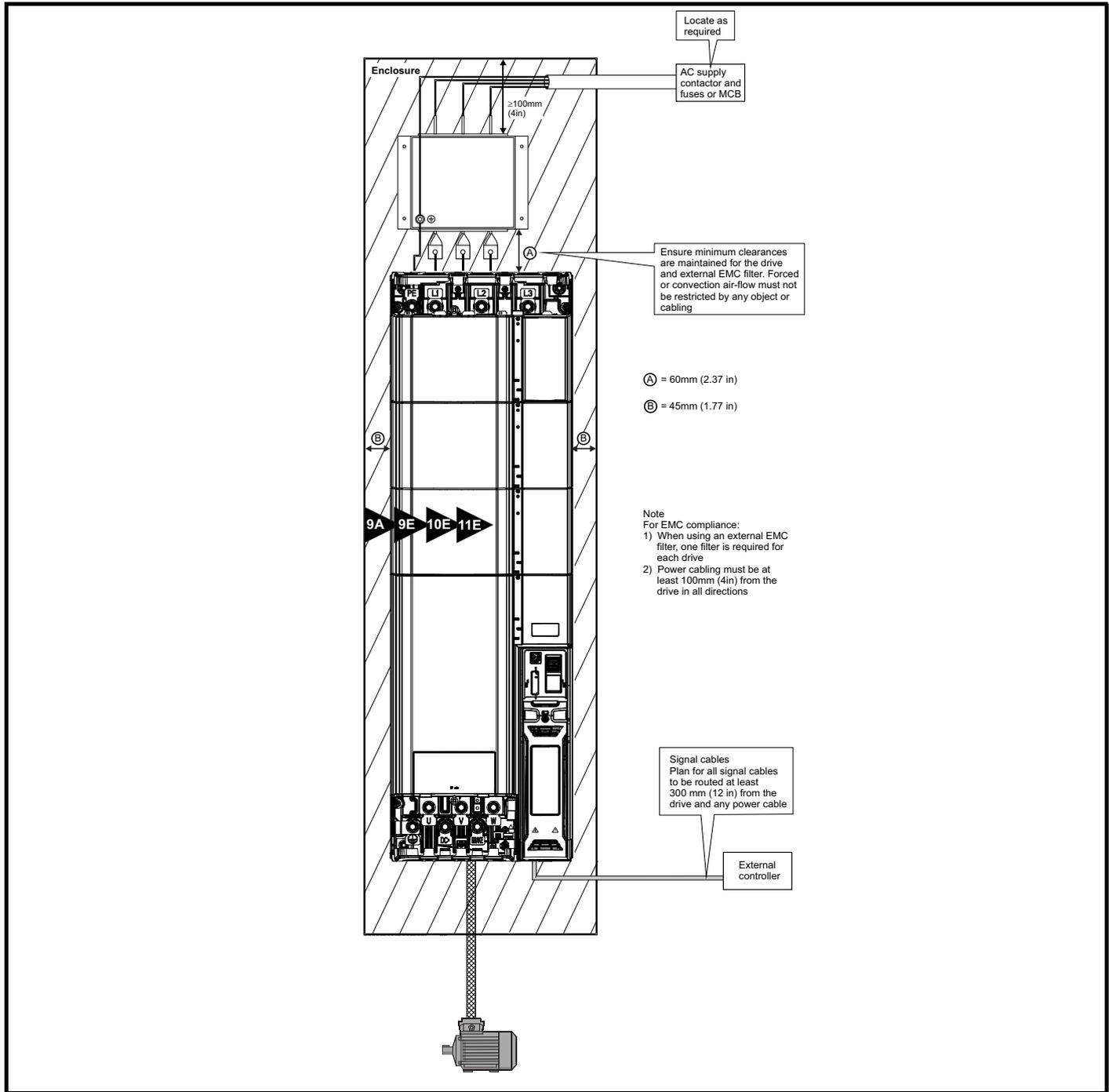


Table 3-6 Spacing required between drive / enclosure and drive (size 9 to 11)

Drive Size	Spacing (B)
9A/9E	45 mm (1.77 in)
10E/11E	

3.6.3 Enclosure sizing

1. Add the dissipation figures from section 12.1.2 *Power dissipation* on page 285 for each drive that is to be installed in the enclosure.
2. If an external EMC filter is to be used with each drive, add the dissipation figures from section 12.2.1 *EMC filter ratings* on page 305 for each external EMC filter that is to be installed in the enclosure.
3. If the braking resistor is to be mounted inside the enclosure, add the average power figures from for each braking resistor that is to be installed in the enclosure.
4. Calculate the total heat dissipation (in Watts) of any other equipment to be installed in the enclosure.
5. Add the heat dissipation figures obtained above. This gives a figure in Watts for the total heat that will be dissipated inside the enclosure.

Calculating the size of a sealed enclosure

The enclosure transfers internally generated heat into the surrounding air by natural convection (or external forced air flow); the greater the surface area of the enclosure walls, the better is the dissipation capability. Only the surfaces of the enclosure that are unobstructed (not in contact with a wall or floor) can dissipate heat.

Calculate the minimum required unobstructed surface area A_e for the enclosure from:

$$A_e = \frac{P}{k(T_{int} - T_{ext})}$$

Where:

A_e	Unobstructed surface area in m^2 ($1 m^2 = 10.9 ft^2$)
T_{ext}	Maximum expected temperature in $^{\circ}C$ <i>outside</i> the enclosure
T_{int}	Maximum permissible temperature in $^{\circ}C$ <i>inside</i> the enclosure
P	Power in Watts dissipated by <i>all</i> heat sources in the enclosure
k	Heat transmission coefficient of the enclosure material in $W/m^2/^{\circ}C$

Example

To calculate the size of an enclosure for the following:

- Two drives operating at the Normal Duty rating
- External EMC filter for each drive
- Braking resistors are to be mounted outside the enclosure
- Maximum ambient temperature inside the enclosure: $40^{\circ}C$
- Maximum ambient temperature outside the enclosure: $30^{\circ}C$

For example, if the power dissipation from each drive is 187 W and the power dissipation from each external EMC filter is 9.2 W.

Total dissipation: $2 \times (187 + 9.2) = 392.4 W$

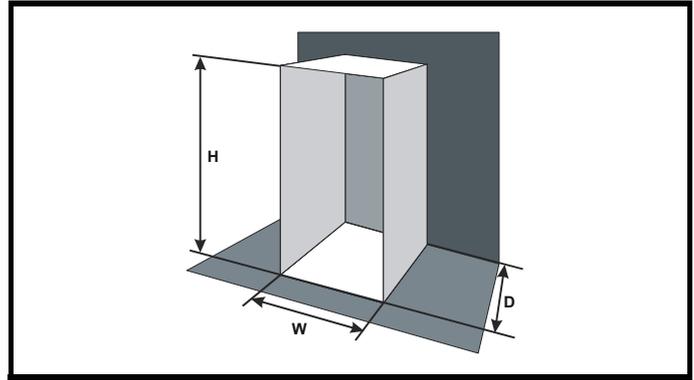
NOTE

Power dissipation for the drives and the external EMC filters can be obtained from Chapter 12 *Technical data* on page 279.

The enclosure is to be made from painted 2 mm (0.079 in) sheet steel having a heat transmission coefficient of $5.5 W/m^2/^{\circ}C$. Only the top, front, and two sides of the enclosure are free to dissipate heat.

The value of $5.5 W/m^2/^{\circ}C$ can generally be used with a sheet steel enclosure (exact values can be obtained by the supplier of the material). If in any doubt, allow for a greater margin in the temperature rise.

Figure 3-41 Enclosure having front, sides and top panels free to dissipate heat



Insert the following values:

T_{int}	$40^{\circ}C$
T_{ext}	$30^{\circ}C$
k	5.5
P	392.4 W

The minimum required heat conducting area is then:

$$A_e = \frac{392.4}{5.5(40 - 30)}$$

$$= 7.135 m^2 (77.8 ft^2) \quad (1 m^2 = 10.9 ft^2)$$

Estimate two of the enclosure dimensions - the height (H) and depth (D), for instance. Calculate the width (W) from:

$$W = \frac{A_e - 2HD}{H + D}$$

Inserting $H = 2m$ and $D = 0.6m$, obtain the minimum width:

$$W = \frac{7.135 - (2 \times 2 \times 0.6)}{2 + 0.6}$$

$$= 1.821 m (71.7 in)$$

If the enclosure is too large for the space available, it can be made smaller only by attending to one or all of the following:

- Using a lower PWM switching frequency to reduce the dissipation in the drives
- Reducing the ambient temperature outside the enclosure, and/or applying forced-air cooling to the outside of the enclosure
- Reducing the number of drives in the enclosure
- Removing other heat-generating equipment

Calculating the air-flow in a ventilated enclosure

The dimensions of the enclosure are required only for accommodating the equipment. The equipment is cooled by the forced air flow.

Calculate the minimum required volume of ventilating air from:

$$V = \frac{3kP}{T_{int} - T_{ext}}$$

Where:

V	Air-flow in m^3 per hour ($1 m^3/hr = 0.59 ft^3/min$)
T_{ext}	Maximum expected temperature in $^{\circ}C$ <i>outside</i> the enclosure
T_{int}	Maximum permissible temperature in $^{\circ}C$ <i>inside</i> the enclosure
P	Power in Watts dissipated by <i>all</i> heat sources in the enclosure
k	Ratio of $\frac{P_o}{P_i}$

Where:

P_o is the air pressure at sea level

P_i is the air pressure at the installation

Typically use a factor of 1.2 to 1.3, to allow also for pressure-drops in dirty air-filters.

Example

To calculate the size of an enclosure for the following:

- Three drives operating at the Normal Duty rating
- External EMC filter for each drive
- Braking resistors are to be mounted outside the enclosure
- Maximum ambient temperature inside the enclosure: 40 °C
- Maximum ambient temperature outside the enclosure: 30 °C

For example, dissipation of each drive: 101 W and dissipation of each external EMC filter: 6.9 W (max).

Total dissipation: $3 \times (101 + 6.9) = 323.7 \text{ W}$

Insert the following values:

T_{int} 40 °C
 T_{ext} 30 °C
 k 1.3
 P 323.7 W

Then:

$$V = \frac{3 \times 1.3 \times 323.7}{40 - 30}$$

$$= 126.2 \text{ m}^3/\text{hr} \text{ (74.5 ft}^3/\text{min)} \quad (1 \text{ m}^3/\text{hr} = 0.59 \text{ ft}^3/\text{min)}$$

3.7 Enclosure design and drive ambient temperature

Drive derating is required for operation in high ambient temperatures

Totally enclosing or through panel mounting the drive in either a sealed cabinet (no airflow) or in a well ventilated cabinet makes a significant difference on drive cooling.

The chosen method affects the ambient temperature value (T_{rate}) which should be used for any necessary derating to ensure sufficient cooling for the whole of the drive.

The ambient temperature for the four different combinations is defined below:

1. Totally enclosed with no air flow (<2 m/s) over the drive
 $T_{rate} = T_{int} + 5 \text{ °C}$
2. Totally enclosed with air flow (>2 m/s) over the drive
 $T_{rate} = T_{int}$
3. Through panel mounted with no airflow (<2 m/s) over the drive
 $T_{rate} = \text{the greater of } T_{ext} + 5 \text{ °C, or } T_{int}$
4. Through panel mounted with air flow (>2 m/s) over the drive
 $T_{rate} = \text{the greater of } T_{ext} \text{ or } T_{int}$

Where:

T_{ext} = Temperature outside the cabinet
 T_{int} = Temperature inside the cabinet
 T_{rate} = Temperature used to select current rating from tables in Chapter 12 *Technical data* on page 279.

3.8 Heatsink fan operation

The drive is ventilated by an internal heatsink mounted fan. The fan housing forms a baffle plate, channelling the air through the heatsink chamber. Thus, regardless of mounting method (surface mounting or through-panel mounting), the installing of additional baffle plates is not required.

Ensure the minimum clearances around the drive are maintained to allow air to flow freely.

The heatsink fan on all sizes is a variable speed fan. The drive controls the speed at which the fan runs based on the temperature of the heatsink and the drive's thermal model system. The maximum speed at which the fan operates can be limited in Pr **06.045**. This could incur an output current derating. Refer to section 3.13.2 *Size 3 to 5 heatsink fan removal procedure* on page 79 for information on fan removal. Size 6 to 11 are also installed with a variable speed fan to ventilate the capacitor bank.

3.9 Enclosing standard drive for high environmental protection

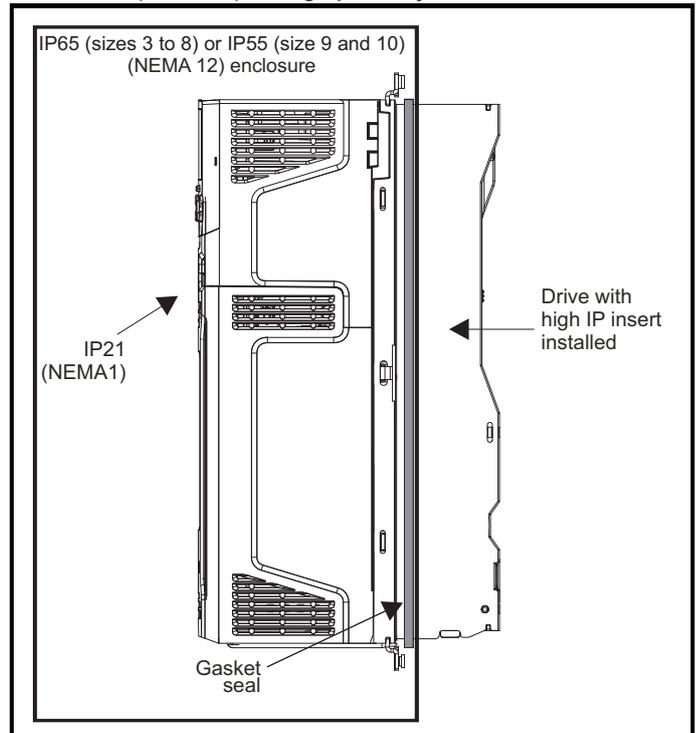
An explanation of environmental protection rating is provided in section 12.1.9 *IP / UL Rating*.

The standard drive is rated to IP20 pollution degree 2 (dry, non-conductive contamination only) (NEMA 1). The high IP drive is rated at IP65. However, it is possible to configure the standard drive to achieve IP65 rating (sizes 3 to 8) or IP55 (size 9, 10 and 11) (NEMA 12) at the rear of the heatsink for through-panel mounting (some current derating is required). Refer to section 12.1.1 *Power and current ratings (Derating for switching frequency and temperature)* on page 279.

This allows the front of the drive, along with various switchgear, to be housed in a high IP enclosure with the heatsink protruding through the panel to the external environment. Thus, the majority of the heat generated by the drive is dissipated outside the enclosure maintaining a reduced temperature inside the enclosure. This also relies on a good seal being made between the heatsink and the rear of the enclosure using the gaskets provided.

There is also an alternative solution to provide IP65 rating for frame sizes 3 to 6 using a sealed cover when through panel mounting is not appropriate or if the drive is to be used outside of a control panel as shown on page 51.

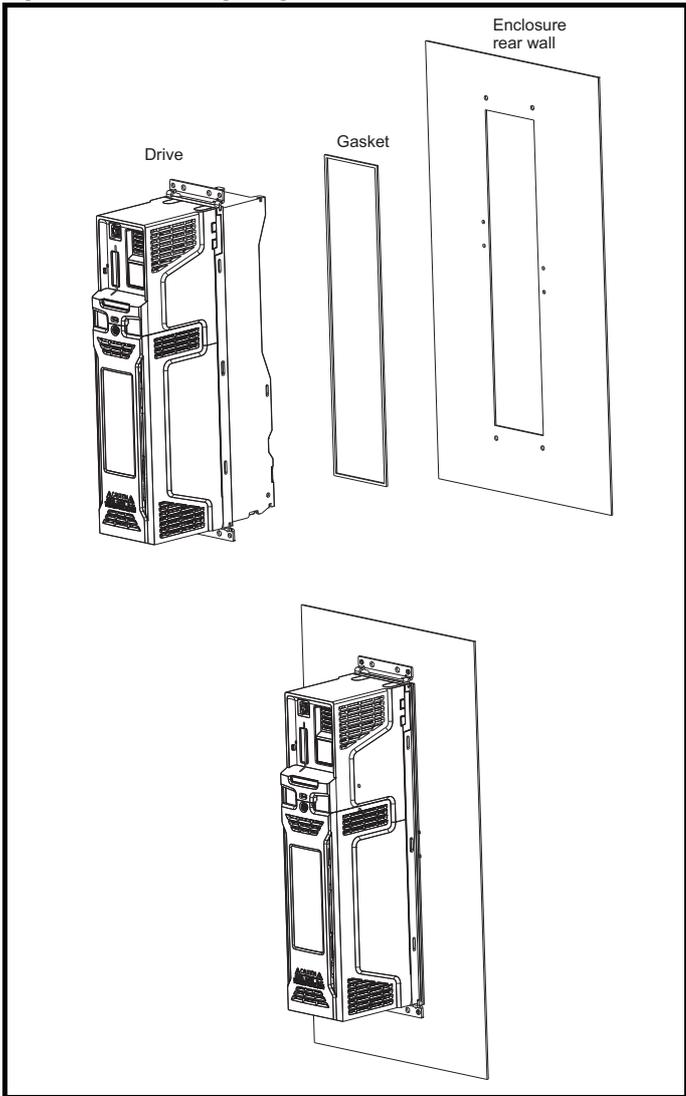
Figure 3-42 Example of IP65 (sizes 3 to 8) or IP55 (size 9 and 10) (NEMA 12) through-panel layout



The main gasket should be installed as shown in Figure 3-43.

On drive sizes 3, 4 and 5, in order to achieve the high IP rating at the rear of the heatsink it is necessary to seal a heatsink vent by installing the high IP insert as shown in Figure 3-45, Figure 3-46 and Figure 3-47.

Figure 3-43 Installing the gasket



To seal the space between the drive and the backplate, use two sealing brackets as shown in Figure 3-44.

Figure 3-44 Through panel mounting

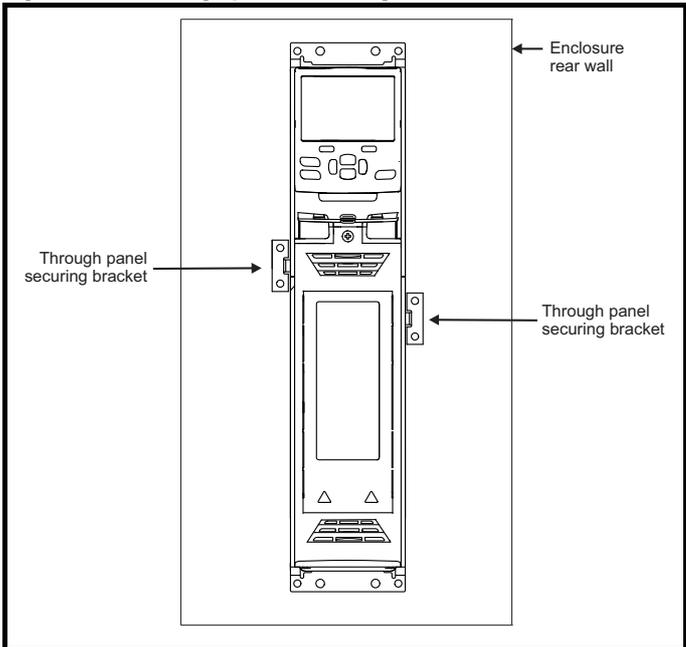
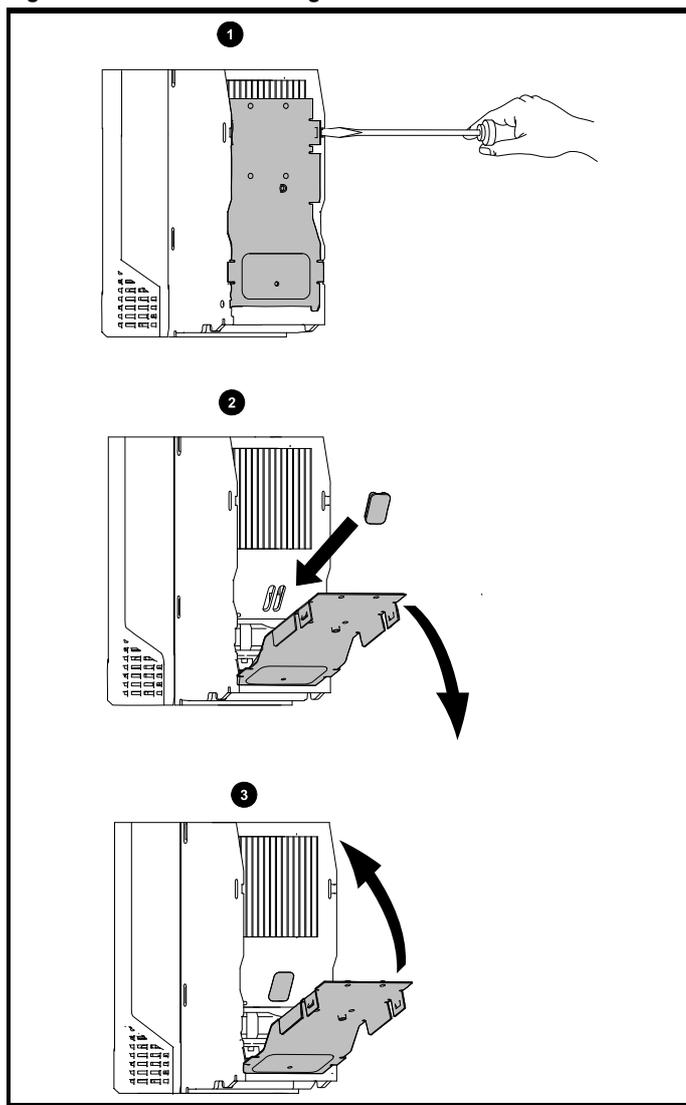


Figure 3-45 Installation of high IP insert for size 3

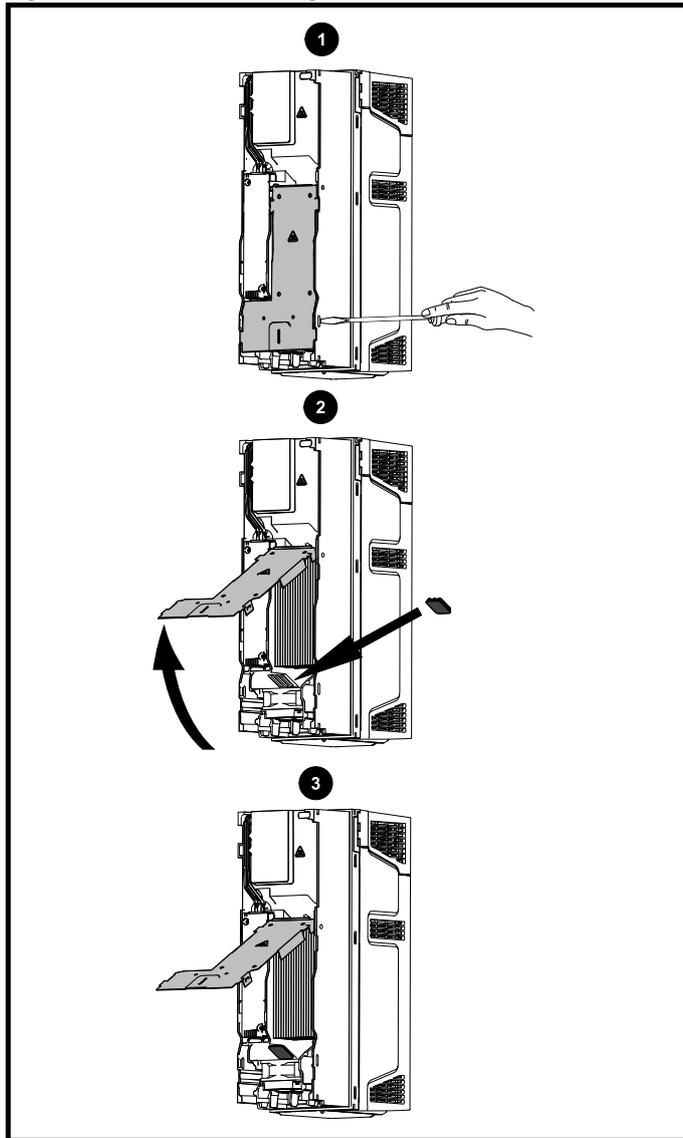


1. To install the high IP insert, firstly place a flat head screwdriver into the slot highlighted (1).
2. Pull the hinged baffle down to expose the ventilation hole, install the high IP insert into the ventilation hole in the heatsink (2). Ensure the high IP insert is securely installed by firmly pressing it into place (3).
3. Close the hinged baffle as shown (1).

To remove the high IP insert, reverse the above instructions.

The guidelines in Table 3-7 should be followed.

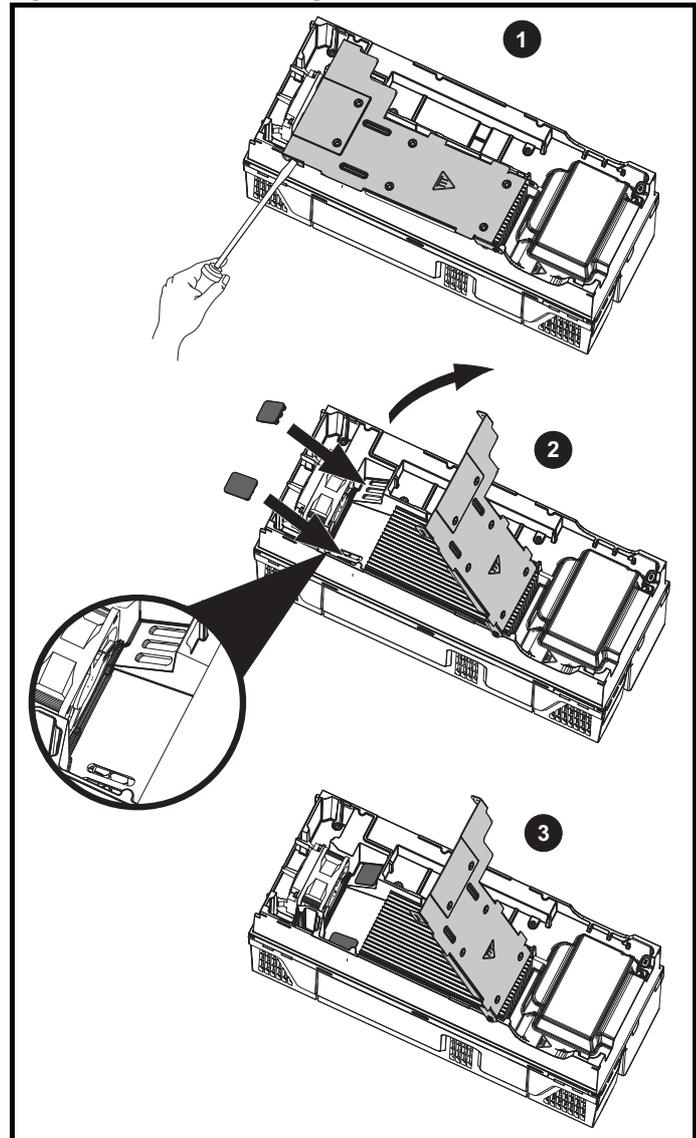
Figure 3-46 Installation of high IP insert for size 4



1. To install the high IP insert, firstly place a flat head screwdriver into the slot highlighted (1).
2. Pull the hinged baffle up to expose the ventilation hole, install the high IP insert into the ventilation hole in the heatsink (2).
3. Ensure the high IP insert is securely installed by firmly pressing it into place (3).
4. Close the hinged baffle as shown (1).

To remove the high IP insert, reverse the above instructions.
The guidelines in Table 3-7 should be followed.

Figure 3-47 Installation of high IP insert for size 5



1. To install the high IP insert, firstly place a flat head screwdriver into the slot highlighted (1).
2. Pull the hinged baffle up to expose the ventilation holes, install the high IP inserts into the ventilation holes in the heatsink (2).
3. Ensure the high IP inserts are securely installed by firmly pressing them into place (3).
4. Close the hinged baffle as shown (1).

To remove the high IP insert, reverse the above instructions.
The guidelines in Table 3-7 should be followed.

Table 3-7 Environment considerations

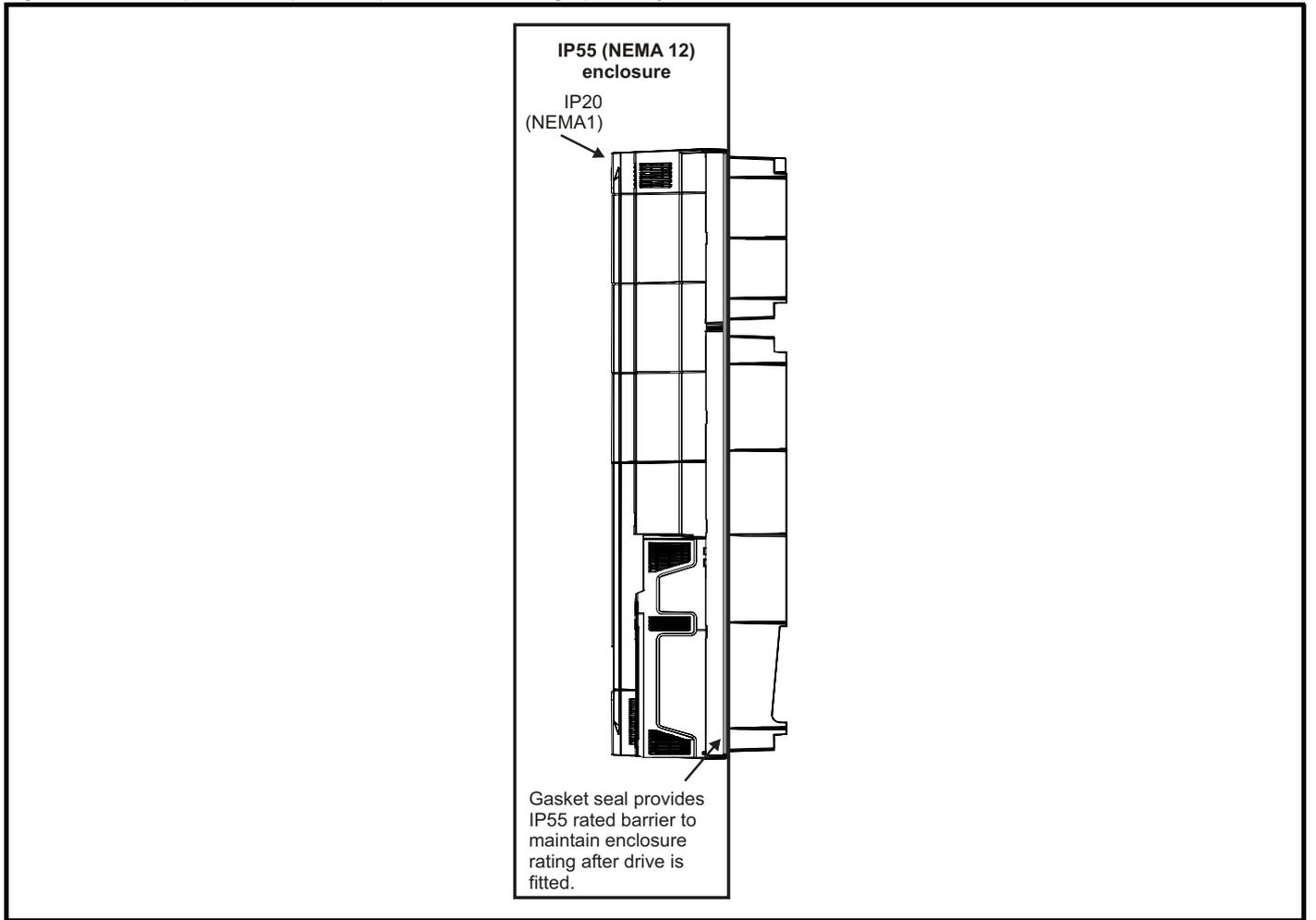
Environment	High IP insert	Comments
Clean	Not installed	
Dry, dusty (non-conductive)	Installed	Regular cleaning recommended
Dry, dusty (conductive)	Installed	
IP65 compliance	Installed	

NOTE

A current derating must be applied to the drive if the high IP insert is installed. Derating information is provided in section 12.1.1 *Power and current ratings (Derating for switching frequency and temperature)* on page 279.

Failure to do so may result in nuisance tripping.

Figure 3-48 Example of IP55 (NEMA 12) size 9 to 11 through-panel layout



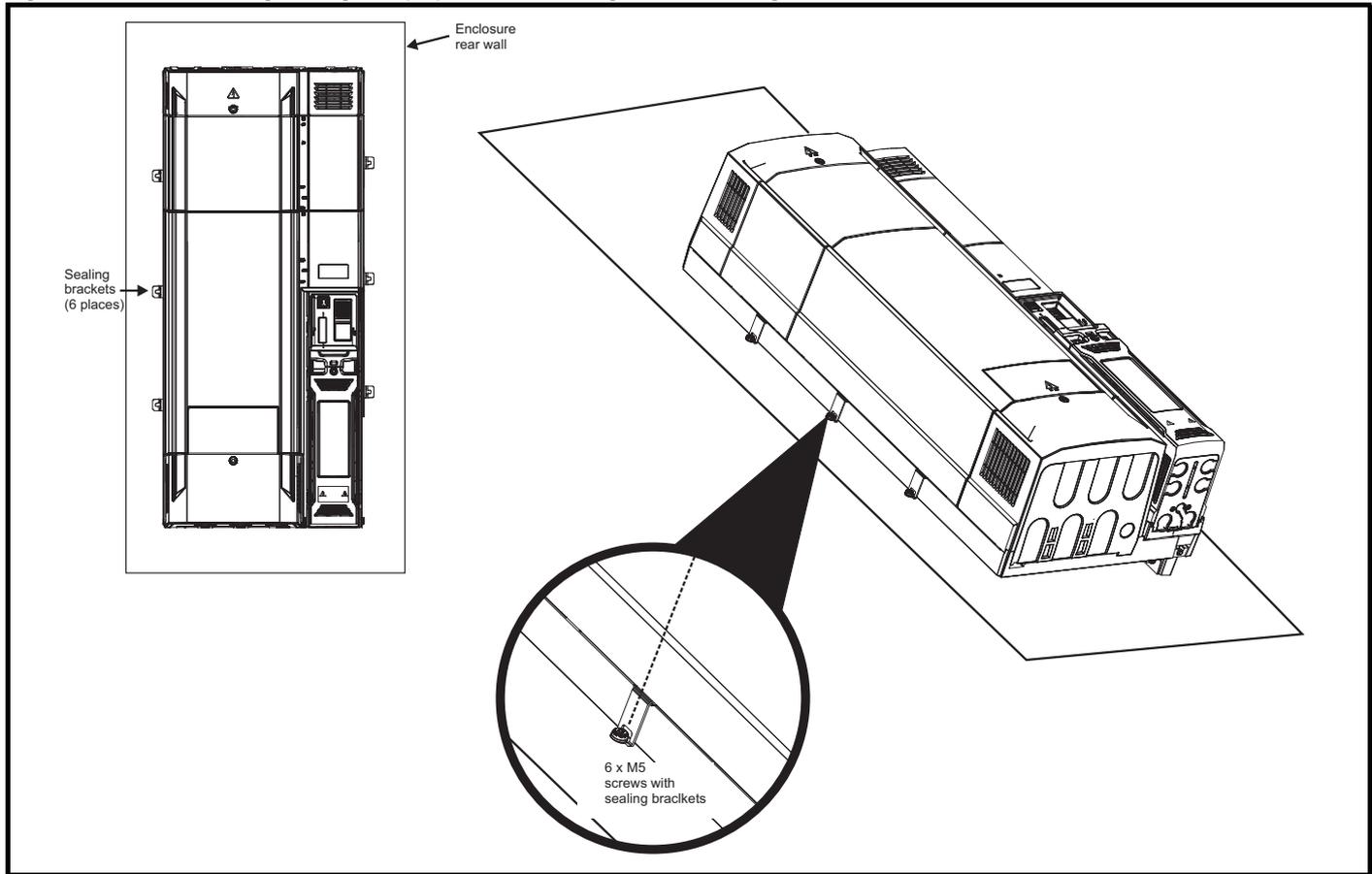
The main gasket should be installed as shown in Figure 3-43. Any screws / bolts that are used for mounting should be installed with M8 flat nylon washers to maintain a seal around the screw hole.

See Figure 3-49 on page 67, sealing clamps are supplied in the through panel mounting kit to aid compression of the gasket.

NOTE

The heatsink fans have conformal coated PCBs and have sealant at cable entry points. Dripping, splashing or sprayed water can impede the operation of the fan, therefore if the environment is such that the fan may be subjected to more than occasional dripping or sprayed water while operational, then suitable drip protection covers should be employed.

Figure 3-49 View showing sealing clamps provided in through hole mounting kit



NOTE

For detailed information regarding IP55 (NEMA 12) Through Panel Mounting see Figure 3-31 *Through panel mount detail for size 9A* on page 52, Figure 3-32 *Through-panel mounting the size 9E and 10E* on page 53 and Figure 3.5.3 *Mounting brackets* on page 58.

NOTE

When designing an IP65 or IP55 enclosure, consideration should be made to the dissipation from the front of the drive.

Table 3-8 Power losses from the front of the drive when through-panel mounted

Frame size	Power loss
3	≤ 50 W
4	≤ 75 W
5	≤ 100 W
6	≤ 100 W
7	≤ 204 W
8	≤ 347 W
9A/9E/10E/11E	≤ 480 W

3.10 External EMC filter

The external EMC filter details for each drive rating are provided in the table below.

Table 3-9 External EMC filter data

Model	CT part number	Weight	
		kg	lb
200 V			
03200066 to 03200127	4200-3230	1.9	4.20
04200180 to 04200250	4200-0272	4.0	8.82
05200300	4200-0312	5.5	12.13
06200500 to 06200580	4200-2300	6.5	14.3
07200750 to 07201170	4200-1132	6	13.2
08201490 to 08201800	4200-1972	9.6	21.1
09202160 to 09202660 (9A)	4200-3021	11	24.3
09202160 to 09202660 (9E)	4200-4460	12	26.5
10203250 to 10203600	4200-4460	12	26.5
400 V			
03400034 to 03400123	4200-3480	2.0	4.40
04400185 to 04400240	4200-0252	4.1	9.04
05400300	4200-0402	5.5	12.13
06400380 to 06400630	4200-4800	6.7	14.8
07400790 to 07401120	4200-1132	6	13.2
08401550 to 08401840	4200-1972	9.6	21.1
09402210 to 09402660 (9A)	4200-3021	11	24.25
09402210 to 09402660 (9E)	4200-4460	12	26.5
10403200 to 10403610	4200-4460	12	26.5
11404370 to 11405070	4200-0400	14.7	32.41
575 V			
05500039 to 05500100	4200-0122	5.5	12.13
06500120 to 06500430	4200-3690	7.0	15.4
07500530 to 07500730	4200-0672	6.2	13.7
08500860 to 08501080	4200-1662	9.4	20.7
09501250 to 09501500 (9A)	4200-1660	5.2	11.46
09501250 to 09501500 (9E)	4200-2210	10.3	22.7
10502000	4200-2210	10.3	22.7
11502480 to 11503150	4200-0690	16.75	36.9
690 V			
07600230 to 07600730	4200-0672	6	13.2
08600860 to 08601080	4200-1662	9.4	20.7
09601250 to 09601550 (9A)	4200-1660	5.2	11.5
09601250 to 09601550 (9E)	4200-2210	10.3	22.7
10601720 to 10601970	4200-2210	10.3	22.7
11602250 to 11603050	4200-0690	16.75	36.9

NOTE

For size 12 drives please refer to Unidrive M Power Module Frame 12 Installation Guide.

The external EMC filters for sizes 0 to 6 can be footprint mounted or bookcase mounted as shown in Figure 3-50 and Figure 3-51. The external EMC filters for sizes 7 to 11, are designed to be mounted above the drive as shown in Figure 3-52.

Mount the external EMC filter following the guidelines in section 4.11.6 *Compliance with generic emission standards* on page 121.

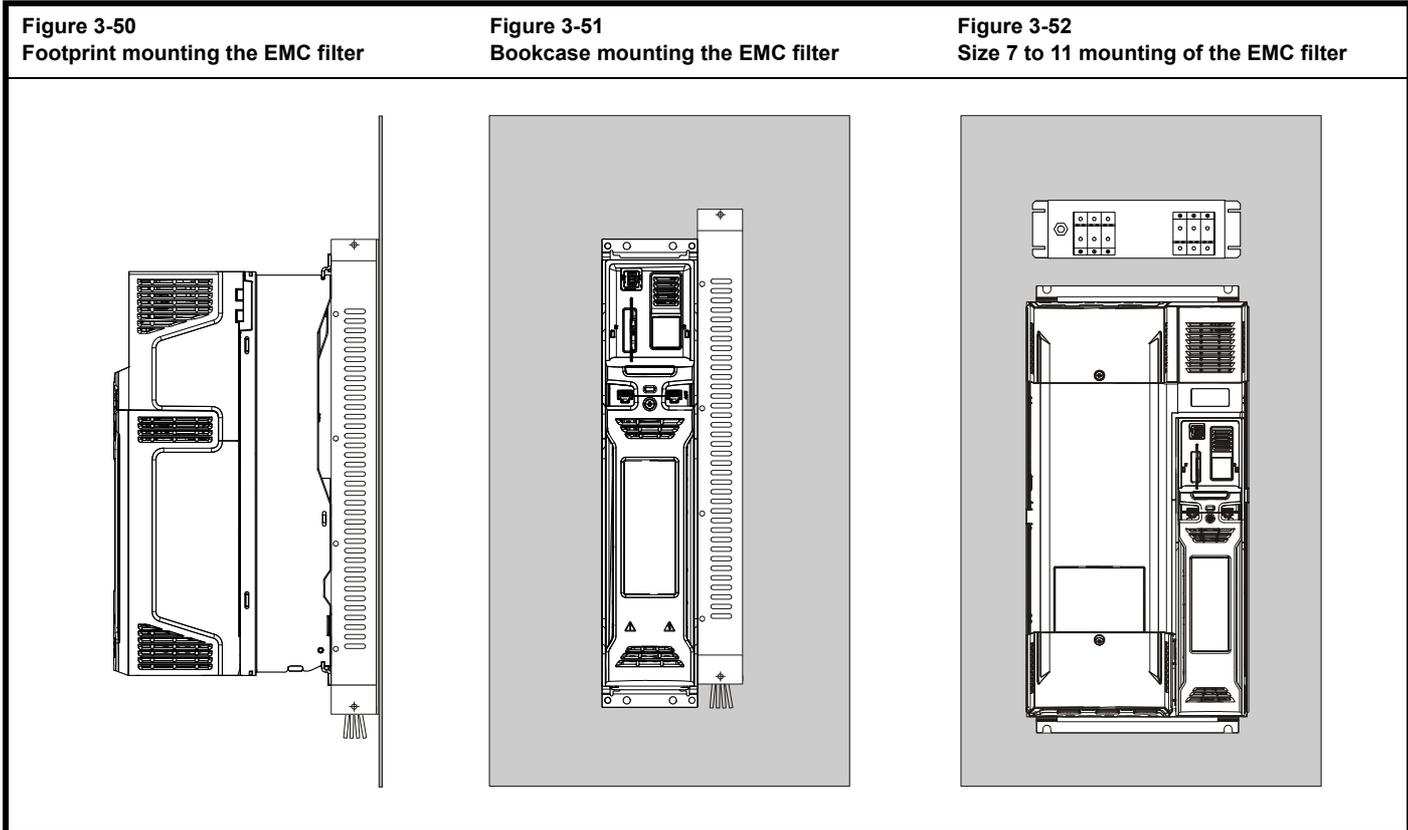
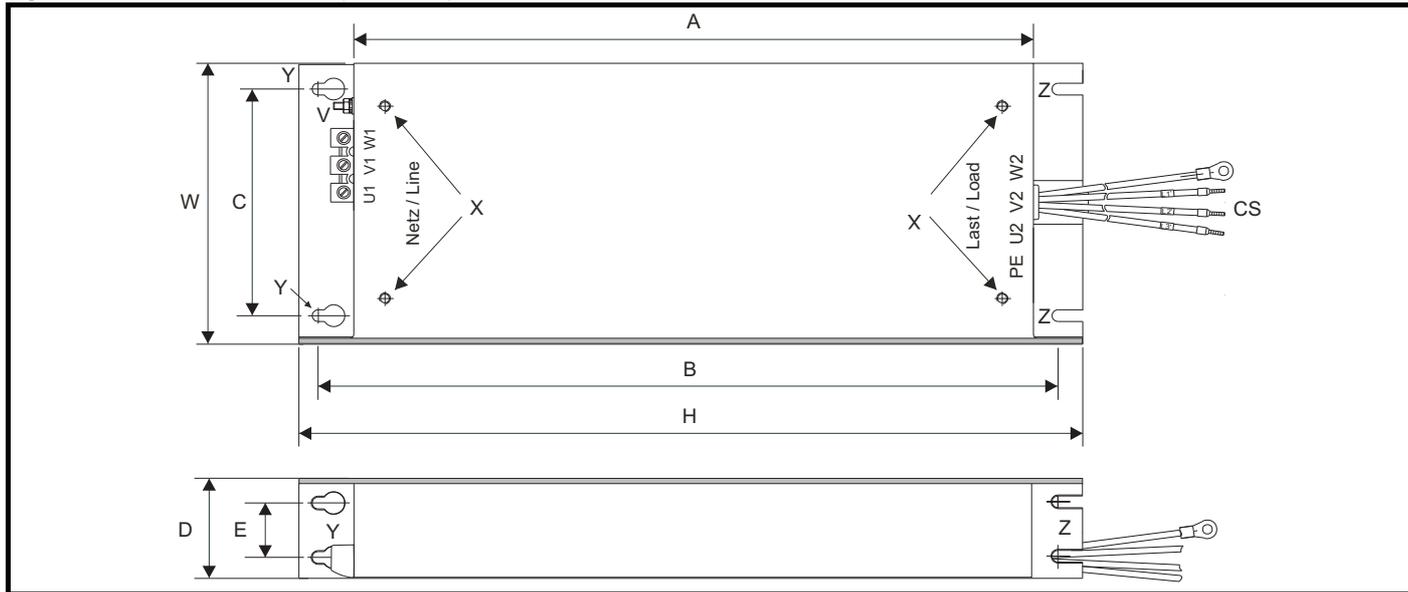


Figure 3-53 External EMC filter (size 3 to 6)



V: Ground stud
 Z: Bookcase mounting slot diameter.
 X: Threaded holes for footprint mounting of the drive
 CS: Cable size
 Y: Footprint mounting hole diameter

Table 3-10 Size 3 external EMC filter dimensions

CT part number	A	B	C	D	E	H	W	V	X	Y	Z	CS
4200-3230	384 mm	414 mm	56 mm	41 mm		426 mm	83 mm	M5	M5	5.5 mm	5.5 mm	2.5 mm ²
4200-3480	(15.12 in)	(16.30 in)	(2.21 in)	(1.61 in)		(16.77 in)	(3.27 in)			(0.22 in)	(0.22 in)	(14 AWG)

Table 3-11 Size 4 external EMC filter dimensions

CT part number	A	B	C	D	E	H	W	V	X	Y	Z	CS
4200-0272	395 mm	425 mm	100 mm	60 mm	33 mm	437 mm	123 mm	M6	M6	6.5 mm (0.26 in)	6.5 mm (0.26 in)	6 mm ² (10 AWG)
4200-0252	(15.55 in)	(16.73 in)	(3.94 in)	(2.36 in)	(1.30 in)	(17.2 in)	(4.84 in)					

Table 3-12 Size 5 external EMC filter dimensions

CT part number	A	B	C	D	E	H	W	V	X	Y	Z	CS
4200-0312	395 mm (15.55 in)	425 mm (16.73 in)	106 mm (4.17 in)	60 mm (2.36 in)	33 mm (1.30 in)	437 mm (17.2 in)	143 mm (5.63 in)	M6	M6	6.5 mm (0.26 in)	6.5 mm (0.26 in)	10 mm ² (8 AWG)
4200-0402												2.5 mm ² (14 AWG)
4200-0122												2.5 mm ² (14 AWG)

Table 3-13 Size 6 external EMC filter dimensions

CT part number	A	B	C	D	E	H	W	V	X	Y	Z	CS
4200-2300	392 mm (15.43 in)	420 mm (16.54 in)	180 mm (7.09 in)	60 mm (2.36 in)	33 mm (1.30 in)	434 mm (17.09 in)	210 mm (8.27 in)	M6	M6	6.5 mm (0.26 in)	6.5 mm (0.26 in)	16 mm ² (6 AWG)
4200-4800												6 mm ² (10 AWG)
4200-3690												6 mm ² (10 AWG)

Figure 3-54 External EMC filter (size 7 to 8)

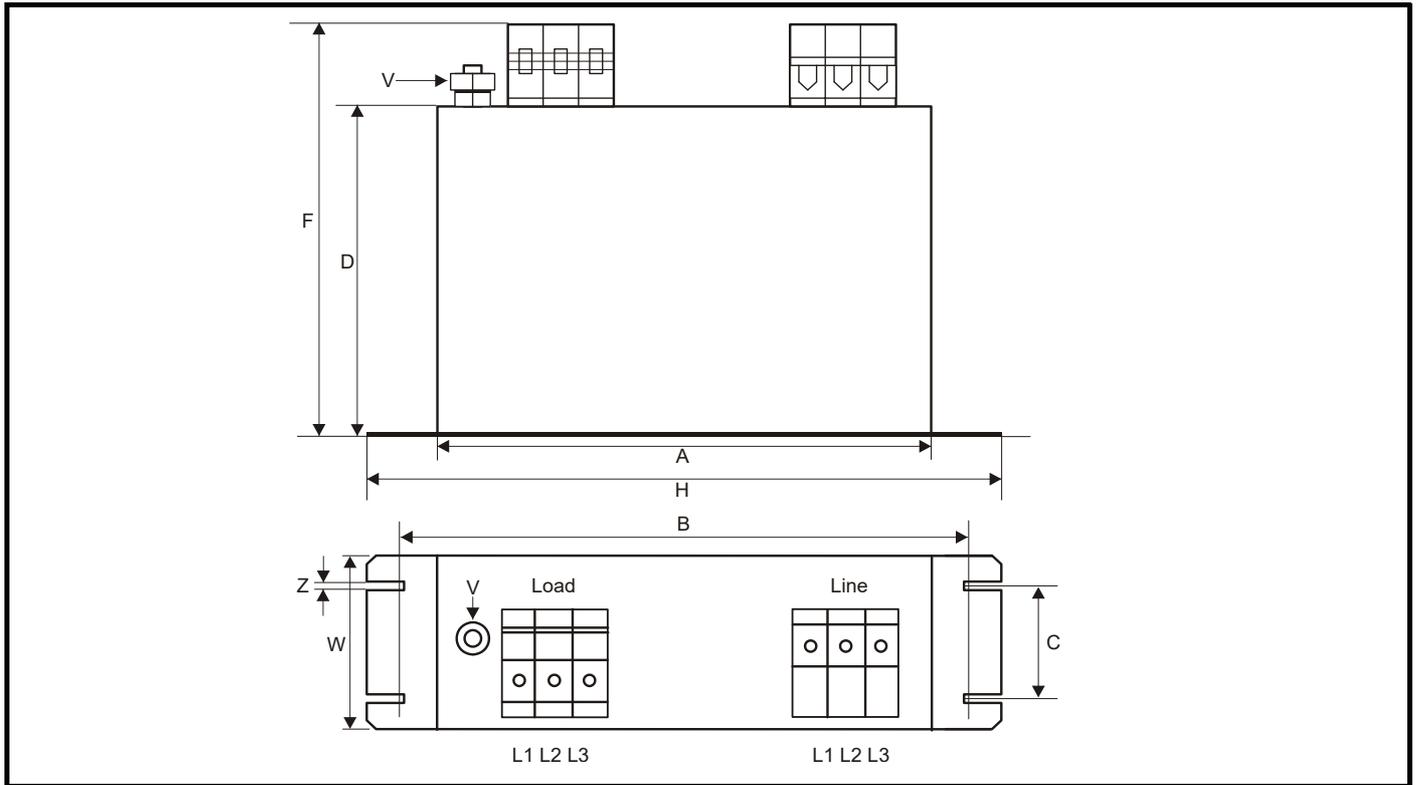


Table 3-14 Size 7 external EMC filter dimensions

CT part number	A	B	C	D	E	F	H	W	V	X	Y	Z
4200-1132	240 mm	255 mm	55 mm	150 mm		205 mm	270 mm	90 mm	M10			6.5 mm (0.26 in)
4200-0672	(9.45 in)	(10.04 in)	(2.17 in)	(5.90 in)		(8.07 in)	(10.63 in)	(3.54 in)				

Table 3-15 Size 8 external EMC filter dimensions

CT part number	A	B	C	D	E	F	H	W	V	X	Y	Z
4200-1972	260 mm	275 mm	85 mm	170 mm		249 mm	300 mm	120 mm	M10			6.5 mm (0.26 in)
4200-1662	(10.24 in)	(10.83 in)	(3.35 in)	(6.69 in)		(9.79 in)	(11.81 in)	(4.72 in)				

Figure 3-55 External EMC filter (size 9A)

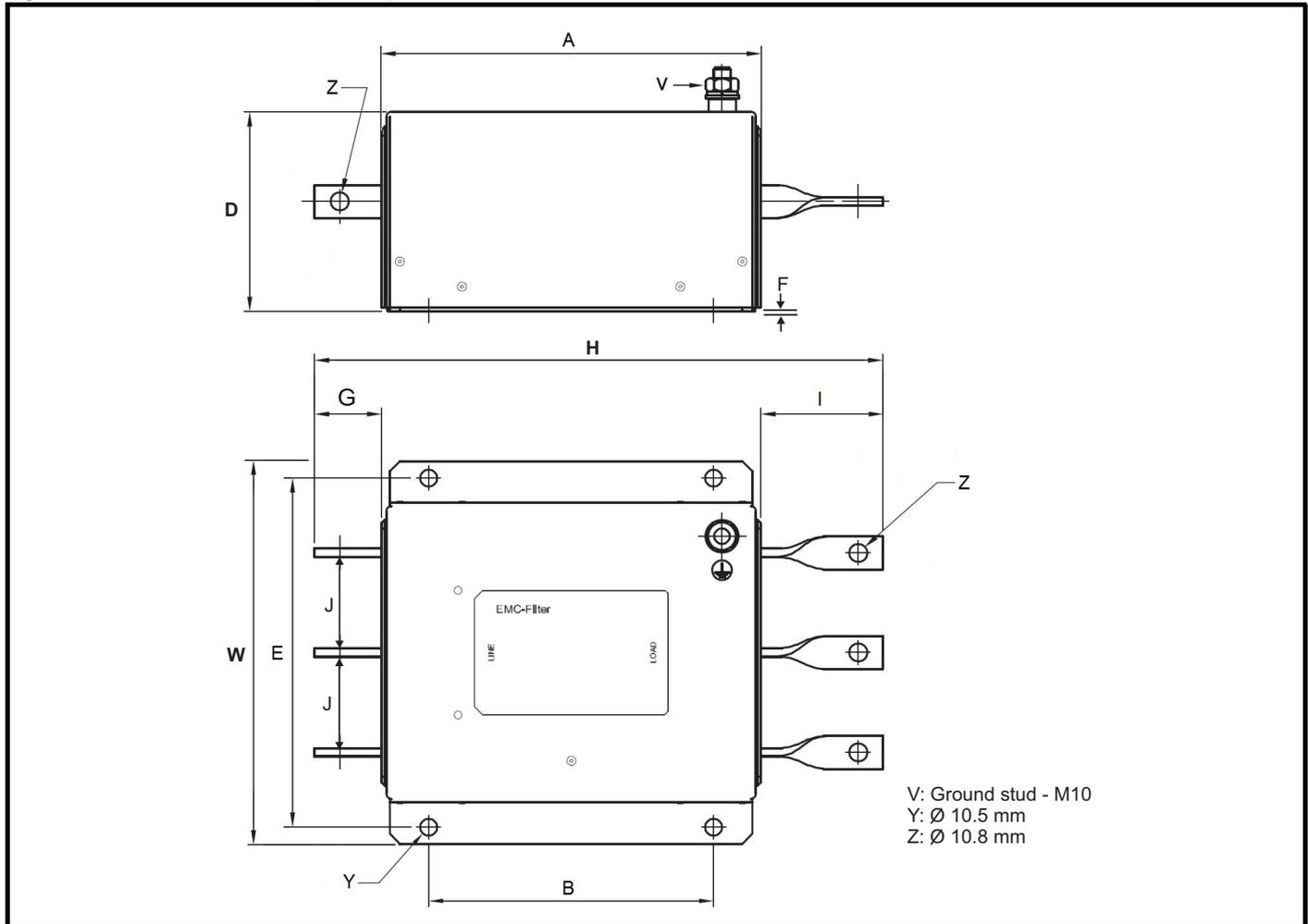


Table 3-16 Size 9A external EMC filter dimensions

CT part number	A	B	D	E	F	G	H	I	J	W
4200-3021	220 mm (8.66 in)	170 mm (6.70 in)	120 mm (4.72 in)	210 mm (8.27 in)	2 mm (0.08 in)	40 mm (1.57 in)	339 mm (13.34)	73 mm (2.87 in)	60 mm (2.36 in)	230 mm (9.06 in)
4200-1660	280 mm (11.02 in)	180 mm (7.09 in)	105 mm (4.13 in)	225 mm (8.86 in)	2 mm (0.08 in)	40 mm (1.57 in)	360 mm (14.17 in)	73 mm (2.87 in)	60 mm (2.36 in)	245 mm (9.65 in)

Figure 3-56 External EMC filter (size 9E and 10)

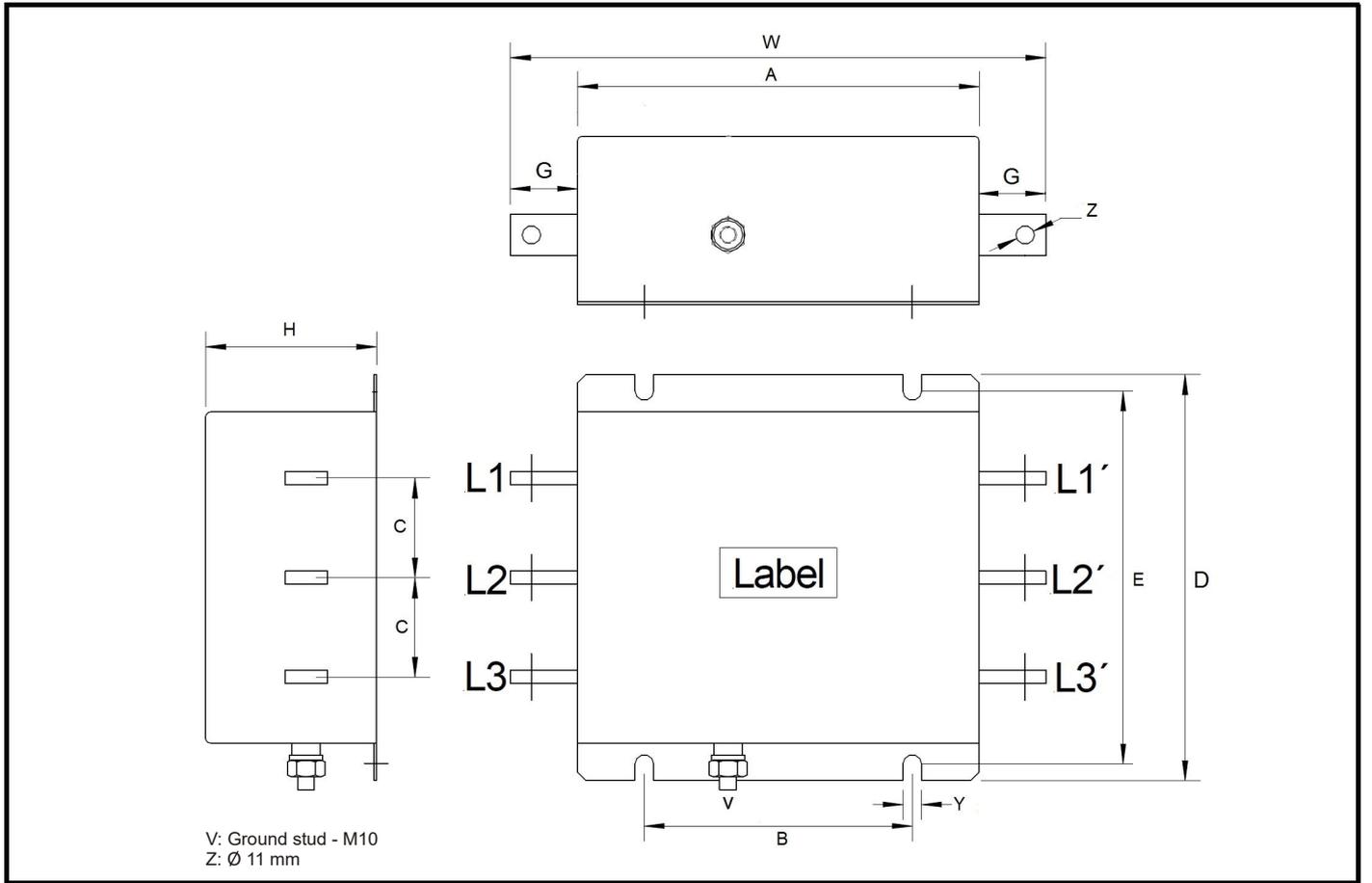


Table 3-17 Size 9E and 10E external EMC filter dimensions

CT part number	A	B	C	D	E	G	H	W	Y
4200-4460	280 mm	180 mm	57 mm	245 mm	225 mm	40 mm	105 mm	360 mm	11 mm
4200-2210	(11.02)	(7.09)	(2.24 mm)	(9.65 in)	(8.86 in)	(1.57 in)	(4.13 in)	(14.7 in)	(0.43 in)

Figure 3-57 External EMC filter (size 11)

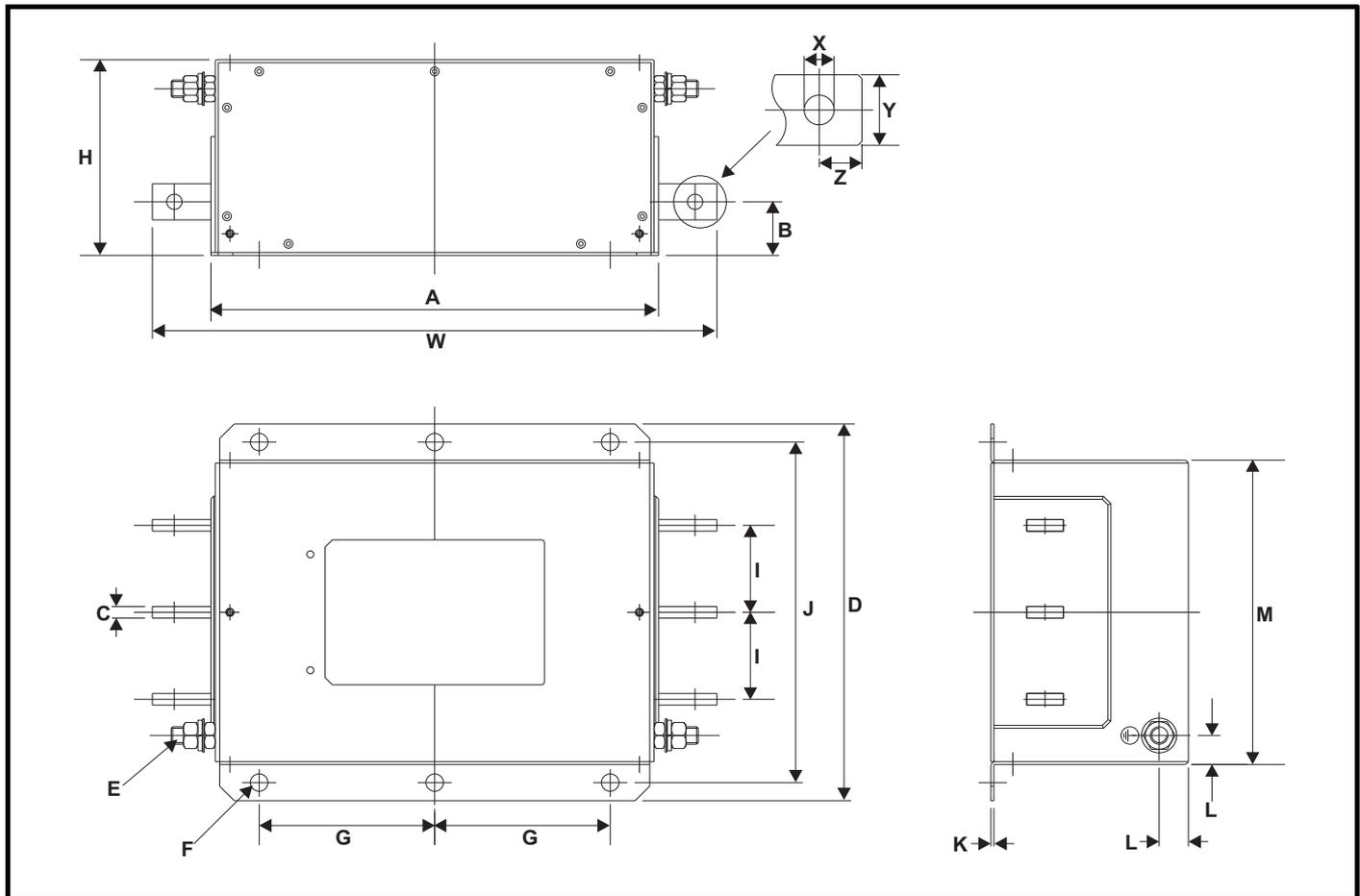


Table 3-18 Size 11 external EMC filter dimensions

CT part number	A	B	C	D	E	F	G	H	I	J	K	L	M	X	Y	Z	W
4200-0400	306 mm	37 mm	8 mm	260 mm	M12	12 mm	120 mm	135 mm	60 mm	235 mm	2 mm	20 mm	210 mm	10.5 mm	25 mm	15 mm	386 mm
4200-0690	(12.05 in)	(1.46 in)	(0.32 in)	(10.2 in)		(0.47 in)	(4.72 in)	(5.32 in)	(2.36 in)	(9.25 in)	(0.08 in)	(0.79 in)	(8.27 in)	(0.41 in)	(0.98 in)	(0.59 in)	(15.20 in)

3.11 Line reactor mounting dimensions for size 9E,10E and 11E

Figure 3-58 Input line reactor (INLX0X) for size 9 and 10

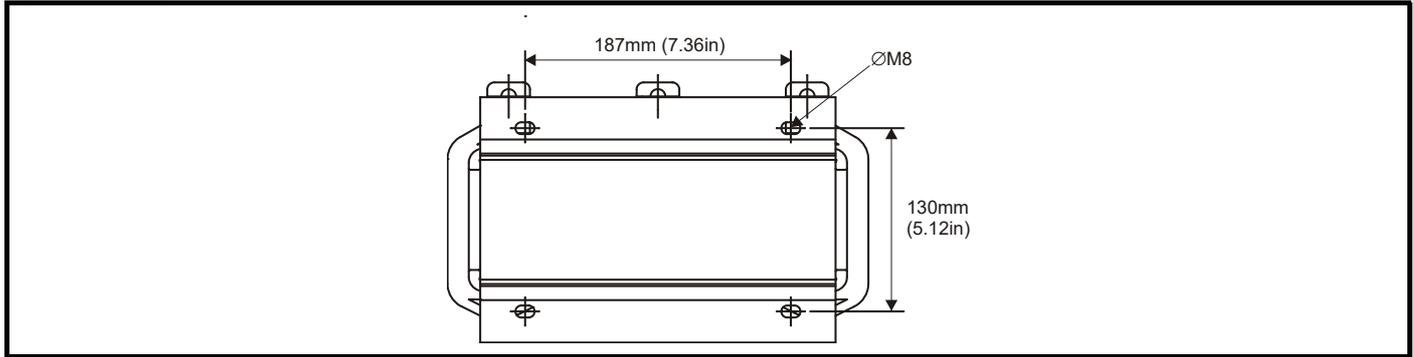
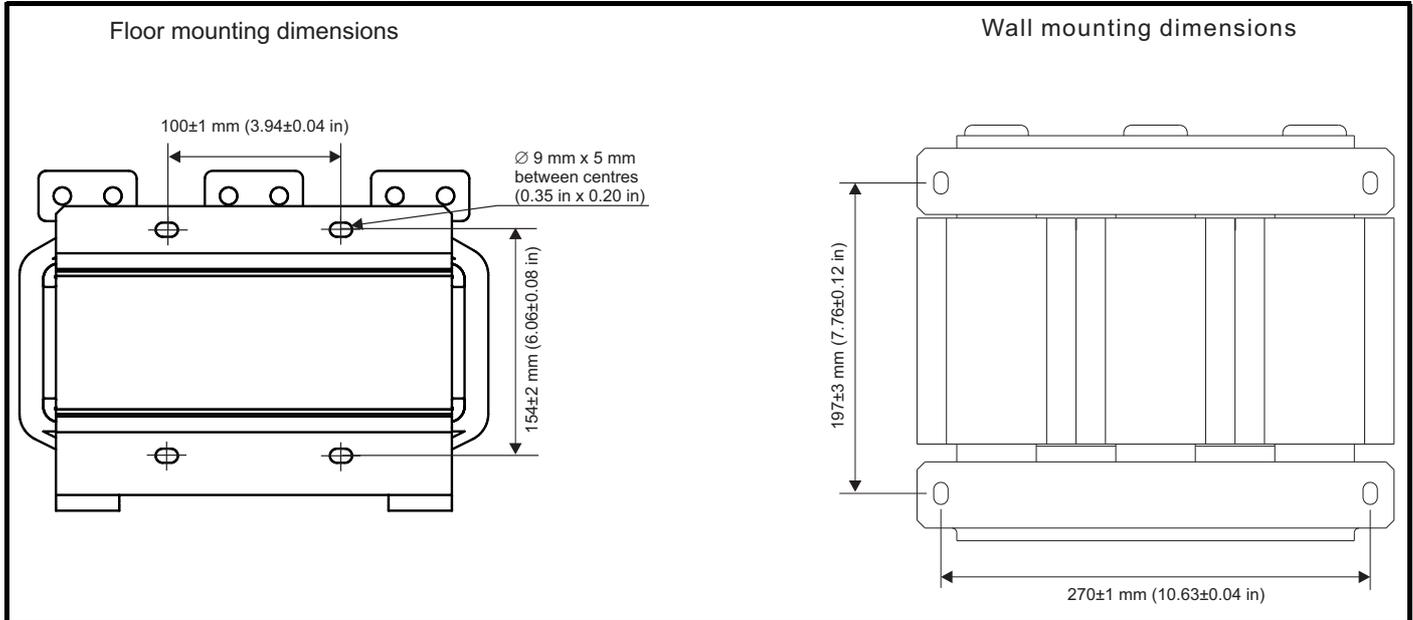


Figure 3-59 Input line reactor (INLX0X) for size 11

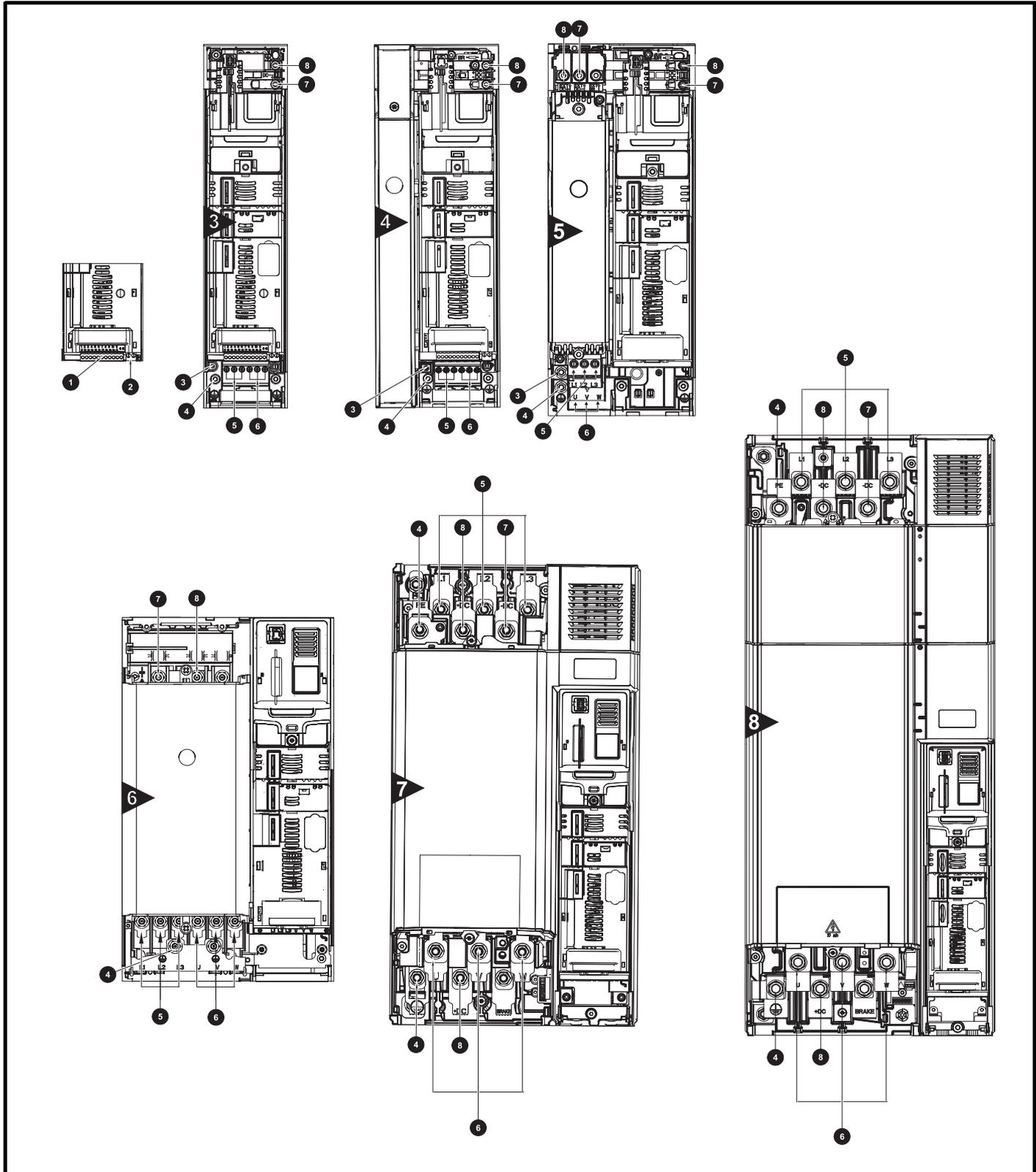


For overall dimensions and other details, refer to Chapter 4.2.3 *Drive model and input line reactor* on page 98.

3.12 Electrical terminals

3.12.1 Location of the power and ground terminals

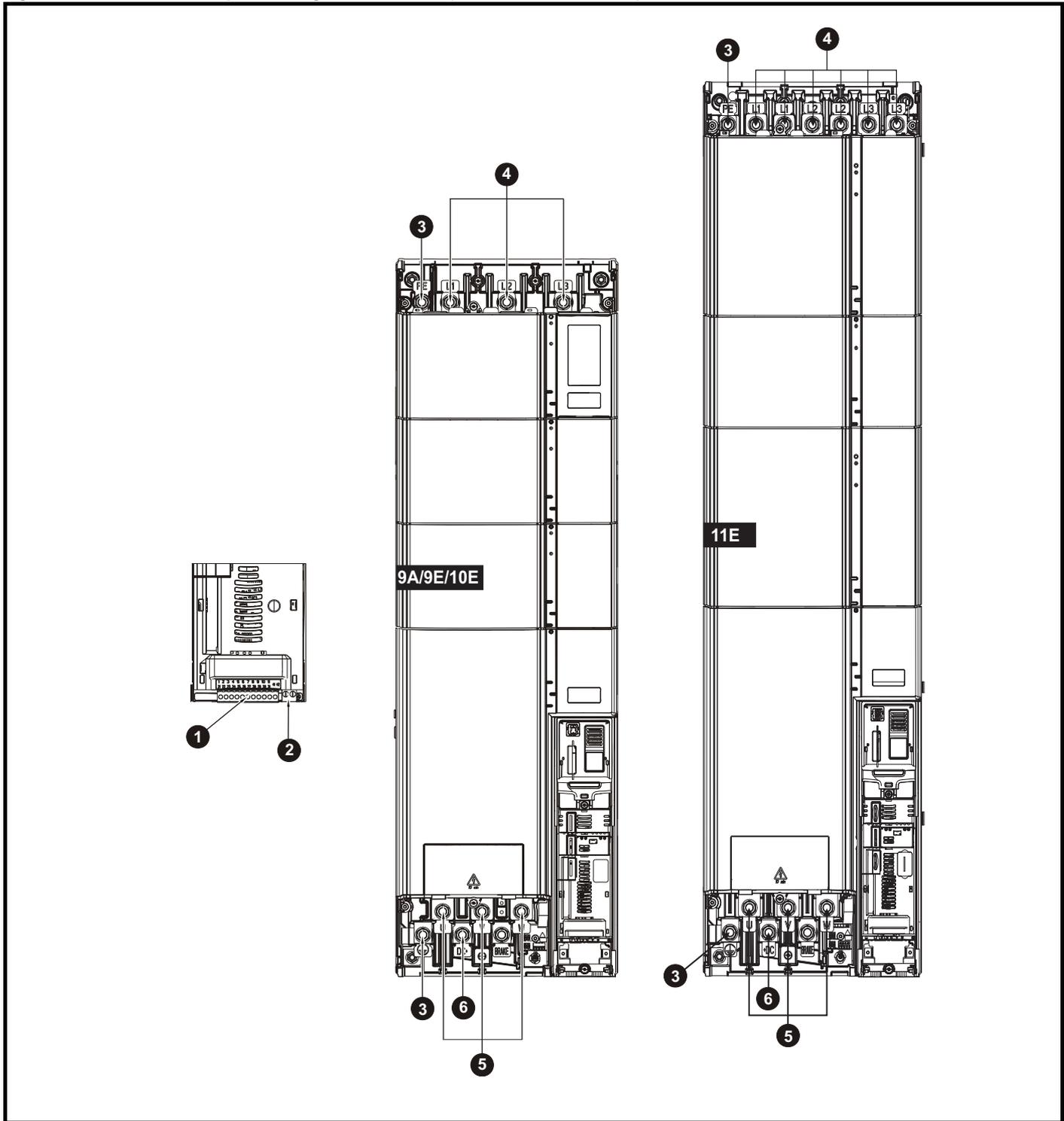
Figure 3-60 Locations of the power and ground terminals (size 3 to 8)



Key

- | | | |
|---------------------------------|-----------------------|-------------|
| 1. Control terminals | 4. Ground connections | 7. DC bus - |
| 2. Relay terminals | 5. AC power terminals | 8. DC bus + |
| 3. Additional ground connection | 6. Motor terminals | |

Figure 3-61 Location of the power and ground terminals (size 9A/9E, 10E and 11E)



Key

- 1. Control terminals
- 2. Relay terminals

- 3. Ground connections
- 4. AC power terminals

- 5. Motor terminals
- 6. DC bus +

3.12.2 Terminal sizes and torque settings



To avoid a fire hazard and maintain validity of the UL listing, adhere to the specified tightening torques for the power and ground terminals. Refer to the following tables.

Table 3-19 Drive power terminal data

Frame size	AC and Motor terminals		DC and braking		Ground terminal	
	Recommended	Maximum	Recommended	Maximum	Recommended	Maximum
3 and 4	Plug-in terminal block		T20 Torx (M4)		T20 Torx (M4) / M4 Nut (7 mm AF)	
	0.7 Nm (6 lb in)	0.8 Nm (7.2 lb in)	2.0 Nm (16.8 lb in)	2.5 Nm (21.6 lb in)	2.0 Nm (16.8 lb in)	2.5 Nm (21.6 lb in)
5	Plug-in terminal block		T20 Torx (M4) / M4 Nut (7 mm AF)		M5 Nut (8 mm AF)	
	1.5 Nm (13.2 lb in)	1.8 Nm (15.6 lb in)	1.5 Nm (13.2 lb in)	2.5 Nm (21.6 lb in)	2.0 Nm (18 lb in)	5.0 Nm (44.4 lb in)
6			M6 Nut (10 mm AF)			
	6.0 Nm (52.8 lb in)	8.0 Nm (72 lb in)	6.0 Nm (52.8 lb in)	8.0 Nm (72 lb in)	6.0 Nm (52.8 lb in)	8.0 Nm (72 lb in)
7	M8 Nut (13 mm AF)		M8 Nut (13 mm AF)		M8 Nut (13 mm AF)	
	12 Nm (106.2 lb in)	14 Nm (124 lb in)	12 Nm (106.2 lb in)	14 Nm (124 lb in)	12 Nm (106.2 lb in)	14 Nm (124 lb in)
8 to 11	M10 Nut (17 mm AF)		M10 Nut (17 mm AF)		M10 Nut (17 mm AF)	
	15 Nm (133.2 lb in)	20 Nm (177.6 lb in)	15 Nm (133.2 lb in)	20 Nm (177.6 lb in)	15 Nm (133.2 lb in)	20 Nm (177.6 lb in)

Table 3-20 Drive control and relay terminal data

Model	Connection type	Torque settings
All	Plug-in terminal block	2.0 Nm (17.7 lb in)
Frame 12		0.5 Nm (4.4 lb in)

Table 3-21 Plug-in terminal block maximum cable sizes

Model size	Terminal block description	Max cable size
All	11 way control connectors	1.5 mm ² (16 AWG)
	2 way relay connector	2.5 mm ² (12 AWG)
3	6 way AC power connector	6 mm ² (10 AWG)
4		
5	3 way AC power connector 3 way motor connector	8 mm ² (8 AWG)
6	2 way low voltage power 24 V supply connector	1.5 mm ² (16 AWG)
7		
8		
9A/9E		
10E/11E		

Table 3-22 External EMC filter terminal data

CT part number	Power connections			Ground connections	
	Bar hole diameter	Max cable size	Max torque	Ground stud size	Max torque
4200-1132	N/A	50 mm ² (1/0 AWG)	8.0 Nm (72 lb in)	M10	18 Nm (159.6 lb in)
4200-0672					
4200-1972		95 mm ² (3/0 AWG)	20 Nm (177.6 lb in)		
4200-1662					
4200-0122		16 mm ² (6 AWG)	2.3 Nm (20.4 lb in)	M6	4.8 Nm (33.6 lb in)
4200-0252					
4200-0272					
4200-0312					
4200-0402					
4200-3230		4 mm ² (12 AWG)	0.8 Nm (7.08 lb in)	M5	3.0 Nm (26.4 lb in)
4200-3480		4 mm ² (12 AWG)	0.8 Nm (7.08 lb in)	M5	
4200-2300		16 mm ² (6 AWG)	2.3 Nm (20.4 lb in)	M6	4.8 Nm (33.6 lb in)
4200-4800					
4200-3690					
4200-3021	10.8 mm	N/A	30 Nm (265.2 lb in)	M10	18 Nm (159.9 lb in)
4200-4460	11 mm				
4200-1660	10.8 mm				
4200-2210	11 mm				
4200-0400	10.5 mm				
4200-0690	10.5 mm			M12	25 Nm (220.8 lb in)

3.13 Routine maintenance

The drive should be installed in a cool, clean, well ventilated location. Contact of moisture and dust with the drive should be prevented.

Regular checks of the following should be carried out to ensure drive / installation reliability are maximized:

Environment	
Ambient temperature	Ensure the enclosure temperature remains at or below maximum specified
Dust	Ensure the drive remains dust free – check that the heatsink and drive fan are not gathering dust. The lifetime of the fan is reduced in dusty environments.
Moisture	Ensure the drive enclosure shows no signs of condensation
Enclosure	
Enclosure door filters	Ensure filters are not blocked and that air is free to flow
Electrical	
Screw connections	Ensure all screw terminals remain tight
Crimp terminals	Ensure all crimp terminals remains tight – check for any discoloration which could indicate overheating
Cables	Check all cables for signs of damage

3.13.1 Real time clock battery replacement

The keypads with the real time clock feature contain a battery to ensure the clock works when the drive is powered down. The battery has a long life time but if the battery needs to be replaced or removed, follow the instructions below.

Low battery voltage is indicated by  low battery symbol on the keypad display.

Figure 3-62 Keypad (rear view)

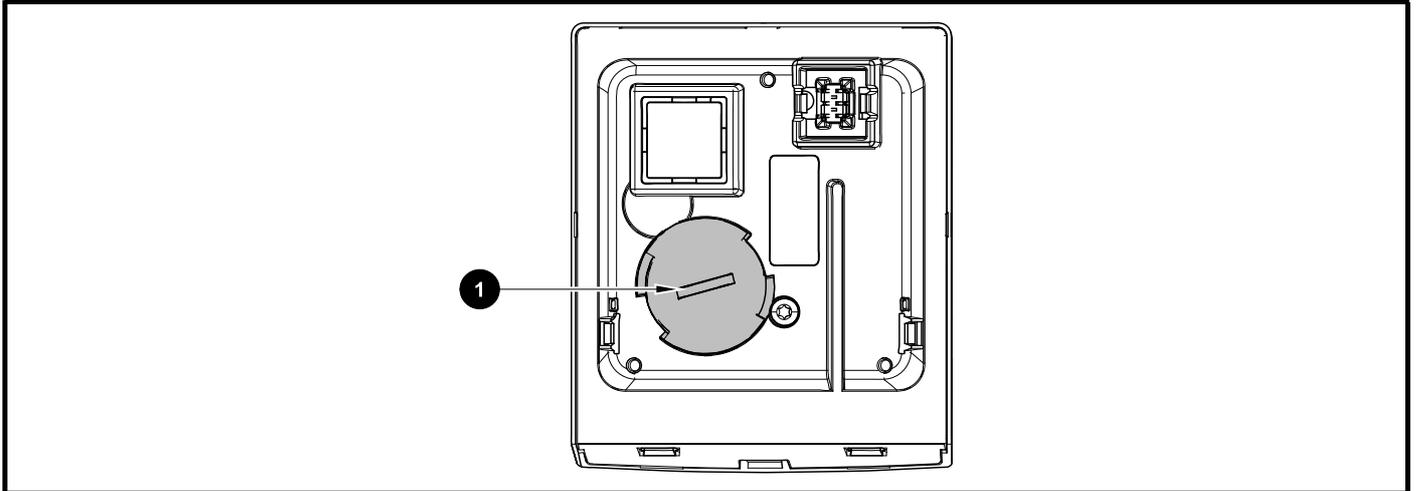


Figure 3-62 above illustrates a rear view of the keypad.

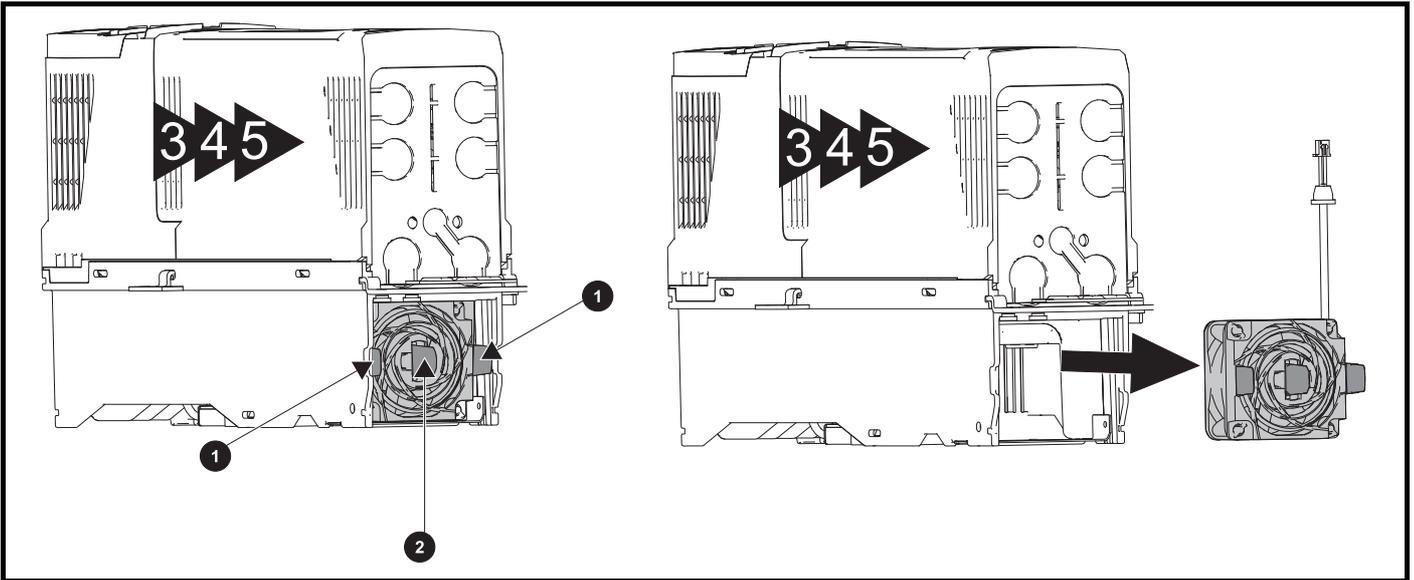
1. To remove the battery cover insert a flat head screwdriver into the slot as shown (1), push and turn anti-clockwise until the battery cover is released.
2. Replace the battery (the battery type is: CR2032).
3. Reverse point 1 above to replace battery cover.

NOTE

Ensure the battery is disposed of correctly.

3.13.2 Size 3 to 5 heatsink fan removal procedure

Figure 3-63 Removal of the size 3, 4 and 5 heatsink fan (size 3 shown)



Ensure the fan cable is disconnected from the drive prior to attempting fan removal.

1. Press the two tabs inwards to release the fan from the drive frame.
2. Using the central fan tab, withdraw the fan assembly from the drive housing.

Replace the fan by reversing the above instructions.

NOTE

If the drive is surface mounted using the outer holes on the mounting bracket, then the heatsink fan can be replaced without removing the drive from the backplate.

Table 3-23 Size 3 to 5 heatsink fan part numbers

Model	Heatsink fan part number
Size 3	3251-2407
Size 4	3251-0245
Size 5	3251-0245

Figure 3-64 Removal of the High IP size 3, 4 and 5 stirring fan

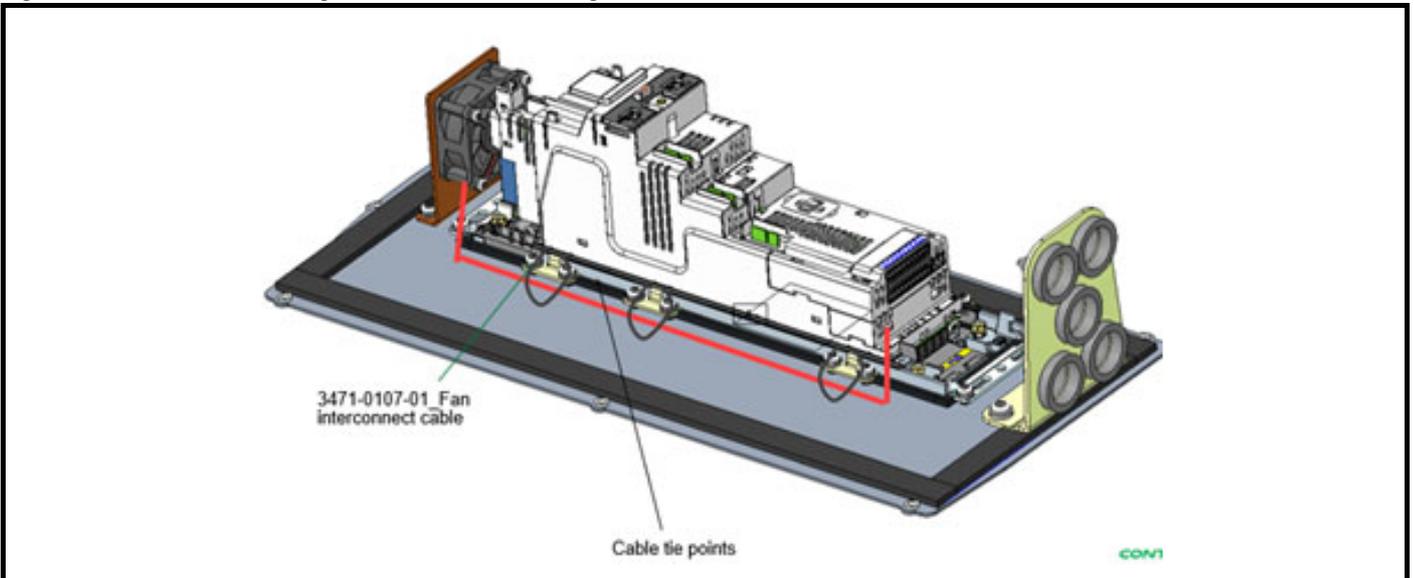
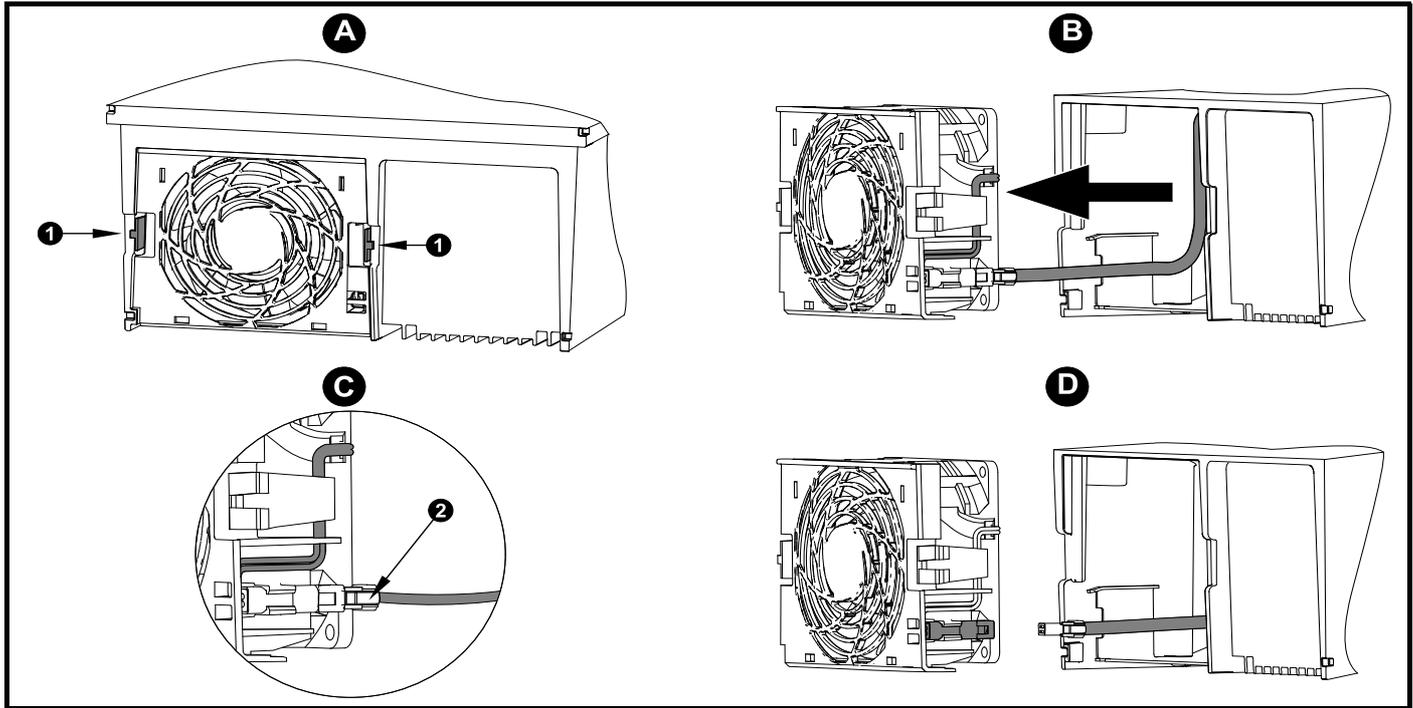


Table 3-24 Size 3 to 5 High IP stirring fan part numbers

Model	Stirring fan part number
Size 3 to 5	3251-0245

3.13.3 Size 6 heatsink fan removal procedure

Figure 3-65 Removal of the size 6 heatsink fan



A: Press the tabs (1) inwards to release the fan assembly from the underside of the drive.

B: Use the tabs (1) to withdraw the fan by pulling it away from the drive.

C: Depress and hold the locking release on the fan cable lead as shown (2).

D: With the locking release depressed (2), take hold of the fan supply cable and carefully pull to separate the connectors.

Figure 3-66 Removal of the High IP size 6 stirring / capacitor bank fan

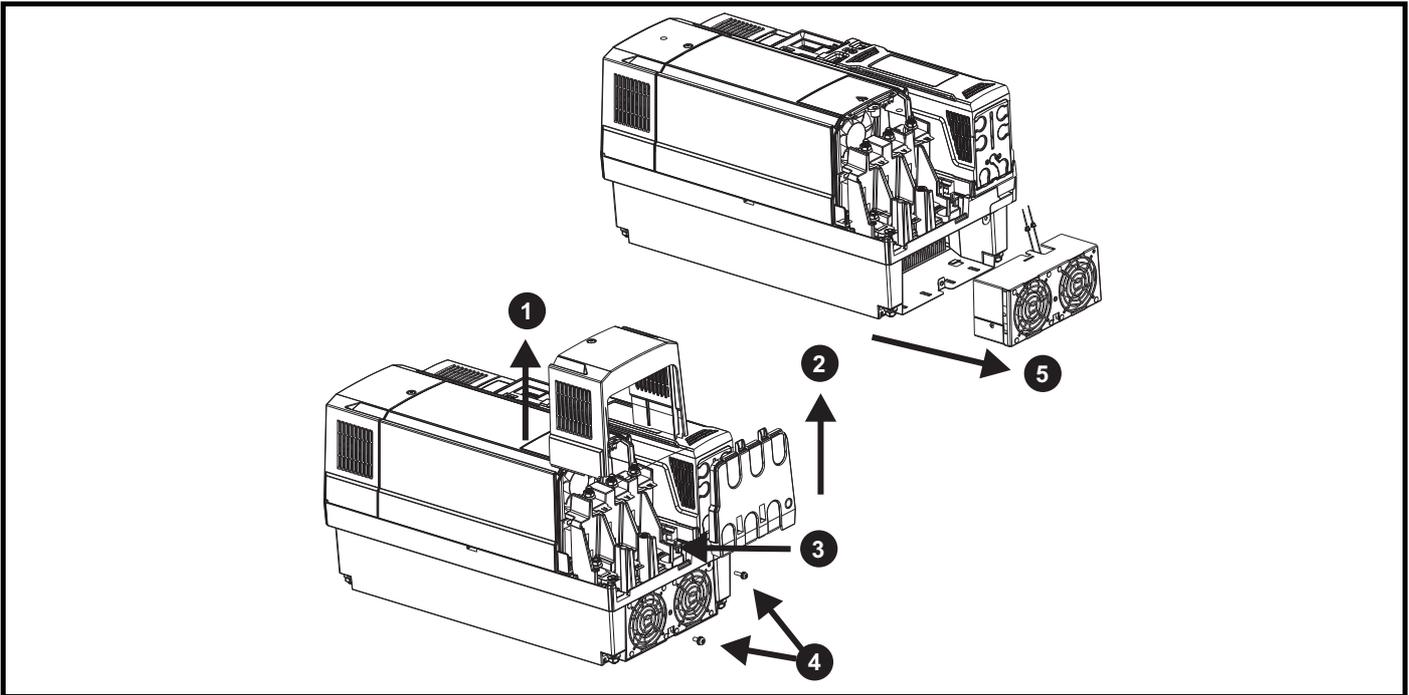


Table 3-25 Size 6 stirring / capacitor bank fan part number (Std and High IP)

Model	Stirring / capacitor fan part number
Size 6	3251-0051

3.13.4 Size 7 heatsink fan replacement

Figure 3-67 Size 7 heatsink fan replacement



Size 7 heatsink fan removal procedure

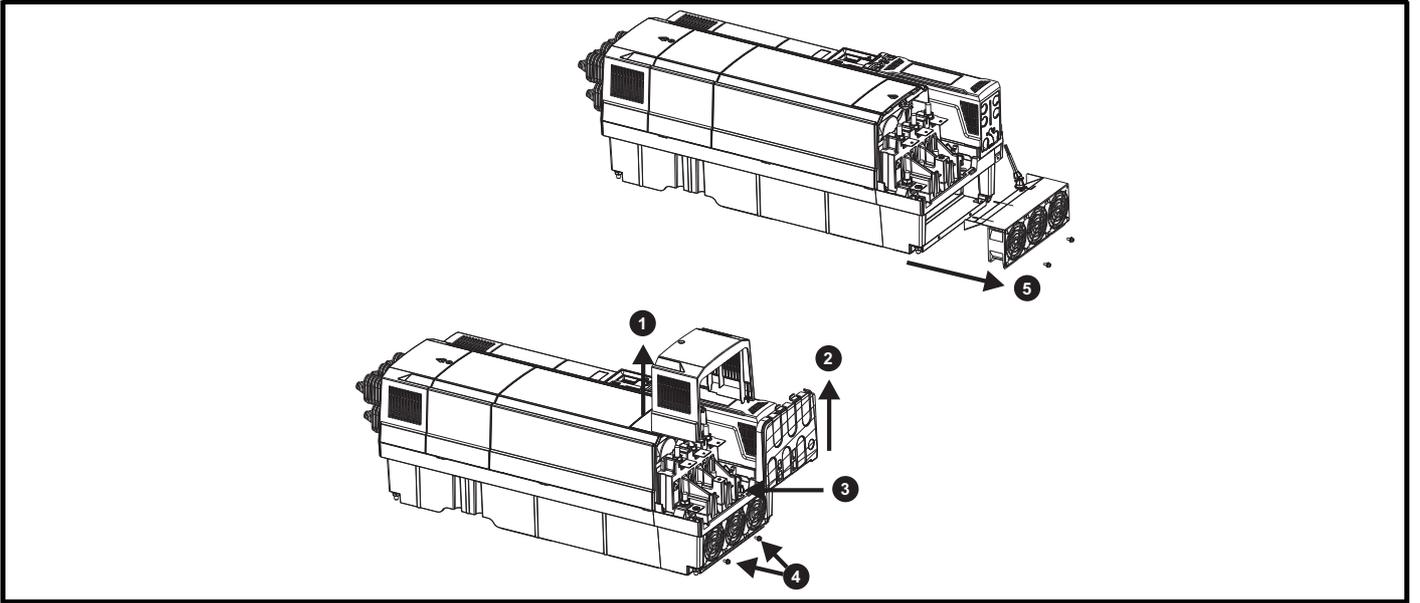
- 1) Remove terminal cover
 - 2) Remove finger guard
 - 3) Disconnect fan cables from drive (making a note of the order) and push grommets down prior to attempting fan removal
 - 4) Remove the mounting screws using a T20 and T25 torque driver
 - 5) Withdraw fan housing from the drive
- After fan(s) have been replaced, reverse the above steps to refit.

Table 3-26 Size 7 heatsink fan part number

Drive model	Heatsink fan part number
Size 7	3251-8247

3.13.5 Size 8 heatsink fan replacement

Figure 3-68 Size 8 heatsink fan replacement



Size 8 heatsink fan removal procedure

- 1) Remove terminal cover
- 2) Remove finger guard
- 3) Disconnect fan cables from drive (making a note of the order) and push grommet down prior to attempting fan removal
- 4) Remove the mounting screws using a T20 torque driver
- 5) Withdraw fan housing from the drive

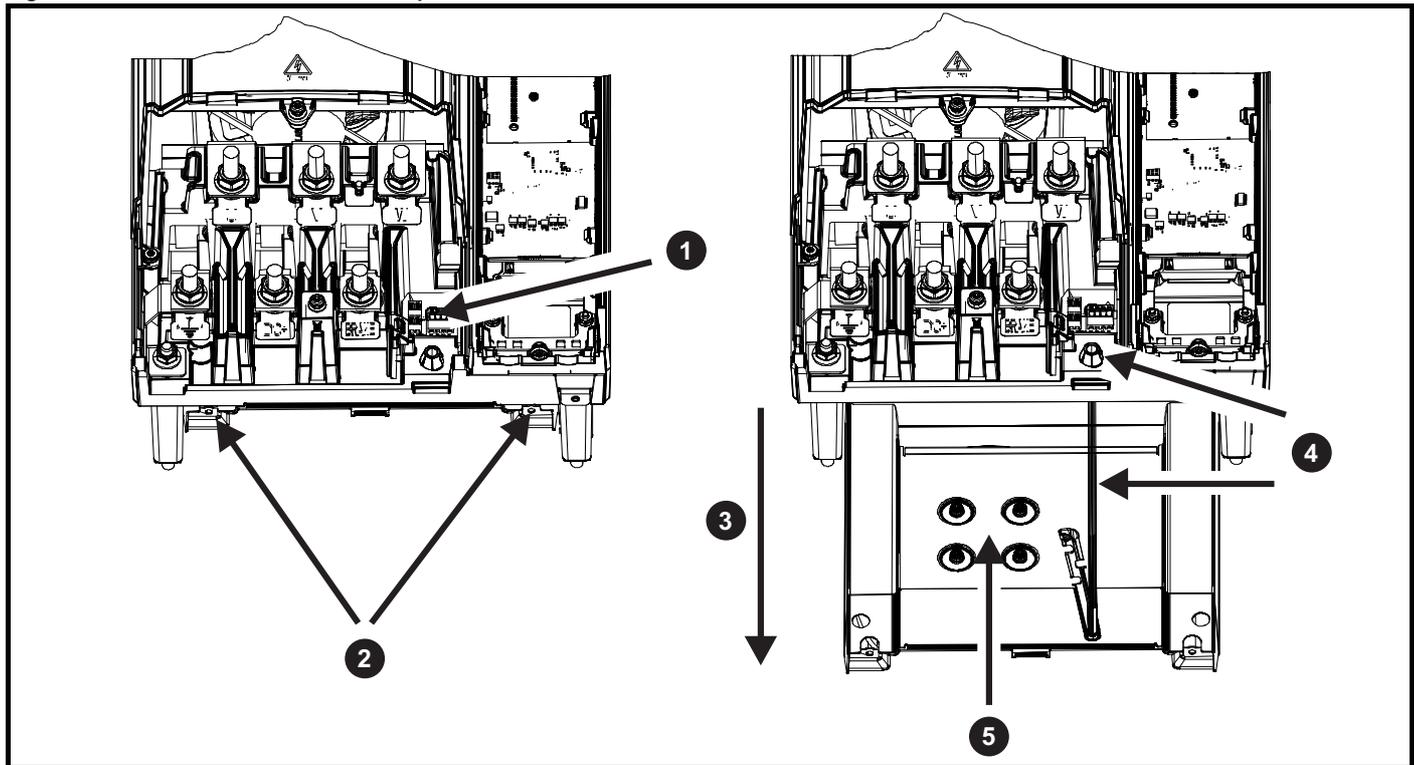
After fan(s) have been replaced, reverse the above steps to refit.

Table 3-27 Size 8 heatsink fan part number

Drive model	Heatsink fan part number
Size 8	3251-8240

3.13.6 Size 9 to 11 heatsink fan replacement

Figure 3-69 Size 9 to 11 Heatsink fan replacement



Heatsink fan removal procedure

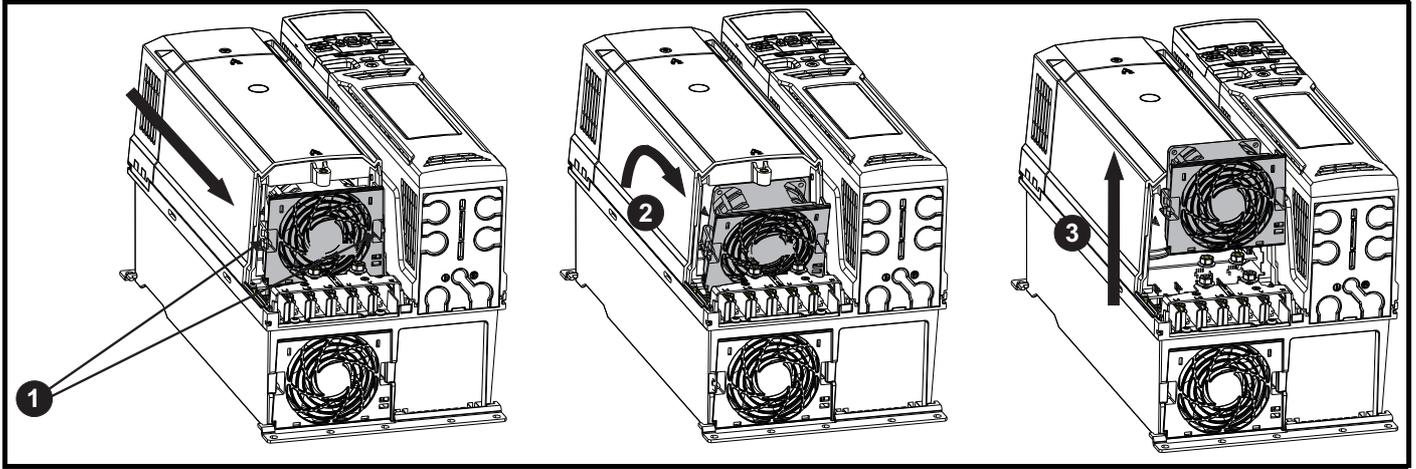
- 1) Using a flat screwdriver remove the fan wires from the fan connector (making a note of the order).
 - 2) Using a T20 Torque driver remove the two screws that retain the heatsink fan housing
 - 3) Withdraw the heatsink fan housing from the drive in the direction shown
 - 4) Pull the fan cable through the fan cable gland
 - 5) Using a T20 Torque driver remove the four screws that retain the fan in the housing
- After fan has been replaced, reverse the above steps to refit.

Table 3-28 Heatsink fan part number

Drive model	Heatsink fan part number
Size 9 to 11	3251-1750

3.13.7 Size 6 auxiliary (capacitor bank) fan replacement

Figure 3-70 Removal of the size 6 auxiliary (capacitor bank) fan



- Press the tabs (1) inwards to release the fan assembly from the drive mid cover.
- Use the tabs (1) to withdraw the fan from the drive by pulling the fan assembly forward and tilting it at a slight angle (2).
- Pull the fan assembly up and away from the drive (3).
- Depress and hold the locking release on the fan cable lead.
- With the locking release depressed, take hold of the fan supply cable and carefully pull to separate the connectors.

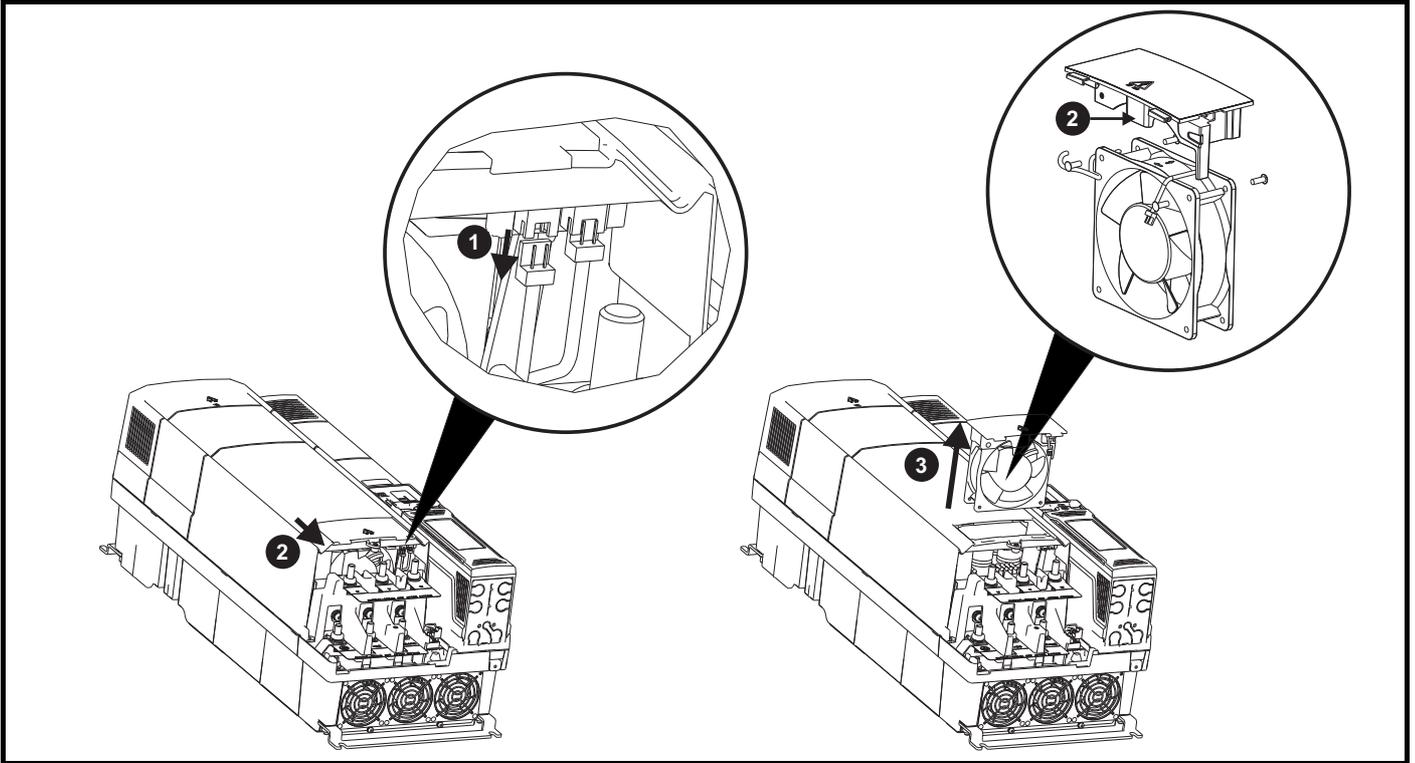
Replace the fan by reversing the above instructions.

Table 3-29 Size 6 auxiliary fan part number

Model	Auxiliary fan part number
Size 6	3251-0030

3.13.8 Size 7 to 11 auxiliary (capacitor bank) fan replacement

Figure 3-71 Size 7 to 11 auxiliary (capacitor bank) fan replacement



Size 7 to 11 auxiliary fan removal procedure

- 1) Disconnect the fan wiring connector shown
- 2) Slide fan housing in the direction shown using tongue shown in enlarged diagram of fan
- 3) Withdraw fan housing from the drive

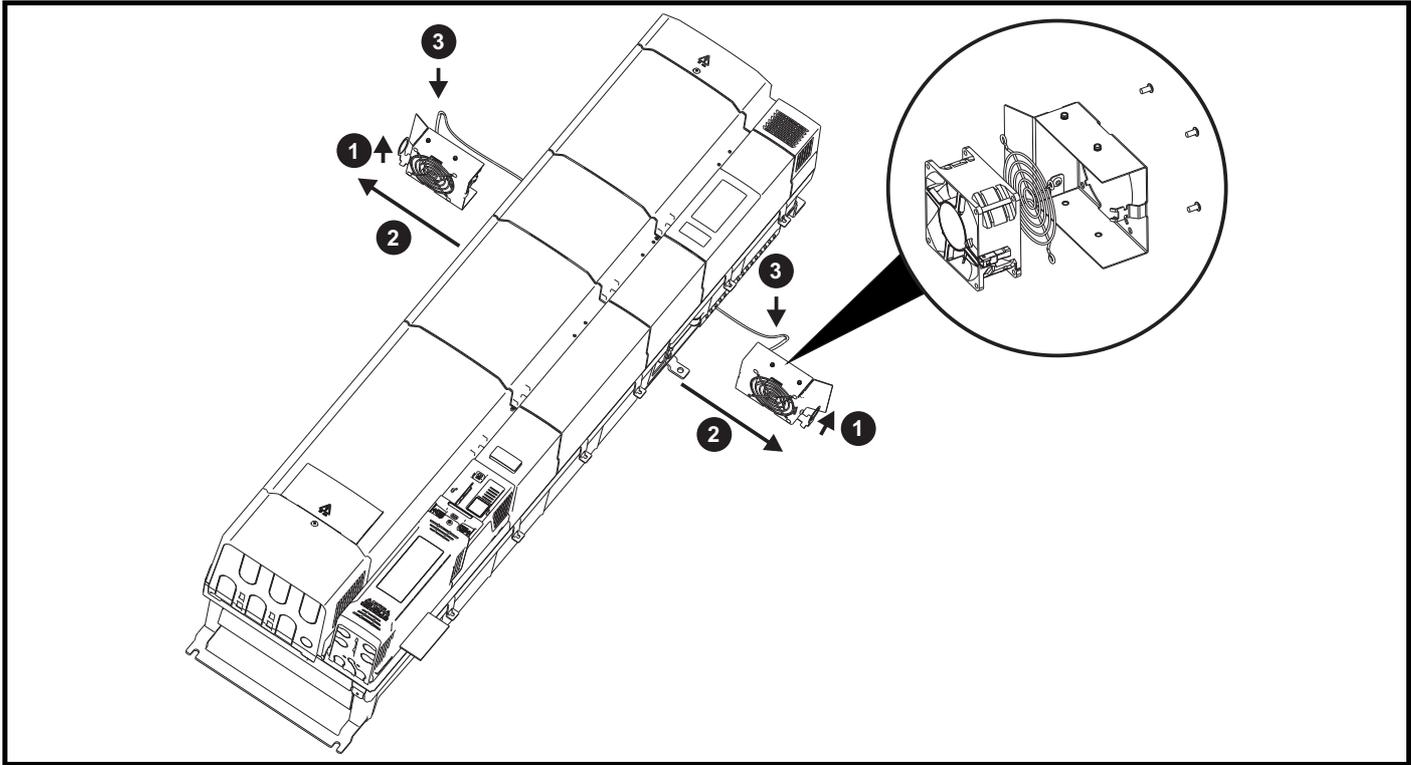
After fan has been replaced, reverse the above steps to refit.

Table 3-30 Size 7 to 11 Auxiliary (capacitor bank) fan part numbers

Drive model	Auxiliary (capacitor bank fan part number)
Size 7	3251-0041
Size 8	3251-2249
Size 9, 10 and 11 (575V and 690V)	3251-0042
Size 11 (400V)	3251-1202

3.13.9 Size 11E rectifier fan replacement

Figure 3-72 Size 11E rectifier fan replacement



Size 11E rectifier fan removal procedure

- 1) Lift the ring eye provided
- 2) Pull the fan housing in the direction shown
- 3) Disconnect the fan wiring at the connector shown

After fans have been replaced, reverse the above steps to refit the fan housing in the rectifier (making sure the fan housing aligns correctly in the slots top and bottom).

Table 3-31 Size 11E rectifier fan part number

Drive model	Rectifier fan part number
Size 11E rectifier	3251-0030

For the IP65 version, frame 3 there is an addition fan inside the drive cover. The part number for this fan is 3251-0029-00 and can be accessed as shown on page 54.

4 Electrical installation

Many cable management features have been incorporated into the product and accessories, this chapter shows how to optimize them. Key features include:

- Safe Torque Off function
- Internal EMC filter
- EMC compliance with shielding / grounding accessories
- Product rating, fusing and cabling information



Electric shock risk

The voltages present in the following locations can cause severe electric shock and may be lethal:

- AC supply cables and connections
- DC cables and connections
- Output cables and connections
- Many internal parts of the drive, and external option units

Unless otherwise indicated, control terminals are single insulated and must not be touched.



Isolation device

The AC and / or DC power supply must be disconnected from the drive using an approved isolation device before any cover is removed from the drive or before any servicing work is performed.



STOP function

The STOP function does not remove dangerous voltages from the drive, the motor or any external option units.



Safe Torque Off function

The Safe Torque Off function does not remove dangerous voltages from the drive, the motor or any external option units.



Stored charge

The drive contains capacitors that remain charged to a potentially lethal voltage after the AC and / or DC power supply has been disconnected. If the drive has been energized, the AC and / or DC power supply must be isolated at least ten minutes before work may continue.

Normally, the capacitors are discharged by an internal resistor. Under certain, unusual fault conditions, it is possible that the capacitors may fail to discharge, or be prevented from being discharged by a voltage applied to the output terminals. If the drive has failed in a manner that causes the display to go blank immediately, it is possible the capacitors will not be discharged. In this case, consult Control Techniques or their authorized distributor.



Equipment supplied by plug and socket

Special attention must be given if the drive is installed in equipment which is connected to the AC supply by a plug and socket. The AC supply terminals of the drive are connected to the internal capacitors through rectifier diodes which are not intended to give safety isolation. If the plug terminals can be touched when the plug is disconnected from the socket, a means of automatically isolating the plug from the drive must be used (e.g. a latching relay).



Permanent magnet motors

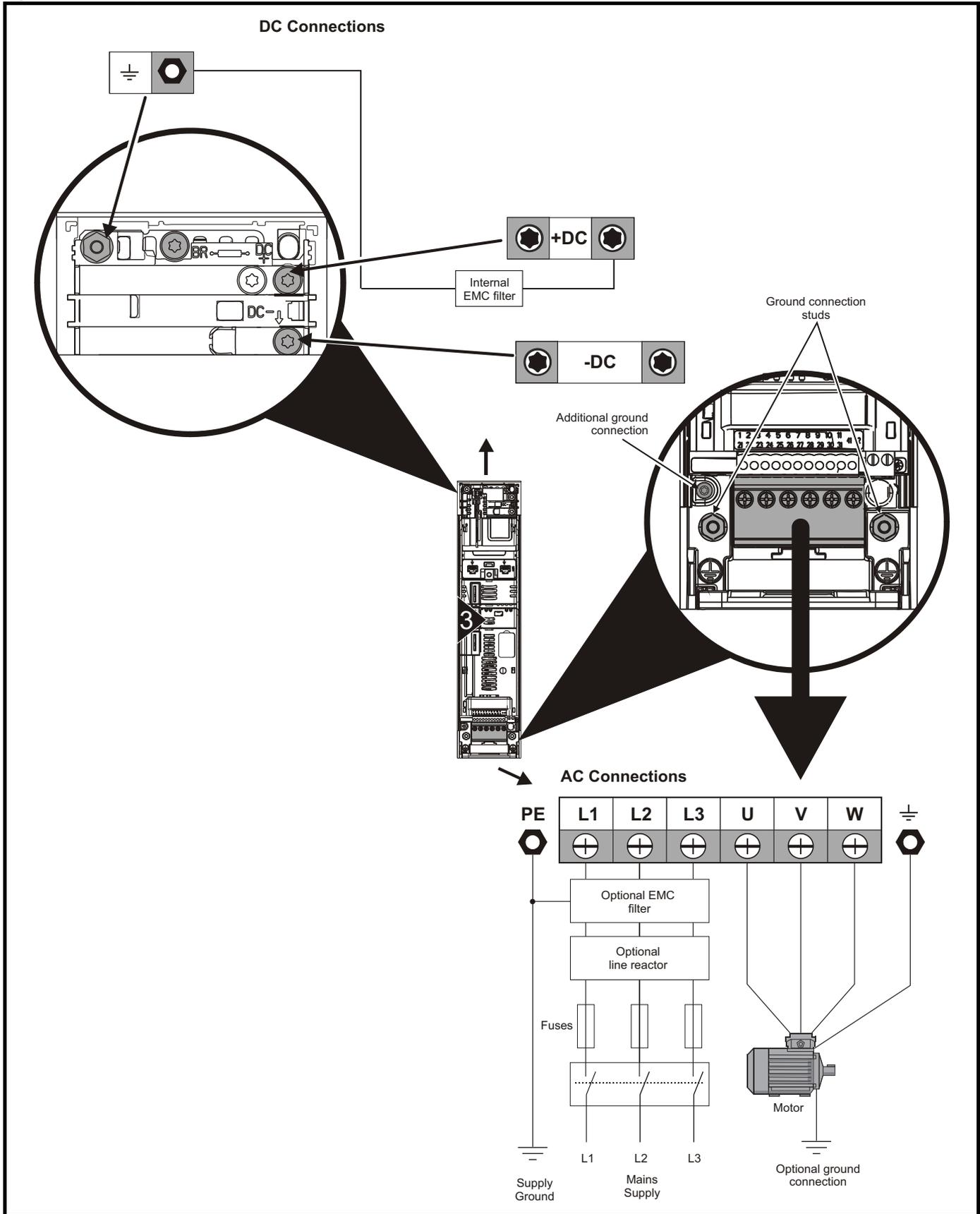
Permanent magnet motors generate electrical power if they are rotated, even when the supply to the drive is disconnected. If that happens then the drive will become energized through its motor terminals.

If the motor load is capable of rotating the motor when the supply is disconnected, then the motor must be isolated from the drive before gaining access to any live parts.

4.1 Power connections

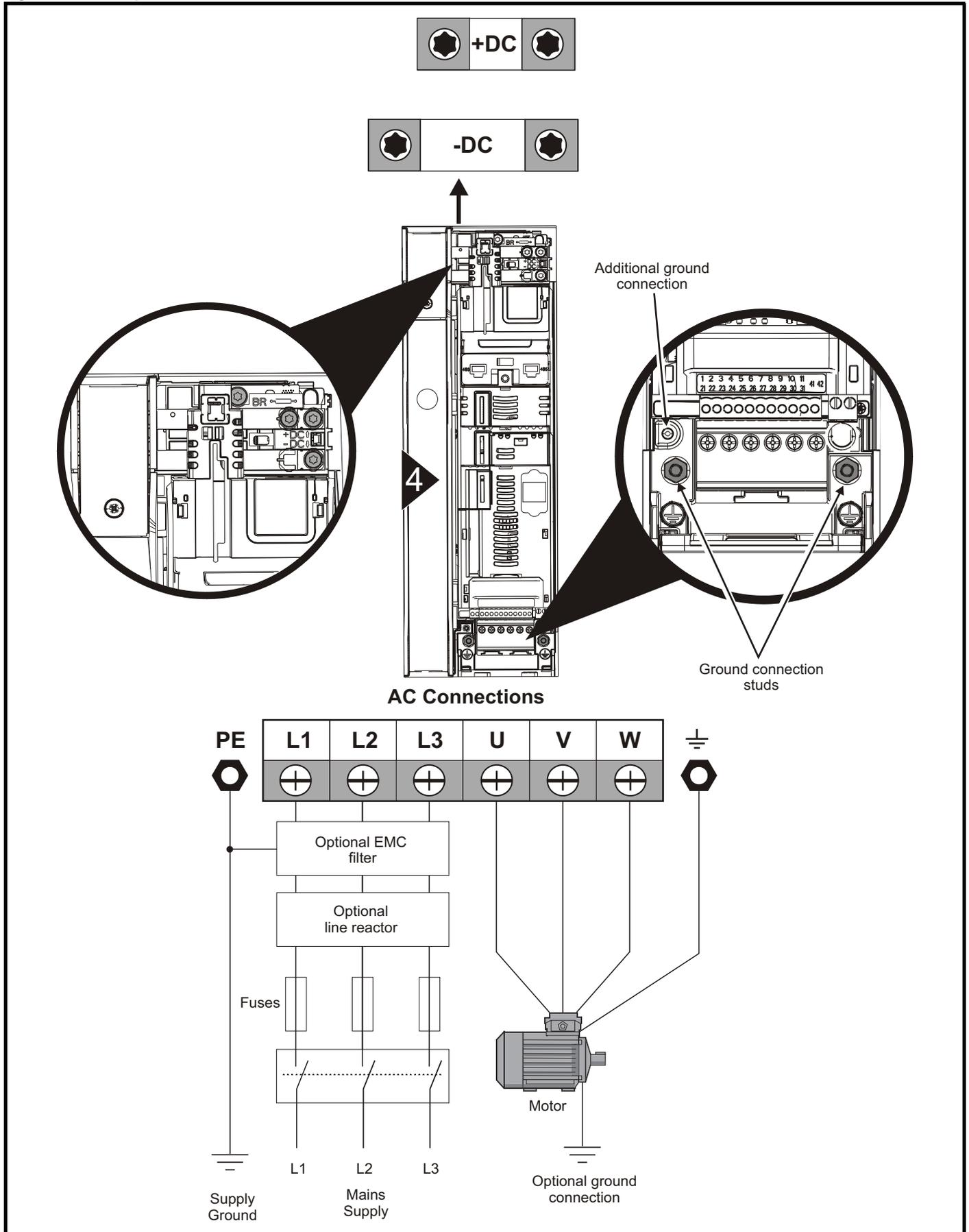
4.1.1 AC and DC connections

Figure 4-1 Size 3 power connections



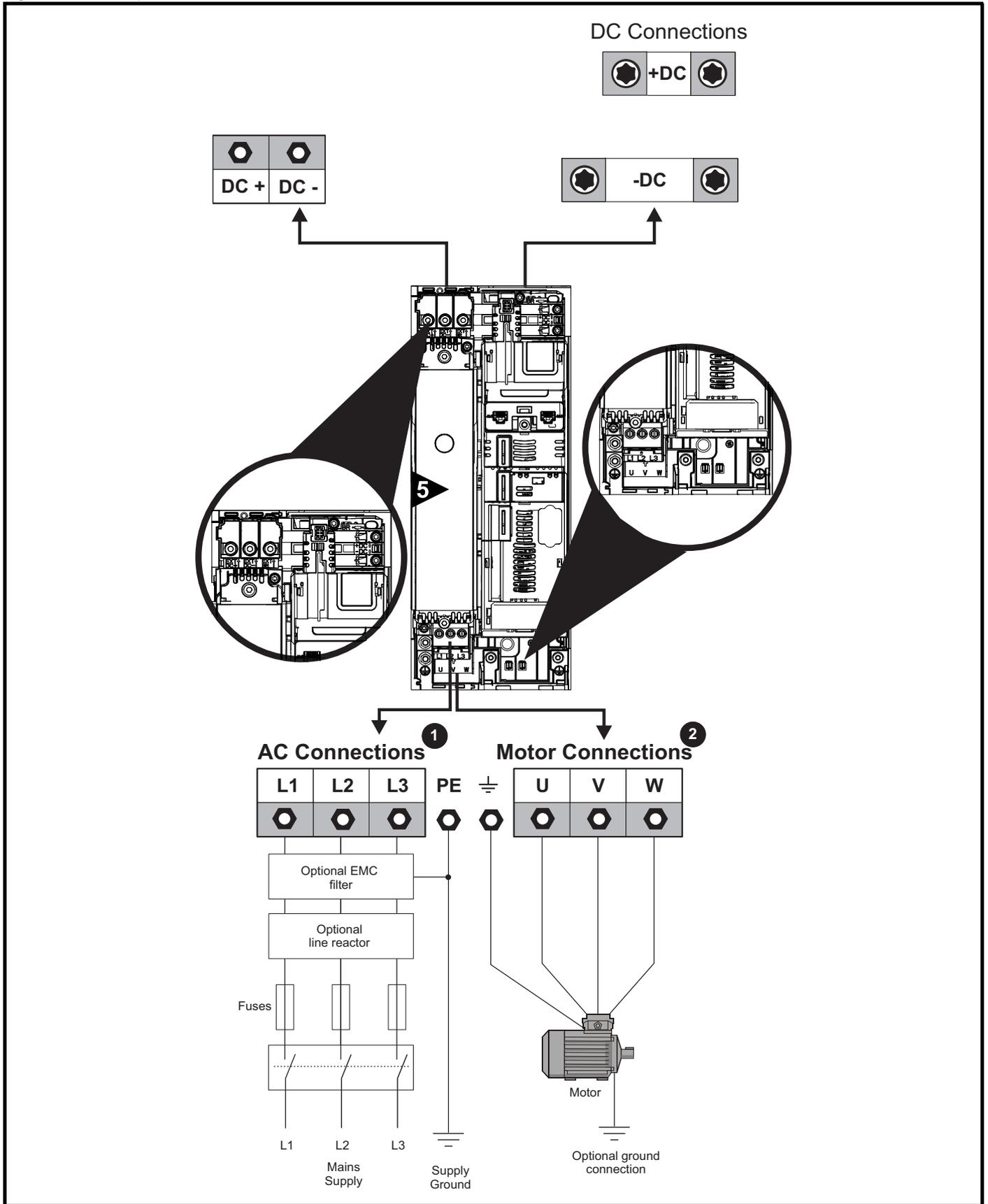
See Figure 4-9 for further information on ground connections.

Figure 4-2 Size 4 power connections



See Figure 4-9 for further information regarding ground connections.

Figure 4-3 Size 5 power connections



The upper terminal block (1) is used for AC supply connection.

The lower terminal block (2) is used for Motor connection.

See Figure 4-10 for further information on ground connections.

Figure 4-4 Size 6 power connections

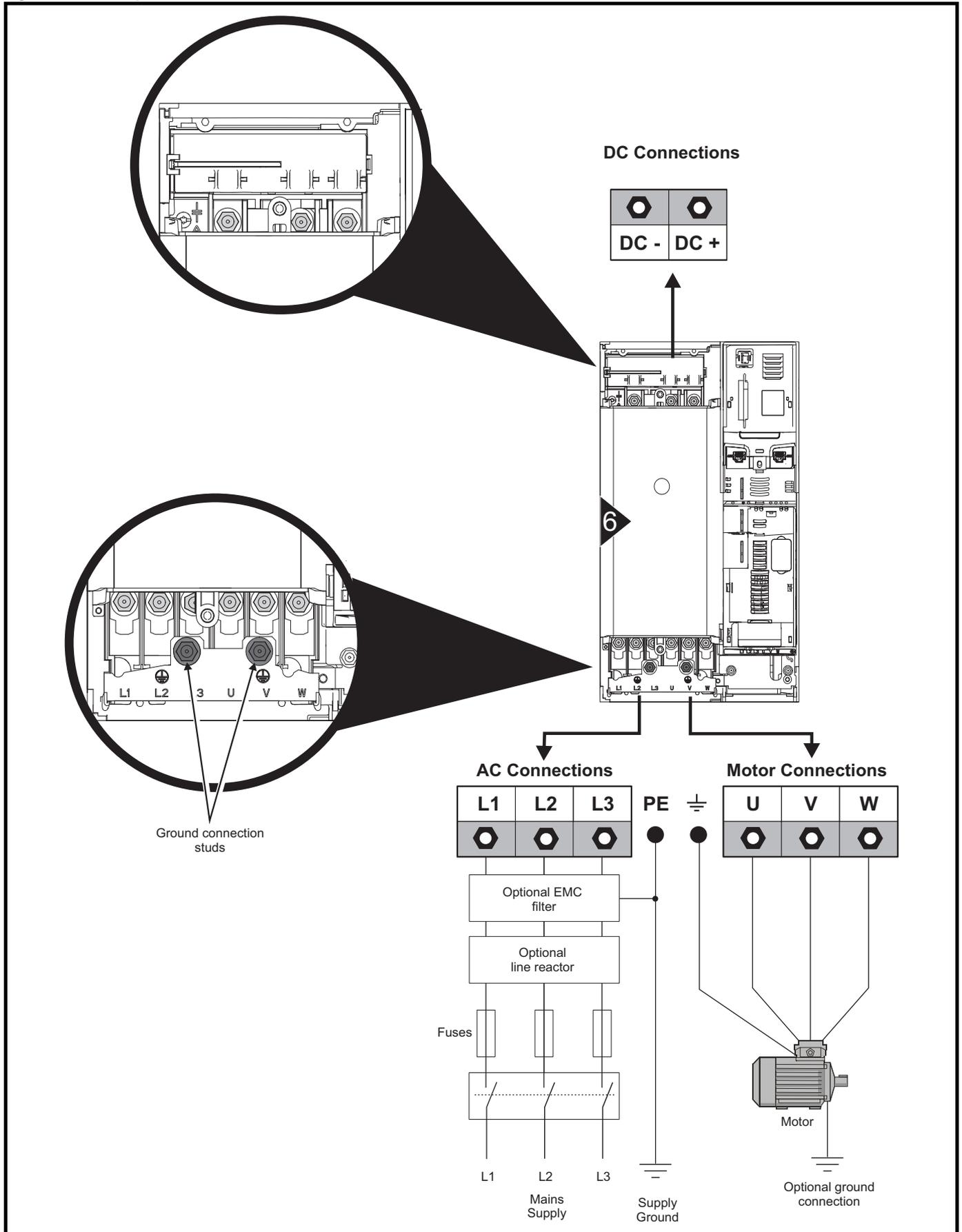


Figure 4-5 Size 7 and 8 power connections (Size 7 shown)

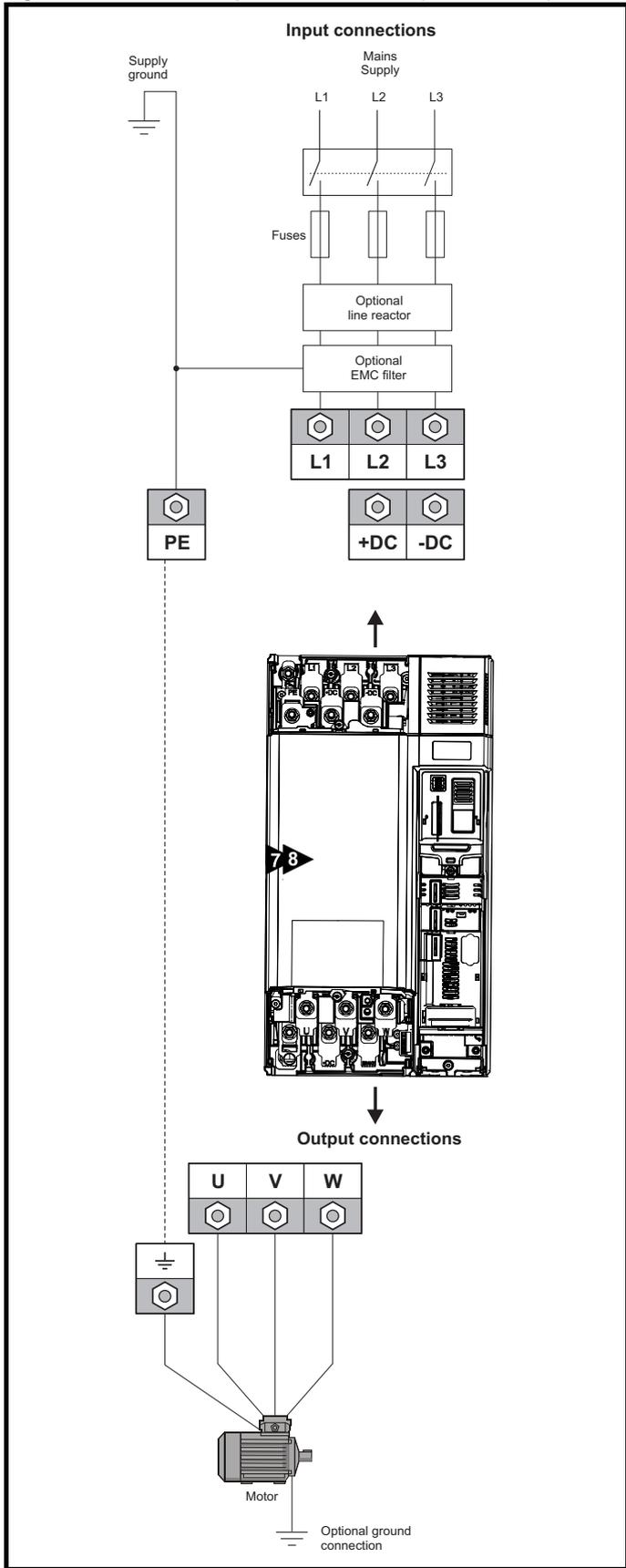


Figure 4-6 Size 9A Power and Ground Connections

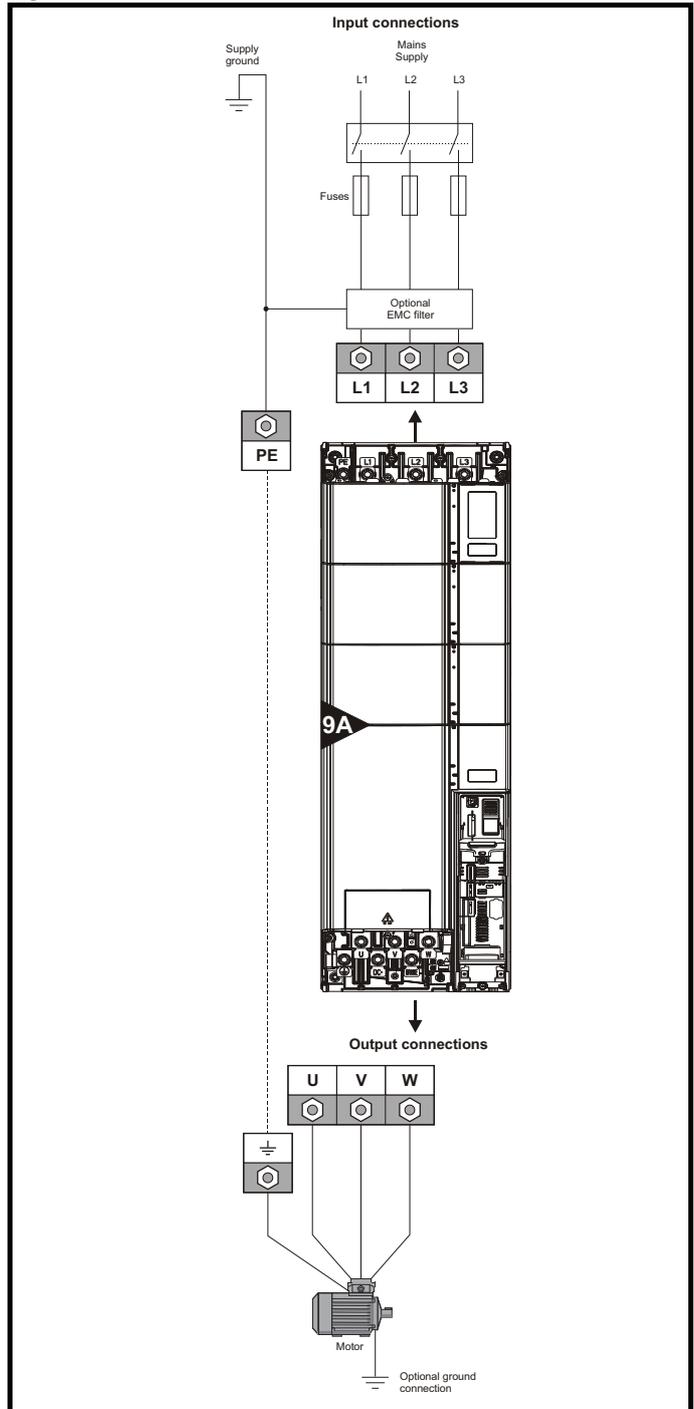
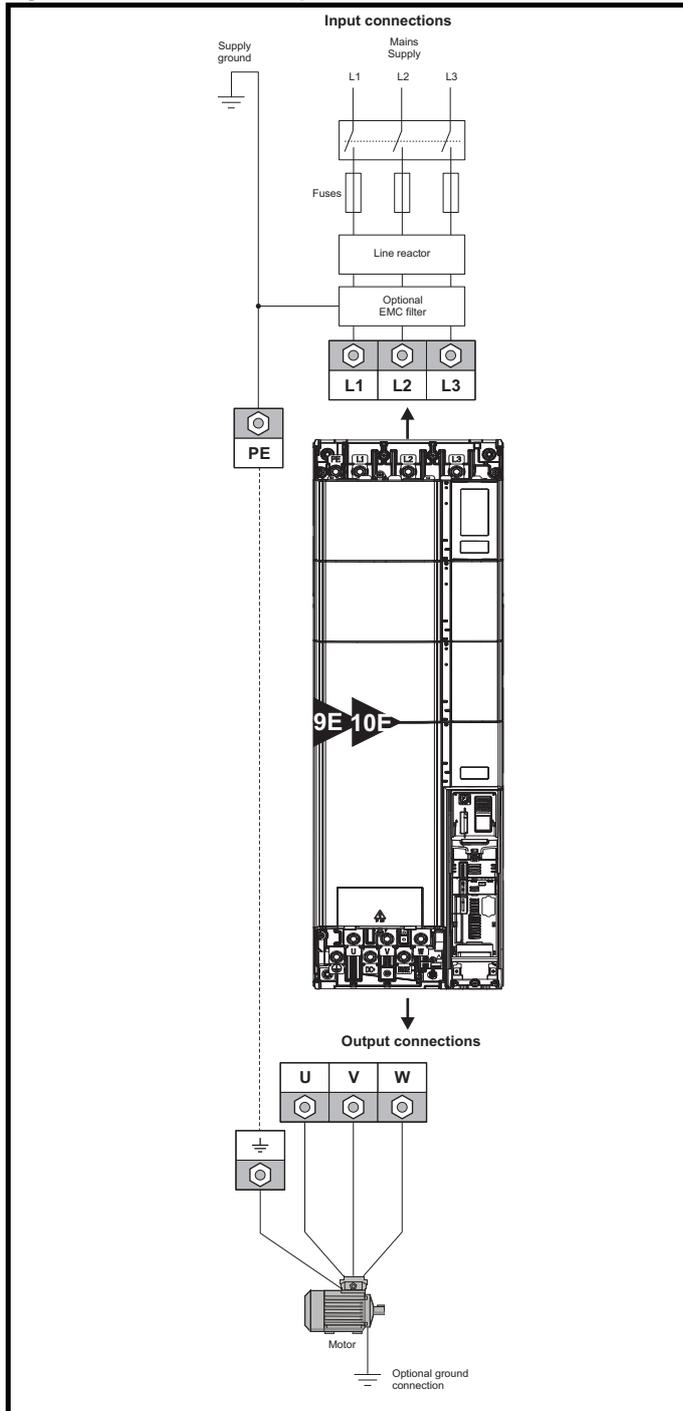
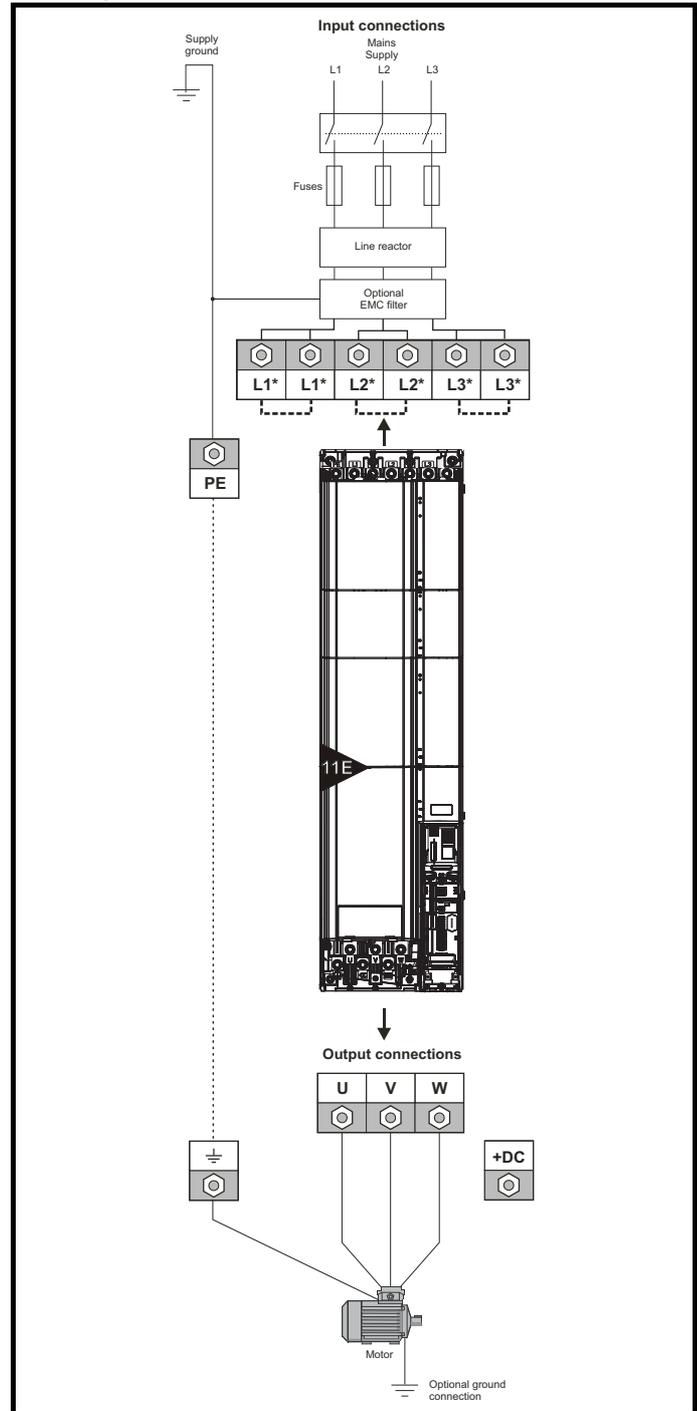


Figure 4-7 Size 9E and 10E power connections

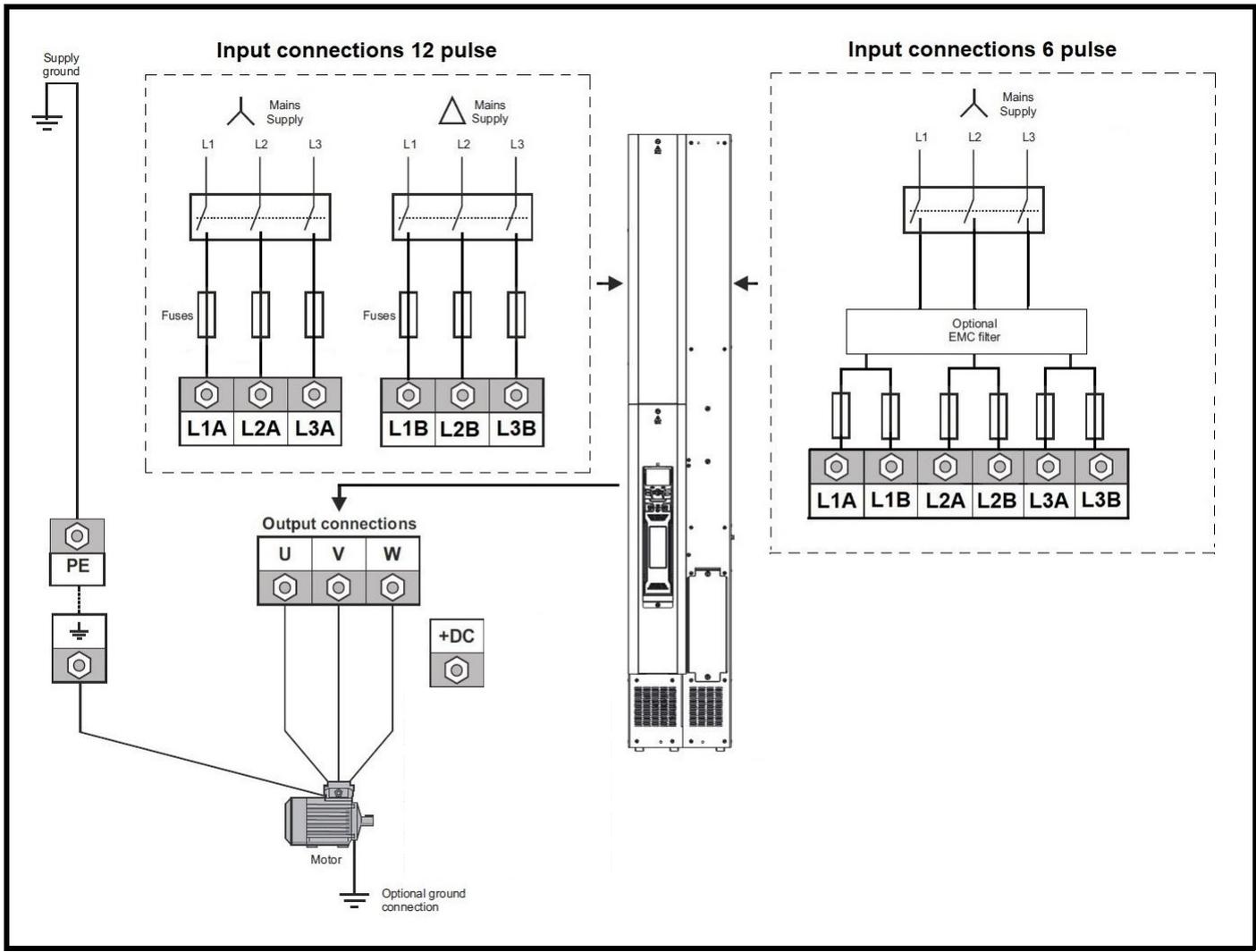


Size 11E power connections



WARNING A separate line reactor (INLXXX) of at least the value shown in Table 4-14 and Table on page 98 must be used with size 9E, 10E and 11E. Failure to provide sufficient reactance could damage or reduce the service life of the drive.

Figure 4-8 Power Module Frame 12 power connections



4.1.2 Ground connections

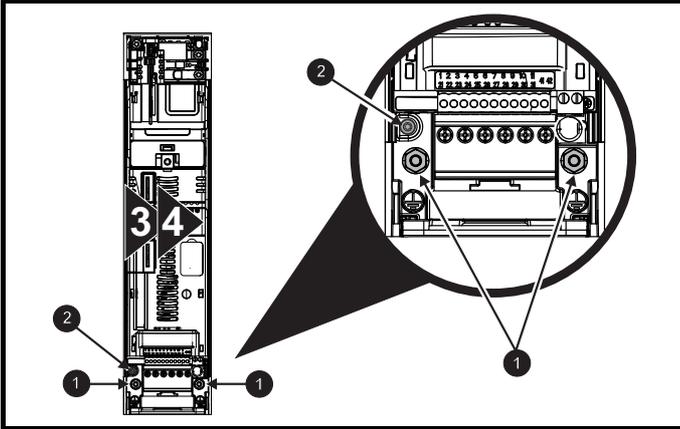


Electrochemical corrosion of grounding terminals
 Ensure that grounding terminals are protected against corrosion i.e. as could be caused by condensation.

Size 3 and 4

On sizes 3 and 4, the supply and motor ground connections are made using the M4 studs located either side of the drive near the plug-in power connector. Refer to Figure 4-9 for additional ground connection.

Figure 4-9 Size 3 and 4 ground connections

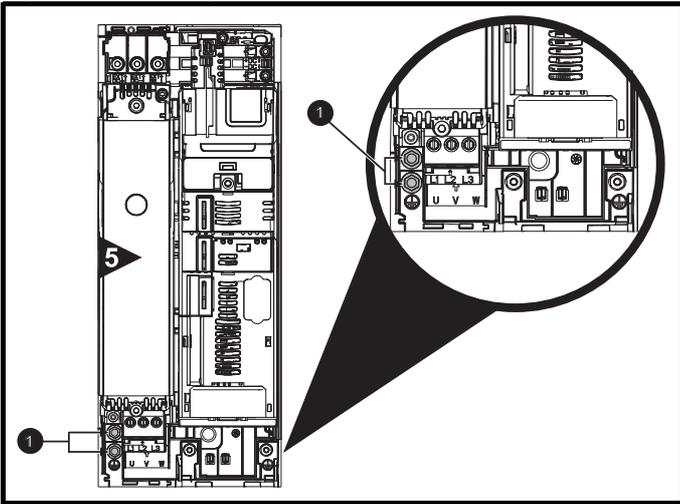


1. Ground connection studs.
2. Additional ground connection.

Size 5

On size 5, the supply and motor ground connections are made using the M5 studs located near the plug-in power connector. Refer to Figure 4-10 for additional ground connection.

Figure 4-10 Size 5 ground connections

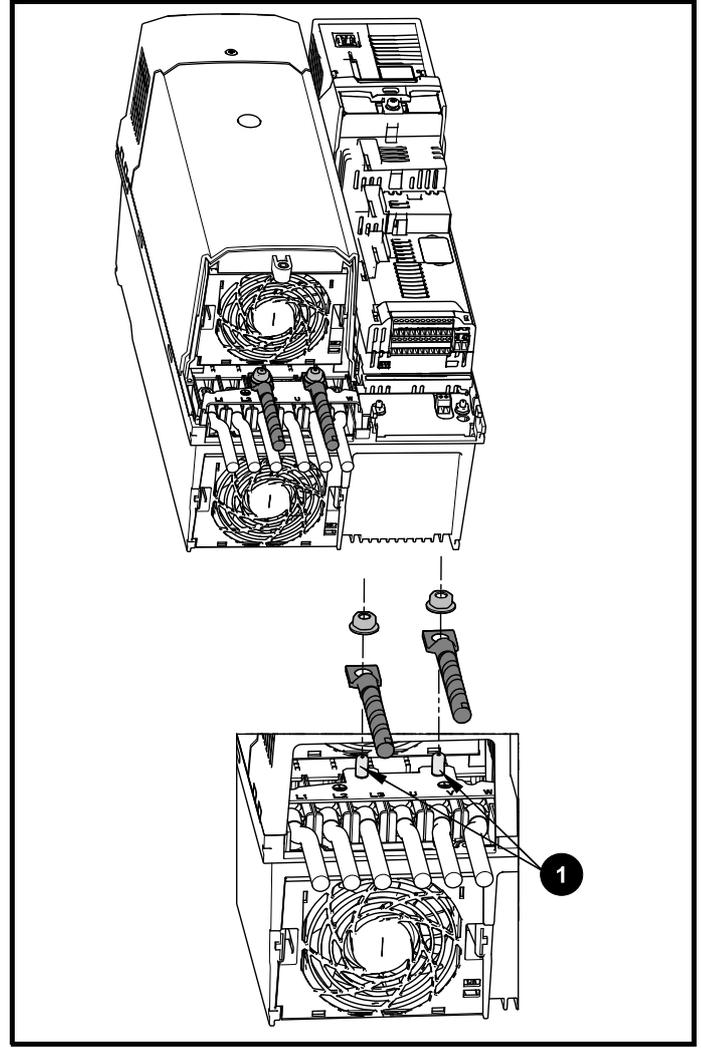


1. Ground connection studs.

Size 6

On a size 6, the supply and motor ground connections are made using the M6 studs located above the supply and motor terminals. Refer to Figure 4-11 below.

Figure 4-11 Size 6 ground connections



1. Ground connection studs

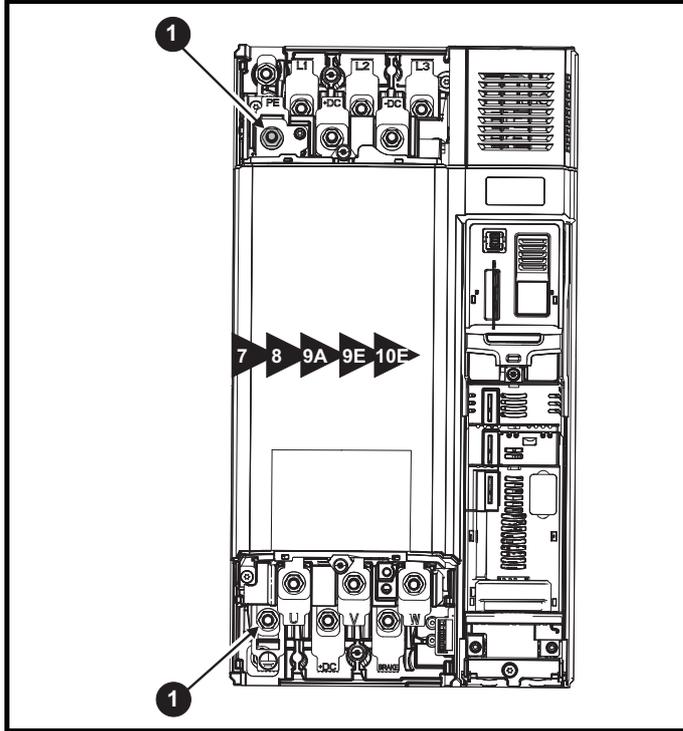
Size 7

On size 7, the supply and motor ground connections are made using the M8 studs located by the supply and motor connection terminals.

Size 8 to 10

On size 8 to 10, the supply and motor ground connections are made using the M10 studs located by the supply and motor connection terminals.

Figure 4-12 Size 7 to 10 ground connections



1. Ground connection studs.



The ground loop impedance must conform to the requirements of local safety regulations.

The drive must be grounded by a connection capable of carrying the prospective fault current until the protective device (fuse, etc.) disconnects the AC supply.

The ground connections must be inspected and tested at appropriate intervals.

Figure 4-13 Size 11E ground connections

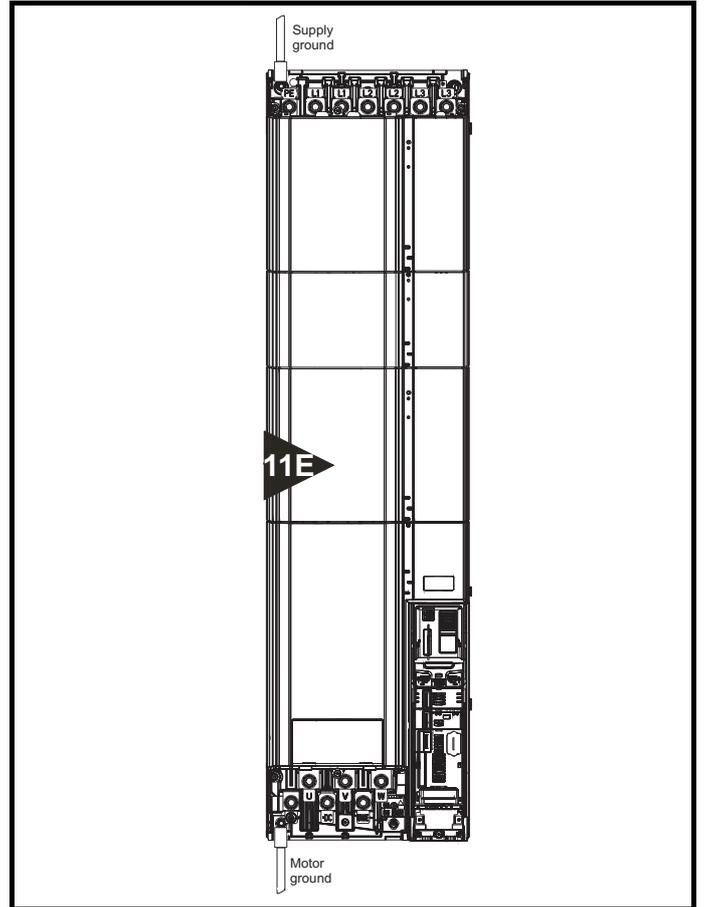


Table 4-1 Protective ground cable ratings

Input phase conductor size	Minimum ground conductor size
$\leq 10 \text{ mm}^2$	Either 10 mm^2 or two conductors of the same cross-sectional area as the input phase conductor (an additional ground connection is provided on sizes 3, 4 and 5 for this purpose).
$> 10 \text{ mm}^2$ and $\leq 16 \text{ mm}^2$	The same cross-sectional area as the input phase conductor
$> 16 \text{ mm}^2$ and $\leq 35 \text{ mm}^2$	16 mm^2
$> 35 \text{ mm}^2$	Half of the cross-sectional area of the input phase conductor

4.2 AC supply requirements

Voltage:

- 200 V drive: 200 V to 240 V $\pm 10\%$
- 400 V drive: 380 V to 480 V $\pm 10\%$
- 575 V drive: 500 V to 575 V $\pm 10\%$
- 690 V drive: 500 V to 690 V $\pm 10\%$

Number of phases: 3

Maximum supply imbalance: 2 % negative phase sequence (equivalent to 3 % voltage imbalance between phases).

Frequency range: 45 to 66 Hz

For UL compliance only, the maximum supply symmetrical fault current must be limited to 100 kA

4.2.1 Supply types

All drives are suitable for use on any supply type i.e TN-S, TN-C-S, TT and IT.

- Supplies with voltage up to 600 V may have grounding at any potential, i.e. neutral, centre or corner ("grounded delta")
- Supplies with voltage above 600 V may not have corner grounding

Drives are suitable for use on supplies of installation category III and lower, according to IEC60664-1. This means they may be connected permanently to the supply at its origin in a building, but for outdoor installation additional over-voltage suppression (transient voltage surge suppression) must be provided to reduce category IV to category III.



Operation with IT (ungrounded) supplies:

Special attention is required when using internal or external EMC filters with ungrounded supplies, because in the event of a ground (earth) fault in the motor circuit the drive may not trip and the filter could be over-stressed. In this case, either the filter must not be used (removed) or additional independent motor ground fault protection must be provided.

For instructions on removal, refer to section 4.11.2 *Internal EMC filter* on page 118. For details of ground fault protection contact the supplier of the drive.

A ground fault in the supply has no effect in any case. If the motor must continue to run with a ground fault in its own circuit then an input isolating transformer must be provided and if an EMC filter is required it must be located in the primary circuit.

Unusual hazards can occur on ungrounded supplies with more than one source, for example on ships. Contact the supplier of the drive for more information.

4.2.2 Supplies requiring line reactors

Input line reactors reduce the risk of damage to the drive resulting from poor phase balance or severe disturbances on the supply network.

Where line reactors are to be used, reactance values of approximately 2 % are recommended. Higher values may be used if necessary, but may result in a loss of drive output (reduced torque at high speed) because of the voltage drop.

For all drive ratings, 2 % line reactors permit drives to be used with a supply unbalance of up to 3.5 % negative phase sequence (equivalent to 5% voltage imbalance between phases).

Severe disturbances may be caused by the following factors, for example:

- Power factor correction equipment connected close to the drive.
- Large DC drives having no or inadequate line reactors connected to the supply.
- Across the line (DOL) started motor(s) connected to the supply such that when any of these motors are started, the voltage dip exceeds 20 %.

Such disturbances may cause excessive peak currents to flow in the input power circuit of the drive. This may cause nuisance tripping, or in extreme cases, failure of the drive.

Drives of low power rating may also be susceptible to disturbance when connected to supplies with a high rated capacity.

Line reactors are particularly recommended for use with the following drive models when one of the above factors exists, or when the supply capacity exceeds 175 kVA:

- 03200066, 03200080, 03200110, 03200127,
- 03400034, 03400045, 03400062, 03400077

Model sizes 03400104 to 07600730 have an internal DC choke and model sizes 08201490 to 0801080 and frame 9A have internal AC line chokes so they do not require AC line reactors except for cases of excessive phase unbalance or extreme supply conditions. Drive sizes 9E, 10E and 11E do not have internal input line reactors hence an external input line reactor must be used. For more information refer to section 4.2.3 *Drive model and input line reactor* on page 98.

Reactor current ratings

The current rating of the line reactors should be as follows:

Continuous current rating:

Not less than the continuous input current rating of the drive

Repetitive peak current rating:

Not less than twice the continuous input current rating of the drive



A separate line reactor (INLXXX) of at least the value shown in Table 4-2 and Table 4-3 must be used with size 9E, 10E and 11E. Failure to provide sufficient reactance could damage or reduce the service life of the drive.

4.2.3 Drive model and input line reactor

Table 4-2 Drive model and line reactor part number

Size	Drive model	Inductor model	Line reactor part number
3	03200066, 03200080	INL 2001	4401-0143
	03200110, 03200127	INL 2002	4401-0144
	03400034, 03400045	INL 4001	4401-0148
	03400062	INL 4002	4401-0149
	03400077, 03400104	INL 4011	4401-0234
4	03400123	INL 4003	4401-0151
	04200180	INL 2002	4401-0144
	04200250	INL 2003	4401-0145
	04400185	INL 4004	4401-0152
5	04400240	INL 4005	4401-0153
	05200300	INL 2008	4401-0226
	05400300	INL 4013	4401-0236
	05500039	INL 5007	4401-0242
6	05500061	INL 5008	4401-0243
	05500100	INL 5009	4401-0244
	06200500	INL 2004	4401-0146
	06200580	INL 2005	4401-0147
	06400380	INL 4006	4401-0154
	06400480	INL 4007	4401-0155
	06400630	INL 4008	4401-0156
	06500120	INL 5001	4401-0157
	06500170	INL 5002	4401-0158
	06500220	INL 5003	4401-0159
7	06500270	INL 5004	4401-0160
	06500340	INL 5005	4401-0161
	06500430	INL 5006	4401-0223
	07200750	INL 2009	4401-0227
	07200940	INL 2010	4401-0228
	07201170	INL 2011	4401-0229
	07400790	INL 4014	4401-0237
	07400940	INL 4015	4401-0238
	07401120	INL 4016	4401-0239
	07500530	INL 5006	4401-0223
	07500730	INL 5010	4401-0245
	07600230	INL 6001	4401-0248
	07600300	INL 6002	4401-0249
8	07600360	INL 6003	4401-0250
	07600460	INL 6004	4401-0251
	07600520	INL 6005	4401-0252
	07600730	INL 6006	4401-0253
	08201490	INL 2012	4401-0230
	08201800	INL 2013	4401-0231
	08401550	INL 4017	4401-0240
9E	08401840	INL 4018	4401-0241
	08500860	INL 5011	4401-0246
	08501080	INL 5012	4401-0247
	08600860	INL 6007	4401-0254
	08601080	INL 6008	4401-0255
10E	09202160, 09202660, 09402210, 09402660	INL 401	4401-0181
	09501250, 09501500, 09601720, 09601970	INL 601	4401-0183
11E	10203250, 10203600, 10403200, 10403610	INL 402	4401-0182
	10502000, 10601720, 10601970	INL 602	4401-0184
11E	11404370	INL 403L**	4401-0274
	11404370, 11404870, 11405070	INL 403*	4401-0259
	11502480, 11502880, 11503150, 11602250, 11602750, 11603050	INL 603*	4401-0261

* Natural cooling.

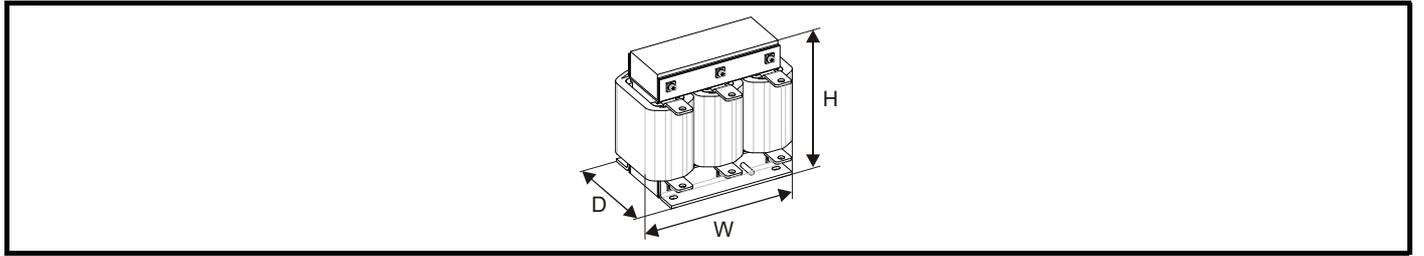
** May represent a more economic solution when operating below 420 A.

Table 4-3 Input line reactor ratings (2%)

Part number	Model	Current	Inductance	Overall width (W)	Overall depth (D)	Overall height (H)	Weight	Max ambient temp	Min airflow	Maximum losses
		A	μH	mm	mm	mm	kg	°C	m/s	W
4401-0143	INL 2001	13.5	790	156	70	125	1.8	50	0	42
4401-0144	INL 2002	20.6	480	156	80	125	2.4	50	0	43
4401-0145	INL 2003	26.8	320	156	80	125	2.5	50	0	48
4401-0148	INL 4001	6.6	2940	80	75	130	1.3	50	0	31
4401-0149	INL 4002	9.1	1620	156	70	125	1.8	50	0	42
4401-0234	INL 4011	13	1120	156	80	125	2.5	50	0	46
4401-0151	INL 4003	15.8	1050	156	80	125	2.6	50	0	47
4401-0152	INL 4004	18.7	790	156	60	145	3.5	50	0	62
4401-0153	INL 4005	24.3	610	156	75	145	4.9	50	0	59
4401-0226	INL 2008	32	260	156	60	145	3.30	50	0	64
4401-0146	INL 2004	48.8	170	156	75	145	4.8	50	0	59
4401-0147	INL 2005	56.6	150	156	120	130	4.9	50	0	58
4401-0236	INL 4013	32	480	156	75	145	4.9	50	0	63
4401-0154	INL 4006	36.5	400	206	140	200	8	50	0	78
4401-0155	INL 4007	46.2	320	206	140	200	9	50	0	84
4401-0156	INL 4008	60.6	240	255	125	195	11	50	0	104
4401-0242	INL 5007	4.3	492	80	75	130	1.4	50	0	35
4401-0243	INL 5008	6.8	311	156	70	125	1.8	50	0	39
4401-0244	INL 5009	11.4	1890	156	60	145	3.2	50	0	60
4401-0157	INL 5001	13.2	1600	156	60	145	3.5	50	0	60
4401-0158	INL 5002	18.7	1130	156	75	145	4.9	50	0	59
4401-0159	INL 5003	24.3	870	206	95	200	6	50	0	73
4401-0160	INL 5004	29.4	720	206	130	200	7.4	50	0	77
4401-0161	INL 5005	37.1	570	230	130	210	11	50	0	108
4401-0223	INL 5006	47	480	255	130	210	12.5	50	0	122
4401-0227	INL 2009	67	130	206	130	160	6.9	50	0	90
4401-0228	INL 2010	88	100	206	140	160	9	50	0	97
4401-0229	INL 2011	105	80	206	140	160	9.5	50	0	90
4401-0230	INL 2012	137	62	254	130	195	12.5	50	0	143
4401-0231	INL 2013	166	51	254	150	195	14	50	0	137
4401-0237	INL 4014	74	200	254	130	195	12	50	0	129
4401-0238	INL 4015	88	170	254	150	195	14	50	0	127
4401-0239	INL 4016	105	140	254	150	195	14	50	0	139
4401-0240	INL 4017	155	95	290	160	205	20	50	0	182
4401-0241	INL 4018	177	83	290	170	205	22	50	0	200
4401-0245	INL 5010	67	340	290	150	205	18	50	0	139
4401-0246	INL 5011	88	250	290	170	205	22	50	0	147
4401-0247	INL 5012	105	200	290	180	225	25	50	0	167
4401-0248	INL 6001	20	1270	206	95	200	5.8	50	0	71
4401-0249	INL 6002	26	980	206	130	200	7.4	50	0	80
4401-0250	INL 6003	32	880	206	140	200	10	50	0	84
4401-0251	INL 6004	39	650	254	130	210	12	50	0	123
4401-0252	INL 6005	45	580	254	130	210	12.5	50	0	124
4401-0253	INL 6006	67	410	290	150	205	18	50	0	123
4401-0254	INL 6007	88	300	290	170	205	22	50	0	169
4401-0255	INL 6008	105	240	290	180	225	25	50	0	204
4401-0181	INL 401	245	63	240	190	225	32	50	1	148
4401-0182	INL 402	370	44	276	200	225	36	50	1	205
4401-0183	INL 601	145	178	240	190	225	33	50	1	88
4401-0184	INL 602	202	133	276	200	225	36	50	1	116
4401-0181	INL 401	245	63	240	190	225	32	50	1	148
4401-0182	INL 402	339	44	276	200	225	36	50	1	205
4401-0274	INL 403L*	420	30	300	216	264	57	40	0	289
4401-0259	INL403*	557	30	300	216	264	57	40	0	330
4401-0183	INL 601	145	178	240	190	225	33	50	1	88
4401-0184	INL 602	192	133	276	200	225	36	50	1	116
4401-0261	INL 603*	331	93	300	216	264	58	40	0	320

* Natural cooling.

Figure 4-14 Input line reactor dimensions



4.2.4 Input inductor calculation

To calculate the inductance required (at Y%), use the following equation:

$$L = \frac{Y}{100} \times \frac{V}{\sqrt{3}} \times \frac{1}{2\pi f I}$$

Where:

I = drive rated input current (A)

L = inductance (H)

f = supply frequency (Hz)

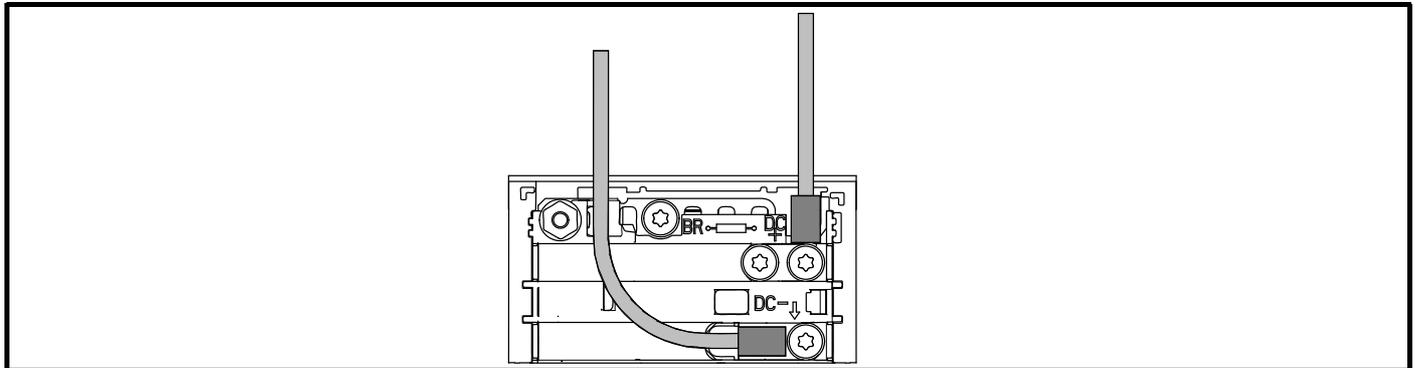
V = voltage between lines

4.3 Supplying the drive with DC

All drive sizes have the option to be powered from an external DC power supply. Refer to section 3.12 *Electrical terminals* on page 75 to identify the location of DC supply connections.

The DC supply connections for size 3 and 4 are located under the DC / Terminal cover. Figure 4-15 below shows DC supply connections and cable routing.

Figure 4-15 DC supply connections (size 3 shown)



NOTE

The Internal EMC filter and plastics have been removed from the above Figure 4-15 to demonstrate the routing of the DC cables.

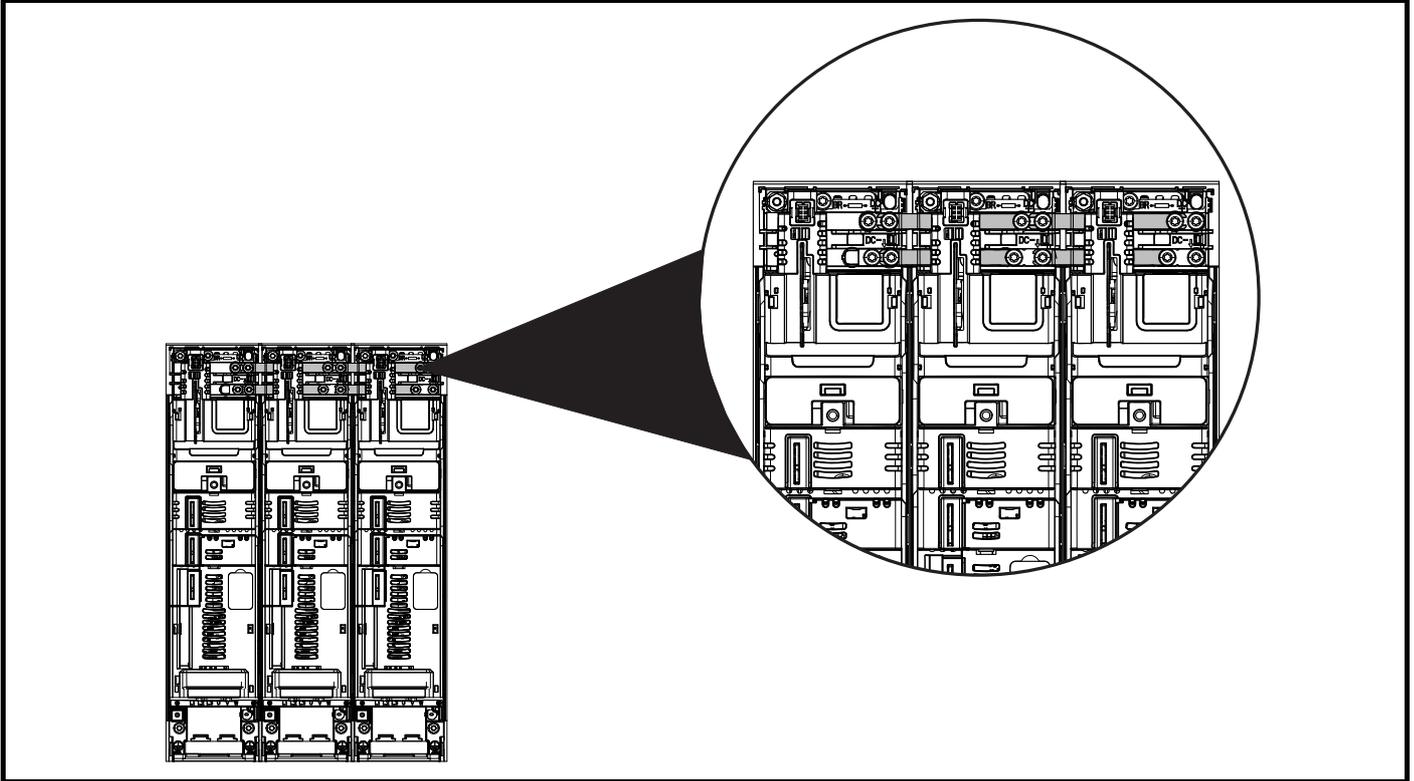
4.4 DC bus paralleling

DC bus paralleling using standard cable / busbars is supported by all frame sizes.

On frame sizes 3, 4, 5 and 6, terminal and enclosure design enables the DC bus of a number of drives to be connected together using pre-made busbars. The diagram below shows how the busbar links connect the DC bus of several drives together.

The connecting of the DC bus between several drives is typically used to return energy from a drive which is being overhauled by the load to a second motoring drive.

Figure 4-16 DC bus paralleling (size 3 shown)



There are limitations to the combinations of drives which can be used in this configuration.

For application data, contact the supplier of the drive.

NOTE

The DC bus paralleling kit is not supplied with the drive but available to order.

Table 4-4 DC bus paralleling kit part numbers

Size	CT part number
3	3470-0048
4	3470-0061
5	3470-0068
6	3470-0063

4.5 24 Vdc supply

The 24 Vdc supply connected to control terminals 1 & 2 provides the following functions:

- It can be used to supplement the drive's own internal 24 V supply when multiple option modules are being used and the current drawn by these modules is greater than the drive can supply.
- It can be used as a back-up power supply to keep the control circuits of the drive powered up when the line power supply is removed. This allows any fieldbus modules, application modules, or serial communications to continue to operate.
- It can be used to commission the drive when the line power supply is not available, as the display operates correctly. However, the drive will be in the Under voltage trip state unless either line power supply or low voltage DC operation is enabled, therefore diagnostics may not be possible. (Power down save parameters are not saved when using the 24 V back-up power supply input).
- If the DC bus voltage is too low to run the main SMPS in the drive, then the 24 V supply can be used to supply all the low voltage power requirements of the drive. *Low Under Voltage Threshold Select* (06.067) must also be enabled for this to happen.

NOTE

On size 6 and larger, the power 24 Vdc supply (terminals 51, 52) must be connected to enable the 24 Vdc supply to be used as a backup supply, when the line power supply is removed. If the power 24 Vdc supply is not connected none of the above mentioned functions can be used, "Waiting For Power System" will be displayed on the keypad and no drive operations are possible. The location of the power 24 Vdc can be identified from Figure 4-17 *Location of the 24 Vdc power supply connection on size 6* on page 102.

Table 4-5 24 Vdc Supply connections

Function	Sizes 3-5	Sizes 6-7
Supplement the drive's internal supply	Terminal 1, 2	Terminal 1, 2
Back-up supply for the control circuit	Terminal 1, 2	Terminal 51, 52

The working voltage range of the control 24 V power supply is as follows:

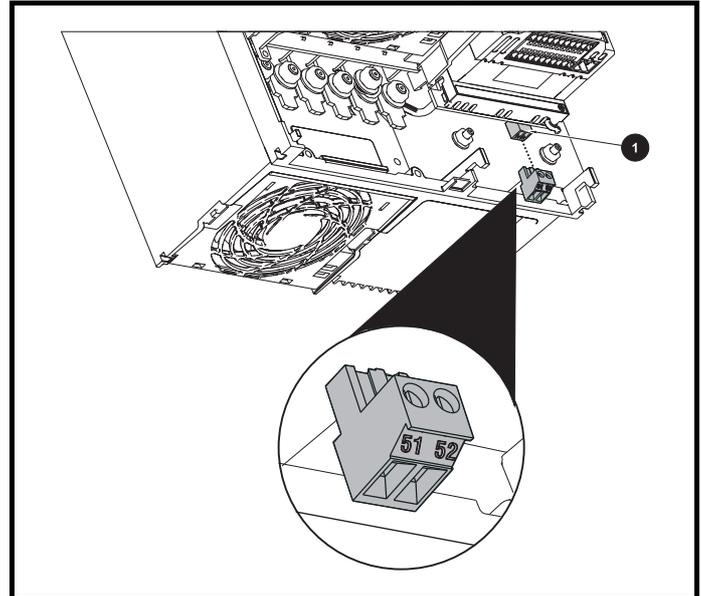
1	0V common
2	+24 Vdc
Nominal operating voltage	24.0 Vdc
Minimum continuous operating voltage	19.2 V
Maximum continuous operating voltage	28.0 V
Minimum start up voltage	21.6 V
Maximum power supply requirement at 24 V	40 W
Recommended fuse	3 A, 50 Vdc

Minimum and maximum voltage values include ripple and noise. Ripple and noise values must not exceed 5 %.

The working range of the 24 V power supply is as follows:

51	0V common
52	+24 Vdc
Size 6	
Nominal operating voltage	24.0 Vdc
Minimum continuous operating voltage	18.6 Vdc
Maximum continuous operating voltage	28.0 Vdc
Minimum startup voltage	18.4 Vdc
Maximum power supply requirement	40 W
Recommended fuse	4 A @ 50 Vdc
Size 7 to 11	
Nominal operating voltage	24.0 Vdc
Minimum continuous operating voltage	19.2 Vdc
Maximum continuous operating voltage	30 Vdc (IEC), 26 Vdc (UL)
Minimum startup voltage	21.6 Vdc
Maximum power supply requirement	60 W
Recommended fuse	4 A @ 50 Vdc

Figure 4-17 Location of the 24 Vdc power supply connection on size 6



1. 24 Vdc power supply connection

Figure 4-18 Location of the 24 Vdc power supply connection on size 7

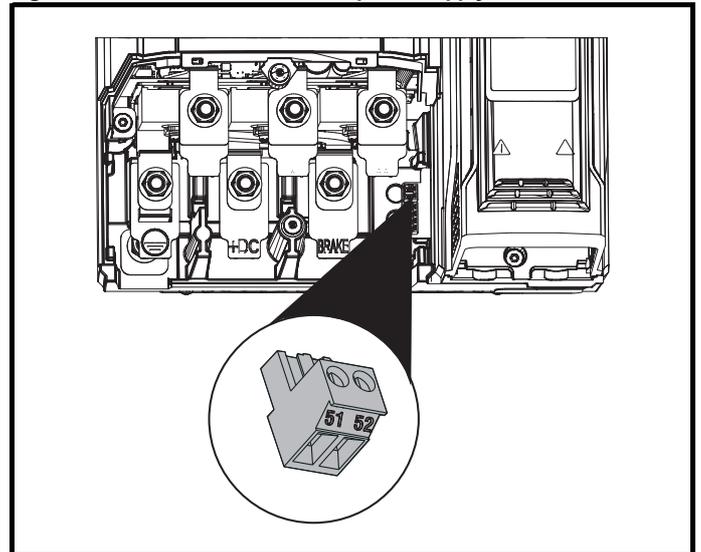


Figure 4-19 Location of the 24 Vdc power supply connection on size 8 to 11

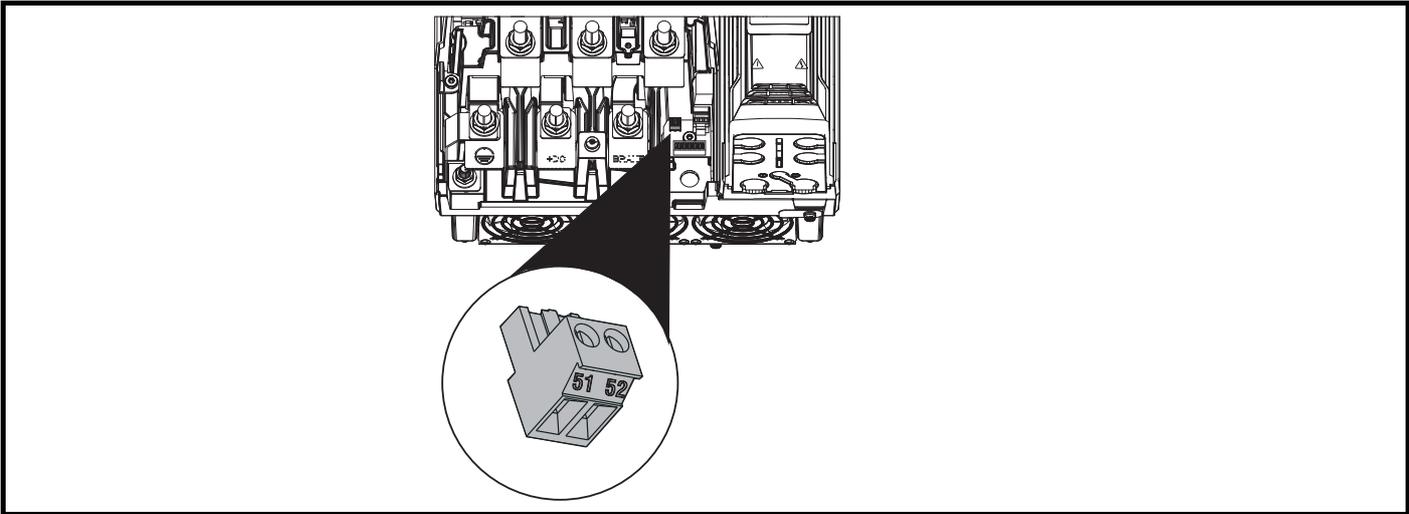
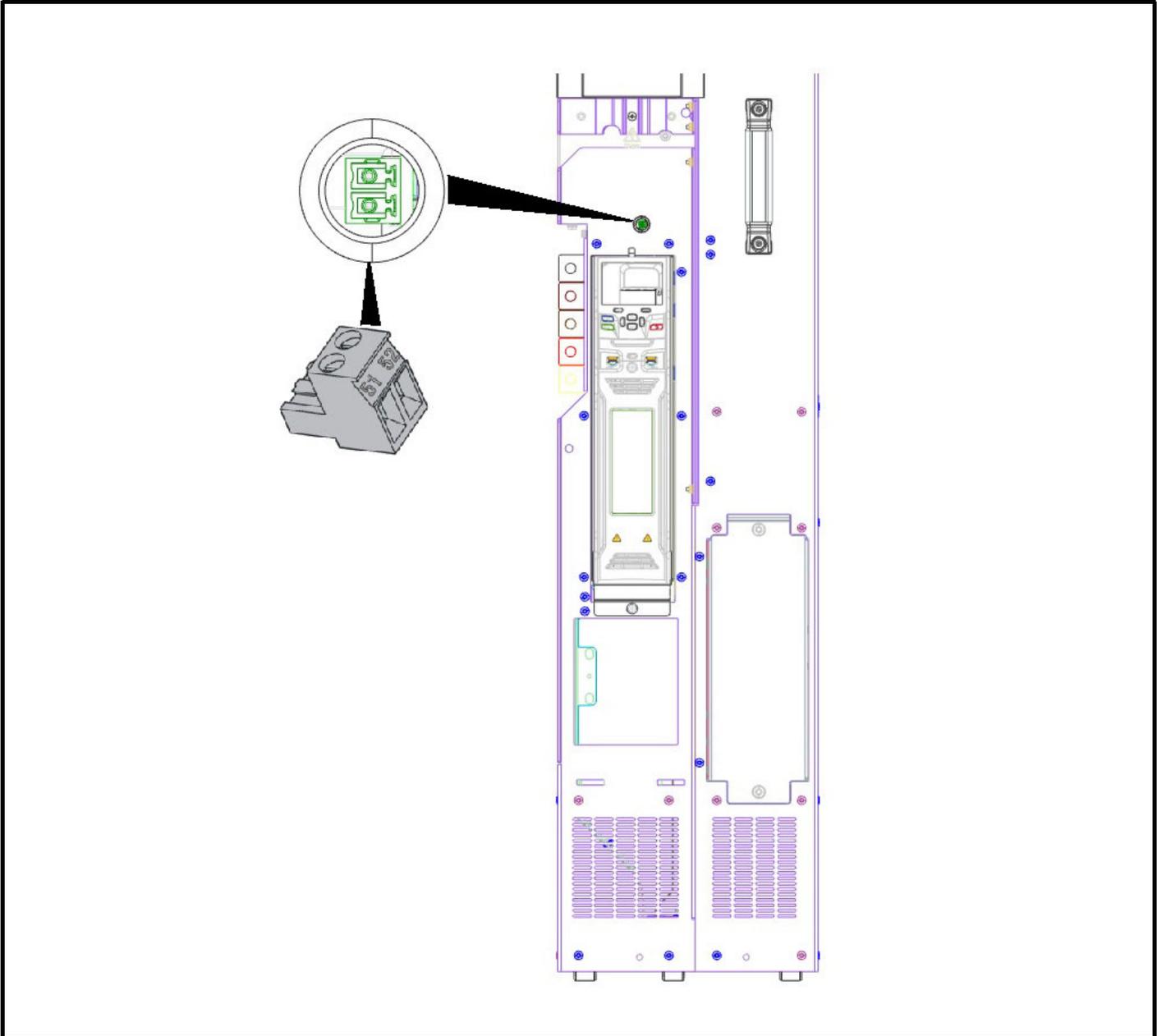


Figure 4-20 Location of the 24 Vdc power supply connection on size 12



4.6 Low voltage operation

With the addition of a 24 Vdc power supply to supply the control circuits, the drive is able to operate from a low voltage DC supply with a range from 24 Vdc to the maximum DC volts. It is possible for the drive to go from operating on a normal line power supply voltage to operating on a much lower supply voltage without interruption.

Going from low voltage operation to normal mains operation requires the inrush current to be controlled. This may be provided externally. If not, the drive supply can be interrupted to utilise the normal soft starting method in the drive.

To fully exploit the new low voltage mode of operation, the under voltage level is now user programmable. For application data, contact the supplier of the drive.

The working voltage range of the low voltage DC power supply is as follows:

Size 3 to 12

Minimum continuous operating voltage:	26 V
Minimum start up voltage:	32 V
Maximum over voltage trip threshold:	230 V drives: 415 V
	400 V drives: 830 V
	575 V drives: 990 V
	690 V drives: 1190 V

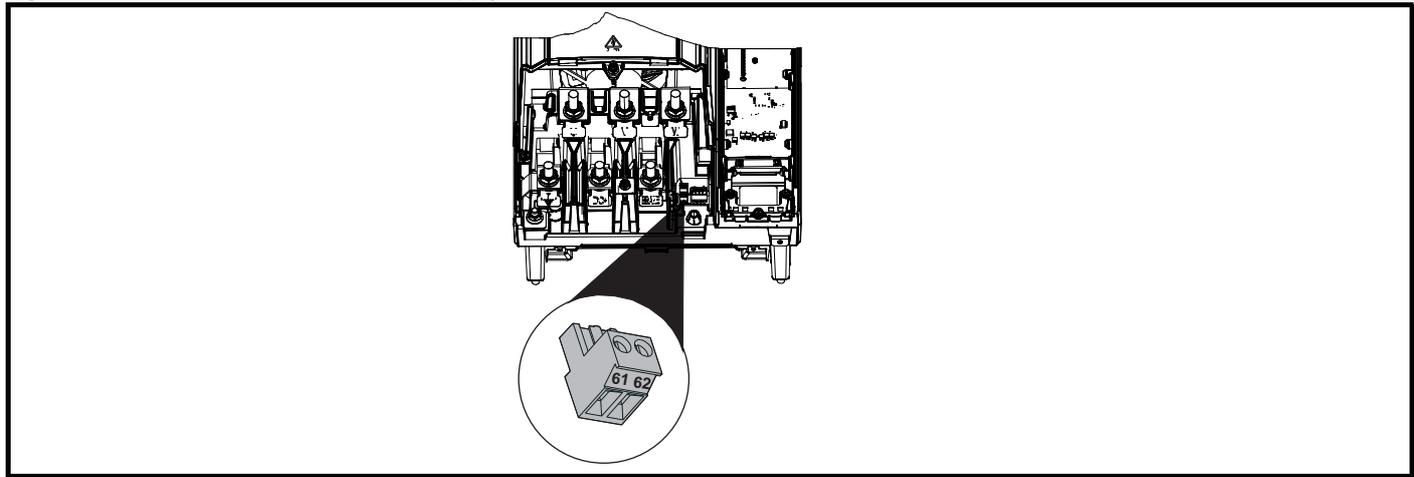
NOTE

Size 9E, 10E and 11E drives do not have an accessible negative DC terminal. It is recommended that 9D, 10D and 11D drives are used as an alternative when this is needed, please refer to the Unidrive M Modular Installation Guide for further details.

In low voltage mode only, with frame size 9 to 11, a 24 V supply needs to be provided for the heatsink fan. The fan supply should be connected to terminal 61 and 62.

61	0V common
62	+24 Vdc heatsink fan supply
Size 9 to 11	
Nominal operating voltage	24.0 Vdc
Minimum continuous operating voltage	23.5 Vdc
Maximum continuous operating voltage	27 Vdc
Current consumption	Size 9 to 10 (all): 6A
Recommended power supply	24 V, 7 A
Recommended fuse	8A fast blow

Figure 4-21 Location of the heatsink fan supply connector on size 9 to 11



4.7 Heatsink fan supply

When operating on normal mains supply the heatsink fan on all drive sizes is supplied internally by the drive. When operating size 9 to 11 in low voltage mode it is necessary to connect an external 24V supply to terminal 61 and 62 if heatsink fan operation is required. Please see section 4-20 *Location of the 24 Vdc power supply connection on size 12* on page 103 for more details.

4.8 Ratings

The input current is affected by the supply voltage and impedance.

Typical input current

The values of typical input current are given to aid calculations for power flow and power loss.

The values of typical input current are stated for a balanced supply.

Maximum continuous input current

The values of maximum continuous input current are given to aid the selection of cables and fuses. These values are stated for the worst case condition with the unusual combination of stiff supply with bad balance. The value stated for the maximum continuous input current would only be seen in one of the input phases. The current in the other two phases would be significantly lower.

The values of maximum input current are stated for a supply with a 2 % negative phase-sequence imbalance and rated at the supply fault current given in Table 4-6.

Table 4-6 Supply fault current used to calculate maximum input currents

Model	Symmetrical fault level (kA)
All	100



Fuses

The AC supply to the drive must be installed with suitable protection against overload and short-circuits. Table 4-7 shows recommended fuse ratings. Failure to observe this requirement will cause risk of fire.

Table 4-7 AC Input current and fuse ratings (200 V)

Model	Typical input current A	Maximum continuous input current A	Maximum overload input current A	Fuse rating							
				IEC			UL / USA				
				Nominal A	Maximum A	Class	Nominal A	Maximum A	Class		
03200066	8.2	10.4	15.8	16	25	gG	20	25	CC, J or T*		
03200080	9.9	12.6	20.9	20							
03200110	14	17	25	25							
03200127	16	20	34	25							
04200180	17	20	30	25	25	gG	25	25	CC, J or T*		
04200250	23	28	41	32			32			30	30
05200300	24	31	52	40	40	gG	40	40	CC, J or T*		
06200500	42	48	64	63	63	gG	60	60	CC, J or T*		
06200580	49	56	85				60				
07200750	58	67	109	80	80	gG	80	80	CC, J or T*		
07200940	73	84	135	100			100			100	
07201170	91	105	149	125			125			125	125
08201490	123	137	213	200	200	gR	200	200	HSJ		
08201800	149	166	243				225			225	
09202160	172	205	270	250	250	gR	250	250	HSJ		
09202660	228	260	319	315			315			300	300
10203250	277	305	421	400			400			400	400
10203600	333	361	494	450	450	gR	450	450	HSJ		

* These fuses are fast acting.

Table 4-8 AC Input current and fuse ratings (400 V)

Model	Typical input current A	Maximum continuous input current A	Maximum overload input current A	Fuse rating						
				IEC			UL / USA			
				Nominal A	Maximum A	Class	Nominal A	Maximum A	Class	
03400034	5	5	7	10	10	gG	10	10	CC, J or T*	
03400045	6	7	9							
03400062	8	9	13							
03400077	11	13	21							
03400104	12		20	20	20					
03400123	14		25							
04400185	17	19	30	25	25	gG	25	25	CC, J or T*	
04400240	22	24	35	32			32			30
05400300	26	29	52	40	40	gG	35	35	CC, J or T*	
06400380	32	36	67	63	63	gG	40	60	CC, J or T*	
06400480	41	46	80				50			
06400630	54	60	90				60			
07400790	67	74	124	100	100	gG	80	80	CC, J or T*	
07400940	80	88	145				100			100
07401120	96	105	188				125			125
08401550	137	155	267	250	250	gR	225	225	HSJ	
08401840	164	177	303							
09402210	211	232	306	315	315	gR	300	300	HSJ	
09402660	245	267	359				350			350
10403200	306	332	445	400	400	gR	400	400	HSJ	
10403610	370	397	523	450			450			450
11404370	424	449	579	500	500	gR	600	600	HSJ	
11404870	455	492	613							
11405070	502	539	752							630

* These fuses are fast acting.

Table 4-9 400 V drive input current, fuse rating and cable size

Model	Maximum continuous input current	Fuse (6 per drive)				Nominal cable size (European) mm ²				Nominal cable size (USA)		
		IEC		UL/USA		Input 6 pulse	Input 12 pulse	Output	Cable type (input & output)	Input 6 pulse	Input 12 pulse	Output
		Nom	Class	Nom	Class							
		3 ph	A	A	A	mm ²	mm ²	mm ²	kcmil	kcmil	kcmil	
12404800T	720	550	aR	400	gR	4 x 120	2 x 120	3 x 150	XLPE/EPR	4 x 3/0 AWG (85 mm ²)	2 x 3/0 AWG (85 mm ²)	4 x 1/0 AWG (53.5 mm ²)
12405660T	777	550		450		4 x 150	2 x 150	4 x 120		4 x 3/0 AWG (85 mm ²)	2 x 3/0 AWG (85 mm ²)	4 x 2/0 AWG (67.4 mm ²)
12406600T	845	550		500		4 x 150	2 x 150	3 x 185		4 x 4/0 AWG (107.2 mm ²)	2 x 4/0 AWG (107.2 mm ²)	4 x 3/0 AWG (85 mm ²)
12407200T	995	550		550		4 x 185	2 x 185	4 x 185		4 x 250 Kcmil (127.2 mm ²)	2 x 250 Kcmil (127.2 mm ²)	4 x 4/0 AWG (107.2 mm ²)

Table 4-10 AC Input current and fuse ratings (575 V)

Model	Typical input current	Maximum continuous input current	Maximum overload input current	Fuse rating						
				IEC			UL / USA			
				Nominal	Maximum	Class	Nominal	Maximum	Class	
A	A	A	A	A	A	A	A	A	Class	
05500039	4	4	7	10	20	gG	10	10	CC, J or T*	
05500061	6	7	9				20	20		
05500100	9	11	15				20	20		
06500120	12	13	22	20	40	gG	20	30	CC, J or T*	
06500170	17	19	33				32			25
06500220	22	24	41				40			30
06500270	26	29	50	50	63	gG	35	50	CC, J or T*	
06500340	33	37	63				40			
06500430	41	47	76				63			50
07500530	41	45	75	50	50	gG	50	50	CC, J or T*	
07500730	57	62	94	80	80		80	80		
08500860	74	83	121	125	125	gR	100	100	HSJ	
08501080	92	104	165	160	160		150	150		
09501250	145	166	190	150	150	gR	150	150	HSJ	
09501500	145	166	221	200	200		175	175		
10502000	177	197	266	250	250	gR	250	250	HSJ	
11502480	240	265	327	400	400	gR	400	400	HSJ	
11502880	285	310	395							
11503150	313	338	473							

* These fuses are fast acting.

Table 4-11 575 V drive input current, fuse rating and cable size

Model	Maximum continuous input current	Fuse (6 per drive)				Nominal cable size (European) mm ²				Nominal cable size (USA)		
		IEC		UL/USA		Input 6 pulse	Input 12 pulse	Output	Cable type (input & output)	Input 6 pulse	Input 12 pulse	Output
		3 ph	Nom	Class	Nom							
		A	A		A	A	mm ²	mm ²	mm ²	kcmil	kcmil	kcmil
12503150T	555	400	aR	315	gR	2 x 150	1 x 150	1 x 185	XLPE/EPR	4 x 3/0 AWG (85 mm ²)	2 x 3/0 AWG (85 mm ²)	4 x 1/0 AWG (53.5 mm ²)
12503600T	625	400		315		3 x 150	1 x 240	1 x 240		4 x 3/0 AWG (85 mm ²)	2 x 3/0 AWG (85 mm ²)	4 x 2/0 AWG (67.4 mm ²)
12504100T	703	400		350		2 x 185	1 x 185	2 x 120		4 x 4/0 AWG (107.2 mm ²)	2 x 4/0 AWG (107.2 mm ²)	4 x 3/0 AWG (85 mm ²)
12504600T	781	400		400		2 x 240	1 x 240	2 x 150		4 x 250 Kcmil (127.2 mm ²)	2 x 250 Kcmil (127.2 mm ²)	4 x 4/0 AWG (107.2 mm ²)

Table 4-12 AC Input current and fuse ratings (690 V)

Model	Typical input current	Maximum continuous input current	Maximum overload input current	Fuse rating					
				IEC			UL / USA		
				Nominal	Maximum	Class	Nominal	Maximum	Class
				A	A		A	A	
07600230	18	20	32	25	50	gG	25	50	CC, J or T*
07600300	23	26	41	32			30		
07600360	28	31	49	40			35		
07600460	36	39	65	50			50		
07600520	40	44	75	80	80	gR	80	80	
07600730	57	62	92				80	80	
08600860	74	83	121	125	125	gR	100	100	HSJ
08601080	92	104	165	160			160		
09601250	124	149	194	150	150	gR	150	150	HSJ
09601550	145	171	226	200			200		
10601720	180	202	268	225	225	gR	250	250	HSJ
10601970	202	225	313	250			250		
11602250	225	256	379	400	400	gR	400	400	HSJ
11602750	217	302	425						
11603050	298	329	465						

* These fuses are fast acting.

Table 4-13 690 V drive input current, fuse rating and cable size

Model	Maximum continuous input current	Fuse (6 per drive)				Nominal cable size (European) mm ²				Nominal cable size (USA)		
		IEC		UL/USA		Input 6 pulse	Input 12 pulse	Output	Cable type (input & output)	Input 6 pulse	Input 12 pulse	Output
		3 ph	Nom	Class	Nom							
		A	A		A	A	mm ²	mm ²	mm ²	kcmil	kcmil	kcmil
12603150T	555	400	aR	315	gR	2 x 150	1 x 150	1 x 185	XLPE/EPR	4 x 3/0 AWG (85 mm ²)	2 x 3/0 AWG (85 mm ²)	4 x 1/0 AWG (53.5 mm ²)
12603600T	625	400		315		3 x 150	1 x 240	1 x 240		4 x 3/0 AWG (85 mm ²)	2 x 3/0 AWG (85 mm ²)	4 x 2/0 AWG (67.4 mm ²)
12604100T	703	400		350		2 x 185	1 x 185	2 x 120		4 x 4/0 AWG (107.2 mm ²)	2 x 4/0 AWG (107.2 mm ²)	4 x 3/0 AWG (85 mm ²)
12604600T	781	400		400		2 x 240	1 x 240	2 x 150		4 x 250 Kcmil (127.2 mm ²)	2 x 250 Kcmil (127.2 mm ²)	4 x 4/0 AWG (107.2 mm ²)

NOTE

Ensure cables used suit local wiring regulations.



CAUTION

The nominal cable sizes below are only a guide. The mounting and grouping of cables affects their current-carrying capacity, in some cases smaller cables may be acceptable but in other cases a larger cable is required to avoid excessive temperature or voltage drop. Refer to local wiring regulations for the correct size of cables.

Table 4-14 Cable ratings (200 V)

Model	Cable size (IEC) mm ²						Cable size (UL) AWG			
	Input			Output			Input		Output	
	Nominal	Maximum	Installation method	Nominal	Maximum	Installation method	Nominal	Maximum	Nominal	Maximum
03200066	1.5	4	B2	1.5	4	B2	14	10	14	10
03200080				4			12			
03200110	4	8	B2	4	8	B2	10	8	10	8
03200127				8			8			
04200180	6	8	B2	6	8	B2	10	8	10	8
04200250	8			8						
05200300	10	10	B2	10	10	B2	8	8	8	8
06200500	16	25	B2	16	25	B2	4	3	4	3
06200580	25			3			3			
07200750	35	70	B2	35	70	B2	2	1/0	2	1/0
07200940				1			1			
07201170				70			1/0		1/0	
08201490	95	2 x 70	B2	95	2 x 70	B2	3/0	2 x 1	3/0	2 x 1
08201800	2 x 70			2 x 1			2 x 1			
09202160	2 x 70	2 x 185	B1	2 x 95	2 x 150	B2	2 x 2/0	2 x 500	2 x 2/0	2 x 350
09202660	2 x 95			2 x 4/0			2 x 4/0			
10203250	2 x 120	2 x 185	B1	2 x 120	2 x 150	C	2 x 250	2 x 500	2 x 250	2 x 350
10203600	2 x 150		C	2 x 120			2 x 300		2 x 300	

Table 4-15 Cable ratings (400 V)

Model	Cable size (IEC) mm ²						Cable size (UL) AWG			
	Input			Output			Input		Output	
	Nominal	Maximum	Installation method	Nominal	Maximum	Installation method	Nominal	Maximum	Nominal	Maximum
03400034	1.5	4	B2	1.5	4	B2	18	10	18	10
03400045				16			16			
03400062				14			14			
03400077									2.5	
03400104	2.5	6	B2	2.5	6	B2	12	8	12	8
03400123				4			4			
04400185	4	6	B2	4	6	B2	10	8	10	8
04400240	6			8			8			
05400300	6	6	B2	6	6	B2	8	8	8	8
06400380	10	25	B2	10	25	B2	6	3	6	3
06400480	16			4			4			
06400630	25			3			3			
07400790	35	70	B2	35	70	B2	1	1/0	1	1/0
07400940	50			2			2			
07401120	70			1/0			1/0			
08401550	2 x 50	2 x 70	B2	2 x 50	2 x 70	B2	2 x 1	2 x 1/0	2 x 1	2 x 1/0
08401840	2 x 70			2 x 1/0			2 x 1/0			
09402210	2 x 70	2 x 185	B1	2 x 95	2 x 150	B2	2 x 3/0	2 x 500	2 x 2/0	2 x 350
09402660	2 x 95			2 x 4/0			2 x 4/0			
10403200	2 x 120	2 x 185	C	2 x 120	2 x 150	C	2 x 300	2 x 500	2 x 250	2 x 350
10403610	2 x 150			2 x 150			2 x 350		2 x 300	
11404370	4 x 95	C	C	2 x 185	2 x 185	C	4 x 3/0		2 x 400	
11404870				2 x 240			2 x 240	4 x 4/0		
11405070				2 x 240	2 x 240		4 x 4/0			

Table 4-16 Cable ratings (575 V)

Model	Cable size (IEC) mm ²						Cable size (UL) AWG			
	Input			Output			Input		Output	
	Nominal	Maximum	Installation method	Nominal	Maximum	Installation method	Nominal	Maximum	Nominal	Maximum
05500039	0.75	1.5	B2	0.75	1.5	B2	16	16	16	16
05500061	1			1			14		14	
05500100	1.5			1.5			14		14	
06500120	2.5	25	B2	2.5	25	B2	14	3	14	3
06500170	4			4			10		10	
06500220	6			6			10		10	
06500270	10			10			8		8	
06500340							6		6	
06500430							16		6	
07500530	16	25	B2	16	25	B2	4	3	4	3
07500730	25			25			3		3	
08500860	35	50	B2	35	50	B2	1	1	1	1
08501080	50			50			1		1	
09501250	2 x 70	2 x 185	B2	2 x 35	2 x 150	B2	2 x 1	2 x 500	2 x 3	2 x 350
09501500				2 x 50					2 x 1	
10502000	2 x 70	2 x 185	B2	2 x 70	2 x 150	B2	2 x 2/0	2 x 500	2 x 2/0	2 x 350
11502480	2 x 70		C	2 x 70		C	2 x 3/0			
11502880	2 x 95			2 x 95			2 x 4/0			
11503150	2 x 120			2 x 120			2 x 250			

Table 4-17 Cable ratings (690 V)

Model	Cable size (IEC) mm ²						Cable size (UL) AWG			
	Input			Output			Input		Output	
	Nominal	Maximum	Installation method	Nominal	Maximum	Installation method	Nominal	Maximum	Nominal	Maximum
07600230	10	25	B2	10	25	B2	8	3	8	3
07600300				6			6			
07600360				6			6			
07600460				4			4			
07600520				4			4			
07600730				25			3		3	
08600860	50	70	B2	50	70	B2	2	1/0	2	1/0
08601080	70			70			1/0		1/0	
09601250	2 x 50	2 x 185	B2	2 x 35	2 x 150	B2	2 x 1	2 x 500	2 x 3	2 x 350
09601550	2 x 70			2 x 50			2 x 1/0		2 x 1	
10601720	2 x 70	2 x 185	B2	2 x 70	2 x 150	B2	2 x 2/0	2 x 500	2 x 1/0	2 x 350
10601970	2 x 95						2 x 3/0		2 x 2/0	
11602250	2 x 70		C	2 x 70		C	2 x 3/0			
11602750	2 x 95			2 x 95			2 x 4/0			
11603050				2 x 95			2 x 250			

NOTE

PVC insulated cable should be used.

NOTE

Cable sizes are from IEC60364-5-52:2001 table A.52.C with correction factor for 40°C ambient of 0.87 (from table A52.14) for cable installation method as specified.

Installation class (ref: IEC60364-5-52:2001)

- B1 - Separate cables in conduit.
- B2 - Multicore cable in conduit.
- C - Multicore cable in free air.

Cable size may be reduced if a different installation method is used, or if the ambient temperature is lower.

NOTE

The nominal output cable sizes assume that the motor maximum current matches that of the drive. Where a motor of reduced rating is used the cable rating may be chosen to match that of the motor. To ensure that the motor and cable are protected against overload, the drive must be programmed with the correct motor rated current. A fuse or other protection must be included in all live connections to the AC supply.

Fuse types

The fuse voltage rating must be suitable for the drive supply voltage.

Ground connections

The drive must be connected to the system ground of the AC supply. The ground wiring must conform to local regulations and codes of practice.

NOTE

For information on ground cable sizes, refer to Table 4-13 *Size 11E ground connections* on page 96.

4.8.1 Main AC supply contactor

The recommended AC supply contactor type for size 3 and 10 is AC1.

4.9 Output circuit and motor protection

The output circuit has fast-acting electronic short-circuit protection which limits the fault current to typically no more than five times the rated output current, and interrupts the current in approximately 20 µs. No additional short-circuit protection devices are required.

The drive provides overload protection for the motor and its cable. For this to be effective, *Rated Current (00.020)* must be set to suit the motor.



Rated Current (00.020) must be set correctly to avoid a risk of fire in the event of motor overload.

There is also provision for the use of a motor thermistor to prevent overheating of the motor, e.g. due to loss of cooling.

4.9.1 Cable types and lengths

Since capacitance in the motor cable causes loading on the output of the drive, ensure the cable length does not exceed the values given in Table 4-18 to section 4-21.

Use 105 °C (221 °F) (UL 60/75 °C temp rise) PVC-insulated cable with copper conductors having a suitable voltage rating, for the following power connections:

- AC supply to external EMC filter (when used)
- AC supply (or external EMC filter) to drive
- Drive to motor
- Drive to braking resistor

Table 4-18 Maximum motor cable lengths (200 V drives)

200 V Nominal AC supply voltage							
Model	Maximum permissible motor cable length for each of the following switching frequencies						
	2 kHz	3 kHz	4 kHz	6 kHz	8 kHz	12 kHz	16 kHz
03200066	65 m (210 ft)						
03200080	100 m (330 ft)						
03200110	130 m (425 ft)			100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)
03200127	200 m (660 ft)	150 m (490 ft)					
04200180	200 m (660 ft)	150 m (490 ft)	100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)	
04200250		150 m (490 ft)		100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)
05200300	200 m (660 ft)	150 m (490 ft)	100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)	
06200500	200 m (660 ft)	150 m (490 ft)	100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)	
06200580		150 m (490 ft)		100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)
07200750	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
07200940		187 m (614 ft)		125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)
07201170		187 m (614 ft)		125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)
08201490	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
08201800		187 m (614 ft)		125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)
09202160	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
09202660		187 m (614 ft)		125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)
10203250	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
10203600		187 m (614 ft)		125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)

Table 4-19 Maximum motor cable lengths (400 V drives)

400 V Nominal AC supply voltage							
Model	Maximum permissible motor cable length for each of the following switching frequencies						
	2 kHz	3 kHz	4 kHz	6 kHz	8 kHz	12 kHz	16 kHz
03400034	65 m (210 ft)						
03400045	100 m (330 ft)						
03400062	130 m (425 ft)			100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)
03400077	200 m (660 ft)		150 m (490 ft)				
03400104	200 m (660 ft)	150 m (490 ft)		100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)
03400123		150 m (490 ft)		100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)
04400185	200 m (660 ft)	150 m (490 ft)	100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)	
04400240		150 m (490 ft)		100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)
05400300	200 m (660 ft)	150 m (490 ft)	100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)	
06400380	200 m (660 ft)	150 m (490 ft)	100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)	
06400480		150 m (490 ft)		100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)
06400630		150 m (490 ft)		100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)
07400790	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
07400940		187 m (614 ft)		125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)
07401120		187 m (614 ft)		125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)
08401550	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
08401840		187 m (614 ft)		125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)
09402210	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
09402660		187 m (614 ft)		125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)
10403200	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
10403610		187 m (614 ft)		125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)
11404370	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)			
11404870		187 m (614 ft)		125 m (410 ft)	93 m (305 ft)		
11405070		187 m (614 ft)		125 m (410 ft)	93 m (305 ft)		

For Frame 12 Drives consult with the Unidrive M Power Module Frame 12 Power Installation Guide.

Table 4-20 Maximum motor cable lengths (575 V drives)

575 V Nominal AC supply voltage							
Model	Maximum permissible motor cable length for each of the following switching frequencies						
	2 kHz	3 kHz	4 kHz	6 kHz	8 kHz	12 kHz	16 kHz
05500039	200 m (660 ft)	150 m (490 ft)	100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)	
05500061							
05500100							
06500120	200 m (660 ft)	150 m (490 ft)	100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)	
06500170							
06500220							
06500270							
06500340							
06500430							
07500530	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
07500730							
08500860	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
08501080							
09501250	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
09501500							
10502000	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
11502480							
11502880	250 m (820 ft)	187 m (614 ft)					
11503150							

Table 4-21 Maximum motor cable lengths (690 V drives)

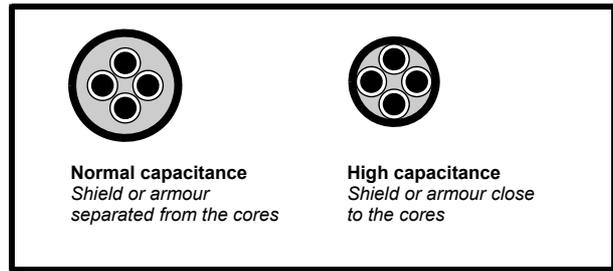
690 V Nominal AC supply voltage							
Model	Maximum permissible motor cable length for each of the following switching frequencies						
	2 kHz	3 kHz	4 kHz	6 kHz	8 kHz	12 kHz	16 kHz
07600230	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
07600300							
07600360							
07600460							
07600520							
07600730							
08600860	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
08601080							
09601250	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
09601550							
10601720	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
10601970							
11602250	250 m (820 ft)	187 m (614 ft)					
11602750							
11603050							

4.9.2 High-capacitance / reduced diameter cables

The maximum cable length is reduced from that shown in Section 4.9.1 *Cable types and lengths* if high capacitance or reduced diameter motor cables are used.

Most cables have an insulating jacket between the cores and the armor or shield; these cables have a low capacitance and are recommended. Cables that do not have an insulating jacket tend to have high capacitance; if a cable of this type is used, the maximum cable length is half that quoted in the tables, (Figure 4-22 shows how to identify the two types).

Figure 4-22 Cable construction influencing the capacitance



The maximum motor cable lengths specified in Section 4.9.1 *Cable types and lengths* is shielded and contains four cores. Typical capacitance for this type of cable is 130 pF/m (i.e. from one core to all others and the shield connected together).

4.9.3 Motor winding voltage

The PWM output voltage can adversely affect the inter-turn insulation in the motor. This is because of the high rate of change of voltage, in conjunction with the impedance of the motor cable and the distributed nature of the motor winding.

For normal operation with AC supplies up to 500 Vac and a standard motor with a good quality insulation system, there is no need for any special precautions. In case of doubt the motor supplier should be consulted. Special precautions are recommended under the following conditions, but only if the motor cable length exceeds 10 m:

- AC supply voltage exceeds 500 V
- DC supply voltage exceeds 670 V (i.e. regenerative / AFE supply)
- Operation of 400 V drive with continuous or very frequent sustained braking
- Multiple motors connected to a single drive

For multiple motors, the precautions given in section 4.9.4 *Multiple motors* on page 113 should be followed.

For the other cases listed, it is recommended that an inverter-rated motor be used taking into account the voltage rating of the inverter. This has a reinforced insulation system intended by the manufacturer for repetitive fast-rising pulsed voltage operation.

Users of 575 V NEMA rated motors should note that the specification for inverter-rated motors given in NEMA MG1 section 31 is sufficient for motoring operation but not where the motor spends significant periods braking. In that case an insulation peak voltage rating of 2.2 kV is recommended.

If it is not practical to use an inverter-rated motor, an output choke (inductor) should be used. The recommended type is a simple iron-cored component with a reactance of about 2 %. The exact value is not critical. This operates in conjunction with the capacitance of the motor cable to increase the rise-time of the motor terminal voltage and prevent excessive electrical stress.

4.9.4 Multiple motors

Open-loop only

If the drive is to control more than one motor, one of the fixed V/F modes should be selected (Pr **05.014** = Fixed or Squared). Make the motor connections as shown in Figure 4-23 and Figure 4-24. The maximum motor cable lengths specified in section 4.9.1 *Cable types and lengths* on page 112 apply to the sum of the total cable lengths from the drive to each motor.

It is recommended that each motor is connected through a protection relay since the drive cannot protect each motor individually. For Δ connection, a sinusoidal filter or an output inductor must be connected as shown in Figure 4-24, even when the cable lengths are less than the maximum permissible. For details of inductor sizes refer to the supplier of the drive.

Figure 4-23 Preferred chain connection for multiple motors

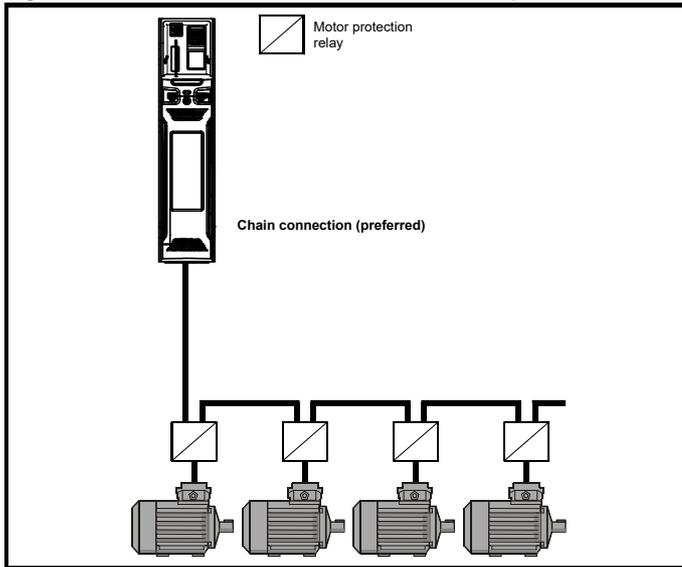
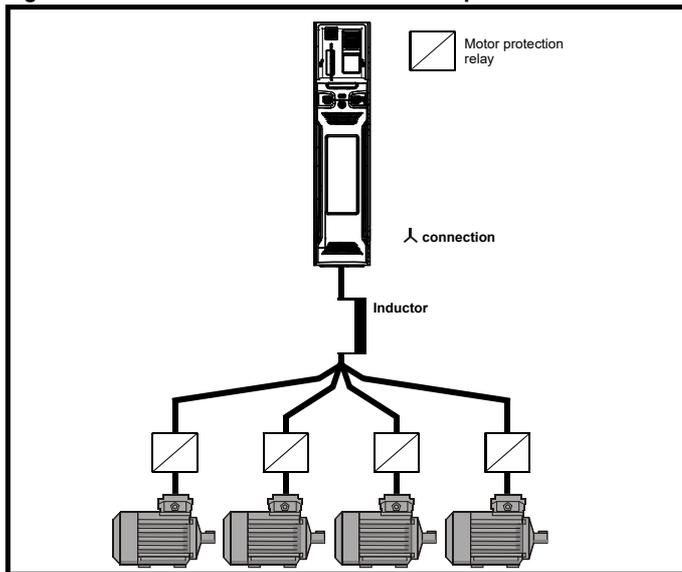


Figure 4-24 Alternative connection for multiple motors



4.9.5 Δ / Δ motor operation

The voltage rating for Δ and Δ connections of the motor should always be checked before attempting to run the motor.

The default setting of the motor rated voltage parameter is the same as the drive rated voltage, i.e.

400 V drive 400 V rated voltage
230 V drive 230 V rated voltage

A typical 3 phase motor would be connected in Δ for 400 V operation or Δ for 230 V operation, however, variations on this are common e.g. Δ 690 V Δ 400 V.

Incorrect connection of the windings will cause severe under or over fluxing of the motor, leading to a very poor output torque or motor saturation and overheating respectively.

4.9.6 Output contactor

WARNING If the cable between the drive and the motor is to be interrupted by a contactor or circuit breaker, ensure that the drive is disabled before the contactor or circuit breaker is opened or closed. Severe arcing may occur if this circuit is interrupted with the motor running at high current and low speed.

A contactor is sometimes required to be installed between the drive and motor for safety purposes.

The recommended motor contactor is the AC3 type.

Switching of an output contactor should only occur when the output of the drive is disabled.

Opening or closing of the contactor with the drive enabled will lead to:

1. OI ac trips (which cannot be reset for 10 seconds)
2. High levels of radio frequency noise emission
3. Increased contactor wear and tear

The Drive Enable terminal (T31) when opened provides a Safe Torque Off function. This can in many cases replace output contactors.

For further information see section 4.15 *Safe Torque Off (STO)* on page 130.

4.10 Ground leakage

The ground leakage current depends upon whether the internal EMC filter is installed or not. The drive is supplied with the filter installed. Instructions for removing the internal filter are given in section 4.11.2 *Internal EMC filter* on page 118.

With internal filter installed:

Size 3 to 5: 28 mA* AC at 400 V 50 Hz
30 μ A DC with a 600 V DC bus (10 M Ω)

Size 7 to 11: 56 mA* AC at 400 V 50 Hz
18 μ A DC with a 600 V DC bus (33 M Ω)

Size 12: 18 mA* AC at 400 V 50 Hz with internal filter in circuit

* Proportional to the supply voltage and frequency.

With internal filter removed:**

<1 mA
Size 12: <63 mA

**Please note that the internal filter is not removable on size 9E, 10E and 11E



When the internal filter is installed the leakage current is high. In this case a permanent fixed ground connection must be provided, or other suitable measures taken to prevent a safety hazard occurring if the connection is lost.

4.10.1 Use of residual current device (RCD)

There are three common types of ELCB / RCD:

1. AC - detects AC fault currents
2. A - detects AC and pulsating DC fault currents (provided the DC current reaches zero at least once every half cycle)
3. B - detects AC, pulsating DC and smooth DC fault currents
 - Type AC should never be used with drives.
 - Type A can only be used with single phase drives
 - Type B must be used with three phase drives



Only type B ELCB / RCD are suitable for use with 3 phase inverter drives.

If an external EMC filter is used, a delay of at least 50 ms should be incorporated to ensure spurious trips are not seen. The leakage current is likely to exceed the trip level if all of the phases are not energized simultaneously.

4.11 EMC (Electromagnetic compatibility)

The requirements for EMC are divided into three levels in the following three sections:

Section 4.11.4, General requirements for all applications, to ensure reliable operation of the drive and minimise the risk of disturbing nearby equipment. The immunity standards specified in Chapter 12 *Technical data* on page 279 will be met, but no specific emission standards are applied. Note also the special requirements given in *Surge immunity of control circuits - long cables and connections outside a building* on page 124 for increased surge immunity of control circuits where control wiring is extended.

Section 4.11.5, Requirements for meeting the EMC standard for power drive systems, IEC61800-3 (EN 61800-3:2004).

Section 4.11.6, Requirements for meeting the generic emission standards for the industrial environment, IEC61000-6-4, EN 61000-6-4:2007.

The recommendations of section 4.11.4 will usually be sufficient to avoid causing disturbance to adjacent equipment of industrial quality. If particularly sensitive equipment is to be used nearby, or in a non-industrial environment, then the recommendations of section 4.11.5 or section 4.11.6 should be followed to give reduced radio-frequency emission.

In order to ensure the installation meets the various emission standards described in:

- The EMC data sheet available from the supplier of the drive
- The Declaration of Conformity at the front of this manual
- Chapter 12 *Technical data* on page 279

The correct external EMC filter must be used and all of the guidelines in section 4.11.4 *General requirements for EMC* on page 120 and section 4.11.6 *Compliance with generic emission standards* on page 121 must be followed.

Table 4-22 Drive and EMC filter cross reference

Model	CT part number
200 V	
03200066 to 03200127	4200-3230
04200180 to 04200250	4200-0272
05200300	4200-0312
06200500 to 06200580	4200-2300
07200750 to 07201170	4200-1132
08201490 to 08201800	4200-1972
09202160 to 09202660 (9A)	4200-3021
09202160 to 09202660 (9E)	4200-4460
10203250 to 10203600	4200-4460
400 V	
03400034 to 03400123	4200-3480
04400185 to 04400240	4200-0252
05400300	4200-0402
06400380 to 06400630	4200-4800
07400790 to 07401120	4200-1132
08401550 to 08401840	4200-1972
09402210 to 09402660 (9A)	4200-3021
09402210 to 09402660 (9E)	4200-4460
10403200 to 10403610	4200-4460
11404370 to 11405070	4200-0400

Model	CT part number
575 V	
05500039 to 05500100	4200-0122
06500120 to 06500430	4200-3690
07500530 to 07500730	4200-0672
08500860 to 08501080	4200-1662
09501250 to 09501500 (9A)	4200-1660
09501250 to 09501500 (9E)	4200-2210
10502000	4200-2210
11502480 to 11503150	4200-0690
690 V	
07600230 to 07600730	4200-0672
08600860 to 08601080	4200-1662
09601250 to 09601550 (9A)	4200-1660
09601250 to 09601550 (9E)	4200-2210
10601720 to 10601970	4200-2210
11602250 to 11603050	4200-0690



High ground leakage current

When an EMC filter is used, a permanent fixed ground connection must be provided which does not pass through a connector or flexible power cord. This includes the internal EMC filter.

NOTE

The installer of the drive is responsible for ensuring compliance with the EMC regulations that apply in the country in which the drive is to be used.

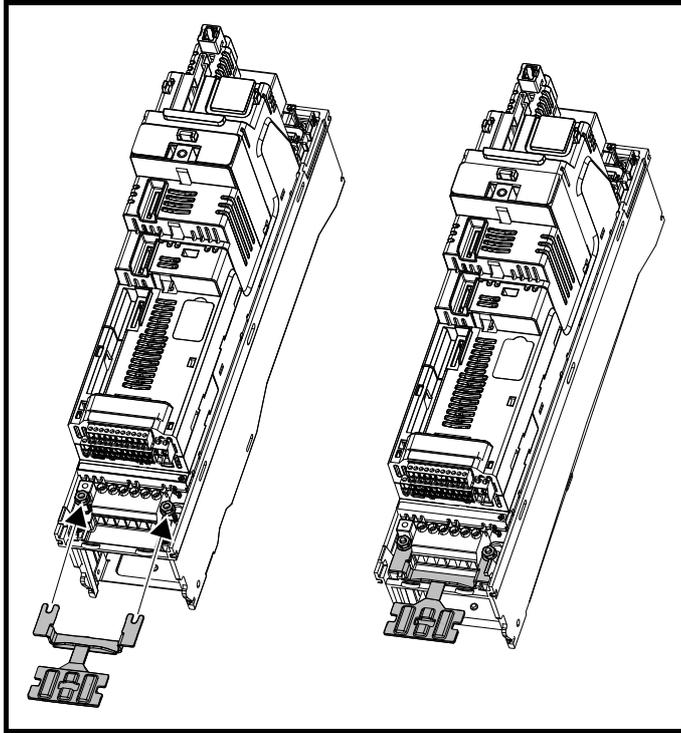
4.11.1 Grounding hardware

The drive is supplied with a grounding bracket and grounding clamp to facilitate EMC compliance. They provide a convenient method for direct grounding of cable shields without the use of "pig-tails". Cable shields can be bared and clamped to the grounding bracket using metal clips or clamps¹ (not supplied) or cable ties. Note that the shield must in all cases be continued through the clamp to the intended terminal on the drive, in accordance with the connection details for the specific signal.

¹ A suitable clamp is the Phoenix DIN rail mounted SK14 cable clamp (for cables with a maximum outer diameter of 14 mm).

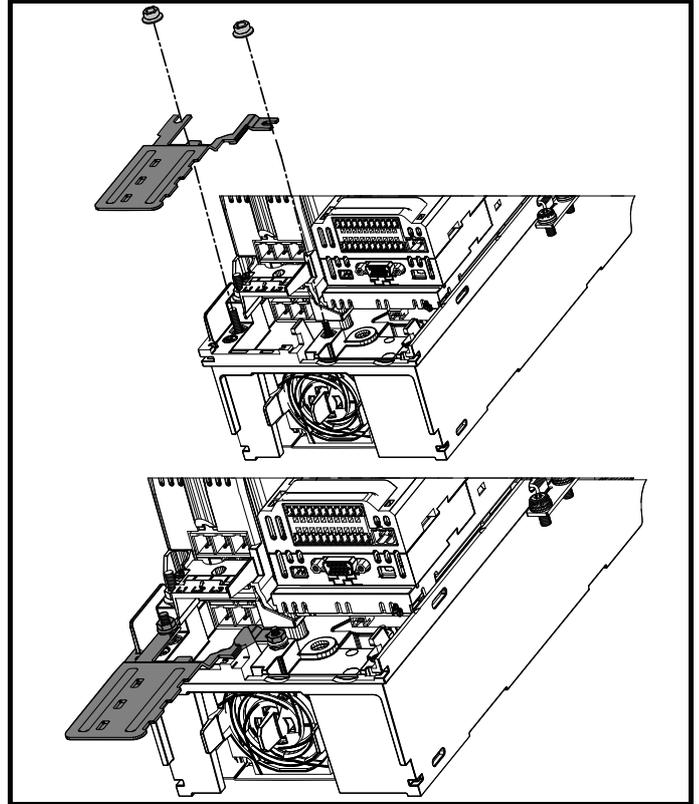
- See Figure 4-25, Figure 4-26 and Figure 4-27 for details on installing the grounding clamp.
- See Figure 4-28 for details on installing the grounding bracket.

Figure 4-25 Installation of grounding clamp (size 3 and 4)



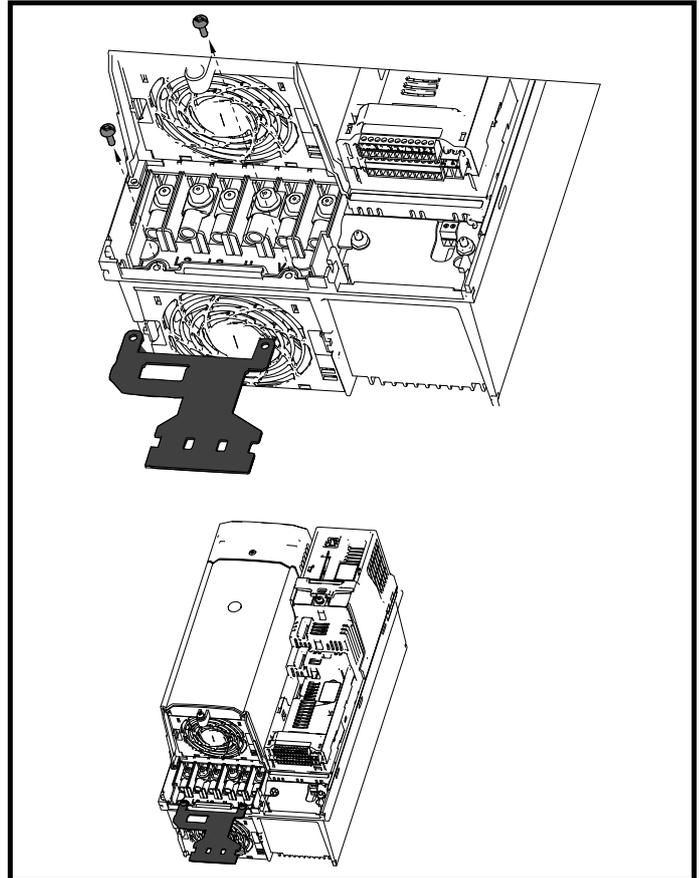
Loosen the ground connection nuts and slide the grounding clamp in the direction shown. Once in place, the ground connection nuts should be tightened with a maximum torque of 2 Nm (17.64 lb in).

Figure 4-26 Installation of grounding clamp (size 5)



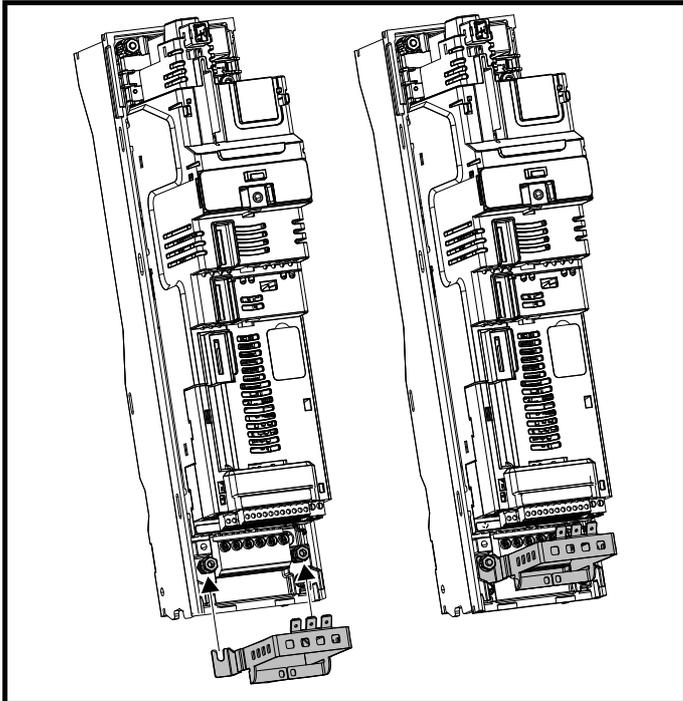
Loosen the ground connection nuts and slide the grounding clamp down onto the pillars in the direction shown. Once in place, the ground connection nuts should be tightened with a maximum torque of 2 Nm (17.64 lb in).

Figure 4-27 Installation of grounding clamp (size 6)



The grounding clamp is secured using the provided 2 x M4 x 10 mm fasteners. The fasteners should be tightened with the maximum torque of 2 Nm (17.64 lb in).

Figure 4-28 Installation of grounding bracket (all sizes -size 3 shown)



Loosen the ground connection nuts and slide the grounding bracket in the direction shown. Once in place, the ground connection nuts should be tightened with a maximum torque of 2 Nm (17.64 lb in).



WARNING On size 3 the grounding bracket is secured using the power ground terminal of the drive. Ensure that the supply ground connection is secure after installing / removing the grounding bracket. Failure to do so will result in the drive not being grounded.

A faston tab is located on the grounding bracket for the purpose of connecting the drive 0V to ground should the user require to do so.

4.11.2 Internal EMC filter

It is recommended that the internal EMC filter be kept in place unless there is a specific reason for removing it.



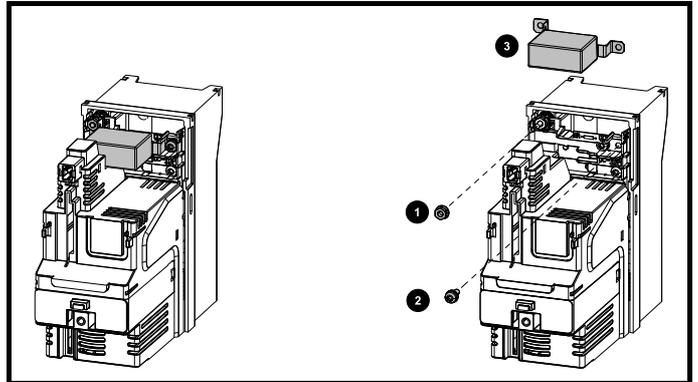
WARNING If the drive is used with ungrounded (IT) supplies, the internal EMC filter must be removed unless additional motor ground fault protection is installed. For instructions on removal refer to section 4.11.2. For details of ground fault protection contact the supplier of the drive.

The internal EMC filter reduces radio-frequency emission into the line power supply. Where the motor cable is short, it permits the requirements of EN 61800-3:2004 to be met for the second environment - see section 4.11.5 *Compliance with EN 61800-3:2004 (standard for Power Drive Systems)* on page 121 and section 12.1.24 *Electromagnetic compatibility (EMC)* on page 301. For longer motor cables the filter continues to provide a useful reduction in emission levels, and when used with any length of shielded motor cable up to the limit for the drive, it is unlikely that nearby industrial equipment will be disturbed. It is recommended that the filter be used in all applications unless the instructions given above require it to be removed, or where the ground leakage current of 28 mA for size 3 is unacceptable. See section 4.11.2 for details of removing and installing the internal EMC filter.



The supply must be disconnected before removing the internal EMC filter.

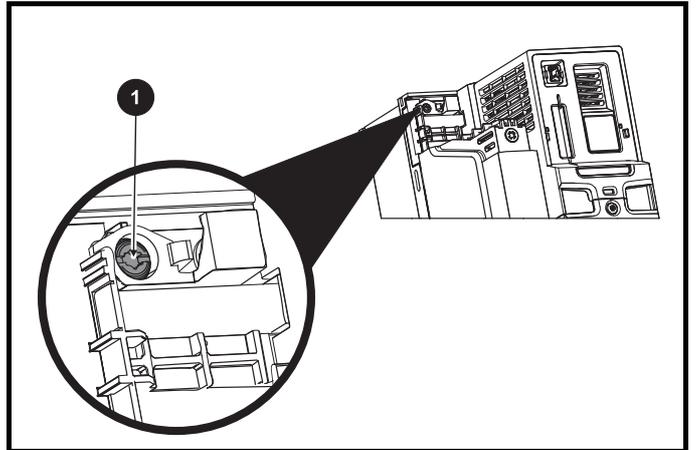
Figure 4-29 Removal of the size 3 internal EMC filter



Remove the screw and nut (1) and (2) as shown above.

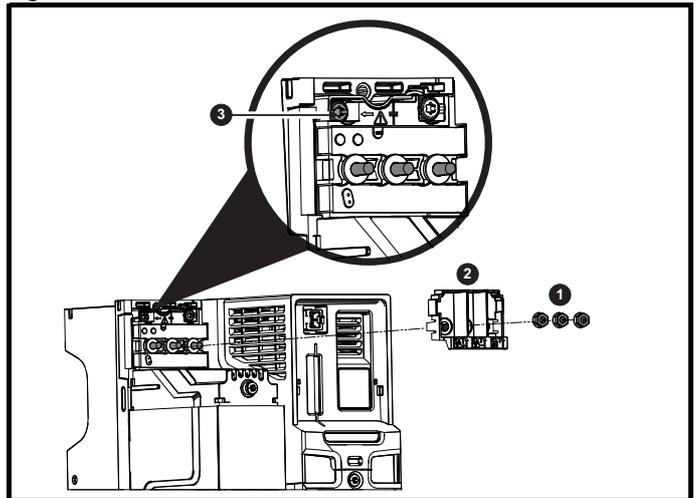
Lift away from the securing points and rotate away from the drive. Ensure the screw and nut are replaced and re-tightened with a maximum torque of 2 Nm (17.64 lb in).

Figure 4-30 Removal of the size 4 internal EMC filter



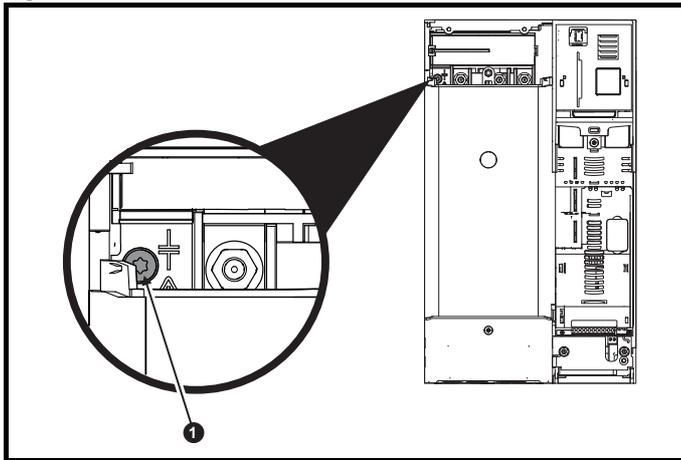
To electrically disconnect the Internal EMC filter, remove the screw as highlighted above (1).

Figure 4-31 Removal of the size 5 internal EMC filter



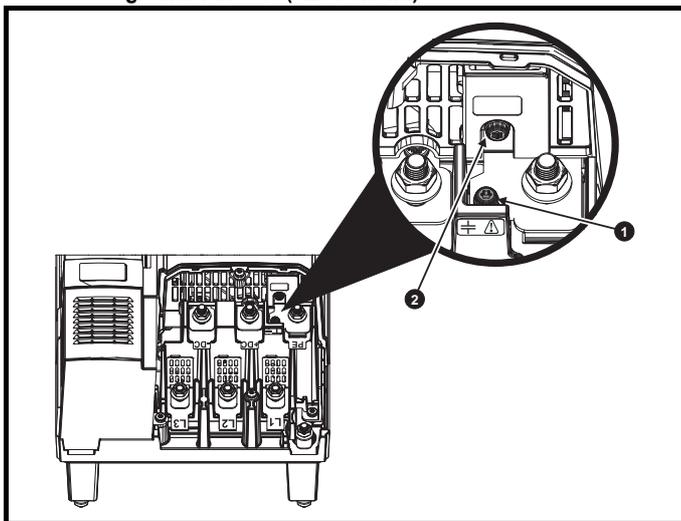
Remove the three M4 terminal nuts (1). Lift away the cover (2) to expose the M4 Torx internal EMC filter removal screw. Finally remove the M4 Torx internal EMC filter removal screw (3) to electrically disconnect the internal EMC filter.

Figure 4-32 Removal of the size 6 internal EMC filter



To electrically disconnect the Internal EMC filter, remove the screw as highlighted above (1).

Figure 4-33 Removal of the size 7, 8 and 9A internal EMC filter and line to ground varistors (size 7 shown)



To electrically disconnect the Internal EMC filter, remove the screw as highlighted above (1).

To electrically disconnect the line to ground varistors, remove the screw as highlighted above (2)

NOTE

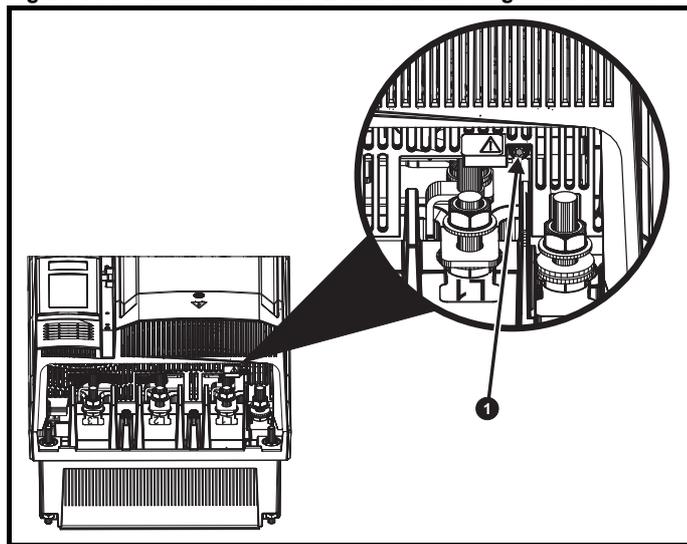
The Internal EMC filter on size 9E, 10E and 11E cannot be removed.

4.11.3 Line to ground varistors



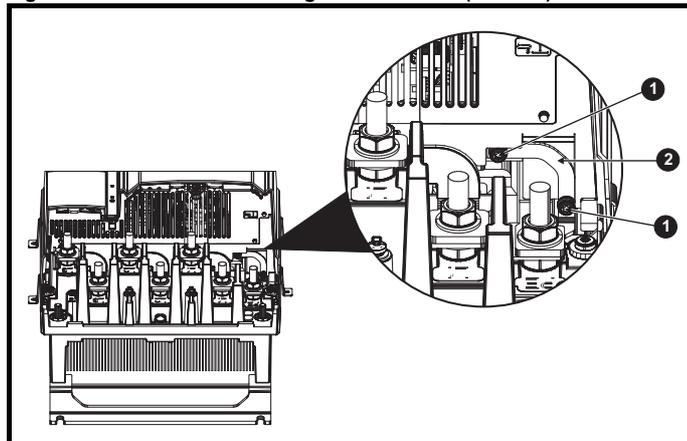
The line to ground varistors should only be removed in special circumstances such as ungrounded supplies with more than one source, for example on ships. Where the line to ground varistors are removed, ensure that line to ground transients are limited to values of category II. This is to ensure that line to ground transients do not exceed 4 kV as the drive insulation system from power to ground is designed to category II. Contact the supplier of the drive for more information.

Figure 4-34 Removal of size 9E and 10E line to ground varistors



To electrically disconnect the line to ground varistors, remove the screw as highlighted above (1).

Figure 4-35 Removal of line to ground varistors (size 11E)



To electrically disconnect the line to ground varistors, remove the two screws highlighted (1) above and remove the bracket (2).

NOTE

The line to ground varistors should only be removed in special circumstances.

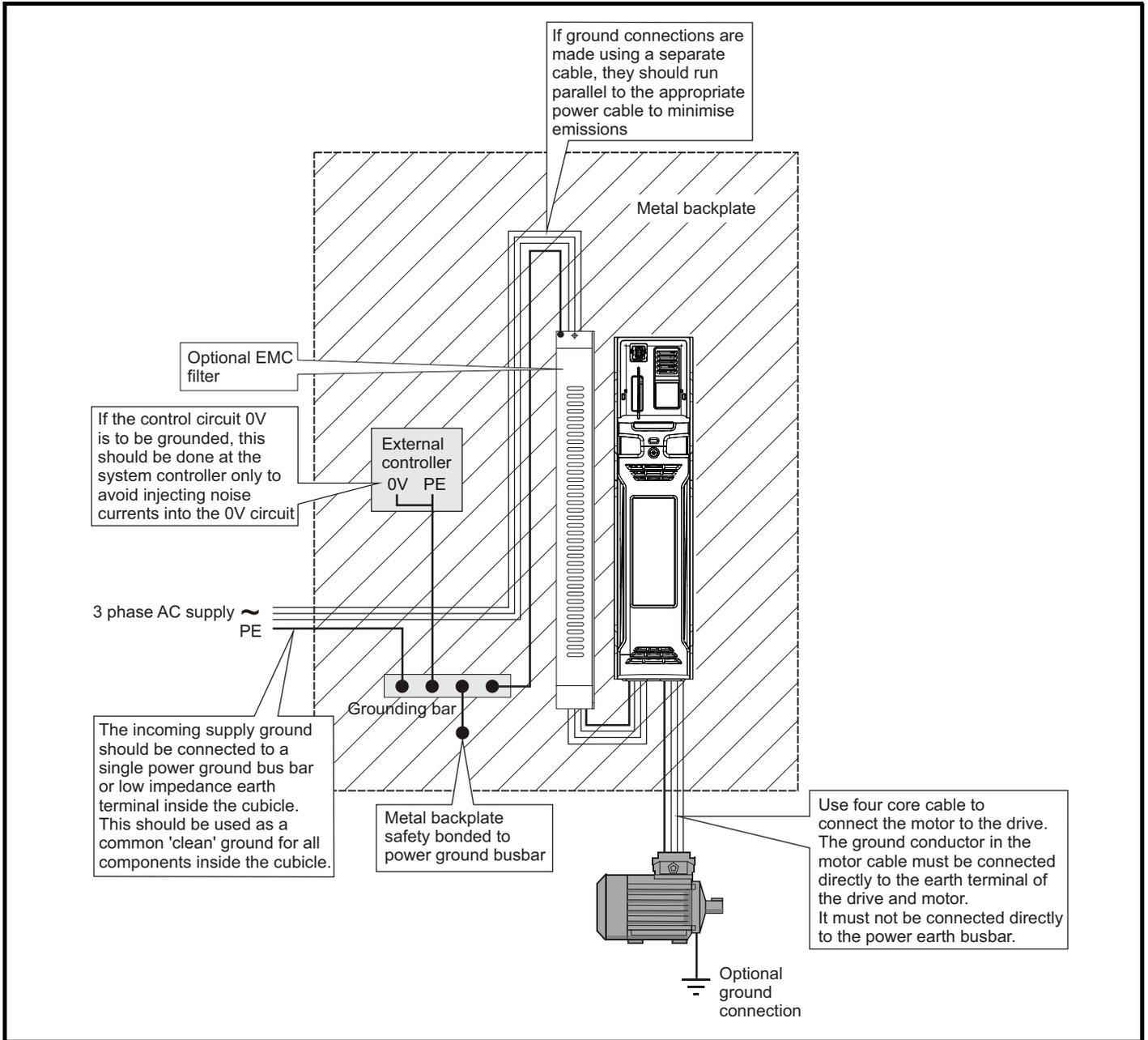
4.11.4 General requirements for EMC

Ground (earth) connections

The grounding arrangements should be in accordance with Figure 4-36, which shows a single drive on a back-plate with or without an additional enclosure.

Figure 4-36 shows how to configure and minimise EMC when using unshielded motor cable. However shielded cable is a better option, in which case it should be installed as shown in section 4.11.6 *Compliance with generic emission standards* on page 121.

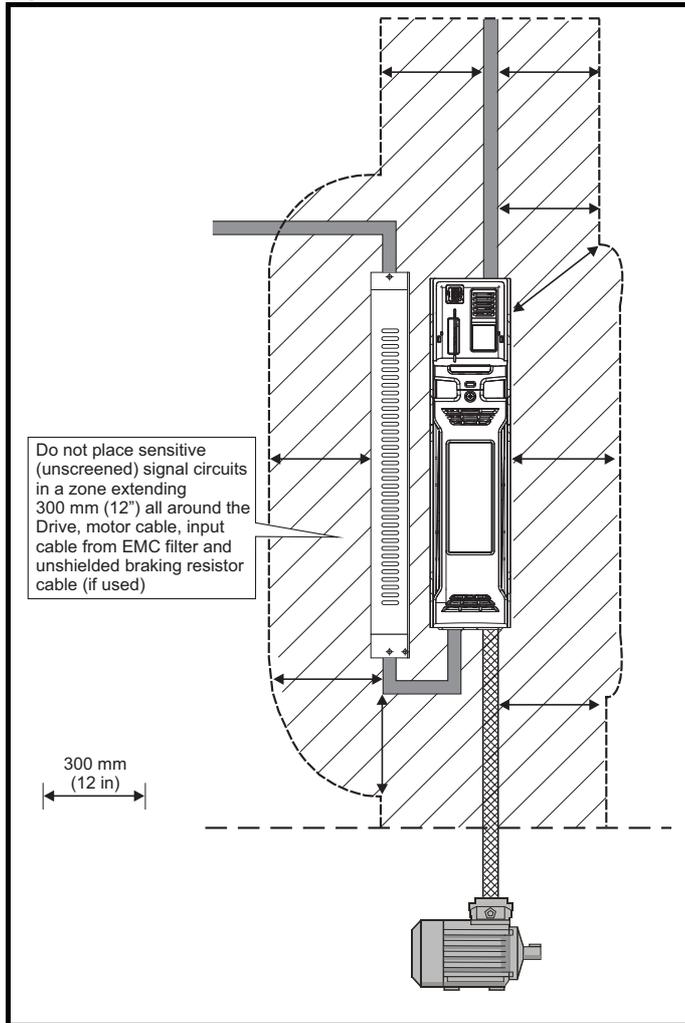
Figure 4-36 General EMC enclosure layout showing ground connections



Cable layout

Figure 4-37 indicates the clearances which should be observed around the drive and related 'noisy' power cables by all sensitive control signals / equipment.

Figure 4-37 Drive cable clearances



NOTE

Any signal cables which are carried inside the motor cable (i.e. motor thermistor) will pick up large pulse currents via the cable capacitance. The shield of these signal cables must be connected to ground close to the motor cable, to avoid this noise current spreading through the control system.

4.11.5 Compliance with EN 61800-3:2004 (standard for Power Drive Systems)

Meeting the requirements of this standard depends on the environment that the drive is intended to operate in, as follows:

Operation in the first environment

Observe the guidelines given in section 4.11.6 *Compliance with generic emission standards* on page 121. An external EMC filter will always be required.



This is a product of the restricted distribution class according to IEC 61800-3

In a residential environment this product may cause radio interference in which case the user may be required to take adequate measures.

Operation in the second environment

In all cases a shielded motor cable must be used, and an EMC filter is required for all drives with a rated input current of less than 100 A.

The drive contains an in-built filter for basic emission control. In some cases feeding the motor cables (U, V and W) once through a ferrite ring can maintain compliance for longer cable lengths.

For longer motor cables, an external filter is required. Where a filter is required, follow the guidelines in Section 4.11.6 *Compliance with generic emission standards*.

Where a filter is not required, follow the guidelines given in section 4.11.4 *General requirements for EMC* on page 120.



CAUTION

The second environment typically includes an industrial low-voltage power supply network which does not supply buildings used for residential purposes. Operating the drive in this environment without an external EMC filter may cause interference to nearby electronic equipment whose sensitivity has not been appreciated. The user must take remedial measures if this situation arises. If the consequences of unexpected disturbances are severe, it is recommended that the guidelines in Section 4.11.6 *Compliance with generic emission standards* be adhered to.

Refer to section 12.1.24 *Electromagnetic compatibility (EMC)* on page 301 for further information on compliance with EMC standards and definitions of environments.

Detailed instructions and EMC information are given in the *EMC Data Sheet* which is available from the supplier of the drive.

4.11.6 Compliance with generic emission standards

The following information applies to frame sizes 3 to 10.

Use the recommended filter and shielded motor cable. Observe the layout rules given in Figure 4-38 and Figure 4-41. Ensure the AC supply and ground cables are at least 100 mm from the power module and motor cable.

Figure 4-38 Supply and ground cable clearance (sizes 3 to 6)

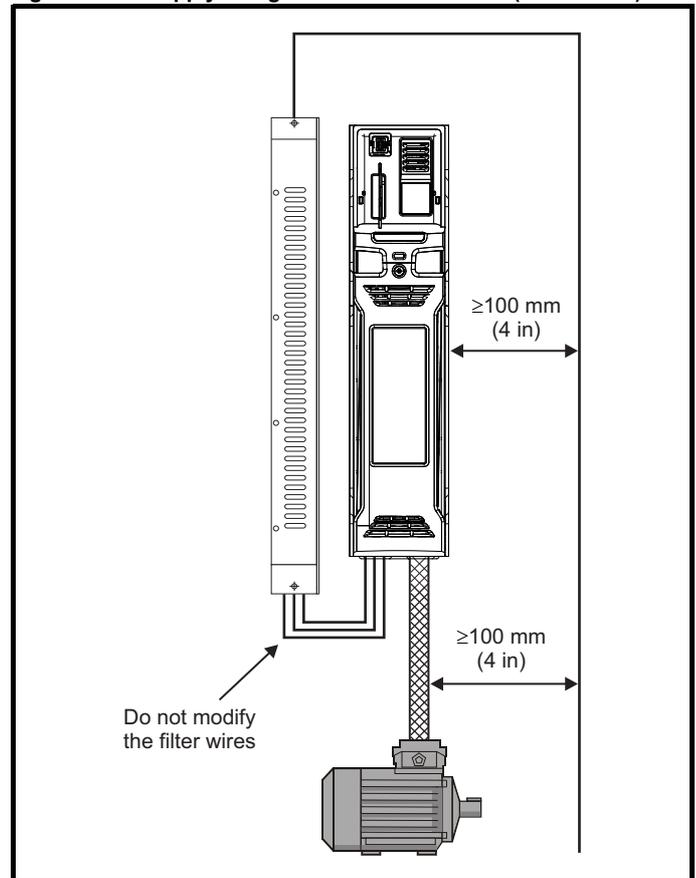
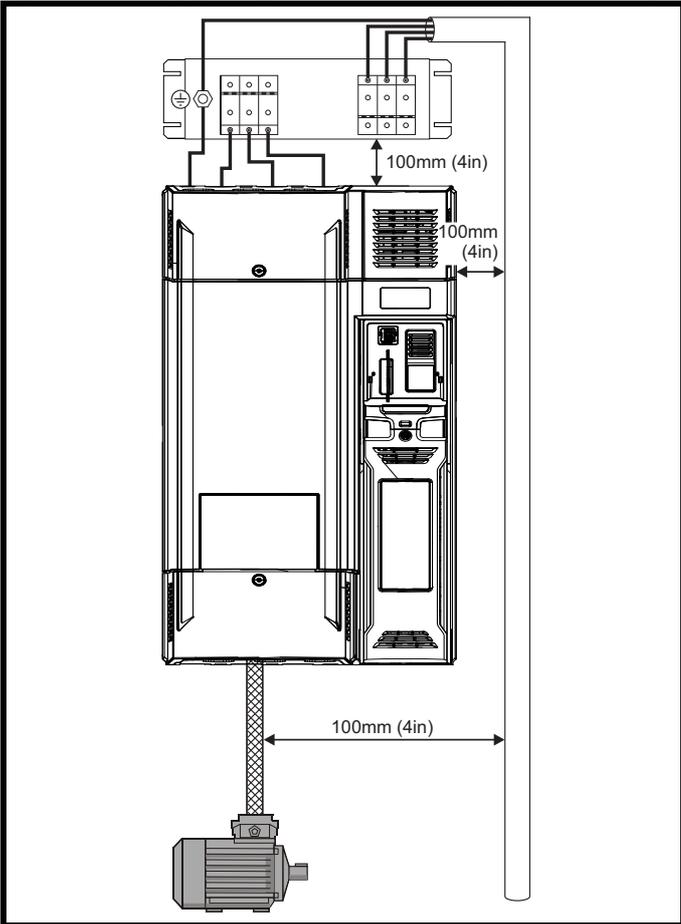
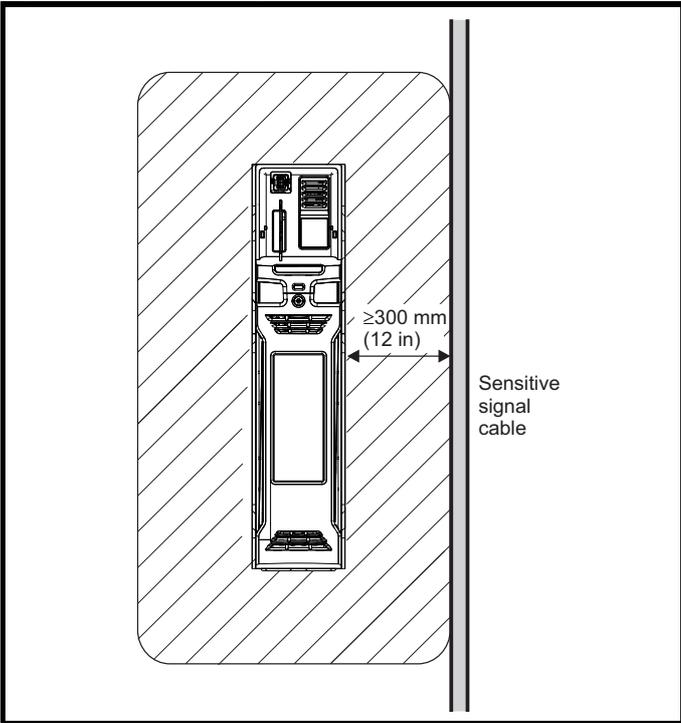


Figure 4-39 Supply and ground cable clearance (size 7 and larger)



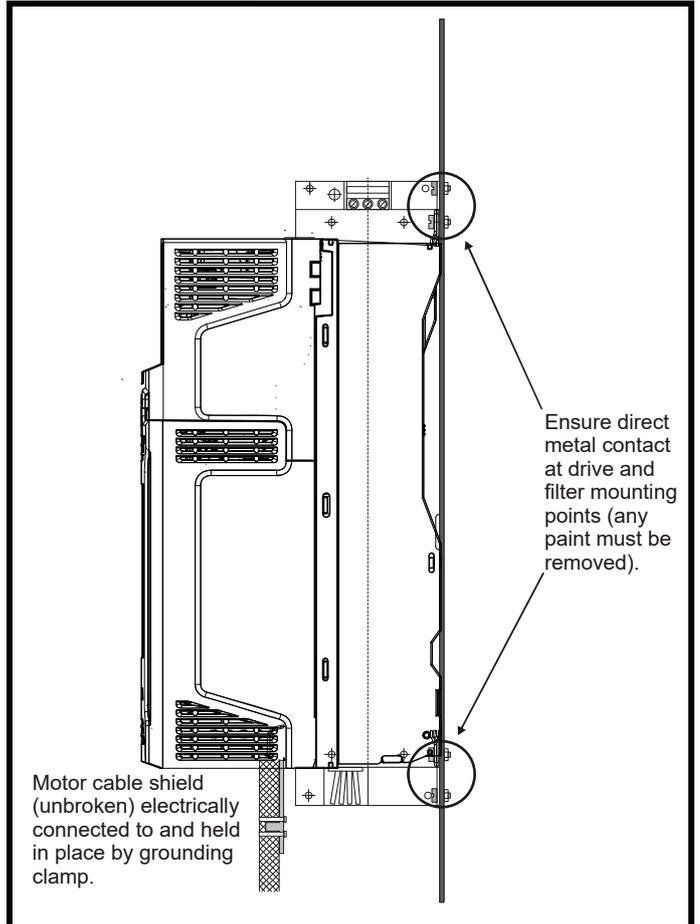
Ensure the AC supply and ground cables are at least 100 mm from the power module and motor cable.

Figure 4-40 Sensitive signal circuit clearance



Avoid placing sensitive signal circuits in a zone 300 mm (12 in) in the area immediately surrounding the power module. Ensure good EMC grounding.

Figure 4-41 Grounding the drive, motor cable shield and filter

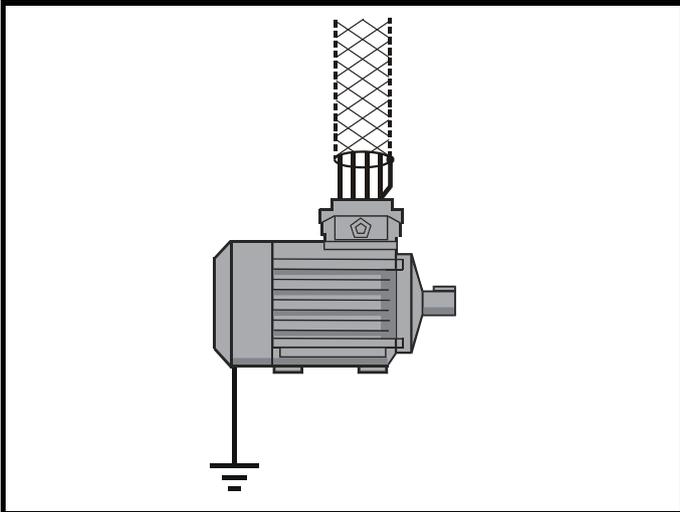


Connect the shield of the motor cable to the ground terminal of the motor frame using a link that is as short as possible and not exceeding 50 mm (2 in) long.

A complete 360° termination of the shield to the terminal housing of the motor is beneficial.

From an EMC consideration it is irrelevant whether the motor cable contains an internal (safety) ground core, or if there is a separate external ground conductor, or where grounding is through the shield alone. An internal ground core will carry a high noise current and therefore it must be terminated as close as possible to the shield termination.

Figure 4-42 Grounding the motor cable shield

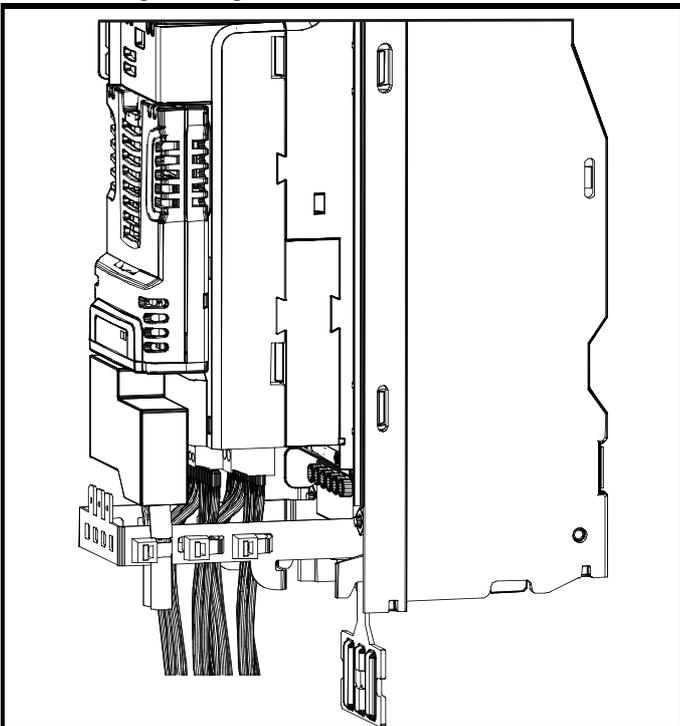


Unshielded wiring to the optional braking resistor(s) may be used provided the wiring runs internally to the enclosure.

If the control wiring is to leave the enclosure, it must be shielded and the shield(s) clamped to the drive using the grounding bracket as shown in Figure 4-43. Remove the outer insulating cover of the cable to ensure the shield(s) make direct contact with the bracket, but keep the shield(s) intact until as close as possible to the terminals

Alternatively, wiring may be passed through a ferrite ring, part number 3225-1004.

Figure 4-43 Grounding of signal cable shields using the grounding bracket



4.11.7 Variations in the EMC wiring

Interruptions to the motor cable

The motor cable should ideally be a single length of shielded or armored cable having no interruptions. In some situations it may be necessary to interrupt the cable, as in the following examples:

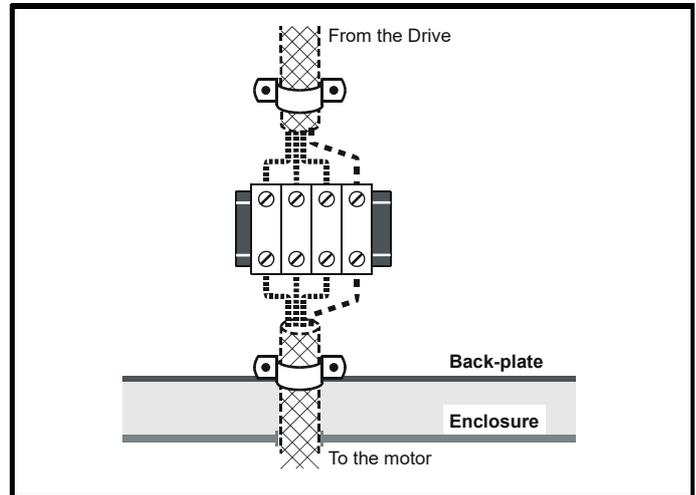
- Connecting the motor cable to a terminal block in the drive enclosure
- Installing a motor isolator / disconnect switch for safety when work is done on the motor

In these cases the following guidelines should be followed.

Terminal block in the enclosure

The motor cable shields should be bonded to the back-plate using uninsulated metal cable-clamps which should be positioned as close as possible to the terminal block. Keep the length of power conductors to a minimum and ensure that all sensitive equipment and circuits are at least 0.3 m (12 in) away from the terminal block.

Figure 4-44 Connecting the motor cable to a terminal block in the enclosure



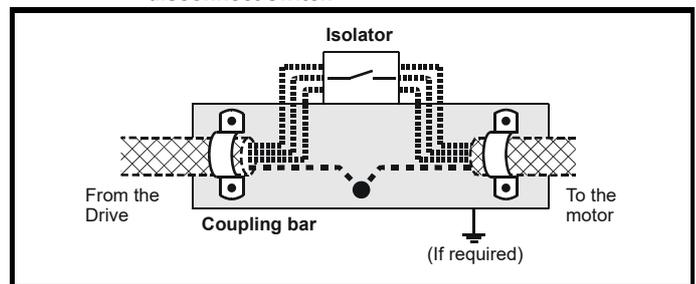
Using a motor isolator / disconnect-switch

The motor cable shields should be connected by a very short conductor having a low inductance. The use of a flat metal coupling-bar is recommended; conventional wire is not suitable.

The shields should be bonded directly to the coupling-bar using uninsulated metal cable-clamps. Keep the length of the exposed power conductors to a minimum and ensure that all sensitive equipment and circuits are at least 0.3 m (12 in) away.

The coupling-bar may be grounded to a known low-impedance ground nearby, for example a large metallic structure which is connected closely to the drive ground.

Figure 4-45 Connecting the motor cable to an isolator / disconnect switch



Surge immunity of control circuits - long cables and connections outside a building

The input/output ports for the control circuits are designed for general use within machines and small systems without any special precautions.

These circuits meet the requirements of EN 61000-6-2:2005 (1 kV surge) provided the 0V connection is not grounded.

In applications where they may be exposed to high-energy voltage surges, some special measures may be required to prevent malfunction or damage. Surges may be caused by lightning or severe power faults in association with grounding arrangements which permit high transient voltages between nominally grounded points. This is a particular risk where the circuits extend outside the protection of a building.

As a general rule, if the circuits are to pass outside the building where the drive is located, or if cable runs within a building exceed 30 m, some additional precautions are advisable. One of the following techniques should be used:

1. Galvanic isolation, i.e. do not connect the control 0V terminal to ground. Avoid loops in the control wiring, i.e. ensure every control wire is accompanied by its return (0V) wire.
2. Shielded cable with additional power ground bonding. The cable shield may be connected to ground at both ends, but in addition the ground conductors at both ends of the cable must be bonded together by a power ground cable (equipotential bonding cable) with cross-sectional area of at least 10 mm², or 10 times the area of the signal cable shield, or to suit the electrical safety requirements of the plant. This ensures that fault or surge current passes mainly through the ground cable and not in the signal cable shield. If the building or plant has a well-designed common bonded network this precaution is not necessary.
3. Additional over-voltage suppression - for the analog and digital inputs and outputs, a zener diode network or a commercially available surge suppressor may be connected in parallel with the input circuit as shown in Figure 4-46 and Figure 4-47.

If a digital port experiences a severe surge its protective trip may operate (I/O Overload trip). For continued operation after such an event, the trip can be reset automatically by setting Pr 10.034 to 5.

Figure 4-46 Surge suppression for digital and unipolar inputs and outputs

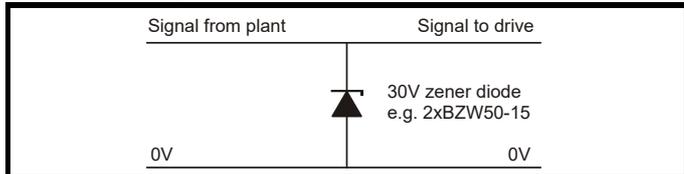
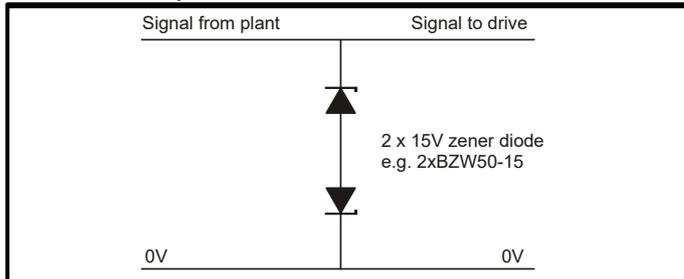


Figure 4-47 Surge suppression for analog and bipolar inputs and outputs



Surge suppression devices are available as rail-mounting modules, e.g. from Phoenix Contact:

- Unipolar TT-UKK5-D/24 DC
- Bipolar TT-UKK5-D/24 AC

These devices are not suitable for fast digital data networks, because the capacitance of the diodes adversely affects the signal. For data networks, follow the specific recommendations for the particular network.

4.12 Communications connections

The drive offers a double isolated 2 wire EIA-485 interface. The drive supports the Modbus RTU or BACnet MSTP protocols. See Table 4-23 for the connection details.

Figure 4-48 Location of the comms connector

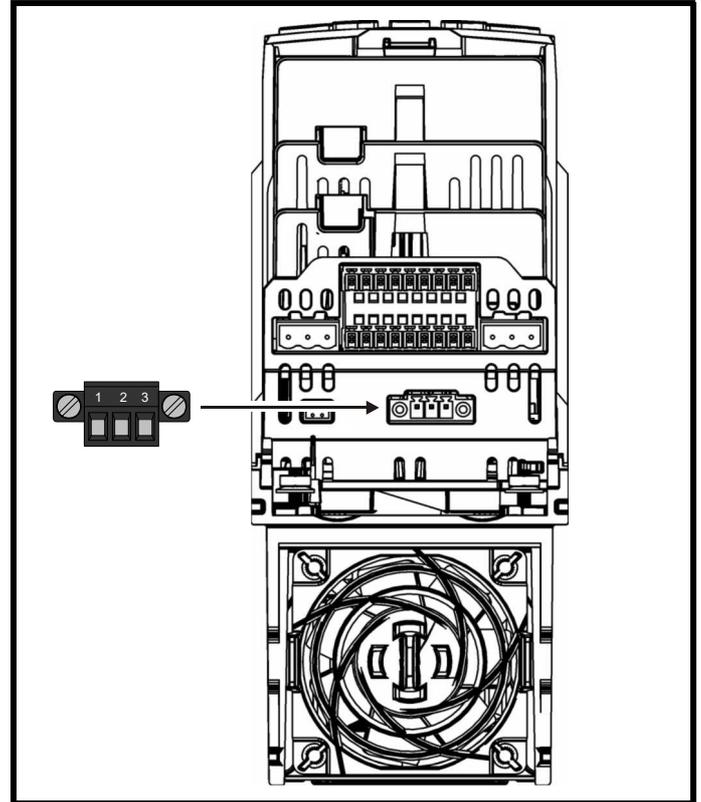


Table 4-23 Serial communication port pin-outs

Pin	Function
1	RX TX
2	Isolated 0V
3	RX\ TX\

4.12.1 Isolation of the EIA-485 serial communications port

The serial PC communications port is double insulated and meets the requirements for SELV in EN 50178:1998. Depending on network topology a termination resistor of 120 Ω maybe required.



WARNING

In order to meet the requirements for SELV in IEC60950 (IT equipment) it is necessary for the control computer to be grounded. Alternatively, when a lap-top or similar device is used which has no provision for grounding, an isolation device must be incorporated in the communications lead.

NOTE

This drive does not provide the necessary line polarization for correct operation of the EIA-485 port, the data lines (Rx Tx and /Rx /Tx) must be correctly biased in accordance with the relevant protocol specification, this is normally done in the communication master or controller. Please refer to the relevant communication protocol specification for more information.

USB/EIA-232 to EIA-485 Communications

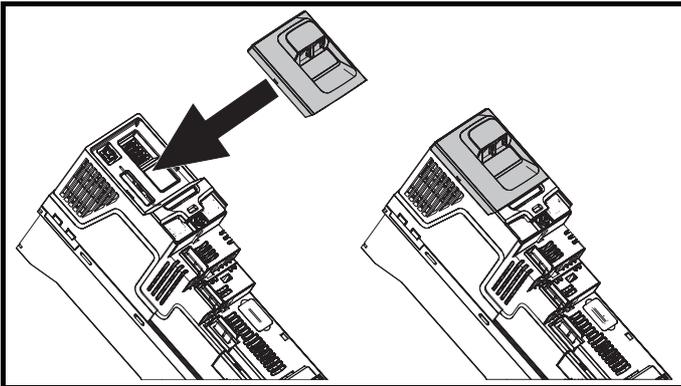
An external USB/EIA-232 hardware interface such as a PC cannot be used directly with the 2-wire EIA-485 interface of the drive.

To gain access to the drive parameters (including connection to Connect), a KI-485 Adaptor should be installed as shown in Figure 4-49 and used in conjunction with a suitable USB to EIA-485 isolated converter. A suitable isolated converter is available from Control Techniques:

- CT USB Comms Cable (CT part number: 4500-0096).

A KI-485 Adaptor is also required for remote LCD keypad operation. The communications cable between the KI-485 Adaptor and keypad is wired one to one. The maximum cable length is 100 m when conductors of 0.129 mm² (AWG 26) or larger are used and the cable shield should be connected to the grounded panel / cubicle at the keypad end of the cable.

Figure 4-49 KI-485 Adaptor Installation



To install, align the KI-485 Adaptor and press gently in the direction shown until it clicks into position.

To remove, reverse the installation instructions.

NOTE

The KI-485 Adaptor can be installed / removed while the drive is powered up and running a motor, providing a remote keypad is not connected to a port on the KI-485 Adaptor and operating in keypad mode.

When using the Control Techniques converters or any other suitable converter with the drive, it is recommended that no terminating resistors be connected on the network. It may be necessary to disconnect the terminating resistor within the converter depending on which type is used.

4.13 Control connections

4.13.1 General

Table 4-24 The control connections consist of:

Function	Qty	Control parameters available	Terminal number
Single ended analog input	2	Mode, offset, invert, scaling, destination	5, 6
Analog output	2	Source, scaling, mode	7, 8
Digital input	3	Destination, invert, logic select	25, 26, 27
Digital input / output	3	Input / output mode select, destination / source, invert, logic select	22, 23, 24
Relay	2	Source, invert	41, 42, 71, 72
Drive enable (Safe Torque Off)	1		29
+24 V User output	1	Source, invert	3
0V common	5		1, 4, 9, 21, 28
+24 V External input	1	Destination, invert	2

Key:

Destination parameter:	Indicates the parameter which is being controlled by the terminal / function
Source parameter:	Indicates the parameter being output by the terminal
Mode parameter:	Analog - indicates the mode of operation of the terminal, i.e. voltage 0-10 V, current 4-20 mA etc. Digital - indicates the mode of operation of the terminal, i.e. positive / negative logic (the Drive Enable terminal is fixed in positive logic), open collector.

All analog terminal functions can be programmed in menu 7.

All digital terminal functions (including the relay) can be programmed in menu 8.

WARNING The control circuits are isolated from the power circuits in the drive by basic insulation (single insulation) only. The installer must ensure that the external control circuits are insulated from human contact by at least one layer of insulation (supplementary insulation) rated for use at the AC supply voltage.

WARNING If the control circuits are to be connected to other circuits classified as Safety Extra Low Voltage (SELV) (e.g. to a personal computer), an additional isolating barrier must be included in order to maintain the SELV classification.

CAUTION If any of the digital inputs (including the drive enable input) are connected in parallel with an inductive load (i.e. contactor coil), then suitable suppression (i.e. diode or varistor) should be used on the coil of the load. If no suppression is used then over voltage spikes can cause damage to the digital inputs and outputs on the drive.

CAUTION Ensure the logic sense is correct for the control circuit to be used. Incorrect logic sense could cause the motor to be started unexpectedly. Positive logic is the default state for the drive.

NOTE

Any signal cables which are carried inside the motor cable (i.e. motor thermistor) will pick up large pulse currents via the cable capacitance. The shield of these signal cables must be connected to ground close to

the point of exit of the motor cable, to avoid this noise current spreading through the control system.

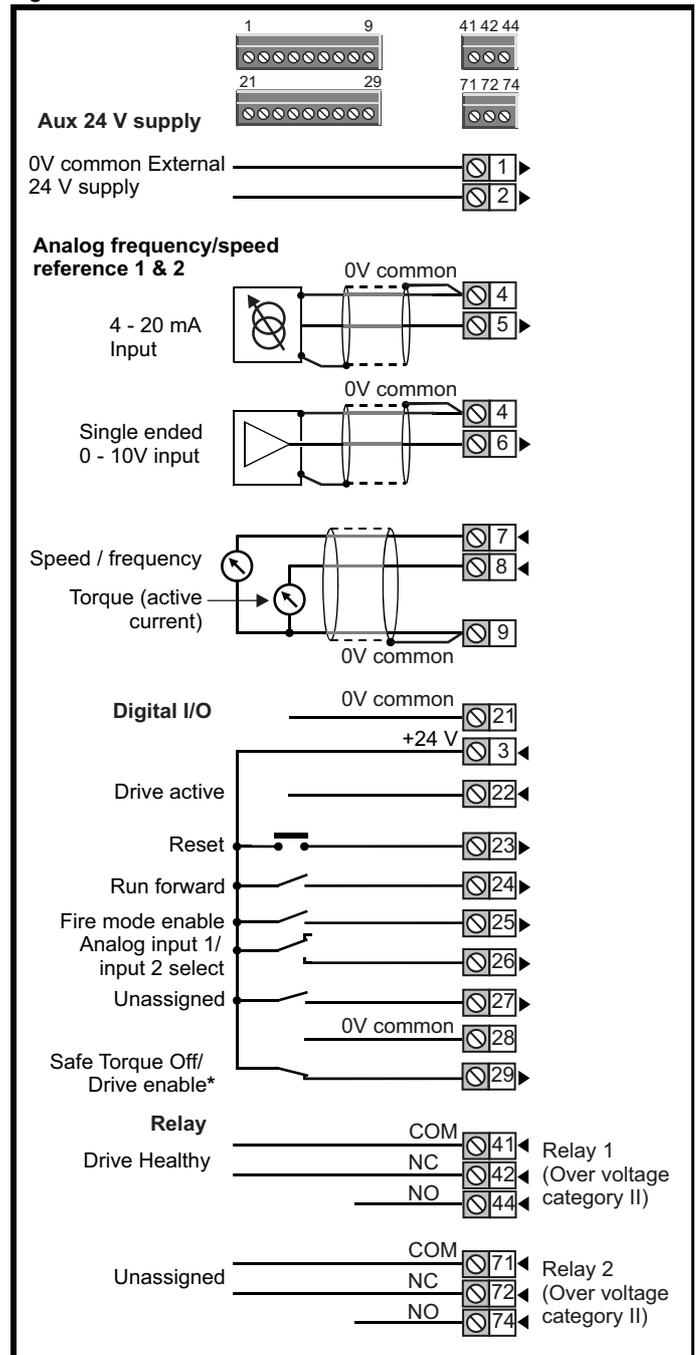
NOTE

The Safe Torque Off drive enable terminal is a positive logic input only. It is not affected by the setting of *Input Logic Polarity* (08.029).

NOTE

The common 0V from analog signals should, wherever possible, not be connected to the same 0V terminal as the common 0V from digital signals. Terminals 1, 4 and 9 should be used for connecting the 0V common of analog signals, and terminals 21 and 28 for digital signals. This is to prevent small voltage drops in the terminal connections causing inaccuracies in the analog signals.

Figure 4-50 Default terminal functions



*The Safe Torque Off / Drive enable terminal is a positive logic input only.

4.13.2 Control terminal specification

1	0V common
Function	Common connection for all external devices

2	+24V external input
Function	To supply the control circuit without providing a supply to the power stage
Programmability	Can be switched on or off to act as a digital input by setting the source Pr 08.063 and input invert Pr 08.053
Nominal voltage	+24.0 Vdc
Minimum continuous operating voltage	+19.2 Vdc
Maximum continuous operating voltage	+28.0 Vdc
Minimum start-up voltage	21.6 Vdc
Recommended power supply	40 W 24 Vdc nominal
Recommended fuse	3 A, 50 Vdc

3	+24 V user output (selectable)
Terminal 3 default function	+24 V user output
Programmability	Can be switched on or off to act as a fourth digital output (positive logic only) by setting the source Pr 08.028 and source invert Pr 08.018
Maximum output current	20 mA
Protection	Current limit and trip
Sample / update period	2 ms when configured as an output (output will only change at the update rate of the source parameter if slower)

4	0V common
Function	Common connection for all external devices

5	Analog input 1
6	Analog input 2
Terminal 5 Default function	Frequency / speed reference (Pr 01.036)
Terminal 6 Default function	Frequency / speed reference (Pr 01.037)
Type of input AI 1 [AI 2]	Unipolar current and unipolar single-ended analog voltage
Mode controlled by...	Pr 07.007 [07.011]
Operating in current mode (Default for terminal 5)	
Current ranges	0 to 20 mA $\pm 5\%$, 20 to 0 mA $\pm 5\%$, 4 to 20 mA $\pm 5\%$, 20 to 4 mA $\pm 5\%$
Maximum offset	250 μ A
Absolute maximum voltage	-10 V to +36 V
Absolute maximum current	± 30 mA
Equivalent input resistance	$\leq 300 \Omega$
Operating in voltage mode (Default for terminal 6)	
Full scale voltage range	± 10 V $\pm 2\%$
Maximum offset	± 10 mV
Absolute maximum voltage range	-10 V to + 36 V
Input resistance	≥ 100 k Ω
Common to all modes	
Resolution	15 bits
Sample / update	250 μ s Filter provided in Pr 07.063 [07.064]
Operating in thermistor input mode	
Voltage range	± 10 V $\pm 2\%$
Supported thermistor types	Din 4408, KTY 84, PT 1000, PT 2000, NI 1000
Internal pull-up voltage	5 V
Trip threshold resistance	User defined in Pr 07.055 [07.060]
Reset resistance	User defined in Pr 07.056 [07.061]
Short-circuit detection resistance	50 $\Omega \pm 40\%$
Common to all modes	
Sample / update period	4 ms

7	Analog output 1
8	Analog output 2
Terminal 7 default function	OL> Motor FREQUENCY output signal
	RFC> SPEED output signal
Terminal 8 default function	Motor active current
Type of output	Unipolar single-ended analog voltage or unipolar current
AOI [AO2] Mode controlled by...	Pr 07.021 [07.024]
Operating in Voltage mode (default)	
Voltage range	0 V to 10 V $\pm 5\%$
Maximum offset	± 120 mV
Maximum output current	± 20 mA
Load resistance	≥ 1 k Ω
Protection	20 mA max. Short circuit protection
Operating in current mode	
Current ranges	0 to 20 mA $\pm 5\%$, 20 to 0 mA $\pm 5\%$ 4 to 20 mA $\pm 5\%$, 20 to 4 mA $\pm 5\%$
Common to all modes	
Resolution	10-bit
Sample / update period	250 μ s (output will only change at update the rate of the source parameter if slower)

9	0V common
Function	Common connection for all external devices

21	0V common
Function	Common connection for all external devices

22	Digital I/O 1
23	Digital I/O 2
24	Digital I/O 3
Terminal 22 default function	DRIVE ACTIVE output
Terminal 23 default function	DRIVE RESET input
Terminal 24 default function	RUN FORWARD input
Type	Positive or negative logic digital inputs, positive logic voltage source outputs
Input / output mode controlled by...	Pr 08.031 , Pr 08.032 and Pr 08.033
Operating as an input	
Logic mode controlled by...	Pr 08.029
Absolute maximum applied voltage range	-3 V to +30 V
Impedance	> 2 mA @15 V from IEC 61131-2, type 1, 6.6 k Ω
Input thresholds	10 V ± 0.8 V from IEC 61131-2, type 1
Operating as an output	
Maximum output current	100 mA (DIO1, 2 & 3 combined)
Common to all modes	
Voltage range	0V to +24 V
Sample / Update period	2 ms (output will only change at the update rate of the source parameter)

25	Digital Input 4
26	Digital Input 5
Terminal 25 default function	FIRE MODE ENABLE input
Terminal 26 default function	Analog INPUT 1 / INPUT 2 select
Type	Negative or positive logic digital inputs
Logic mode controlled by...	Pr 08.029
Voltage range	0V to +24 V
Absolute maximum applied voltage range	-3 V to +30 V
Impedance	> 2 mA @15 V from IEC 61131-2, type 1, 6.6 k Ω
Input thresholds	10 V ± 0.8 V from IEC 61131-2, type 1
Sample / Update period	2 ms

27	Digital Input 6
Terminal 27 default function	Unassigned input
Type	Negative or positive logic digital inputs
Logic mode controlled by...	Pr 08.029
Voltage range	0V to +24 V
Absolute maximum applied voltage range	-3 V to +30 V
Impedance	> 2 mA @15 V from IEC 61131-2, type 1, 6.6 k Ω
Input thresholds	10 V ± 0.8 V from IEC 61131-2, type 1
Sample / Update period	2 ms

28	0V common
Function	Common connection for all external devices

29	Safe Torque Off function (drive enable)
Type	Positive logic only digital input
Voltage range	0V to +24 V
Absolute maximum applied voltage	30 V
Logic Threshold	10 V ± 5 V
Low state maximum voltage for disable to SIL3 and PL e	5 V
Impedance	> 8 mA @15 V (similar to IEC 61131-2, type 1 except the maximum current can be up to 20 mA) Effective input capacitance: 20 nF
Low state maximum current for disable to SIL3 and PL e	0.5 mA
Response time	Nominal: 8 ms Maximum: 20 ms
The Safe Torque Off function may be used in a safety-related application in preventing the drive from generating torque in the motor to a high level of integrity. The system designer is responsible for ensuring that the complete system is safe and designed correctly according to the relevant safety standards. If the Safe Torque Off function is not required, this terminal is used for enabling the drive.	

Refer to section 4.15 *Safe Torque Off (STO)* on page 130 for further information.

41	Relay 1 Common
42	Relay 1 Normally closed
44	Relay 1 Normally open
Default function	Drive Healthy indicator
Contact voltage rating	240 Vac, Installation over-voltage category II
Contact maximum current rating	2 AAC 240 V 4 A DC 30 V resistive load 0.5 A DC 30 V inductive load (L/R = 40 ms)
Contact minimum recommended rating	12 V 100 mA
Contact type	Common - 41 Normally closed - 42 Normally open - 44
Default contact condition	Closed when power applied and drive is healthy
Update period	4 ms



To prevent the risk of a fire hazard in the event of a fault, a fuse or other over-current protection must be installed in the relay circuit.

WARNING

NOTE

With the H300, high IP units there is maximum of 46 mA (24 V) available for user option modules.

This will not affect the use of most of the option modules, however, using the digital outputs of SI-IO modules will require an external 24 V power supply to be used if the total current required exceeds 46 mA.

51	0V common*
52	+24 Vdc*
Size 6	
Nominal operating voltage	24.0 Vdc
Minimum continuous operating voltage	18.6 Vdc
Maximum continuous operating voltage	28.0 Vdc
Minimum startup voltage	18.4 Vdc
Maximum power supply requirement	40 W
Recommended fuse	4 A @ 50 Vdc
Size 7 to 11	
Nominal operating voltage	24.0 Vdc
Minimum continuous operating voltage	19.2 Vdc
Maximum continuous operating voltage	30 Vdc (IEC), 26 Vdc (UL)
Minimum startup voltage	21.6 Vdc
Maximum power supply requirement	60 W
Recommended fuse	4 A @ 50 Vdc

*see Figure 4-17 to Figure 4-19 on page 103 for location.

71	Relay 2 Common
72	Relay 2 Normally closed
74	Relay 2 Normally open
Default function	UNASSIGNED
Contact voltage rating	240 Vac, Installation over-voltage category II
Contact maximum current rating	2 AAC 240 V 4 A DC 30 V resistive load 0.5 A DC 30 V inductive load (L/R = 40 ms)
Contact minimum recommended rating	12 V 100 mA
Contact type	Common - 71 Normally closed - 72 Normally open - 74
Update period	4 ms

4.14 Building automation network connections

Table 4-25 Specifications

1	RX TX
2	Isolated ground
3	RX\ TX\
Cable specification	Shielded twisted pair
	Characteristic impedance: 100 to 130 W
	Capacitance between conductors: <100 pF
	Maximum length: 1200 m with AWG 18 cable
Termination resistor	120 W

4.15 Safe Torque Off (STO)

The Safe Torque Off function provides a means for preventing the drive from generating torque in the motor, with a very high level of integrity. It is suitable for incorporation into a safety system for a machine. It is also suitable for use as a conventional drive enable input.

The safety function is active when the STO input is in the logic-low state as specified in the control terminal specification. The function is defined according to EN 61800-5-2 and IEC 61800-5-2 as follows. (In these standards a drive offering safety-related functions is referred to as a PDS(SR)):

'Power, that can cause rotation (or motion in the case of a linear motor), is not applied to the motor. The PDS (SR) will not provide energy to the motor which can generate torque (or force in the case of a linear motor).'

This safety function corresponds to an uncontrolled stop in accordance with stop category 0 of IEC 60204-1.

The Safe Torque Off function makes use of the special property of an inverter drive with an induction motor, which is that torque cannot be generated without the continuous correct active behaviour of the inverter circuit. All credible faults in the inverter power circuit cause a loss of torque generation.

The Safe Torque Off function is fail-safe, so when the Safe Torque Off input is disconnected the drive will not operate the motor, even if a combination of components within the drive has failed. Most component failures are revealed by the drive failing to operate. Safe Torque Off is also independent of the drive firmware. This meets the requirements of the following standards, for the prevention of operation of the motor.

Machinery Applications

The Safe Torque Off Function has been independently assessed by Notified Body, TÜV Rheinland for use as a safety component of a machine:

Prevention of unintended motor operation: The safety function "Safe Torque Off" can be used in applications up to Cat 4. PL e according to EN ISO 13849-1, SIL 3 according to EN 61800-5-2/ EN 62061/ IEC 61508 and in lift applications according to EN 81-1 and EN81-2

Type examination certificate No.	Date of issue	Models
01.205/5270.01/14	2014-11-11	H300

This certificate is available for download from the TÜV Rheinland website at: <http://www.tuv.com>

Safety Parameters as verified by TÜV Rheinland:

According to IEC 61508-1 to 07 / EN 61800-5-2 / EN 62061

Type	Value	Percentage of SIL 3 allowance
Proof test interval	20 years	
High demand or a continuous mode of operation		
PFH (1/h)	4.21×10^{-11} 1/h	<1 %

Type	Value	Percentage of SIL 3 allowance
Low demand mode of operation (not EN 61800-5-2)		
PFDAvg	3.68×10^{-6}	< 1 %

According to EN ISO 13849-1

Type	Value	Classification
Category	4	
Performance Level (PL)	e	
MTTF _D	>2500 years	High
DC _{avg}	≥99 %	High
Mission time	20 years	

NOTE

Logic levels comply with IEC 61131-2:2007 for type 1 digital inputs rated at 24 V. Maximum level for logic low to achieve SIL3 and PL e 5 V and 0.5 mA.

UL Approval

The Safe Torque Off function has been independently assessed by Underwriters Laboratories (UL). The on-line certification (yellow card) reference is: FSPC.E171230.

Safety Parameters as verified by UL:

According to IEC 61508-1 to 7

Type	Value
Safety Rating	SIL 3
SFF	> 99 %
PFH (1/h)	4.43×10^{-10} 1/h (<1 % of SIL 3 allowance)
HFT	1
Beta Factor	2 %
CFF	Not applicable

According to EN ISO 13849-1

Type	Value
Category	4
Performance Level (PL)	e
MTTF _D	2574 years
Diagnostic coverage	High
CCF	65

Note on response time of Safe Torque Off, and use with safety controllers with self-testing outputs:

Safe Torque Off has been designed to have a response time of greater than 1 ms so that it is compatible with safety controllers whose outputs are subject to a dynamic test with a pulse width not exceeding 1 ms.

Note on the use of servo motors, other permanent-magnet motors, reluctance motors and salient-pole induction motors:

When the drive is disabled through Safe Torque Off, a possible (although highly unlikely) failure mode is for two power devices in the inverter circuit to conduct incorrectly.

This fault cannot produce a steady rotating torque in any AC motor. It produces no torque in a conventional induction motor with a cage rotor. If the rotor has permanent magnets and/or saliency, then a transient alignment torque may occur. The motor may briefly try to rotate by up to 180° electrical, for a permanent magnet motor, or 90° electrical, for a salient pole induction motor or reluctance motor. This possible failure mode must be allowed for in the machine design.



WARNING

The design of safety-related control systems must only be done by personnel with the required training and experience. The Safe Torque Off function will only ensure the safety of a machine if it is correctly incorporated into a complete safety system. The system must be subject to a risk assessment to confirm that the residual risk of an unsafe event is at an acceptable level for the application.



WARNING

Safe Torque Off inhibits the operation of the drive, this includes inhibiting braking. If the drive is required to provide both braking and Safe Torque Off in the same operation (e.g. for emergency stop) then a safety timer relay or similar device must be used to ensure that the drive is disabled a suitable time after braking. The braking function in the drive is provided by an electronic circuit which is not fail-safe. If braking is a safety requirement, it must be supplemented by an independent fail-safe braking mechanism.



WARNING

Safe Torque Off does not provide electrical isolation. The supply to the drive must be disconnected by an approved isolation device before gaining access to power connections.

With Safe Torque Off there are no single faults in the drive which can permit the motor to be driven. Therefore it is not necessary to have a second channel to interrupt the power connection, nor a fault detection circuit.

It is important to note that a single short-circuit from the Safe Torque Off input to a DC supply of >5 V could cause the drive to be enabled. This can be excluded under EN ISO 13849-2 by the use of protected wiring. The wiring can be protected by either of the following methods:

- By placing the wiring in a segregated cable duct or other enclosure.
- or**
- By providing the wiring with a grounded shield in a positive-logic grounded control circuit. The shield is provided to avoid a hazard from an electrical fault. It may be grounded by any convenient method; no special EMC precautions are required.



WARNING

It is essential to observe the maximum permitted voltage of 5 V for a safe low (disabled) state of Safe Torque Off. The connections to the drive must be arranged so that voltage drops in the 0V wiring cannot exceed this value under any loading condition. It is strongly recommended that the Safe Torque Off circuit be provided with a dedicated 0V conductor which should be connected to terminal 28 at the drive.

Safe Torque Off over-ride

The drive does not provide any facility to over-ride the Safe Torque Off function, for example for maintenance purposes.

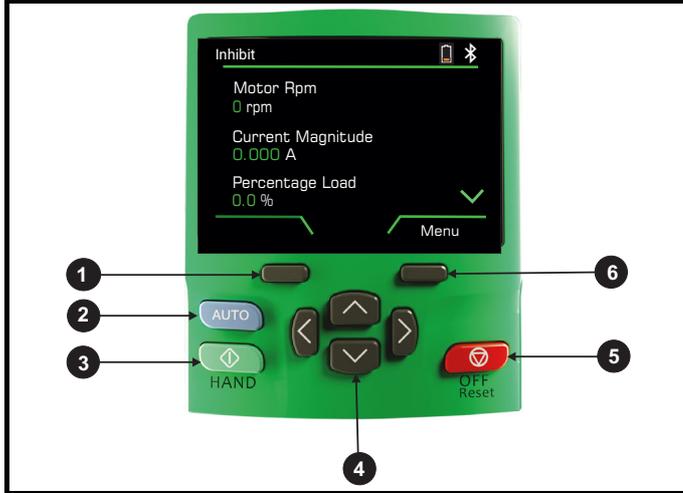
5 Getting started

This chapter introduces the user interfaces, menu structure and security levels of the drive.

5.1 Using the keypad

The keypad display provides information to the user regarding the operating status of the drive, alarms and trip codes. The keypad buttons provide a means for changing parameters, stopping and starting the drive, and the ability to perform a drive reset.

Figure 5-1 Keypad key identifier



1. Soft key (for text above)
2. Auto
3. Hand
4. Navigation
5. Off / Reset
6. Soft key (for text above)

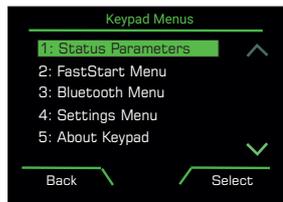
Press and hold the Hand or Auto buttons for 2 s to select those functions. A short press will activate the Off function.

NOTE

The red stop  button is also used to reset the drive.

The parameter value is correctly displayed in the lower row of the keypad display, see table below.

Figure 5-2 Keypad menu



Keypad display information can be accessed through Main menu / Keypad menus.

Table 5-1 Icons

The top right corner of the display on the KI-Keypad Plus shows several different status icons. Table 3-1 below details the meaning of these icons.

Icon	Description
	Alarm active
	Bluetooth enabled and connected (Blue)
	Bluetooth enabled but not connected (White)
	Security active and locked
	Security active but unlocked (Orange)
	Keypad real-time clock battery low
	Onboard user program running

The following animated icon will be displayed at the bottom centre of the display when the drive is running.

Table 5-2 Running icons

Icon	Description
	Drive running in the forward direction
	Drive running in the reverse direction

NOTE

Low battery voltage is indicated by  low battery symbol on the keypad display. Refer to section 3.13.1 *Real time clock battery replacement* on page 78 for information on battery replacement.

Figure 5.2 *Instructions to edit parameters* on page 133, shows an example of moving between menus and editing parameters.

5.1.1 Hand / Off / Auto

Hand / Off / Auto functions are enabled if Pr **01.052** is set to a non-zero value, otherwise the keypad buttons are allocated as follows:

- Blue  - Forward/Reverse
- Green  - Run
- Red  - Reset

When Hand / Off / Auto functions are enabled (Pr **01.052** set to either 1, 2 or 3), then the keypad buttons will be allocated as follows:

- Blue  - Auto
- Green  - Hand
- Red  - Off/Reset

The value in Pr **01.052** selects Hand/Off/Auto mode on power-up as shown in Table 5-3.

Table 5-3 Hand/Off/Auto mode

Pr 1.052	Power up
0	Hand/Off/Auto disabled
1	Auto Mode
2	Off Mode
3	See table Table 5-4

Table 5-4 Power-up modes if Pr 01.052 = 3

Power-down	Power-up
Hand	Off
Off	Off
Auto	Auto

Auto

In Auto mode, the reference for the motor speed/frequency will be selected by the value set in Pr **01.014**.

Hand

The speed/frequency reference Pr **01.014** is automatically set to keypad reference. The motor speed is determined by the value in the keypad control mode reference Pr **01.017**, which can be adjusted by pressing the Up/Down arrows on the keypad.

When Hand is selected from Auto, Pr **01.017** will be set to the value of the *Pre-ramp reference* (Pr **01.003**) on mode transition, so the current motor speed is maintained.

If Hand mode is selected from Off mode, the motor will ramp up to the speed determined by the value in Pr **01.017**.

Off

In Off mode, the motor will be stopped. The speed/frequency reference (Pr **1.014**) is automatically set to keypad reference allowing the value in the *keypad control mode reference* (Pr **01.017**) to be modified by pressing the Up/Down arrow keys. If Hand mode is then selected, the motor will ramp up to the speed determined by the value in Pr **01.017**.

5.2 Instructions to edit parameters

Selecting "Menu" shows the following Main Menu Screen



Selecting "Drive Menus" Provides access to all Menu Lists. Use the ^ (Up) / v (Down) navigation keys to highlight the required menu then select.

Menu Number	Menu Name (Open-Loop mode listed. RFC-A and RFC-S menus vary slightly)
0	Quick SetUp
1	Frequency Reference
2	Frequency Ramps
3	Frequency Monitoring
4	Torque and Current Control
5	Motor Control
6	Sequencer and Clock
7	Analog I/O
8	Digital I/O
9	User Functions 1

Menu Number	Menu Name (Open-Loop mode listed. RFC-A and RFC-S menus vary slightly)
10	Status and Trips
11	Miscellaneous
12	User Functions 2
14	User PID Controller
15	Option Slot 1
16	Option Slot 2
17	Option Slot 3
18	Application Menu 1
19	Application Menu 2
22	Application Menu 2
24	Menu 0 Set-up

5.2.1 Parameter quick action mode

The quick access mode allows direct access to any parameter without scrolling through menus and parameters.

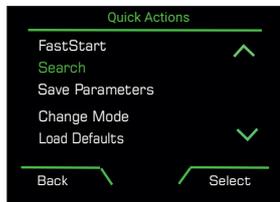
To enter the quick actions mode, press select on the keypad while in 'parameter mode'.

Figure 5-3 Parameter Quick Actions Mode

Main Menu lists the main menu below with a H300 out of the box, and will show any additional I/O slots if fitted.



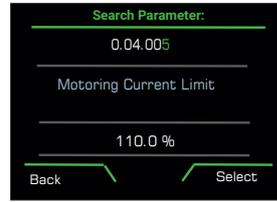
Use search facility to then access a known parameter value, by selecting the actual value using the Navigation Up/Down Left /Right keys. Use select to move to next screen, to change the parameter setting select edit and then use the navigation keys to select the number field.



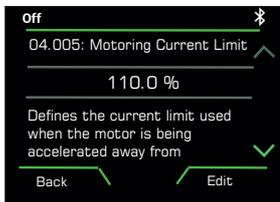
Select



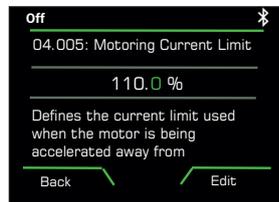
Using navigation keys select parameter number



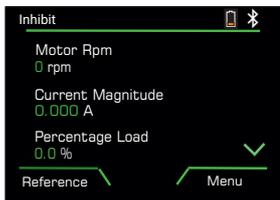
Select



Edit



Keypad power up screen



NOTE

The power up screen has 8 status parameters that provide users with direct access to chosen parameters, use the down navigation key to access further default status parameters are listed below.

Default status Parameters are accessed via Menu / Main Menu / Keypad Menus / Status Parameters.

Pr 05.004 Motor RPM

Pr 04.001 Current Magnitude

Pr 04.020 Percentage Load

Pr 02.001 Post Ramp Reference

Pr 11.023 Serial Address

Pr Custom selectable parameter Enabled by Status Parameter Pr 01.012 Use Custom Status Parameters = On.

Pr Custom selectable parameter Enabled by Status Parameter Pr 01.012 Use Custom Status Parameters = On.

Pr Custom selectable parameter Enabled by Status Parameter Pr 01.012 Use Custom Status Parameters = On.

Trip Message

The Drive will display a trip message in the banner at the top of the display this is also logged in the Pr 10.020 Trip 0 parameter.

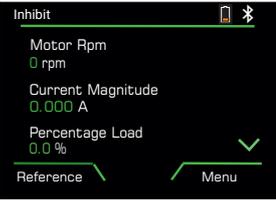
See section 13.4 for fault descriptions



5.3 Keypad Menu Structure

The drive parameter structure consists of menus and parameters.

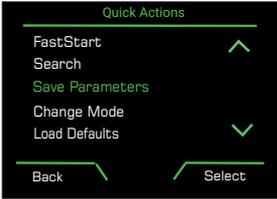
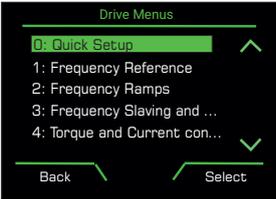
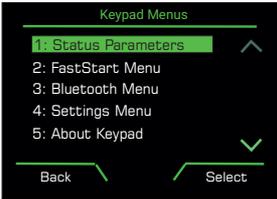
The drive initially powers up so that only Menu 0 can be viewed. The navigation keys are used to navigate between parameters and once Pr **00.031** has been set to 'All Menus' the left and right navigation keys are used to navigate between menus. For further information, refer to section 5.9 *Parameter access level and security* on page 144



The figures below are examples of the keypad main menu screen, followed by the selectable screens within that.

Figure 5-4 Menu structure



Main Menu	Follow on menus	
 <p>NOTE Option modules will also be displayed here when fitted</p>	Quick Actions	Drive Menu
		
	Keypad Menu	About
		

5.4 Menu 0

Menu 0 is used to bring together various commonly used parameters for basic easy set up of the drive. The parameters displayed in Menu 0 can be configured in Menu 22.

Appropriate parameters are copied from the Advanced parameters into Menu 0 and thus exist in both locations.

For further information, refer to Chapter 6 *Basic parameters* on page 147. A list of these menus is also available in section 6.

5.5 Advanced menus

The advanced menus consist of groups or parameters appropriate to a specific function or feature of the drive. Menus 0 to 41 can be viewed on the keypad.

The option module menus (S.mm.ppp) are only displayed if option modules are installed. Where S signifies the option module slot number and the mm.ppp signifies the menu and parameter number of the option module's internal menus and parameter.

Table 5-5 Advanced menu descriptions

Menu	Description
0	Commonly used basic set up parameters for quick / easy programming
1	Frequency / Speed reference
2	Ramps
3	Speed feedback and speed control
4	Torque and current control
5	Motor control
6	Sequencer and clock
7	Analog I/O, Temperature monitoring
8	Digital I/O
9	Programmable logic, motorized pot, binary sum, timers and scope
10	Status and trips
11	Drive set-up and identification, serial communications
12	Threshold detectors and variable selectors
14	User PID controller
15	Option module slot 1 set-up menu
16	Option module slot 2 set-up menu
17	Option module slot 3 set-up menu
18	General option module application menu 1
19	General option module application menu 2
20	General option module application menu 3
22	Menu 0 set-up
23	Not allocated
29	Building Automation communications configuration
Slot 1	Slot 1 option menus*
Slot 2	Slot 2 option menus*
Slot 3	Slot 3 option menus*

*Only displayed when the option modules are installed.

5.5.1 Keypad setup

The keypad set up menus can be accessed via the Main Menu / Keypad Menus.

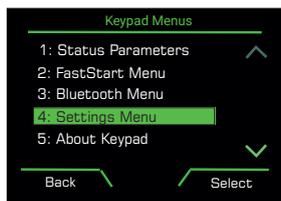


Table 5-6 Keypad set-up parameters

No	Description
0	Select Language English, Spanish, Chinese, Turkish, Polish, Italian, French, German,
1	Brightness 0-100%
2	Colour Customization
3	Custom Colour
4	Custom Accent Colour
5	Status Screen Timeout Default setting is 300 s

No	Description
6	Advanced Navigation allowing previous KI Keypad keystroke format for accessing and changing parameters using the Left, Right navigation keys for Menu Number and Up/Down navigation Keys to select parameter
7	Wink Display Winks display 5 times then resets to off.
10	Restore Keypad Parameters to Defaults
11	Save keypad parameters
19	Parameter Recache required
20	Show Low Baud Rate Prompt
21	Show Guided Setup Prompt Default 0, 1= Run guided setup on startup
22	Guided Setup Complete 0 = the user will be prompted to run the guided setup tool at power on
23	Show Language selection on switch on
50-51	Manufacturer Reserved
55-59	Diagnostic 1-5 Manufacturer reserved for diagnostic testing

NOTE

It is not possible to access the keypad parameters via any communications channel.

* The languages available will depend on the keypad software version.

5.5.2 Display messages

The following tables indicate the various possible mnemonics which may be displayed by the drive and their meaning.

Table 5-7 Status indications

Upper row string	Description	Drive output stage
Inhibit	The drive is inhibited and cannot be run. The Safe Torque Off signal is not applied to Safe Torque Off terminals or Pr 06.015 is set to 0. The other conditions that can prevent the drive from enabling are shown as bits in <i>Enable Conditions</i> (06.010)	Disabled
Off	The drive is stopped	Disabled
Hand	The drive is active and running. The motor speed/frequency is determined by the value in the Keypad Control Mode Reference Pr 01.017	Enabled
Auto	The drive is active and running. The reference for the motor speed/frequency is defined by Reference Selector Pr 01.014	Enabled
Supply Loss	Supply loss condition has been detected	Enabled
Deceleration	The motor is being decelerated to zero speed / frequency because the final drive run has been deactivated	Enabled
dc injection	The drive is applying dc injection braking	Enabled
Trip	The drive has tripped and no longer controlling the motor. The trip code appears in the lower display	Disabled
Under Voltage	The drive is in the under voltage state either in low voltage or high voltage mode	Disabled
Heat	The motor pre-heat function is active	Enabled

5.5.3 Alarm indications

An alarm is an indication given on the display by alternating the alarm string with the drive status string on the upper row and showing the alarm symbol in the last character in the upper row. Alarms strings are not displayed when a parameter is being edited, but the user will still see the alarm character on the upper row.

Table 5-8 Alarm indications

Alarm string	Description
Motor Overload	<i>Motor Protection Accumulator</i> (04.019) in the drive has reached 75.0 % of the value at which the drive will trip and the load on the drive is >100 %.
Drive Overload	Drive over temperature. <i>Percentage Of Drive Thermal Trip Level</i> (07.036) in the drive is greater than 90 %.
Auto Tune	The autotune procedure has been initialized and an autotune in progress.

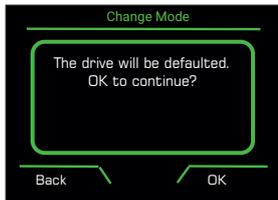
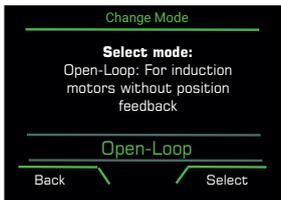
Table 5-9 Option module and NV media card and other status indications at power-up

First row string	Second row string	Status
Booting	Parameters	Parameters are being loaded
Drive parameters are being loaded from a NV Media Card		
Booting	Option Program	User program being loaded
User program is being loaded from a NV Media Card to the option module in slot X		
Writing To	NV Card	Data being written to NV Media Card
Data is being written to a NV Media Card to ensure that its copy of the drive parameters is correct because the drive is in Auto or Boot mode		
Waiting For	Power System	Waiting for power stage
The drive is waiting for the processor in the power stage to respond after power-up		
Waiting For	Options	Waiting for an option module
The drive is waiting for the options modules to respond after power-up		
Uploading From	Options	Loading parameter database
At power-up it may be necessary to update the parameter database held by the drive because an option module has changed or because an applications module has requested changes to the parameter structure. This may involve data transfer between the drive an option modules. During this period 'Uploading From Options' is displayed		

5.6 Changing the operating mode

Open Loop is default, if RFC-A Mode is required then Main Menu / Quick Actions/Mode Change.

When entering this mode it displays the current mode the drive is saved with. Open Loop is also the factory default. Use the Keypad ^ ∨ navigation keys navigate to the mode required.



On Selecting OK, a message will appear "preparing Drive", after a few seconds "Mode Change Successful" will appear. Then go back to "Quick Actions" and save parameters.



5.7 Running the drive for the first time

Action	Detail
Before power up.	Open the Enable or Safe Torque Off, Hand and Auto mode switches so the drive powers up in the <i>Inhibit</i> state. Ensure that the motor shaft is free to turn and that all safety guidelines are adhered to. Check that the Drive is in the inhibited state and that The drive enable signal is not given (terminal 29), and Run signals are not active.
Power up the drive.	After power up the display indicates as shown below. <div style="display: flex; justify-content: space-around;"> <div style="border: 1px solid black; padding: 5px; width: 45%;"> <p>Open-Loop Mode</p> </div> <div style="border: 1px solid black; padding: 5px; width: 45%;"> <p>RFC-A Mode</p> </div> </div>
Ensure Pr 11.031 is set to Open-Loop (Note - Open-Loop is factory default)	<div style="display: flex; justify-content: space-around;"> <div style="border: 1px solid black; padding: 5px; width: 45%;"> <p>Open-Loop Mode</p> </div> <div style="border: 1px solid black; padding: 5px; width: 45%;"> <p>RFC-A Mode</p> </div> </div>

Configure the motor name plate details.

- Open-Loop and RFC-A**
- Motor rated voltage in Pr **00.018** (V) - check if Δ or \triangle connection
 - Set *Rated Speed* Pr **00.019**, the motor rated speed in rpm
 - Set *Rated Current* Pr **00.020** to the motor rated current in Amps
 - Set *Rated Frequency* Pr **00.021**, the motor rated frequency in Hz

Typical motor nameplate examples

MOT. 3 ~ LS 80 L T					
N° 734570 BJ 002 Kg 9					
IP 55	I cl.F	40°C	S1		
V	Hz	min ⁻¹	kW	cos φ	A
Δ 230	50	2800	0,75	0,83	0,3
3	2	4	1	IEC 34-1 (B7)	

Mot X XXXXXXXXX					
No XXXXXXXXXX kg					
IP55	I cl.F	°C	40	s	S1
V	Hz	min ⁻¹	kW	cosφ	A
Δ 230	50	1445	2,20	0,80	8,50
Δ 400					4,90
CN = 14,5Nm					
Δ 240	50	1445	2,20	0,76	8,50
Δ 415					4,90
CN = 14,4Nm					
CTP-VEN-1PHASE-120-60-F-110V-0,6-30Nm					

Configure motor thermal protection.

For Open-Loop and RFC-A modes, if the Motor requires thermal protection the H300 Drives has the following Thermistor types programmed within parameter Pr **00.029** Analog Input 2 Thermistor Type.

- DIN44082 (Default)
- KTY84
- PT100
- PT1000
- PT2000
- NI1000

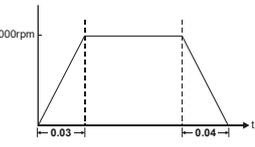
Parameter Pr **00.027** Analog Input 2 Mode will need to be set to either of the following as required by the application.

- Therm Short Cct
- Thermistor
- Therm No Trip



Set acceleration and deceleration rate

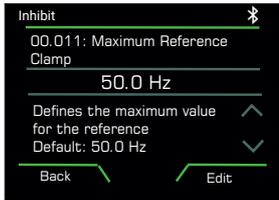
- For Open-Loop and RFC-A modes, Enter:
- Acceleration rate in Pr **00.012** (s to Pr **01.006**)
 - Deceleration rate in Pr **00.013** (s from Pr **01.006**)



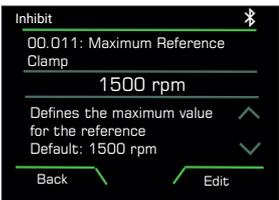
<p>Autotune</p>	<p>For Open-Loop and RFC-A modes, the drive is able to perform either a stationary or a rotating autotune. The motor must be at a standstill before an autotune is enabled. NOTE A rotating autotune should be used whenever possible so the measured value of power factor of the motor is used by the drive (Pr 00.024 set to 2).</p> <div style="border: 1px solid black; padding: 5px; margin: 10px 0;">  <p>A rotating autotune will cause the motor to accelerate up to $\frac{2}{3}$ base speed in the direction selected regardless of the reference provided. Once complete the motor will coast to a stop. The enable signal must be removed before the drive can be made to run at the required reference. The drive can be stopped at any time by removing the run signal or removing the drive enable.</p> </div> <p>Open Loop</p> <p>1. Basic</p> <p>This test measures the basic control parameters without moving the motor.</p> <ol style="list-style-type: none"> 1. A stationary Auto Tune is performed on a motor that may be loaded that cannot be uncoupled from load. 2. A stationary auto tune test is performed to measure Stator Resistance (Pr 05.017), Transient Inductance (Pr 05.024), Maximum Deadtime Compensation (Pr 05.059) and Current At Maximum Deadtime Compensation (Pr 05.060). If Enable Stator Compensation (Pr 05.049) = 1 then Stator Base Temperature (Pr 05.048) is made equal to Stator Temperature (Pr 05.046). <p>2. Improved</p> <p>The improved Autotune should only be used if the motor is uncoupled from the load. This test measures the parameters for improved performance by rotating the motor.</p> <ol style="list-style-type: none"> 1. Auto-tune test 1 is performed. 2. A rotating test is performed in which the motor is accelerated with the currently selected ramps up to a frequency of Rated Frequency (Pr 05.006) x 2/3, and the frequency is maintained at that level for 4 seconds. Stator Inductance (Pr 05.025) is measured and this value is used in conjunction with other motor parameters to calculate Rated Power Factor (Pr 05.010). The no-load motor core losses are measured and written to No-load Core Loss (Pr 04.045). It is not possible to measure the rated load motor core losses, and so Rated Core Loss (Pr 04.046) is set to zero. The motor should be unloaded for this test. <p>RFCA</p> <p>1. Basic</p> <p>This test measures the basic control parameters without moving the motor.</p> <ol style="list-style-type: none"> 1. A stationary Auto Tune is performed on a motor that may be loaded that cannot be uncoupled from load. 2. A stationary test is performed to measure Stator Resistance (Pr 05.017), Transient Inductance (Pr 05.024), Maximum Deadtime Compensation (Pr 05.059) and Current At Maximum Deadtime Compensation (Pr 05.060). If Enable Stator Compensation (Pr 05.049) = 1 then Stator Base Temperature (Pr 05.048) is made equal to Stator Temperature (Pr 05.046). 3. Stator Resistance (Pr 05.017) and Transient Inductance (Pr 05.024) are used to set up Current Controller Kp Gain (Pr 04.013) and Current Controller Ki Gain (Pr 04.014). This is only performed once during the test, and so the user can make further adjustments to the current controller gains if required. <p>2. Improved</p> <p>The improved Autotune should only be used if the motor is uncoupled from the load. This test measures the parameters for improved performance by rotating the motor.</p> <ol style="list-style-type: none"> 1. Auto-tune 1 test is performed. 2. A rotating test is performed in which the motor is accelerated with the currently selected ramps up to a frequency of Rated Frequency (Pr 05.006) x 2/3, and the frequency is maintained at that level for up to 40 seconds. Stator Inductance (Pr 05.025) is measured and this value is used in conjunction with other motor parameters to calculate Rated Power Factor (Pr 05.010). Saturation Breakpoint 1 (Pr 05.029), Saturation Breakpoint 3 (Pr 05.030), Saturation Breakpoint 2 (Pr 05.062) and Saturation Breakpoint 4 (Pr 05.063) are measured. The no-load motor core losses are measured and written to No-load Core Loss (Pr 04.045). It is not possible to measure the rated load motor core losses, and so Rated Core Loss (Pr 04.046) is set to zero. The motor should be unloaded for this test. <p>To perform an autotune:</p> <p>Set Pr 00.024 = 1 for a stationary autotune or set Pr 00.024 = 2 for a rotating autotune Close the Drive Enable signal (terminal 29). The drive will display 'Off'. Close the run signal (terminal 24). The upper row of the display will flash 'Auto Tune' while the drive is performing the autotune.</p> <ul style="list-style-type: none"> • Wait for the drive to display 'Inhibit' and for the motor to come to a standstill. <p>Remove the drive enable and run signal from the drive.</p>
<p>Save parameters</p>	<p>Select 'Save Parameters' in Pr mm.000 (enter a value of 1001 in Pr mm.000) using the navigations keys and press the red  reset button or toggle the reset digital input. Alternatively, save parameters using the Main Menu / Quick Actions / Save Parameters</p>

Set the Maximum Reference Clamp. By default, *Maximum Reference Clamp Pr 00.011* normally matches *Rated Frequency Pr 00.021*

Open-loop Mode

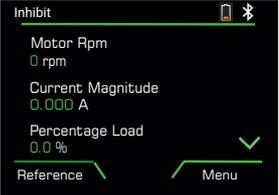


RFC-A Mode

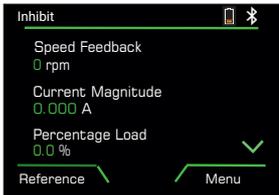


Set the Hand Mode Reference frequency. The Drive's reference frequency by default is set to auto within Pr 01.052 at start up, and the reference by default will come through Analog input terminal T5 (by default set to 4-20 mA), by pressing the Hand mode, the keypad reference will be activated and the speed reference will then be determined by the up/Down arrows of the keypad, and will move between the min ref clamp (Pr 00.010 and max ref clamp (Pr 00.011).

Open-loop Mode

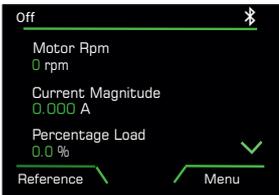


RFC-A Mode

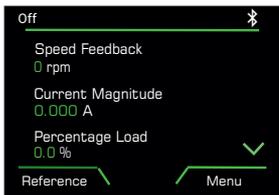


Enable the drive. Close the Enable or Safe Torque Off input switch to the drive. **NOTE** The screen will change from Inhibit to Off.

Open-loop Mode

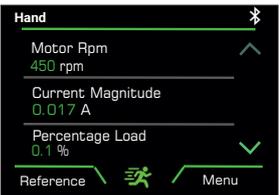


RFC-A Mode

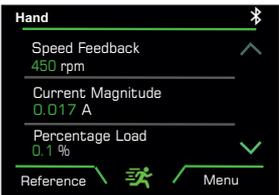


Start the motor in Hand mode. Make sure it is safe to run the motor. Press the Green HAND button, the drive will start and the motor will accelerate to the hand speed reference which is nominally the minimum clamp frequency setting.

Open-loop Mode



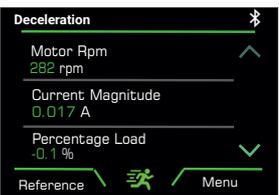
RFC-A Mode



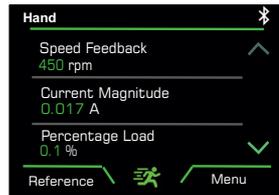
HAND 

Pressing the RED off button will then initiate a stop and the motor will decelerate to zero speed, note the inhibit will remain OFF.

Open-loop Mode



RFC-A Mode

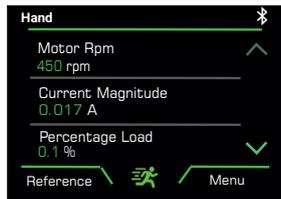


OFF
Reset 

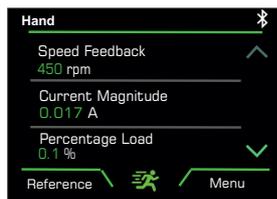
Check the motor is turning in the correct direction.

Check that the motor is rotating in the correct direction. **NOTE** The speed may need to be lowered in order to note the direction

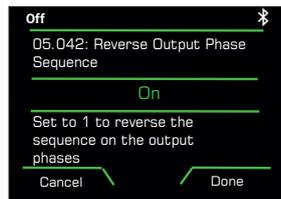
Open-loop Mode



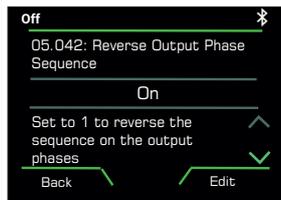
RFC-A Mode



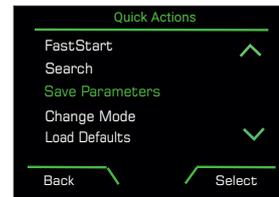
If the motor appears to be running in the wrong direction stop the drive from running by pressing the red OFF / Reset button or by opening the Hand switch. The software status changes to Off (Ready). Either reverse two motor phases electrically when safe to do so, or alternatively, set Reverse Output Phase Sequence Pr **05.042** to On.



After Done is selected the parameter is in use and will work until drive is power cycled.



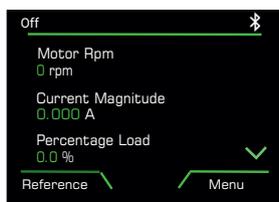
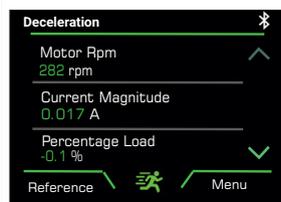
Navigate back to the Main Menu Screen then use ^ v navigations keys on the keypad to navigate to Quick Actions.



Navigate to Save Parameters and select, screen will display "Saving Parameters", then "Save Complete".

Stop the motor.

For Open-Loop and RFC-A mode, stop the motor by pressing the red OFF / Reset button or by opening the Hand switch. The software status changes to Off (Ready).



Save parameters for Open-loop and RFC-A modes

Action	Detail
Save parameters	Select 'Save Parameters' in Pr mm.000 (alternatively enter a value of 1001 in Pr mm.000) and press red  reset button or toggle the reset digital input. Alternatively, save parameters using the Main Menu / Quick Actions / Save Parameters
Run	Drive is now ready to run 

5.8 Restoring parameter defaults

Restoring parameter defaults by this method saves the default values in the drives memory. *User security status* (00.031) and *User security code* (00.030) are not affected by this procedure).

Procedure

1. Ensure the drive is not enabled, i.e. terminal 29 is open or Pr **06.015** is OFF (0)
2. Select 'Reset 50 Hz Defs' or 'Reset 60 Hz Defs' in Pr **mm.000**. (alternatively, enter 1233 (50 Hz settings) or 1244 (60 Hz settings) in Pr **mm.000**).
3. Either:
 - Press the red  reset button
 - Toggle the reset digital input
 - Carry out a drive reset through serial communications by setting Pr **10.038** to 100

On KI-Keypad Plus, defaults can be accessed through Main Menu/Quick Action/Load Default

5.9 Parameter access level and security

The parameter access level determines whether the user has access to Menu 0 only or to all the advanced menus (Menus 1 to 41) in addition to Menu 0.

The User Security determines whether the access to the user is read only or read write.

Both the User Security and Parameter Access Level can operate independently of each other as shown in Table 5-10.

Table 5-10 Parameter access level and security (Pr 11.044)

User security status (11.044)	Access level	User security	Menu 0 status	Advanced menu status
0	Menu 0	Open	RW	Not visible
		Closed	RO	Not visible
1	All Menus	Open	RW	RW
		Closed	RO	RO
2	Read-only Menu 0	Open	RO	Not visible
		Closed	RO	Not visible
3	Read-only	Open	RO	RO
		Closed	RO	RO
4	Status only	Open	Not visible	Not visible
		Closed	Not visible	Not visible
5	No access	Open	Not visible	Not visible
		Closed	Not visible	Not visible

The default settings of the drive are Parameter Access Level Menu 0 and user Security Open i.e. read / write access to Menu 0 with the advanced menus not visible.

5.9.1 User Security Level / Access Level

The drive provides a number of different levels of security that can be set by the user via *User Security Status* (11.044); these are shown in the table below.

User Security Status (Pr 11.044)	Description
Menu 0 (0)	All writable parameters are available to be edited but only parameters in Menu 0 are visible
All menus (1)	All parameters are visible and all writable parameters are available to be edited
Read-only Menu 0 (2)	Access is limited to Menu 0 parameters only. All parameters are read-only
Read-only (3)	All parameters are read-only however all menus and parameters are visible
Status only (4)	The keypad remains in status mode and no parameters can be viewed or edited
No access (5)	The keypad remains in status mode and no parameters can be viewed or edited. Drive parameters cannot be accessed via a comms/ fieldbus interface in the drive or any option module

5.9.2 Changing the User Security Level /Access Level

The security level is determined by the setting of Pr **00.031** or Pr **11.044**. The Security Level can be changed through the keypad even if the User Security Code has been set.

5.9.3 User Security Code

The User Security Code, when set, prevents write access to any of the parameters in any menu.

Setting User Security Code

Enter Value 0-2147483647 in Pr **00.030**. Navigation arrow keys.

The Security code has now been set to this value. To activate the drive security, the security level must be set to the desired level from section 5.9.1 above in Pr **00.031**. When the drive is reset the security code will have been activated.

Unlocking User Security Code on a locked Drive

On entering the Menu screen from the default main screen a message "Enter Security Code" appears.

Enter the correct code using the navigation keys.

Locking the Drive

Go to Pr **00.031** and choose either of the following:

Read-Only

Read-only Menu 0

5.10 Displaying parameters with non-default values only

By selecting 'Show non-default' in Pr **mm.000** (Alternatively, enter 12000 in Pr **mm.000**), the only parameters that will be visible to the user will be those containing a non-default value. This function does not require a drive reset to become active. In order to deactivate this function, return to Pr **mm.000** and select 'No action' (alternatively enter a value of 0). Please note that this function can be affected by the access level enabled, refer to section 5.9 *Parameter access level and security* on page 144 for further information regarding access level.

5.11 Displaying destination parameters only

By selecting 'Destinations' in Pr **mm.000** (Alternatively enter 12001 in Pr **mm.000**), the only parameters that will be visible to the user will be destination parameters. This function does not require a drive reset to become active. In order to deactivate this function, return to Pr **mm.000** and select 'No action' (alternatively enter a value of 0).

Please note that this function can be affected by the access level enabled, refer to section 5.9 *Parameter access level and security* on page 144 for further information regarding access level.

5.12 Communications

As standard the H300 drive is provided with a 2 wire EIA-485 interface located beneath the control terminals, see Figure 4-48 *Location of the comms connector* on page 124. It allows communication to other devices via three building automation network protocols (Modbus RTU and BACnet MSTP).

5.12.1 EIA-485 Serial communications

The serial communications port is a 3 way screw type connector, which is isolated from the power stage and the other control terminals (see section 4.12 *Communications connections* on page 124 for connection and isolation details). The communications port applies a 2 unit load to the communications network.

USB/EIA-232 to EIA-485 Communications

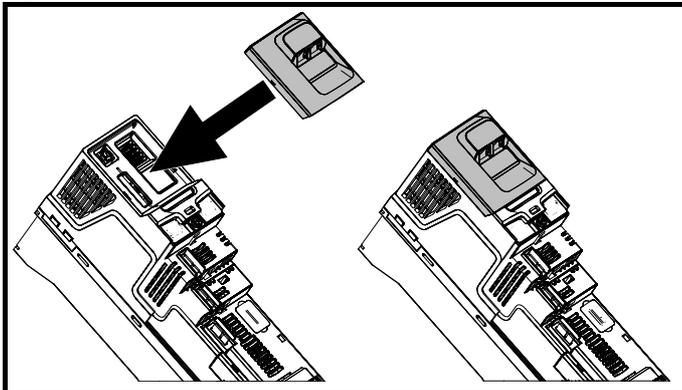
An external USB/EIA-232 hardware interface such as a PC cannot be used directly with the 2-wire EIA-485 interface of the drive.

To gain access to the drive parameters (including connection to HVAC Connect), a KI-485 Adaptor should be installed as shown in Figure 5-5 and used in conjunction with a suitable USB to EIA-485 isolated converter. A suitable isolated converter is available from Control Techniques:

- CT USB Comms Cable (CT part number: 4500-0096).

A KI-485 Adaptor is also required for remote LCD keypad operation. The communications cable between the KI-485 Adaptor and keypad is wired one to one. The maximum cable length is 100 m when conductors of 0.129 mm² (AWG 26) or larger are used and the cable shield should be connected to the grounded panel / cubicle at the keypad end of the cable.

Figure 5-5 KI-485 Adaptor Installation



To install, align the KI-485 Adaptor and press gently in the direction shown until it clicks into position. To remove, reverse the installation instructions.

NOTE

The KI-485 Adaptor can be installed / removed while the drive is powered up and running a motor, providing a remote keypad is not connected to a port on the KI-485 Adaptor and operating in keypad mode

When using the Control Techniques converters or any other suitable converter with the drive, it is recommended that no terminating resistors be connected on the network. It may be necessary to disconnect the terminating resistor within the converter depending on which type is used.

Serial communications set-up parameters

The following parameters need to be set according to the system requirements.

Serial communications set-up parameters						
<i>Serial Mode</i> (11.024) {00.035}	Data Bits	Stop Bits	Parity	Register Mode	Pr 11.024	This parameter defines the supported data formats used by the EIA-485 comms port on the drive. This parameter can be changed via the drive keypad, via a option module or via the comms interface itself.
	8	2	NP	Standard	0	
	8	1	NP	Standard	1	
	8	1	EP	Standard	2	
	8	1	OP	Standard	3	
	8	2	NP	Modified	4	
	8	1	NP	Modified	5	
	8	1	EP	Modified	6	
	8	1	OP	Modified	7	
	7	2	NP	Standard	8	
	7	1	NP	Standard	9	
	7	1	EP	Standard	10	
	7	1	OP	Standard	11	
	7	2	NP	Modified	12	
	7	1	NP	Modified	13	
7	1	EP	Modified	14		
7	1	OP	Modified	15		
<i>Serial Baud Rate</i> (11.025) {00.036}	300 (0), 600 (1), 1200 (2), 2400 (3), 4800 (4), 9600 (5), 19200 (6), 38400 (7), 57600(8), 76800(9), 115200 (10)				This parameter can be changed via the drive keypad, via a option module or via the comms interface itself. If it is changed via the comms interface, the response to the command uses the original baud rate. The master should wait at least 20 ms before sending a new message using the new baud rate.	
<i>Serial Address</i> (11.023) {00.037}	1 to 247				This parameter defines the serial address and an addresses between 1 and 247 are permitted.	

See Chapter 10 *Building Automation* on page 198 for further information

about the three building automation network (BAN) protocols available with the HVAC drive H300.

NOTE

This drive does not provide the necessary line polarization for correct operation of the EIA-485 port, the data lines (Rx Tx and /Rx /Tx) must be correctly biased in accordance with the relevant protocol specification, this is normally done in the communication master or controller. Please refer to the relevant communication protocol specification for more information.

6 Basic parameters

6.1 Menu 0: Basic parameters

Menu 0 is used to bring together various commonly used parameters for basic easy set up of the drive. All the parameters in Menu 0 appear in other menus in the drive (denoted by {...}). Menu 22 can be used to configure the parameters in Menu 0.

Parameter	Range			Default			Type							
	OL	RFC-A	RFC-S	OL	RFC-A	RFC-S								
00.001	Motor Rpm	{05.004}	±180000 rpm					RO	Num	ND	NC	PT	FI	
	Speed Feedback	{03.002}	VM_SPEED rpm					RO	Num	ND	NC	PT	FI	
00.002	Output Frequency	{05.001}	VM_SPEED_FREQ_REF Hz	±2000.0 Hz					RO	Num	ND	NC	PT	FI
00.003	Current Magnitude	{04.001}	0.000 to VM_DRIVE_CURRENT_UNIPOLAR A						RO	Bit	ND	NC	PT	FI
00.004	Output Power	{05.003}	VM_POWER kW						RO	Num	ND	NC	PT	FI
00.005	Software Version	{11.029}	00.00.00.00 to 99.99.99.99						RO	Num	ND	NC	PT	
00.010	Minimum Reference Clamp	{01.007}	VM_NEGATIVE_REF_CLAMP1 Hz / rpm		15 Hz	450 rpm		RW	Num				US	
00.011	Maximum Reference Clamp	{01.006}	VM_POSITIVE_REF_CLAMP1 Hz / rpm		50 Hz default: 50.0 Hz 60 Hz default: 60.0 Hz	50 Hz default: 1500.0 rpm 60 Hz default: 1800.0 rpm	3000.0 rpm	RW	Num				US	
00.012	Acceleration Rate 1	{02.011}	0.0 to VM_ACCEL_RATE s to Pr 01.006	0.000 to VM_ACCEL_RATE s to Pr 01.006		10.0 s to Pr 01.006	10.000 s to Pr 01.006		RW	Num			US	
00.013	Deceleration Rate 1	{02.021}	0.0 to VM_ACCEL_RATE s from Pr 01.006	0.000 to VM_ACCEL_RATE s from Pr 01.006		10.0 s from Pr 01.006	10.000 s from Pr 01.006		RW	Num			US	
00.014	Open-loop Control Mode	{05.014}	Ur S (0), Ur (1), Fixed (2), Ur Auto (3), Ur I (4), Square (5), Sync Motor (6)		Fixed (2)				RW	Txt			US	
	Speed Controller Proportional Gain Kp1	{03.010}	0.0000 to 200.0000 s/rad				0.0300 s/rad		RW	Num			US	
00.015	Dynamic V to F Select	{05.013}	Off (0) or On (1)		On (1)				RW	Bit			US	
	Speed Controller Integral Feedback Gain Ki 1	{03.011}	0.00 to 655.35 s ² /rad				0.10 s ² /rad		RW	Num			US	
00.016	Low Frequency Voltage Boost	{05.015}	0.0 to 25.0 %		0.50 %				RW	Num			US	
	Speed Controller Differential Feedback Gain Kd1	{03.012}	0.00000 to 0.65535 1/rad				0.00000 1/rad		RW	Num			US	
00.017	Number Of Motor Poles	{05.011}	Automatic (0) to 480 Poles (240)			Automatic (0) 8 Poles (4)		RW	Num				US	
00.018	Rated Voltage	{05.009}	0 to VM_AC_VOLTAGE_SET V			200V drive: 230V 50Hz default 400V drive: 400V 60Hz default 400V drive: 460V 575V drive: 575V 690V drive: 690V		RW	Num		RA		US	
00.019	Rated Speed	{05.008}	0 to 33000 rpm	0.00 to 33000.00 rpm		50 Hz default - 1500 rpm 60 Hz default- 1800 rpm	50 Hz default - 1450.00 rpm 60 Hz default- 1750.00 rpm	3000.00 rpm	RW	Num				US
			0.000 to VM_RATED_CURRENT A			Maximum rated current (Pr 11.060) A			RW	Num		RA		US
00.021	Rated Frequency	{05.006}	0.0 to 550.0 Hz				50Hz default: 50.0 60Hz default: 60.0	RW	Num				US	
	Volts per 1000 rpm	{05.033}	0 to 10000 V / 1000 rpm				98 V / 1000 rpm	RW	Num				US	
00.022	Maximum Switching Frequency	{05.018}	2 kHz (0), 3 kHz (1), 4 kHz (2), 6 kHz (3), 8 kHz (4), 12 kHz (5), 16 kHz (6)			3 kHz (1)		RW	Txt		RA		US	
00.023	Catch A Spinning Motor	{06.009}	Disable (0), Enable (1), Fwd Only (2), Rev Only (3)		Enable (1)				RW	Txt			US	
00.024	Auto-tune	{05.012}	0 to 2	0 to 2	0, 1, 2, 6	0		RW	Num		NC			
00.025	Analog Input 1 Mode	{07.007}	4-20 mA Low (-4), 20-4 mA Low (-3), 4-20 mA Hold (-2), 20-4 mA Hold (-1), 0-20 mA (0), 20-0 mA (1), 4-20 mA Trip (2), 20-4 mA Trip (3), 4-20 mA (4), 20-4 mA (5), Volt (6), Therm Short Cct (7), Thermistor (8), Therm No Trip (9)			4-20 mA (4)		RW	Txt				US	

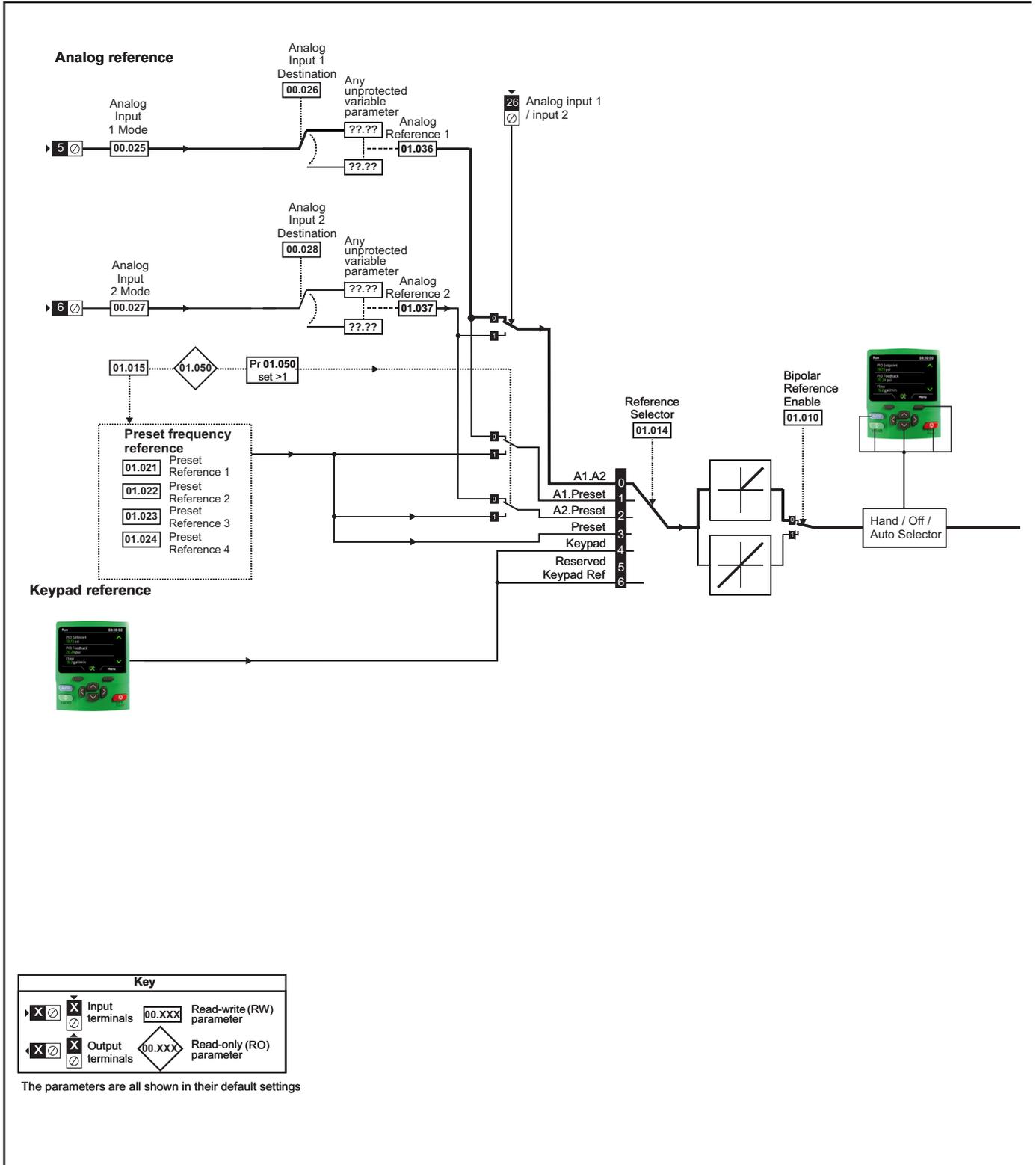
Parameter	Range			Default			Type							
	OL	RFC-A	RFC-S	OL	RFC-A	RFC-S								
00.026	Analog Input 1 Destination	{07.010}	0.000 to 59.999			01.036			RW	Num	DE		PT	US
00.027	Analog Input 2 Mode	{07.011}	4-20 mA Low (-4), 20-4 mA Low (-3), 4-20 mA Hold (-2), 20-4 mA Hold (-1), 0-20 mA (0), 20-0 mA (1), 4-20 mA Trip (2), 20-4 mA Trip (3), 4-29 mA (4), 20-4 mA (5), Volt (6), Therm Short Cct (7), Thermistor (8), Therm No Trip (9)			Volt (6)			RW	Txt				US
00.028	Analog Input 2 Destination	{07.014}	00.000 to 59.999			01.037			RW	Num	DE		PT	US
00.029	Analog Input 2 Thermistor Type	{07.058}	DIN44082 (0), KTY84 (1), PT100 (2), PT1000 (3), PT2000 (4), NI1000 (5)			DIN44082 (0)			RW	Txt				US
00.030	User Security Code	{11.030}	0 to 2147483647			0			RW	Num	ND	NC	PT	US
00.031	User Security Status	{11.044}	Menu 0 (0), All Menus (1), Read-only Menu 0 (2), Read-only (3), Status Only (4), No Access (5)			Menu 0 (0)			RW	Txt	ND		PT	
00.032	NV Media Card Data Previously Loaded	{11.036}	0 to 999			0			RO	Num		NC	PT	
00.033	Parameter Cloning	{11.042}	None (0), Read (1), Program (2), Auto (3), Boot (4)			None (0)			RW	Txt		NC		US
00.034	Date	{06.016}	00-00-00 to 31-12-99						RW	Date	ND	NC	PT	
00.035	Time	{06.017}	00:00:00 to 23:59:59						RW	Time	ND	NC	PT	
00.036	Day Of Week	{06.018}	Sunday (0), Monday (1), Tuesday (2), Wednesday (3), Thursday (4), Friday (5), Saturday (6)						RO	Txt	ND	NC	PT	
00.037	Date/Time Selector	{06.019}	Set (0), Powered (1), Running (2), Acc Powered (3), Local Keypad (4), Remote Keypad (5), Slot 1 (6), Slot 2 (7), Slot 3 (8), Slot 4 (9)			Local Keypad (4)			RW	Txt				US
00.038	Date Format	{06.020}	Std (0) or US (1)			US (1)			RW	Txt				US
00.040	RFC Low Speed Mode	{05.064}			Injection (0), Non-salient (1), Current (2), Current No Test (3)		Non-salient (1)	RW	Txt					US
00.041	Low Speed Sensorless Mode Current	{05.071}			0.0 to 1000.0 %		20.0 %	RW	Num		RA			US
00.042	No-load Lq	{05.072}			0.000 to 500.000 mH		0.000 mH	RW	Num		RA			US
00.043	Iq Test Current for Inductance Measurement	{05.075}			0 to 200 %		100 %	RW	Num					US
00.044	Phase Offset At Iq Test Current	{05.077}			±90.0 °		0.0 °	RW	Num		RA			US
00.045	Lq At The Defined Iq Test Current	{05.078}			0.000 to 500.000 mH		0.000 mH	RW	Num		RA			US
00.046	Id Test Current for Inductance Measurement	{05.082}			-100 to 0 %		-50 %	RW	Num					US
00.047	Lq At The Defined Id Test Current	{05.084}			0.000 to 500.000 mH		0.000 mH	RW	Num		RA			US
00.048	Number Of Auto-reset Attempts	{10.034}	None (0), 1 (1), 2 (2), 3 (3), 4 (4), 5 (5), Infinite (6)			5 (5)			RW	Txt				US
00.049	Auto-reset Delay	{10.035}	1.0 to 600.0 s			5.0 s			RW	Num				US
00.050	Trip 0	{10.020}	0 to 255						RO	Txt	ND	NC	PT	PS
00.051	Trip 1	{10.021}	0 to 255						RO	Txt	ND	NC	PT	PS
00.052	Trip 2	{10.022}	0 to 255						RO	Txt	ND	NC	PT	PS
00.053	Trip 3	{10.023}	0 to 255						RO	Txt	ND	NC	PT	PS
00.054	Trip 4	{10.024}	0 to 255						RO	Txt	ND	NC	PT	PS
00.055	Trip 5	{10.025}	0 to 255						RO	Txt	ND	NC	PT	PS
00.056	Trip 6	{10.026}	0 to 255						RO	Txt	ND	NC	PT	PS
00.057	Trip 7	{10.027}	0 to 255						RO	Txt	ND	NC	PT	PS
00.058	Trip 8	{10.028}	0 to 255						RO	Txt	ND	NC	PT	PS
00.059	Trip 9	{10.029}	0 to 255						RO	Txt	ND	NC	PT	PS
00.060	Trip 0 Date	{10.041}	00-00-00 to 31-12-99						RO	Date	ND	NC	PT	PS
00.061	Trip 0 Time	{10.042}	00:00:00 to 23:59:59						RO	Time	ND	NC	PT	PS
00.062	Trip 1 Date	{10.043}	00-00-00 to 31-12-99						RO	Date	ND	NC	PT	PS
00.063	Trip 1 Time	{10.044}	00:00:00 to 23:59:59						RO	Time	ND	NC	PT	PS
00.064	Trip 2 Date	{10.045}	00-00-00 to 31-12-99						RO	Date	ND	NC	PT	PS
00.065	Trip 2 Time	{10.046}	00:00:00 to 23:59:59						RO	Time	ND	NC	PT	PS
00.066	Trip 3 Date	{10.047}	00-00-00 to 31-12-99						RO	Date	ND	NC	PT	PS

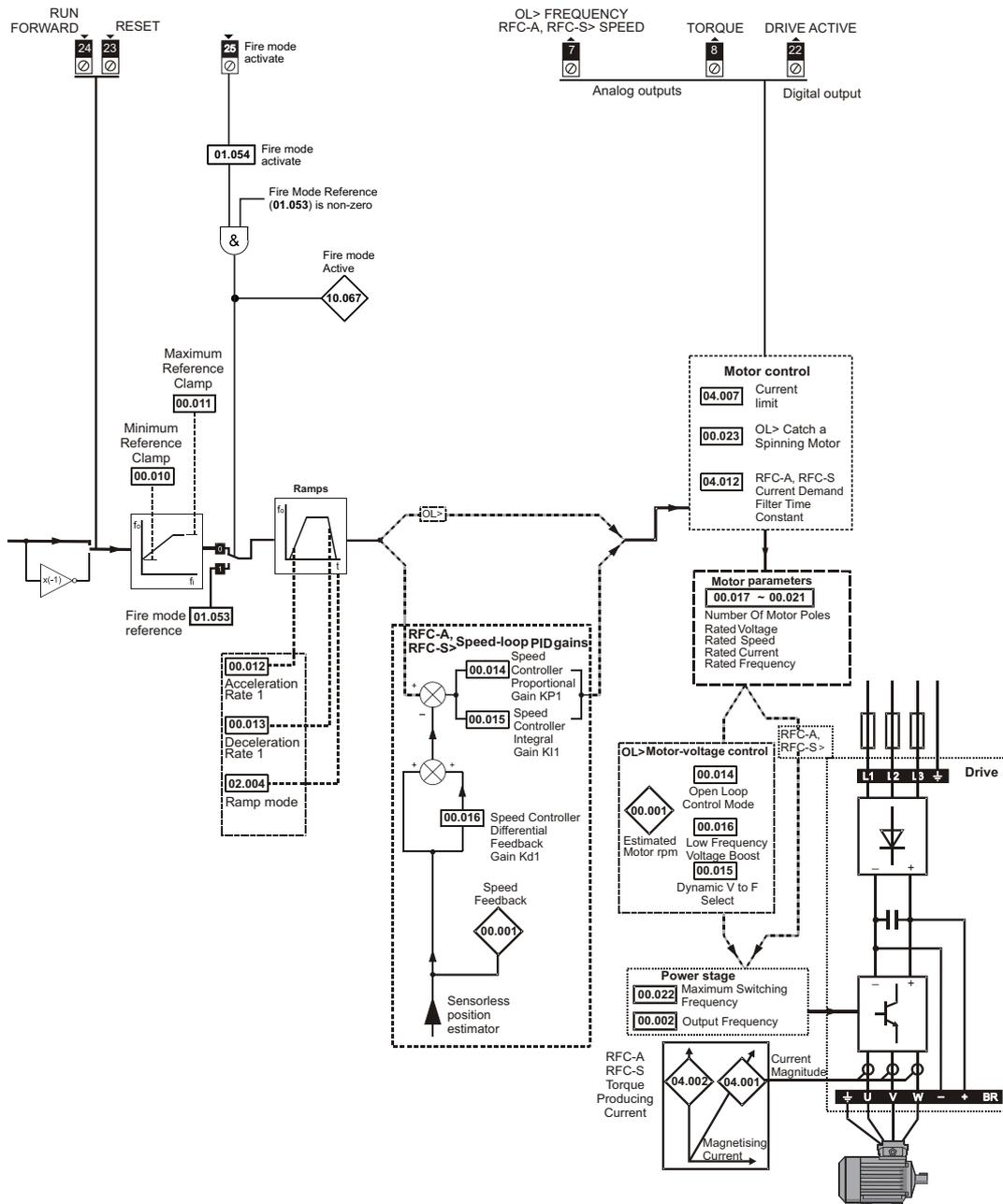
Safety information	Product information	Mechanical installation	Electrical installation	Getting started	Basic parameters	Running the motor	Optimization	NV Media Card Operation	Building Automation	Advanced parameters	Technical data	Diagnostics	UL listing information
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Parameter	Range			Default			Type						
	OL	RFC-A	RFC-S	OL	RFC-A	RFC-S	RO	Time	ND	NC	PT	PS	
00.067	Trip 3 Time	{10.048}	00:00:00 to 23:59:59					RO	Time	ND	NC	PT	PS
00.068	Trip 4 Date	{10.049}	00-00-00 to 31-12-99					RO	Date	ND	NC	PT	PS
00.069	Trip 4 Time	{10.050}	00:00:00 to 23:59:59					RO	Time	ND	NC	PT	PS
00.070	Trip 5 Date	{10.051}	00-00-00 to 31-12-99					RO	Date	ND	NC	PT	PS
00.071	Trip 5 Time	{10.052}	00:00:00 to 23:59:59					RO	Time	ND	NC	PT	PS
00.072	Trip 6 Date	{10.053}	00-00-00 to 31-12-99					RO	Date	ND	NC	PT	PS
00.073	Trip 6 Time	{10.054}	00:00:00 to 23:59:59					RO	Time	ND	NC	PT	PS
00.074	Trip 7 Date	{10.055}	00-00-00 to 31-12-99					RO	Date	ND	NC	PT	PS
00.075	Trip 7 Time	{10.056}	00:00:00 to 23:59:59					RO	Time	ND	NC	PT	PS
00.076	Trip 8 Date	{10.057}	00-00-00 to 31-12-99					RO	Date	ND	NC	PT	PS
00.077	Trip 8 Time	{10.058}	00:00:00 to 23:59:59					RO	Time	ND	NC	PT	PS
00.078	Trip 9 Date	{10.059}	00-00-00 to 31-12-99					RO	Date	ND	NC	PT	PS
00.079	Trip 9 Time	{10.060}	00:00:00 to 23:59:59					RO	Time	ND	NC	PT	PS
00.080	NV Media Card Action Status	{11.078}	None (0), Active (1), Card Slot 1 (2), Card Slot 2 (3), Card Slot 3 (4), Card Slot 4 (5), Card Product (6), Card User Prog (7), Card Busy (8), Card Data Exists (9), Card Option (10), Card Read Only (11), Card Error (12), Card No Data (13), Card Full (14), Card File Error (15), Card Rating (16), Card File Data (17), Card Derivative (18)					RO	Txt	ND	NC	PT	

RW	Read / Write	RO	Read only	Num	Number parameter	Bit	Bit parameter	Txt	Text string	Bin	Binary parameter	FI	Filtered
ND	No default value	NC	Not copied	PT	Protected parameter	RA	Rating dependent	US	User save	PS	Power-down save	DE	Destination
IP	IP address	Mac	Mac address	Date	Date parameter	Time	Time parameter						

Figure 6-1 Menu 0 logic diagram





6.2 Parameter descriptions

6.2.1 Pr mm.000

Pr **mm.000** is available in all menus, commonly used functions are provided as text strings in Pr **mm.000** shown in Table 6-1. The functions in Table 6-1 can also be selected by entering the appropriate numeric values (as shown in Table 6-2) in Pr **mm.000**. For example, enter 7001 in Pr **mm.000** to erase the file in NV media card location 001.

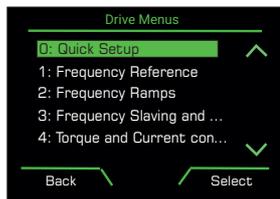


Table 6-1 Commonly used functions in xx.000

Value	Equivalent value	String	Action
0	0	[No Action]	
1001	1	[Save parameters]	Save parameters under all conditions
6001	2	[Load file 1]	Load the drive parameters from NV media card file 001
4001	3	[Save to file 1]	Transfer the drive parameters to parameter file 001
6002	4	[Load file 2]	Load the drive parameters from NV media card file 002
4002	5	[Save to file 2]	Transfer the drive parameters to parameter file 002
6003	6	[Load file 3]	Load the drive parameters from NV media card file 003
4003	7	[Save to file 3]	Transfer the drive parameters to parameter file 003
12000	8	[Show non-default]	Displays parameters that are different from defaults
12001	9	[Destinations]	Displays parameters that are set
1233	10	[Reset 50Hz Defs]	Load parameters with standard (50 Hz) defaults
1244	11	[Reset 60Hz Defs]	Load parameters with US (60 Hz) defaults
1070	12	[Reset modules]	Reset all option modules
11001	13	[Read Enc. NP P1]	No function on the H300
11051	14	[Read Enc. NP P2]	

Table 6-2 Functions in Pr mm.000

Value	Action
1000	Save parameters when <i>Under Voltage Active</i> (Pr 10.016) is not active and <i>Low Under Voltage Threshold Select</i> mode (Pr 06.067 = Off) is not active.
1001	Save parameter under all conditions
1070	Reset all option modules
1233	Load standard (50 Hz) defaults
1234	Load standard (50 Hz) defaults to all menus except option module menus (i.e 15 to 20 and 24 to 28)
1244	Load US (60 Hz) defaults
1245	Load US (60 Hz) defaults to all menus except option module menus (i.e 15 to 20 and 24 to 28)
1253	Change drive mode and load standard (50 Hz) defaults
1254	Change drive mode and load US (60 Hz) defaults
1255	Change drive mode and load standard (50 Hz) defaults except for menus 15 to 20 and 24 to 28
1256	Change drive mode and load US (60 Hz) defaults except for menus 15 to 20 and 24 to 28
1299	Reset {Stored HF} trip.
2001*	Create a boot file on a non-volatile media card based on the present drive parameters including all Menu 20 parameters
4yyy*	NV media card: Transfer the drive parameters to parameter file xxx
5yyy*	NV media card: Transfer the onboard user program to onboard user program file xxx. On Board user program, not supported on H300
6yyy*	NV media card: Load the drive parameters from parameter file xxx
7yyy*	NV media card: Erase file xxx
8yyy*	NV Media card: Compare the data in the drive with file xxx
9555*	NV media card: Clear the warning suppression flag
9666*	NV media card: Set the warning suppression flag
9777*	NV media card: Clear the read-only flag
9888*	NV media card: Set the read-only flag
9999*	NV media card: Erase and format the NV media card
12000**	Only display parameters that are different from their default value. This action does not require a drive reset.
12001**	Only display parameters that are used to set-up destinations (i.e. DE format bit is 1). This action does not require a drive reset.

* See Chapter 9 *NV Media Card Operation* on page 193 for more information on these functions.

** These functions do not require a drive reset to become active. All other functions require a drive reset to initiate the function.

To allow easy access to some commonly used functions, refer to the table overleaf. Equivalent values and strings are also provided in the table above.

6.3 Full descriptions

Table 6-3 Key to parameter table coding

Coding	Attribute
RW	Read/Write: can be written by the user
RO	Read only: can only be read by the user
Bit	1 bit parameter. 'On' or 'Off' on the display
Num	Number: can be uni-polar or bi-polar
Txt	Text: the parameter uses text strings instead of numbers.
Bin	Binary parameter
IP	IP Address parameter
Mac	Mac Address parameter
Date	Date parameter
Time	Time parameter
Chr	Character parameter
FI	Filtered: some parameters which can have rapidly changing values are filtered when displayed on the drive keypad for easy viewing.
DE	Destination: This parameter selects the destination of an input or logic function.
RA	Rating dependent: this parameter is likely to have different values and ranges with drives of different voltage and current ratings. Parameters with this attribute will be transferred to the destination drive by non-volatile storage media when the rating of the destination drive is different from the source drive and the file is a parameter file. However, the values will be transferred if only the current rating is different and the file is a difference from default type file.
ND	No default: The parameter is not modified when defaults are loaded
NC	Not copied: not transferred to or from non-volatile media during copying.
PT	Protected: cannot be used as a destination.
US	User save: parameter saved in drive EEPROM when the user initiates a parameter save.
PS	Power-down save: parameter automatically saved in drive EEPROM when the under volts (UV) trip occurs.

6.3.1 Parameter x.00

00.000 {mm.000}	Parameter zero
↕	0 to 65,535 ⇒

6.3.2 Monitoring

00.001 {05.004}	Motor Rpm				
RO	Num	ND	NC	PT	FI
OL	↕	±180000 rpm	⇒		

Open-loop

Pr **00.001 (05.004)** indicates the value of the motor speed that is estimated from the following:

- 02.001** Post Ramp Reference
- 00.017** Number Of Motor Poles

00.001 {03.002}	Speed Feedback				
RO	Num	ND	NC	PT	FI
RFC-A	↕	VM_SPEED rpm	⇒		
RFC-S					

RFC-A / RFC-S

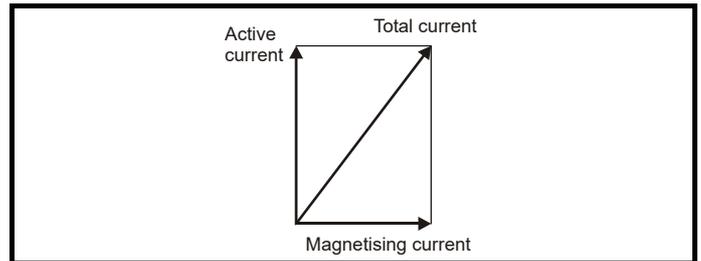
Pr **00.001 (03.002)** indicates the value of the motor speed which is obtained from the speed feedback.

00.002 {05.001}	Output Frequency				
RO	Num	ND	NC	PT	FI
OL	↕	VM_SPEED_FREQ_REF Hz	⇒		
RFC-A		±2000.0 Hz	⇒		
RFC-S					

Pr **00.002 (05.001)** displays the frequency at the drive output.

00.003 {04.001}	Current Magnitude				
RO	Bit	ND	NC	PT	FI
OL	↕	0.000 to VM_DRIVE_CURRENT_UNIPOLAR A	⇒		
RFC-A					
RFC-S					

Pr **00.003** displays the rms value of the output current of the drive in each of the three phases. The phase currents consist of an active component and a reactive component, which can form a resultant current vector as shown in the following diagram:



The active current is the torque producing current and the reactive current is the magnetizing or flux-producing current.

00.004 {05.003}	Output Power				
RO	Num	ND	NC	PT	FI
OL	↕	VM_POWER kW	⇒		
RFC-A					
RFC-S					

The output power (**05.003**) is the power flowing via the a.c. terminals of the drive. The power is derived as the dot product of the the output voltage and current vectors, and so this is correct even if the motor parameters are incorrect and the motor model does not align the reference frame with the flux axis of a motor in RFC-A mode. For Open-loop, RFC-A and RFC-S modes, a positive value of power indicates power flowing from the drive to the motor.

6.3.3 Status information

00.005 {11.029} Software Version	
RW	Num
OL	00.00.00.00 to 99.99.99.99
RFC-A	
RFC-S	

The parameter displays the software version of the drive

6.3.4 Speed limits

00.010 {01.007} Minimum Reference Clamp	
RW	Num
OL	15 Hz
RFC-A	VM_NEGATIVE_REF_CLAMP1 Hz / rpm
RFC-S	450 rpm

Open-loop

Set Pr **00.010** at the required minimum output frequency of the drive for both directions of rotation. The drive speed reference is scaled between Pr **00.010** and Pr **00.011**. [**00.010**] is a nominal value; slip compensation may cause the actual frequency to be higher.

RFC-A / RFC-S

Set Pr **00.010** at the required minimum motor speed for both directions of rotation. The drive speed reference is scaled between Pr **00.010** and Pr **00.011**.

00.011 {01.006} Maximum Reference Clamp 1	
RW	Num
OL	50Hz default: 50.0 Hz 60Hz default: 60.0 Hz
RFC-A	50Hz default: 1500.0 rpm 60Hz default: 1800.0 rpm
RFC-S	3000 rpm

(The drive has additional over-speed protection).

Open-loop

Set Pr **00.011** at the required maximum output frequency for both directions of rotation. The drive speed reference is scaled between Pr **00.010** and Pr **00.010**. [**00.011**] is a nominal value; slip compensation may cause the actual frequency to be higher.

RFC-A / RFC-S

Set Pr **00.011** at the required maximum motor speed for both directions of rotation. The drive speed reference is scaled between Pr **00.010** and Pr **00.011**.

For operating at high speeds see section 8.4 *High speed operation* on page 188.

6.3.5 Ramps

00.012 {02.011} Acceleration Rate 1	
RW	Num
OL	0.0 to VM_ACCEL_RATE
RFC-A	0.000 to VM_ACCEL_RATE
RFC-S	

Set Pr **00.012** to the required rate of acceleration.

Note that larger values produce lower acceleration. The rate applies in both directions of rotation.

00.013 {02.021} Deceleration Rate 1	
RW	Num
OL	0.0 to VM_ACCEL_RATE
RFC-A	0.000 to VM_ACCEL_RATE
RFC-S	

Set Pr **00.013** to the required rate of deceleration.

Note that larger values produce lower deceleration. The rate applies in both directions of rotation.

6.3.6 Voltage boost, (open-loop), Speed-loop PID gains (RFC-A / RFC-S)

00.014 {05.014} Open-loop Control Mode	
RW	Txt
OL	Ur S (0), Ur (1), Fixed (2), Ur Auto (3), Ur I (4), Square (5), Sync Motor (6)

Open-loop

There are seven voltage modes available, which fall into three categories, vector control, fixed boost and single phase current output. For further details, refer to section 8.1.1 *Open loop motor control* on page 177.

00.014 {03.010} Speed Controller Proportional Gain Kp1	
RW	Num
RFC-A	0.0000 to 200.000 s/rad
RFC-S	0.0300 s/rad

RFC-A/ RFC-S

Pr **00.014 (03.010)** operates in the feed-forward path of the speed-control loop in the drive. See Figure 11-4 *Menu 3 RFC-A, RFC-S logic diagram* on page 234 for a schematic of the speed controller. For information on setting up the speed controller gains, refer to section 8 *Optimization* on page 177.

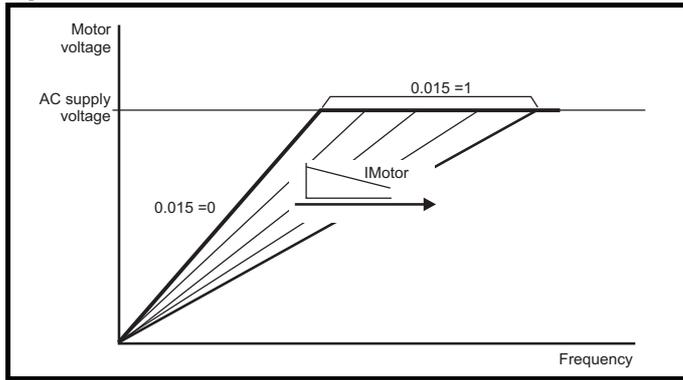
00.015 {05.013} Dynamic V to F Select	
RW	Bit
OL	Off (0) or On (1)

Open-loop

Set Pr **00.015 (05.013)** at 0 when the V/f characteristic applied to the motor is to be fixed. It is then based on the rated voltage and frequency of the motor.

Set Pr **00.015** at 1 when reduced power dissipation is required in the motor when it is lightly loaded. The V/f characteristic is then variable resulting in the motor voltage being proportionally reduced for lower motor currents. Figure shows the change in V/f slope when the motor current is reduced.

Figure 6-2 Fixed and variable V/f characteristics



RFC-S

This parameter must be set correctly for the vector control algorithms to operate correctly. When auto is selected the number of poles is set to 6.

00.018 {05.009} Rated Voltage		RW	Num	RA	US
OL					200 V drive: 230 V
RFC-A	↕		±VM_AC_VOLTAGE_SET	⇒	50Hz default 400 V drive: 400 V 60Hz default 400 V drive: 460 V
RFC-S					575 V drive: 575 V 690 V drive: 690 V

Open-loop and RFC-A

Enter the value from the rating plate of the motor.

00.015 {03.011} Speed Controller Integral Feedback Gain Ki 1		RW	Num	US
RFC-A	↕		0.00 to 655.35 s ² /rad	⇒ 0.10 s ² /rad
RFC-S				

RFC-A / RFC-S

Pr **00.015 (03.011)** operates in the feedback path of the speed-control loop in the drive. See section 11-4 *Menu 3 RFC-A, RFC-S logic diagram* on page 234 for a schematic of the speed controller. For information on setting up the speed controller gains, refer to section 8 *Optimization* on page 177.

00.019 {05.008} Rated Speed		RW	Num	US
OL	↕		0 to 33000 rpm	⇒ 50 Hz default: 1500 rpm 60 Hz default: 1800 rpm
RFC-A	↕		0.00 to 33000.00 rpm	⇒ 50 Hz default: 1450 rpm 60 Hz default: 1750 rpm
RFC-S	↕		0.00 to 33000.00 rpm	⇒ 3000.00 rpm

Open-loop

This is the speed at which the motor would rotate when supplied with its base frequency at rated voltage, under rated load conditions (= synchronous speed - slip speed). Entering the correct value into this parameter allows the drive to increase the output frequency as a function of load in order to compensate for this speed drop.

Slip compensation is disabled if Pr **00.019** is set to 0 or to synchronous speed, or if Pr **05.027** is set to 0.

If slip compensation is required, this parameter should be set to the value from the rating plate of the motor, which should give the correct rpm for a hot machine. Sometimes it will be necessary to adjust this when the drive is commissioned because the nameplate value may be inaccurate. Slip compensation will operate correctly both below base speed and within the field weakening region. Slip compensation is normally used to correct for the motor speed to prevent speed variation with load. The rated load rpm can be set higher than synchronous speed to deliberately introduce speed droop. This can be useful to aid load sharing with mechanically coupled motors.

00.016 {05.015} Low Frequency Voltage Boost		RW	Num	US
OL	↕		0.0 to 25.0 %	⇒ 0.50 %

00.016 {03.012} Speed Controller Differential Feedback Gain Kd 1		RW	Num	US
RFC-A	↕		0.00000 to 0.65535 1/rad	⇒ 0.00000 1/rad
RFC-S				

6.3.7 Motor parameters

00.017 {05.011} Number Of Motor Poles		RW	Num	US
OL				
RFC-A	↕		Automatic (0) to 480 Poles (240)	⇒ Automatic (0)
RFC-S				⇒ 8 Poles (4)

Open-loop

This parameter is used in the calculation of motor speed, and in applying the correct slip compensation. When Automatic (0) is selected, the number of motor poles is automatically calculated from the *Rated Frequency (00.021)* and the *Rated Speed rpm (00.019)*. The number of poles = 120 * rated frequency / rpm rounded to the nearest even number.

RFC-A

This parameter must be set correctly for the vector control algorithms to operate correctly. When Automatic (0) is selected, the number of motor poles is automatically calculated from the *Rated Frequency (00.021)* and the *Rated Speed rpm (00.019)* rpm. The number of poles = 120 * rated frequency / rpm rounded to the nearest even number.

RFC-A

Rated load rpm is used with motor rated frequency to determine the full load slip of the motor which is used by the vector control algorithm. Incorrect setting of this parameter can result in the following:

- Reduced efficiency of motor operation
- Reduction of maximum torque available from the motor
- Failure to reach maximum speed
- Over-current trips
- Reduced transient performance
- Inaccurate control of absolute torque in torque control modes

The nameplate value is normally the value for a hot machine, however, some adjustment may be required when the drive is commissioned if the nameplate value is inaccurate. The rated full load rpm can be optimized by the drive (For further information, refer to section 8.1.2 *RFC-A Sensorless mode* on page 180).

RFC-S

The rated speed is not used by the motor control algorithms, but is used by the motor thermal protection system.

00.020 {05.007} Rated Current										
RW	Num						RA	US		
OL	↕	0.000 to VM_RATED_CURRENT A					⇒	Maximum rated current (11.060) A		
RFC-A										
RFC-S										

Enter the name-plate value for the motor rated current.

00.021 {05.006} Rated Frequency										
RW	Num						RA	US		
OL	↕	0.0 to 550.0 Hz					⇒	50 Hz default: 50.0 Hz 60 Hz default: 60.0 Hz		

Enter the value from the rating plate of the motor.

00.021 {05.033} Volts per 1000 rpm										
RW	Num						RA	US		
RFC-A	↕	0.0 to 550.0 Hz					⇒	50 Hz default: 50.0 Hz 60 Hz default: 60.0 Hz		
RFC-S	↕	0 to 10000 V / 1000 rpm					⇒	98 V / 1000 rpm		

Enter the value from the rating plate of the motor.

00.022 {05.018} Maximum Switching Frequency										
RW	Txt						RA	US		
OL	↕	2 kHz (0), 3 kHz (1), 4 kHz (2), 6 kHz (3), 8 kHz (4), 12 kHz (5), 16 kHz (6)					⇒	3 kHz (1)		
RFC-A										
RFC-S										

This parameter defines the required switching frequency. The drive may automatically reduce the actual switching frequency (without changing this parameter) if the power stage becomes too hot. A thermal model of the IGBT junction temperature is used based on the heatsink temperature and an instantaneous temperature drop using the drive output current and switching frequency. The estimated IGBT junction temperature is displayed in Pr 07.034. If the temperature exceeds 145 °C the switching frequency is reduced if this is possible (i.e >3 kHz). Reducing the switching frequency reduces the drive losses and the junction temperature displayed in Pr 07.034 also reduces. If the load condition persists the junction temperature may continue to rise again above 145 °C and the drive cannot reduce the switching frequency further the drive will initiate an 'OHT Inverter' trip. Every second the drive will attempt to restore the switching frequency to the level set in Pr 00.022.

The full range of switching frequencies is not available on all ratings of Unidrive M. See section 8.3 *Switching frequency* on page 187 for the maximum available switching frequency for each drive rating.

00.023 {06.009} Catch A Spinning Motor OL and RFC-A										
RW	Txt						RA	US		
OL	↕	Disable (0), Enable (1), Fwd Only (2), Rev Only (3)					⇒	Enable (1)		
RFC-A										

Open-loop

When the drive is enabled with Pr 00.023 = 0, the output frequency starts at zero and ramps to the required reference. When the drive is enabled when Pr 00.023 has a non-zero value, the drive performs a

start-up test to determine the motor speed and then sets the initial output frequency to the synchronous frequency of the motor. Restrictions may be placed on the frequencies detected by the drive as follows:

Pr 00.023	Pr string	Function
0	Disable	Disabled
1	Enable	Detect all frequencies
2	Fwd only	Detect positive frequencies only
3	Rev only	Detect negative frequencies only

RFC-A mode

If sensorless mode is being used then it is recommended that catch a spinning motor is disabled if the motor will always be stationary when the drive is enabled as this gives a smooth start and avoids unwanted transient movement of the motor on starting. If catch a spinning motor is enabled, but the motor is at standstill or rotating slowly it is likely that some unwanted movement will occur. This can be reduced by reducing Magnetising Current Limit (04.049), however if this is reduced too much, especially with larger motors, and over-current trip may occur on starting. It is possible, although not likely, that the drive does not correctly detect the speed of the motor when sensorless control is active. If this is the case Spin Start Boost (05.040) can be increased to correct this.

00.024 {05.012} Auto-tune										
RW	Num						NC			
OL	↕	0 to 2					⇒	0		
RFC-A	↕	0 to 2					⇒			
RFC-S	↕	0, 1, 2, 6					⇒			

Open-Loop

There are two autotune tests available in open loop mode, a stationary and a rotating test. A rotating autotune should be used whenever possible so the measured value of power factor of the motor is used by the drive.

Autotune test 1:

- A stationary autotune can be used when the motor is loaded and it is not possible to remove the load from the motor shaft. The stationary test measures the *Stator Resistance* (05.017) and *Transient Inductance* (05.024) which are required for good performance in vector control modes (see Open Loop Control Mode (00.014). The stationary autotune does not measure the power factor of the motor so the value on the motor nameplate must be entered into Pr 05.010. To perform a Stationary autotune, set Pr 00.024 to 1, and provide the drive with both an enable signal (on terminal 29) and a run signal (on terminal 24).

Autotune test 2:

- A rotating autotune should only be used if the motor is unloaded. A rotating autotune first performs a stationary autotune, as above, then a rotating test is performed in which the motor is accelerated with currently selected ramps up to a frequency of *Rated Frequency* (05.006) x $\frac{2}{3}$, and the frequency is maintained at that level for 4 seconds. *Stator Inductance* (05.025) is measured and this value is used in conjunction with other motor parameters to calculate *Rated Power Factor* (05.010). To perform a Rotating autotune, set Pr 00.024 to 2, and provide the drive with both an enable signal (on terminal 29) and a run signal (on terminal 24).

Following the completion of an autotune test the drive will go into the inhibit state. The drive must be placed into a controlled disable condition before the drive can be made to run at the required reference. The drive can be put in to a controlled disable condition by removing the Safe Torque Off signal from terminal 29, setting the *Drive Enable* (06.015) to OFF (0) or disabling the drive via the *Control Word* (06.042) and *Control Word Enable* (06.043).

RFC-A

There are two autotune tests available in RFC-A mode, a stationary test, and a rotating test. A stationary autotune will give moderate performance whereas a rotating autotune will give improved performance as it measures the actual values of the motor parameters required by the drive.

It is highly recommended that a rotating autotune is performed (Pr **00.024** set to 2).

Autotune test 1:

- A stationary autotune can be used when the motor is loaded and it is not possible to remove the load from the motor shaft. The stationary autotune measures the *Stator Resistance* (**05.017**) and *Transient Inductance* (**05.024**) of the motor. These are used to calculate the current loop gains, and at the end of the test the values in Pr **04.013** and Pr **04.014** are updated. A stationary autotune does not measure the power factor of the motor so the value on the motor nameplate must be entered into Pr **05.010**.

To perform a Stationary autotune, set Pr **00.024** to 1, and provide the drive with both an enable signal (on terminal 29) and a run signal (on terminal 24).

Autotune test 2:

- A rotating autotune should only be used if the motor is unloaded. A rotating autotune first performs a stationary autotune, a rotating test is then performed which the motor is accelerated with currently selected ramps up to a frequency of *Rated Frequency* (**05.006**) $\times 2/3$, and the frequency is maintained at the level for up to 40 s. During the rotating autotune the *Stator Inductance* (**05.025**) is modified by the drive. The power factor is also modified for user information only, but is not used after this point as the stator inductance is used in the vector control algorithm instead. To perform a Rotating autotune, set Pr **00.024** to 2, and provide the drive with both an enable signal (on terminal 29) and a run signal (on terminal 24).

Following the completion of an autotune test, the drive will go into the inhibit state. The drive must be placed into a controlled disable condition before the drive can be made to run at the required reference. The drive can be put in to a controlled disable condition by removing the Safe Torque Off signal from terminal 29, setting the *Drive Enable* (**06.015**) to OFF (0) or disabling the drive via the control word (Pr **06.042** & Pr **06.043**).

RFC-S

There are three autotune tests available in RFC-S sensorless mode, a stationary autotune and a rotating autotune.

Autotune test 1:

- The stationary autotune can be used to measure all the necessary parameters for basic control. The tests measure *Stator Resistance* (**05.017**), *Ld* (**05.024**) and *No Load Lq* (**05.072**) The *Stator Resistance* (**05.017**) and the *Ld* (**05.024**) are then used to set up *Current controller Kp Gain* (**04.013**) and *Current Controller Ki Gain* (**04.014**). To perform a Stationary autotune, set Pr **00.024** to 1, and provide the drive with both an enable signal (on terminal 29) and a run signal (on terminal 24).

Autotune test 2:

- In sensorless mode, if Rotating autotune is selected (Pr **00.024** = 2), then a stationary autotune is performed.

Autotune test 6:

- Locket rotor test for load dependant parameters. This test is not implemented at the time of writing.

Following the completion of an autotune test the drive will go into the inhibit state. The drive must be placed into a controlled disable condition

before the drive can be made to run at the required reference. The drive can be put in to a controlled disable condition by removing the Safe Torque Off signal from terminal 29, setting the drive *Enable Parameter* (**06.015**) to OFF (0) or disabling the drive via the control word (Pr **06.042** & Pr **06.043**).

00.025 {07.007} Analog Input 1 Mode									
RW	Txt								US
OL									
RFC-A									
RFC-S	↕	4-20 mA Low (-4), 20-4 mA Low (-3), 4-20 mA Hold (-2), 20-4 mA Hold (-1), 0-20 mA (0), 20-0 mA (1), 4-20 mA Trip (2), 20-4 mA Trip (3), 4-20 mA (4), 20-4 mA (5), Volt (6), Therm Short Cct (7), Thermistor (8), Therm No Trip (9)	⇒					4-20 mA (4)	

In modes 2 and 3, a current loop loss trip is generated if the current falls below 3 mA.

In modes -4, -3, 2 and 3 the analog input level goes to 0.0 % if the input current falls below 3 mA.

In modes -2 and -1 the analog input remains at the value it had in the previous sample before the current fell below 3 mA.

Pr Value	Pr string	Comments
-4	4-20 mA Low	4-20 mA low value on current loss (1)
-3	20-4 mA Low	20-4 mA low value on current loss (1)
-2	4-20 mA Hold	4-20 mA hold at level before loss on current loss
-1	20-4 mA Hold	20-4 mA hold at level before loss on current loss
0	0-20 mA	
1	20-0 mA	
2	4-20 mA Trip	4-20 mA trip on current loss
3	20-4 mA Trip	20-4 mA trip on current loss
4	4-20 mA	
5	20-4 mA	
6	Volt	
7	Therm Short Cct	Temperature Measurement Input With Short Circuit Detection
8	Thermistor	Temperature Measurement Without Short Circuit Detection
9	Therm No Trip	Temperature Measurement Input With No Trips

00.026 {07.010} Analog Input 1 Destination									
RW	Num	DE					PT	US	
OL									
RFC-A	↕								
RFC-S		00.000 to 59.999	⇒					01.036	

Pr 00.026 sets the destination of analog input 1

00.027 {07.011} Analog Input 2 Mode									
RW	Txt								US
OL									
RFC-A									
RFC-S	↕	4-20 mA Low (-4), 20-4 mA Low (-3), 4-20 mA Hold (-2), 20-4 mA Hold (-1), 0-20 mA (0), 20-0 mA (1), 4-20 mA Trip (2), 20-4 mA Trip (3), 4-20 mA (4), 20-4 mA (5), Volt (6), Therm Short Cct (7), Thermistor (8), Therm No Trip (9)	⇒					Volt (6)	

In modes 2 and 3, a current loop loss trip is generated if the current falls below 3 mA.

In modes -4, -3, 2 and 3 the analog input level goes to 0.0 % if the input current falls below 3 mA.

In modes -2 and -1 the analog input remains at the value it had in the previous sample before the current fell below 3 mA.

Pr Value	Pr string	Comments
-4	4-20 mA Low	4-20 mA low value on current loss (1)
-3	20-4 mA Low	20-4 mA low value on current loss (1)
-2	4-20 mA Hold	4-20 mA hold at level before loss on current loss
-1	20-4 mA Hold	20-4 mA hold at level before loss on current loss
0	0-20 mA	
1	20-0 mA	
2	4-20 mA Trip	4-20 mA trip on current loss
3	20-4 mA Trip	20-4 mA trip on current loss
4	4-20 mA	
5	20-4 mA	
6	Volt	
7	Therm Short Cct	Temperature Measurement Input With Short Circuit Detection
8	Thermistor	Temperature Measurement Without Short Circuit Detection
9	Therm No Trip	Temperature Measurement Input With No Trips

00.028 {07.014} Analog Input 2 Destination									
RW	Num	DE					PT	US	
OL									
RFC-A	↕								
RFC-S		00.000 to 59.999	⇒					01.037	

Pr 00.028 sets the destination of analog input 2

00.029 {07.058}		Analog Input 2 Thermistor Type											
RW	Txt												US
OL		DIN44082 (0)											
RFC-A	⇕	KTY84 (1) PT100 (2) PT1000 (3) PT2000 (4) NI1000 (5)										⇒	DIN44082(0)
RFC-S													

Analog Input 2 Thermistor Type (00.029) selects the type of temperature feedback device used with analog Input 2 when Analog Input 2 Mode (00.027) is set-up for temperature feedback mode. When a temperature feedback mode is selected, 5V is applied to the output via a 3.3K Ω resistor to supply current through the temperature measuring device.

00.030 {11.030}		User Security Code											
RW	Num	ND	NC	PT									US
OL		0 to 2147483647											
RFC-A	⇕											⇒	0
RFC-S													

If any number other than 0 is programmed into this parameter, user security is applied so that no parameters except Pr 00.031 can be adjusted with the keypad. When this parameter is read via a keypad, it appears as 0. For further details refer to section 5.9.3 User Security Code on page 144.

00.031 {11.044}		User Security Status											
RW	Txt	ND		PT									
OL		Menu 0 (0), All Menus (1), Read-only Menu 0 (2), Read-only (3), Status Only (4), No Access (5)											
RFC-A	⇕											⇒	Menu 0 (0)
RFC-S													

This parameter controls access via the drive keypad as follows:

Security level	Description
0 (Menu 0)	All writable parameters are available to be edited but only parameters in Menu 0 are visible.
1 (All Menus)	All writable parameters are visible and available to be edited.
2 (Read-only Menu 0)	All parameters are read-only. Access is limited to Menu 0 parameters only.
3 (Read-only)	All parameters are read-only however all menus and parameters are visible.
4 (Status Only)	The keypad remains in status mode and no parameters can be viewed or edited.
5 (No Access)	The keypad remains in status mode and no parameters can be viewed or edited. Drive parameters cannot be accessed via a comms / fieldbus interface in the drive or any option module.

The keypad can adjust this parameter even when user security is set.

00.032 {11.044}		NV Media Card Data Previously Loaded											
RO	Num		NC	PT									
OL		0 to 999											
RFC-A	⇕											⇒	0
RFC-S													

This parameter shows the number of the data block last transferred from a SMARTCARD to the drive.

00.033 {11.042}		Parameter Cloning											
RW	Txt		NC										US
OL		None (0), Read (1), Program (2), Auto (3), Boot (4)											
RFC-A	⇕											⇒	None (0)
RFC-S													

* Only a value of 3 or 4 in this parameter is saved.

NOTE

If Pr 00.033 is equal to 1 or 2, this value is not transferred to the EEPROM or the drive. If Pr 00.033 is set to a 3 or 4 the value is transferred.

Pr String	Pr value	Comment
None	0	Inactive
Read	1	Read parameter set from the NV Media Card
Program	2	Programming a parameter set to the NV Media Card
Auto	3	Auto save
Boot	4	Boot mode

For further information, please refer to section 9 NV Media Card Operation on page 193.

00.034 {06.016}		Date											
RW	Date	ND	NC	PT									
OL		00-00-00 to 31-12-99											
RFC-A	⇕											⇒	
RFC-S													

Date (00.034), Time (00.035) and Day Of Week (00.036) show the date and time as selected by Date/Time Selector (00.037). Date (00.034) stores the date in dd.mm.yy format regardless of the setting made in Date Format (00.038) however if the parameter is viewed using a keypad the date will be displayed in the format selected in Date Format (00.038). If a real time clock is selected from an option module then the days, months and years are from the real time clock and the day of the week is displayed in Day Of Week (00.036). Otherwise the days have a minimum value of 0 and roll over after 30, the months have a minimum value of 0 and roll over after 11, and Day Of Week (00.036) is always 0 (Sunday).

If when setting the date/time this parameter is being written via comms or from an applications module then the value should be written in standard dd/mm/yy format as described below.

The value of this parameter as seen over comms or to an applications module is as follows.

$$\text{Value} = (\text{day}[1..31] \times 10000) + (\text{month}[1..12] \times 100) + \text{year}[0..99]$$

00.035 {06.017}		Time											
RW	Time	ND	NC	PT									
OL		00:00:00 to 23:59:59											
RFC-A	⇕											⇒	
RFC-S													

See Date (00.034)

00.036 {06.018}		Day of Week		
RO	Txt	ND	NC	PT
OL	Sunday (0), Monday (1), Tuesday (2), Wednesday (3), Thursday (4), Friday (5), Saturday (6)			
RFC-A				
RFC-S				

See Date (00.034)

00.037 {06.019}		Date / Time Selector	
RW	Txt		US
OL	Set (0), Powered (1), Running (2), Acc Powered (3), Local Keypad (4), Remote Keypad (5), Slot 1 (6), Slot 2 (7), Slot 3 (8), Slot 4 (9)		
RFC-A			
RFC-S			

When the Date/Time Selector (00.037) = 0, the Date (00.034) and Time (00.035) can be written by the user and the values in these parameters are transferred to the real time clocks in the keypad or any option modules that support this feature that are fitted to the drive. When Date/Time Selector (00.037) is changed to any other value, the real time clocks are allowed to run normally again. When Date/Time Selector (00.037) is changed from any value to 0 the date and time from a real time clock, if present, is automatically loaded into Date (00.034) and Time (00.035), so that this date and time is used as the initial value for editing. If more than one real time clock is present the date/time from the keypad is used, if present, and if not then the date/time from the lowest number slot with a real time clock is used.

Date (00.034) and Time (00.035) are used by the timers in Menu 09 and for time stamping trips. These features will continue to use the originally selected clock even if Date/Time Selector (00.037) is changed until a drive reset is initiated. If Date/Time Selector (00.037) has been changed and a reset is initiated Timer 1 Repeat Function (09.039) and Timer 2 Repeat Function (09.049) are set to zero to disable the timers, and the trip dates and times (00.060 to 00.079) are reset to zero.

Date / Time selector (00.037) is used to select the drive date and time as shown in the table below.

Date/Time Selector (06.019)	Date/Time Source
0: Set	Date and time parameters can be written by the user.
1: Power	Time since the drive was powered up.
2: Running	Accumulated drive running time since the drive was manufactured.
3: Acc Power	Accumulated powered-up time since the drive was manufactured.
4: Local Keypad	If a keypad fitted to the front of the drive includes a real time clock, then the date/time from this clock is displayed, otherwise the date/time is set to zero.
5: Remote Keypad	If a keypad connected to the user comms port of the drive with a EIA-485 includes a real time clock, then the date/time from this clock is displayed, otherwise the date/time is set to zero.
6: Slot 1	As 4 above, but for option slot 1.
7: Slot 2	As 4 above, but for option slot 2.
8: Slot 3	As 4 above, but for option slot 3.
9: Slot 4	As 4 above, but for option slot 4.

00.038 {06.020}		Date Format	
RW	Txt		US
OL	Std (0) or US (1)		
RFC-A			
RFC-S			

Date Format (00.038) selects the display style for Date (00.034), Timer 1 Start Date (09.035), Timer 1 Stop Date (09.037), Timer 2 Start Date (09.045), Timer 2 Stop Date (09.047), and for the trip time stamping date parameters (10.041, 10.043, 10.045, 10.047, 10.049, 10.051, 10.053, 10.055, 10.057 and 10.059) when displayed on a keypad connected to the drive. The format selection made in this parameter does not affect the value of these parameters if they are read using comms or by an applications program.

If Date Format (00.038) is 0 then standard format is used and the date is displayed on the keypad as dd.mm.yy and if Date Format (00.038) is 1 then US format is used and the date is displayed on the keypad as mm.dd.yy.

6.3.8 Additional parameters for RFC-S sensorless control

00.040 {05.064}		RFC Low Speed Mode	
RW	Txt		US
OL	Injection (0), Non-salient (1), Current (2), Current No Test (3)		
RFC-A			
RFC-S			

If sensorless mode is being used and is active (i.e. *Sensorless Mode Active* (03.078) = 1) and the motor speed is below *Rated Speed* (00.019) / 10 then a special low speed algorithm must be used to control the motor. *RFC Low Speed Mode* (00.040) is used to select the algorithm to be used.

0: Injection

A high frequency signal is injected into the motor to detect the motor flux axis. This can be used in a similar way to operation with position feedback except that for the drive to remain stable the speed controller bandwidth may need to be limited to 10 Hz or less and the current limit may need to be limited (see *Low Speed Sensorless Mode Current* (00.041)).

1: Non-salient

If the ratio $Lq/Ld < 1.1$ on no load then the injection mode cannot be used and this mode should be used instead. This mode does not provide the same level of control as injection mode and has the following restrictions:

- Speed control is possible, but not torque control.
- Spinning start is not possible and the motor must start from standstill.
- Below *Rated Speed* (00.019) / 10 it will not be possible to produce more than approximately 60 % to 70 % of rated torque.
- There may be some movement of the motor shaft in either direction as the motor starts.
- It is not possible to measure the motor inertia using auto-tuning with *Auto-tune* (00.024) = 4.
- Normally the ramp rate should not be slower than 5 s/1000 rpm when operating in the region below *Rated Speed* (00.019) / 10.
- This mode is not intended to control the motor for prolonged periods below *Rated Speed* (00.019) / 10, but is intended to allow the motor to be started from standstill to run outside the low speed region.
- This mode is not intended to allow motor reversals. If the direction does need to be reversed, the motor should be stopped and any

oscillations must die away, before the motor is restarted in the other direction.

Low Speed Sensorless Mode Current (00.041) defines a current applied in the motor d axis to aid starting. The default value is suitable for most motors with a load of up to 60% rated torque. However, in some applications this level may need to be adjusted.

2: Current

This method, which applies a rotating current vector at the frequency defined by the speed reference, can be used with any motor with no saliency or moderate saliency. It should only be used with motors where more of the torque is produced in conjunction with the magnet flux rather than from saliency torque. This mode does not provide the same level of control at low speed as injection mode, but is easier to set up and more flexible than "Non-salient" mode. The following should be considered:

1. Only speed control can be used when low speed mode operation is active.
2. A current specified by Low Speed Sensorless Mode Current (00.041) is applied when low speed mode is active. This current should be sufficient to start the motor with the highest expected load. If the motor has some saliency with no-load applied, and a suitable saturation characteristic, the drive can detect the rotor position and apply the current at the correct angle to avoid starting transient. If the motor is non-salient as defined by the conditions for Inductance trip then the drive will not attempt to detect the rotor position and the current will be applied at an arbitrary angle. This could cause a starting transient if the level of current applied is high, and so Low Speed Sensorless Mode Current (00.041) should not be set to a higher level than necessary. To minimise the movement as a result of applying the current, it is increased over the period defined by Sensorless Mode Current Ramp (05.063) in the form of a squared characteristic (i.e. it is increased with a low rate of change at the beginning and the rate of change is gradually increased).
3. It is not possible to measure the motor inertia using auto-tuning with Auto-tune (00.023) = 4.
4. As the level of current when low speed mode is active is not dependent on the applied load, but is as defined by Low Speed Sensorless Mode Current (00.041), and so the motor may become too hot if low speed mode is active for a prolonged period of time.
5. Generally Low Speed Sensorless Mode Current (00.041) should be set to a level higher than the expected maximum load, and can be set to a much higher level than the load if the saliency and saturation characteristic allow the position of the rotor to be detected on starting. However, Low Speed Sensorless Mode Current (00.041) should be matched more closely to the expected load under the following conditions: the load inertia is high compared to the motor inertia, or there is very little damping/loss in the load system, or where the q axis inductance of the motor changes significantly with load.

3: Current no test

The "Current" method is used, but no attempt is made to determine the position of the rotor before applying the current. This can be selected for example, if the motor does not have a suitable saturation characteristic to allow the rotor position to be determined during starting, or if faster starting is required. The initial current vector angle will be at an arbitrary position with respect to the actual rotor position. As the vector sweeps round it must make the rotor start to rotate. If the ramp rate is too high the rotor may not keep up with the current vector and the motor may not start. If this is the case then the ramp rate should be reduced and/or the current used to start the motor should be increased.

00.041 {05.071} Low Speed Sensorless Mode Current												
RW	Num					RA				US		
OL	⇕					⇒						
RFC-A												
RFC-S	⇕		0.0 to 1000.0 %			⇒				100.0 %		

Injection mode

For low speed sensorless operation with signal injection (*RFC Low Speed Mode (00.040) = 0*) it is necessary to have a ratio of $L_q/L_d = 1.1$. Even if a motor has a larger ratio on no load, this ratio normally reduces as the q axis current is increased from zero. *Low Speed Sensorless Mode Current Limit (00.041)* should be set at a level that is lower than the point where the inductance ratio falls to 1.1. The value of this parameter is used to define the drive current limits when signal injection is active and prevent loss of control of the motor.

Non-salient mode

For low speed sensorless operation for non-salient motors (*RFC Low Speed Mode (00.040) = 1*) defines a current applied in the d axis to aid starting. For most motors and applications requiring up to 60 % torque on starting, the default value is suitable. However the level of current may need to be increased to make the motor start.

00.042 {05.072} No-load Lq												
RW	Num					RA				US		
OL	⇕					⇒						
RFC-A												
RFC-S	⇕		0.000 to 500.000 mH							0.000 mH		

Motor q axis inductance with no current in the motor.

00.043 {05.075} Iq Test Current For Inductance Measurement												
RW	Num									US		
OL	⇕					⇒						
RFC-A												
RFC-S	⇕		0 to 200 %			⇒				100 %		

Maximum test current level used for I_q during auto-tuning when measuring the motor inductance and phase offset as a percentage of *Rated Current (00.020)*. This value is also used by the sensorless control algorithm to define the motor inductance and a reference frame phase offset at different levels of I_q . The values of *Lq At The Defined Iq Test Current (00.045)*, and *Phase Offset At Iq Test Current (00.044)*, should be the values which correspond to the test current level. For most motors, *Phase Offset At Iq Test Current (00.044)* will be zero and have little effect on the performance, however L_q is likely to vary significantly with I_q and should be set up correctly for good performance. *If Lq At The Defined Iq Test Current (00.045)*, or *Iq Test Current For Inductance Measurement (00.043)* are zero, then the estimate of L_q will not be affected by the level of I_q , and if *Phase Offset At Iq Test Current (00.044)* or *Iq Test Current For Inductance Measurement (00.043)* are zero the phase offset will not be affected by the level of I_q .

00.044 {05.077} Phase Offset At Iq Test Current	
RW	Num
OL	
RFC-A	
RFC-S	±90.0 °

This parameter defines the offset of the point of minimum inductance as an electrical angle from the point with no current in the motor, to the point with a level of Iq equivalent to *Iq Test Current For Inductance Measurement (00.043)*. When the value is left at its default value of zero, no compensation for phase offset with changes in Iq are made. *Phase Offset At Iq Test Current (00.044)* is used for low speed RFC sensorless control using injection mode. A positive value advances the point of minimum inductance with positive Iq. See *RFC Low Speed Mode (00.040)*. For most motors a value of zero is acceptable.

00.045 {05.078} Lq At The Defined Iq Test Current	
RW	Num
OL	
RFC-A	
RFC-S	0.000 to 500.000 mH

Motor q axis inductance with no current in the d axis and the current defined by *Iq Test Current For Inductance Measurement (00.043)* in the q axis of the motor. If this parameter is left at its default value of zero, then no compensation is made to the value of Lq with changes in Iq.

00.046 {05.082} Id Test Current For Inductance Measurement	
RW	Num
OL	
RFC-A	
RFC-S	-100 to 0 %

Minimum test current level used for Id during auto-tuning when measuring the motor inductance as a percentage of *Rated Current (00.020)*. This is then used in a similar way as *Iq Test Current For Inductance Measurement (00.043)*, to estimate the value of Lq used in the control algorithms as Id changes. If *Lq At The Defined Id Test Current (00.047)*, or *Id Test Current for Inductance Measurement (00.046)* are set to zero, then no compensation is made for changes in Lq with Id.

00.047 {05.084} Lq At The Id Test Current	
RW	Num
OL	
RFC-A	
RFC-S	0.000 to 500.000 mH

Motor q axis inductance with no current in the q axis and the current defined by *Id Test Current for Inductance Measurement (00.046)* in the d axis of the motor. If this parameter is left at its default value of zero then no compensation is made to the value of Lq with changes in Id.

00.048 {10.034} Number Of Auto Reset Attempts	
RW	Txt
OL	
RFC-A	None (0), 1 (1), (2), 3 (3), 4 (4), 5 (5), Infinite (6)
RFC-S	5 (5)

00.049 {10.035} Auto Reset Delay	
RW	Num
OL	
RFC-A	1.0 to 600.0s
RFC-S	5.0s

If Number Of Auto-reset Attempts (00.048) = 0 then no auto-reset attempts are made. Any other value will cause the drive to automatically reset following a trip for the number of times programmed after a delay defined by Auto-reset Delay (00.049) subject to the minimum reset time allowed for the type of trip. Note that for some trips the minimum is 10s. The auto-reset count is only incremented when the trip is the same as the previous trip otherwise it is reset to 0.

When the auto-reset count reaches the programmed value, any further trip of the same value will not cause an auto-reset. If the number of auto-reset attempts defined by Number Of Auto-reset Attempts (00.048) has not been reached and there has been no trip for 5 minutes then the auto-reset count is cleared. Auto reset will not occur after any trips with priority levels 1, 2 or 3 as defined in section 13.2 *Trip indications* on page 307. When a manual reset occurs the auto-reset counter is reset to zero.

If Number Of Auto-reset Attempts (00.048) = 6 the auto-reset counter is held at zero, and so there is no limit on the number of auto-reset attempts.

00.050 {10.020} Trip 0 to Trip 9	
RO	Txt
OL	
RFC-A	0 to 255
RFC-S	

00.060 {10.041}	Trip 0 Date
00.062 {10.043}	Trip 1 Date
00.064 {10.045}	Trip 2 Date
00.066 {10.047}	Trip 3 Date
00.068 {10.049}	Trip 4 Date
00.070 {10.051}	Trip 5 Date
00.072 {10.053}	Trip 6 Date
00.074 {10.055}	Trip 7 Date
00.076 {10.057}	Trip 8 Date
00.078 {10.059}	Trip 9 Date

RO	Txt	ND	NC	PT	PS
OL					
RFC-A	00-00-00 to 31-12-99				
RFC-S					

00.061 {10.042}	Trip 0 Time												
00.063 {10.044}	Trip 1 Time												
00.065 {10.046}	Trip 2 Time												
00.067 {10.048}	Trip 3 Time												
00.069 {10.050}	Trip 4 Time												
00.071 {10.052}	Trip 5 Time												
00.073 {10.054}	Trip 6 Time												
00.075 {10.056}	Trip 7 Time												
00.077 {10.058}	Trip 8 Time												
00.079 {10.060}	Trip 9 Time												
RO	Time	ND	NC	PT								PS	
OL		00:00:00 to 23:59:59											
RFC-A	⇕											⇒	
RFC-S													

Trip 0 (00.050) to Trip 9 (00.059) store the most recent 10 trips that have occurred where Trip 0 (00.050) is the most recent and Trip 9 (00.059) is the oldest. When a new trip occurs it is written to Trip 0 (00.050) and all the other trips move down the log, with oldest being lost. The date and time when each trip occurs are also stored in the date and time log, i.e. Trip 0 Date (00.060) to Trip 9 Time (00.079). The date and time are taken from Date (00.034) and Time (00.035).

00.080 {11.078}	NV Media Card Status												
RW	Txt	ND	NC	PT									
OL		0 to 18											
RFC-A	⇕											⇒	
RFC-S													

7 Running the motor

This chapter takes the new user through all the essential steps to running a motor for the first time, in each of the possible operating modes.

For information on tuning the drive for the best performance, see *Chapter 8 Optimization* on page 177.



Ensure that no damage or safety hazard could arise from the motor starting unexpectedly.



The values of the motor parameters affect the protection of the motor. The default values in the drive should not be relied upon. It is essential that the correct value is entered in Pr **00.020 Rated Current**. This affects the thermal protection of the motor.



If the drive is started using the keypad it will run to the speed defined by the keypad reference (Pr **01.017**). This may not be acceptable depending on the application. The user must check in Pr **01.017** and ensure that the keypad reference has been set to 0.



If the intended maximum speed affects the safety of the machinery, additional independent over-speed protection must be used.

7.1 Quick start connections



Fire Mode - Important Warning

When Fire Mode is active the motor overload and thermal protection are disabled, as well as a number of drive protection functions. Fire Mode is provided for use only in emergency situations where the safety risk from disabling protection is less than the risk from the drive tripping - typically in smoke extraction operation to permit evacuation of a building. The use of Fire Mode itself causes a risk of fire from overloading of the motor or drive, so it must only be used after careful consideration of the balance of risks. Care must be taken to prevent inadvertent activation or deactivation of Fire Mode. Fire Mode is indicated by a flashing display text warning "Fire mode active". Care must be taken to ensure that parameters Pr **01.053** or Pr **01.054** are not inadvertently re-allocated to different inputs or variables. It should be noted that, by default, Pr **01.054** is controlled from digital input 4 and changing Pr **08.024** can re-allocate this digital input to another parameter. These parameters are at access level 2 in order to minimize the risk of inadvertent or unauthorized changes. It is recommended that User Security be applied to further reduce the risk (see section 5.9 *Parameter access level and security* on page 144). These parameters may also be changed via serial communications so adequate precautions should be taken if this functionality is utilized.

7.1.1 Basic requirements

This section shows the basic connections which must be made for the drive to run in the required mode. For minimal parameter settings to run in each mode please see the relevant part of section 7.3 *Quick start commissioning / start-up* on page 170.

Table 7-1 Minimum control connection requirements for each control mode

Drive control method	Requirements
Auto mode	Drive enable Speed reference Run forward
Hand mode	Drive enable
Serial communications	Drive enable Serial communications link

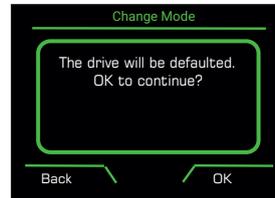
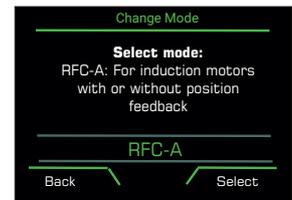
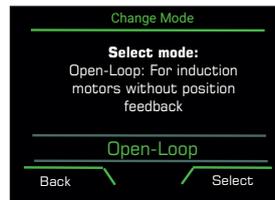
Table 7-2 Minimum requirements for each mode of operation

Operating mode	Requirements
Open loop mode	Induction motor
RFC – A sensorless (without feedback position)	Induction motor without speed feedback
RFC - S sensorless (without position feedback)	Permanent magnet motor without speed and position feedback

7.2 Changing the operating mode

Open Loop is default, if RFC-A Mode is required then Main Menu / Quick Actions/Mode Change.

When entering this mode it displays the current mode the drive is saved with. Open Loop is also the factory default. Use the Keypad \wedge \vee navigations keys navigate to the mode required.



On Selecting OK, a message will appear "Preparing Drive", after a few seconds "Mode Change Successful" will appear. Then go back to "Quick Actions" and save parameters.

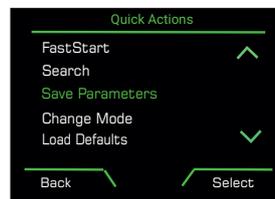


Figure 7-1 Minimum connections to get the motor running in any operating mode (size 3 and 4)

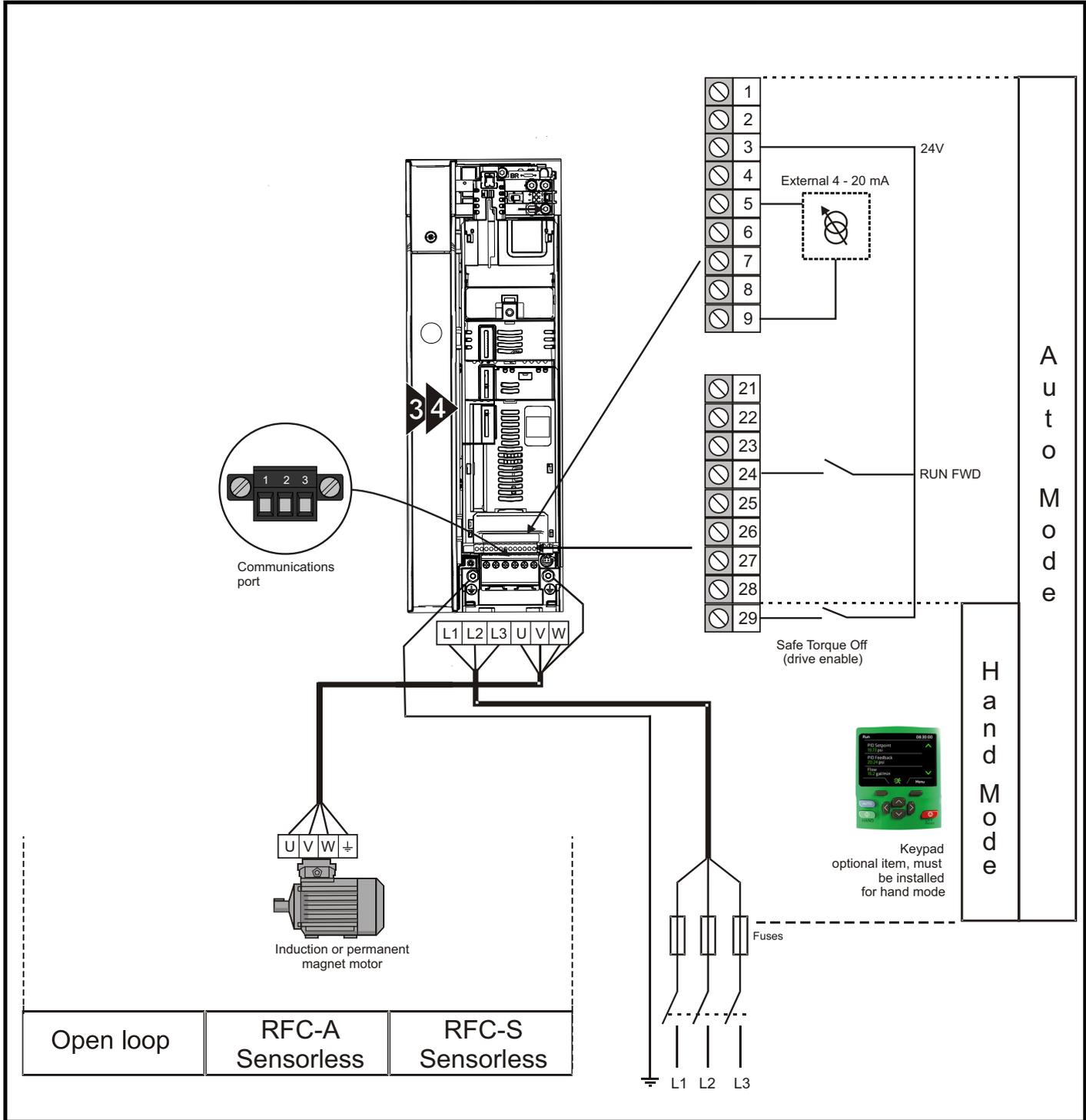


Figure 7-2 Minimum connections to get the motor running in any operating mode (size 5)

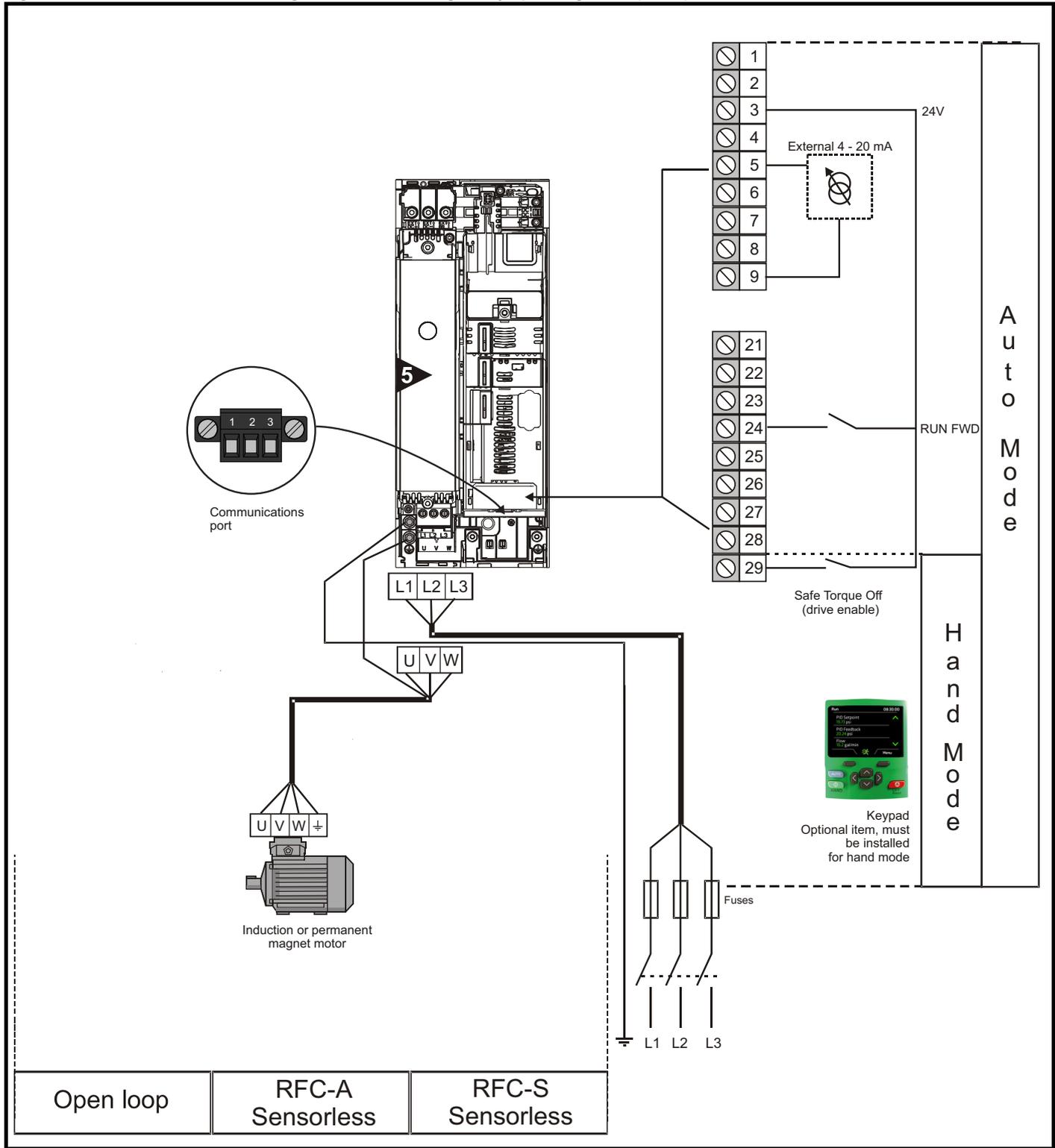


Figure 7-3 Minimum connections to get the motor running in any operating mode (size 6)

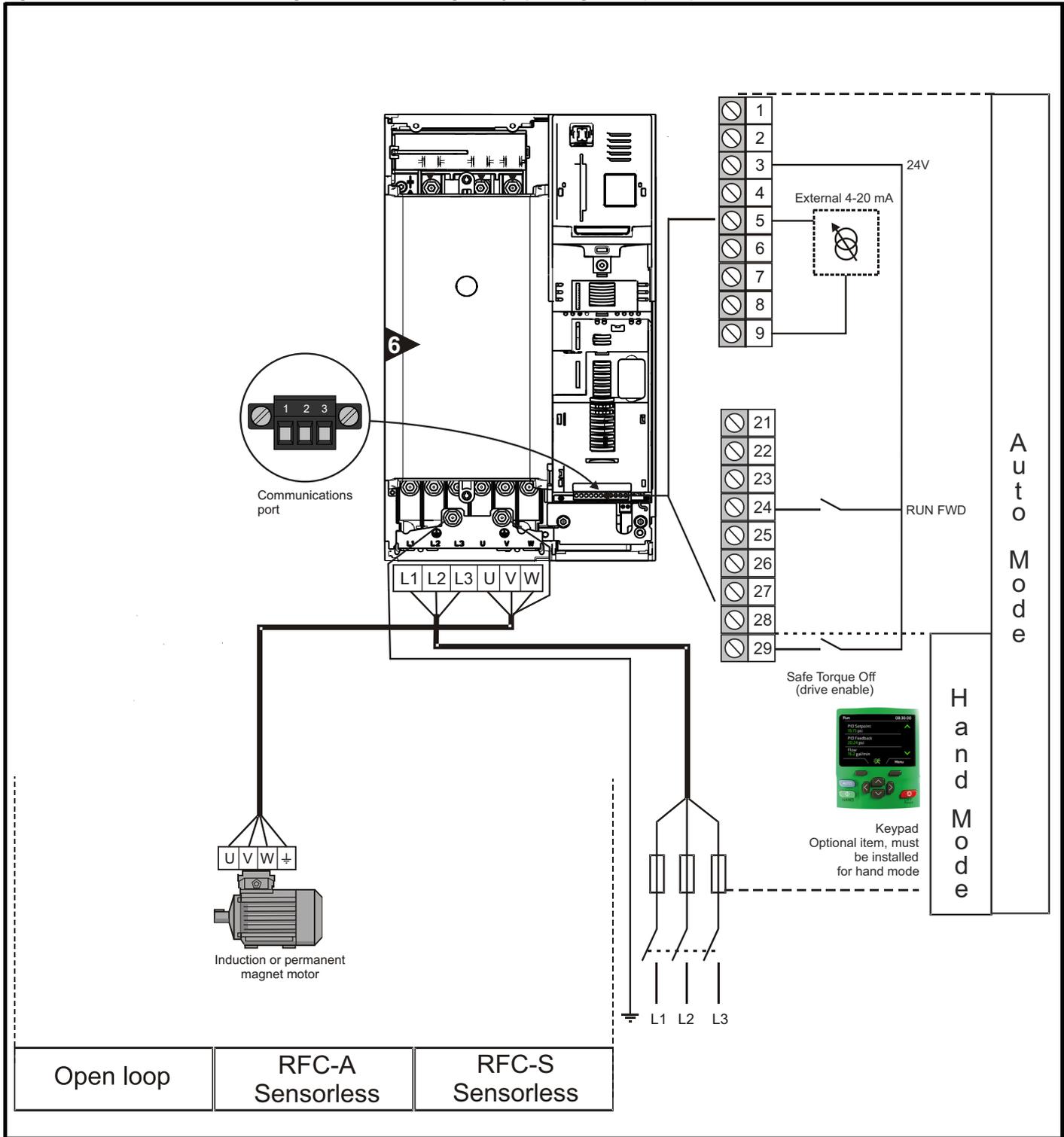
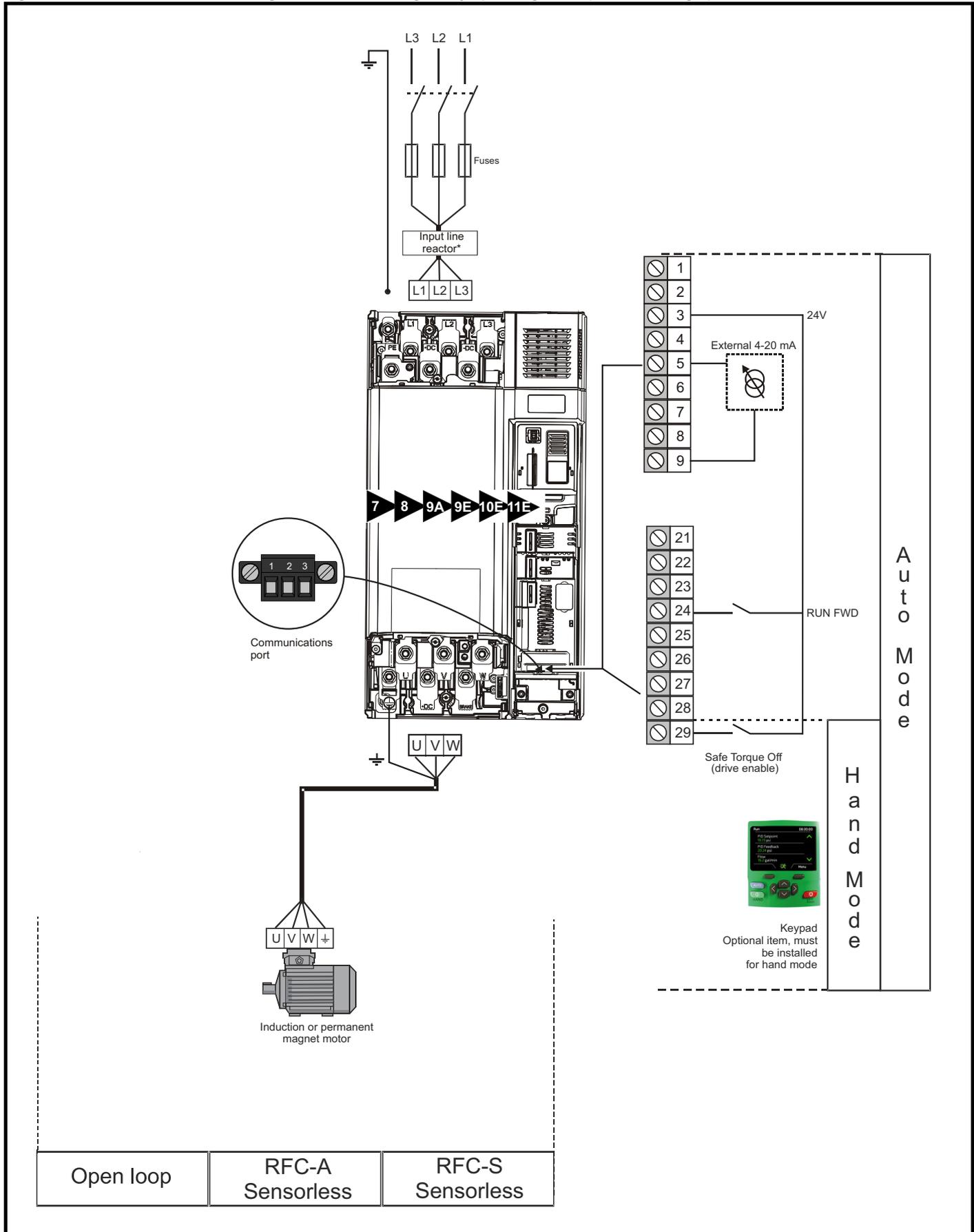


Figure 7-4 Minimum connections to get the motor running in any operating mode (size 7 and larger)



* Required for size 9E, 10E and 11E.

7.3 Quick start commissioning / start-up

7.3.1 Open loop

Action	Detail	
Before power-up	Ensure: <ul style="list-style-type: none"> The drive enable signal is not given (terminal 29) Run signal is not given Motor is connected 	
Power-up the drive	Verify that Open Loop mode is displayed as the drive powers up. If the mode is incorrect see section 5.6 <i>Changing the operating mode</i> on page 139. Ensure: <ul style="list-style-type: none"> Drive displays 'Inhibit' If the drive trips, see Chapter 13 <i>Diagnostics</i> on page 307.	
Enter motor nameplate details	Enter: <ul style="list-style-type: none"> Motor rated voltage in Pr 00.018 (V) - check if Δ or Δ connection Motor rated speed in Pr 00.019 (rpm) Motor rated frequency in Pr 00.021 (Hz) Motor rated current in Pr 00.020 (A) 	
Set maximum frequency	Enter: <ul style="list-style-type: none"> Maximum frequency in Pr 00.011 (Hz) 	
Set acceleration / deceleration rates	Enter: <ul style="list-style-type: none"> Acceleration rate in Pr 00.012 (s to Pr 01.006) Deceleration rate in Pr 00.013 (s from Pr 01.006) 	
Motor thermistor set-up	The motor thermistor can be selected in Pr 07.011 . Refer to Pr 07.011 for further information.	
Autotune	<p>The drive is able to perform either a stationary or a rotating autotune. The motor must be at a standstill before an autotune is enabled. A rotating autotune should be used whenever possible so the measured value of power factor of the motor is used by the drive.</p> <div style="border: 1px solid black; padding: 5px; margin-bottom: 10px;"> <p>WARNING A rotating autotune will cause the motor to accelerate up to $\frac{2}{3}$ base speed in the direction selected regardless of the reference provided. Once complete the motor will coast to a stop. The enable signal must be removed before the drive can be made to run at the required reference. The drive can be stopped at any time by removing the run signal or removing the drive enable.</p> </div> <ul style="list-style-type: none"> A stationary autotune can be used when the motor is loaded and it is not possible to uncouple the load from the motor shaft. A stationary autotune measures stator resistance and transient inductance of the motor and values relating to deadtime compensation from the drive. These are required for good performance in vector control modes. A stationary autotune does not measure the power factor of the motor so the value on the motor nameplate must be entered into Pr 05.010. A rotating autotune should only be used if the motor is uncoupled. A rotating autotune first performs a stationary autotune before rotating the motor at $\frac{2}{3}$ base speed in the direction selected. The rotating autotune measures the power factor of the motor. <p>To perform an autotune:</p> <ul style="list-style-type: none"> Set Pr 00.024 = 1 for a stationary autotune or set Pr 00.024 = 2 for a rotating autotune Close the Drive Enable signal (terminal 29). The drive will display 'Ready'. Close the run signal (terminal 24). The upper row of the display will flash 'Auto Tune' while the drive is performing the autotune. Wait for the drive to display 'Inhibit' and for the motor to come to a standstill. <p>If the drive trips, see Chapter 13 <i>Diagnostics</i> on page 307.</p> <ul style="list-style-type: none"> Remove the drive enable and run signal from the drive. 	

7.3.2 Save parameters for Open-loop

Action	Detail	
Save parameters	Select 'Save Parameters' in Pr mm.000 (alternatively enter a value of 1001 in Pr mm.000) and press the red reset button or toggle the reset digital input.	
Run	Drive is now ready to run	

7.3.3 RFC-A Sensorless

Induction motor without position feedback

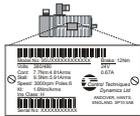
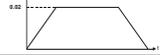
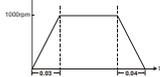
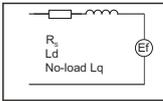
Action	Detail	
Before power-up	Ensure: <ul style="list-style-type: none"> The drive enable signal is not given (terminal 29) Run signal is not given Motor is connected 	
Power-up the drive	Verify that RFC-A mode is displayed as the drive powers up. If the mode is incorrect see section 5.6 <i>Changing the operating mode</i> on page 139, otherwise restore parameter defaults (See section 5.8 <i>Restoring parameter defaults</i> on page 144). Ensure: <ul style="list-style-type: none"> Drive displays 'Inhibit' If the drive trips, see <i>Chapter 13 Diagnostics</i> on page 307.	
Enter motor nameplate details	Enter: <ul style="list-style-type: none"> Motor rated voltage in Pr 00.018 (V) - check if Δ or Y connection Motor rated speed in Pr 00.019 (rpm) Motor rated current in Pr 00.020 (A) Motor rated frequency in Pr 00.021 (Hz) 	
Set maximum speed	Enter: <ul style="list-style-type: none"> Maximum speed in Pr 00.011 (rpm) 	
Set acceleration / deceleration rates	Enter: <ul style="list-style-type: none"> Acceleration rate in Pr 00.012 (s to Pr 01.006) Deceleration rate in Pr 00.013 (s from Pr 01.006) 	
Autotune	<p>The drive is able to perform either a stationary or a rotating autotune. The motor must be at a standstill before an autotune is enabled. A stationary autotune will give moderate performance whereas a rotating autotune will give improved performance as it measures the actual values of the motor parameters required by the drive.</p> <p>NOTE It is highly recommended that a rotating autotune is performed (Pr 00.024 set to 2).</p> <div style="border: 1px solid black; padding: 5px; margin: 10px 0;"> <p>A rotating autotune will cause the motor to accelerate up to $\frac{2}{3}$ base speed in the direction selected regardless of the reference provided. Once complete the motor will coast to a stop. The enable signal must be removed before the drive can be made to run at the required reference. The drive can be stopped at any time by removing the run signal or removing the drive enable.</p> </div> <ul style="list-style-type: none"> A stationary autotune can be used when the motor is loaded and it is not possible to uncouple the load from the motor shaft. The stationary autotune measures the stator resistance and transient inductance of the motor and values relating to deadtime compensation from the drive. Measured values are used to calculate the current loop gains, and at the end of the test the values in Pr 04.013 and Pr 04.014 are updated. A stationary autotune does not measure the power factor of the motor so the value on the motor nameplate must be entered into Pr 05.010. A rotating autotune should only be used if the motor is uncoupled. A rotating autotune first performs a stationary autotune before rotating the motor at $\frac{2}{3}$ base speed in the direction selected. The rotating autotune measures the stator inductance of the motor and calculates the power factor. <p>To perform an autotune:</p> <ul style="list-style-type: none"> Set Pr 00.024 = 1 for a stationary autotune or set Pr 00.024 = 2 for a rotating autotune Close the drive enable signal (terminal 29). The drive will display 'Ready' or 'Inhibit'. Close the run signal (terminal 24). The lower display will flash 'Autotune' while the drive is performing the autotune. Wait for the drive to display 'Inhibit' and for the motor to come to a standstill. <p>If the drive trips, see <i>Chapter 13 Diagnostics</i> on page 307.</p> <ul style="list-style-type: none"> Remove the drive enable and run signal from the drive. 	

7.3.4 Save parameters for RFC-A Sensorless

Action	Detail	
Save parameters	Select 'Save Parameters' in Pr mm.000 (alternatively enter a value of 1001 in Pr mm.000) and press the red reset button or toggle the reset digital input. Alternatively, save parameters using the Main Menu / Quick Actions / Save Parameters.	
Run	Drive is now ready to run	

7.3.5 RFC-S Sensorless

Permanent magnet motor without position feedback

Action	Detail	
Before power-up	Ensure: <ul style="list-style-type: none"> The drive enable signal is not given (terminal 29). Run signal is not given Motor is connected 	
Power-up the drive	Verify that RFC-S mode is displayed as the drive powers up. If the mode is incorrect see Chapter 5.6 <i>Changing the operating mode</i> on page 139, otherwise restore parameter defaults (see Chapter 5.8 <i>Restoring parameter defaults</i> on page 144). Ensure: <ul style="list-style-type: none"> Drive displays 'inhibit' If the drive trips, see Chapter 13 <i>Diagnostics</i> on page 307.	
Enter motor nameplate details	Enter <ul style="list-style-type: none"> Number of poles in Pr 00.017 Motor rated voltage in Pr 00.018 (V) Motor rated current in Pr 00.020 (A) 	
Set maximum speed	Enter: <ul style="list-style-type: none"> Maximum speed in Pr 00.002 (rpm) 	
Set acceleration / deceleration rates	Enter: <ul style="list-style-type: none"> Acceleration rate in Pr 00.012 (s to Pr 01.006) Deceleration rate in Pr 00.013 (s from Pr 01.006) 	
Autotune	The drive is able to perform a stationary autotune. The motor must be at a standstill before an autotune is enabled. A stationary autotune will give moderate performance. <ul style="list-style-type: none"> A stationary autotune is performed to locate the flux axis of the motor. The stationary autotune measures the stator resistance, inductance in flux axis, inductance in torque axis with no load on the motor and values relating to deadtime compensation from the drive. Measured values are used to calculate the current loop gains, and at the end of the test the values in Pr 04.013 and Pr 04.014 are updated. To perform an autotune: <ul style="list-style-type: none"> Set Pr 00.024 = 1 or 2 for a stationary autotune. (Both perform the same tests). Close the run signal (terminal 24). Close the drive enable signal (terminal 29). The upper row of the display will flash 'Auto Tune' while the drive is performing the test. Wait for the drive to display 'Inhibit'. If the drive trips it cannot be reset until the drive enable signal (terminal 29) has been removed. See Chapter 13 <i>Diagnostics</i> on page 307. <ul style="list-style-type: none"> Remove the drive enabled and run signal from the drive. 	
Check Saliency	In sensorless mode, when the motor speed is below Pr 00.019 / 10, a special low speed algorithm must be used to control the motor. There are three modes available, with the mode chosen based on the saliency of the motor. The ratio No-load Lq (Pr 00.042) / Ld (Pr 05.024) provides a measure of the saliency. If this value is > 1.1, then Injection (0) mode may be used. Current (2) mode may be used (but with limitations). If this value is < 1.1, then Current (2) mode must be used. Set Pr 00.040 for the required mode: Injection (0), Non-salient (1), Current (2) or Current No Test (3).	

7.3.6 Save parameters for RFC-S Sensorless

Action	Detail	
Save parameters	Select 'Save Parameters' in Pr mm.000 (alternatively enter a value of 1001 in Pr mm.000) and press the red  reset button or toggle the reset digital input. Alternatively, save parameters using the Main Menu / Quick Actions / Save Parameters.	
Run	Drive is now ready to run	

7.4 Quick start commissioning / start-up using HVAC Drive Connect (V02.00.05 onwards)

HVAC Drive Connect is a Windows™ based software commissioning/start-up tool for H300 drives. HVAC Drive Connect can be used for commissioning / start-up and monitoring, drive parameters can be uploaded, downloaded and compared and simple or custom menu listings can be created. Drive menus can be displayed in standard list format or as live block diagrams. HVAC Drive Connect is able to communicate with a single drive or a network. HVAC Drive Connect can be downloaded from www.controltechniques.com (file size approximately 100 MB). A KI-485 Adaptor and suitable USB to EIA-485 isolated converter is required for connection to HVAC Drive Connect. A suitable isolated converter is available from Control Techniques:

- CT USB Comms Cable (CT part number 4500-0096).

HVAC Drive Connect system requirements

Connect v02.20xx and before Win 7, v02.20.xx onwards Win 10 & 11.

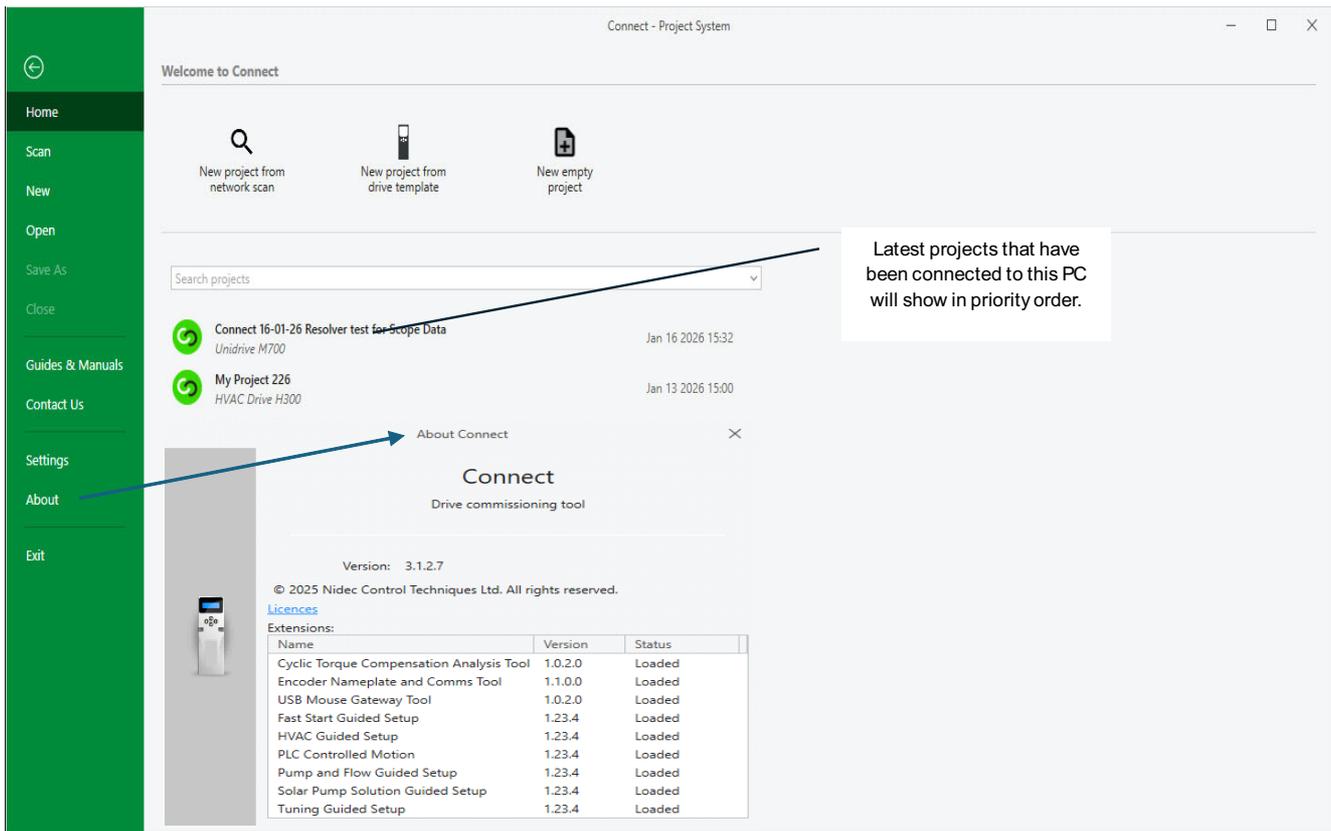
Connect v03.xx is: Operating system: Windows 10, Windows 11 (32-bit or 64-bit).

Disk space: 2GB or more free..net framework then Install Connect on Microsoft Windows (10 or later) by running the installation program provided. Your computer will need to have Microsoft .Net 4.8 installed too - in the unlikely event it hasn't the installer will download it from the internet

Any previous copy of HVAC Drive Connect should be uninstalled before proceeding with the installation (existing projects will not be lost). Included within the software is the *Parameter Reference Guide* for H300.

7.4.1 Power-up the drive

1. Start HVAC Drive Connect, and on the 'Project Management' screen select 'Scan serial RTU network' or 'Scan all connected drives'. Select the discovered drive.
Power Up the Drive the following screen will occur and select "About" provides the user with Version number and Extensions version numbers. The Screens below will reflect Connect Version 3.1.2



2. Select one of the following functions on highlighting a selection the selected requested option has Blue surround, the description below is assuming Bluetooth connection, other connections are similar but may have slight differences.

Select New Project with the selected drive option and the following screen with dashboard will be shown

Select wink this will show a flashing display on the drive that is connected.

Address	Type	Name	Serial number	Wink
C5:DD:73:BA:90:49 (Paired)	HVAC Drive H300	H300	7232415655	Wink
E6:89:04:03:7E:34 (Unpaired)	Unidrive M700	M700	123456789	Wink

1. When the drive is Online to the PC the Online Icon is highlighted Blue.
2. Selecting "Mode and Region" in "Drive and Settings" allows for the selection of the Drive Control Mode of Open Loop, RFC-A, or RFC-S, whilst the AC Supply frequency can also be changed to suit the supply frequency to the drive. Once the correct settings have been applied select Apply.
3. Note: There is a technical description for each Mode in the text field alongside each mode selection.

Dashboard (C5:DD:73:BA:90:49)
Commands for working with a drive. Commands can also be found in the ribbon and by right-clicking.

Quick Start
Drive: HVAC Drive H300
Slot 1: (Empty)
Slot 2: (Empty)
Slot 3: SI-Ethernet

Diagnostics
Parameter Listings -
Parameter Reference Guide
Block Diagrams -
Reset

Drive & Setup
Online
Connection settings
Change Firmware
Setup
Set real-time clock
Set mode and region
Set model
Keyboard Programming
SP Smartcard Migration
Deploy user
Delete user

Drive Settings

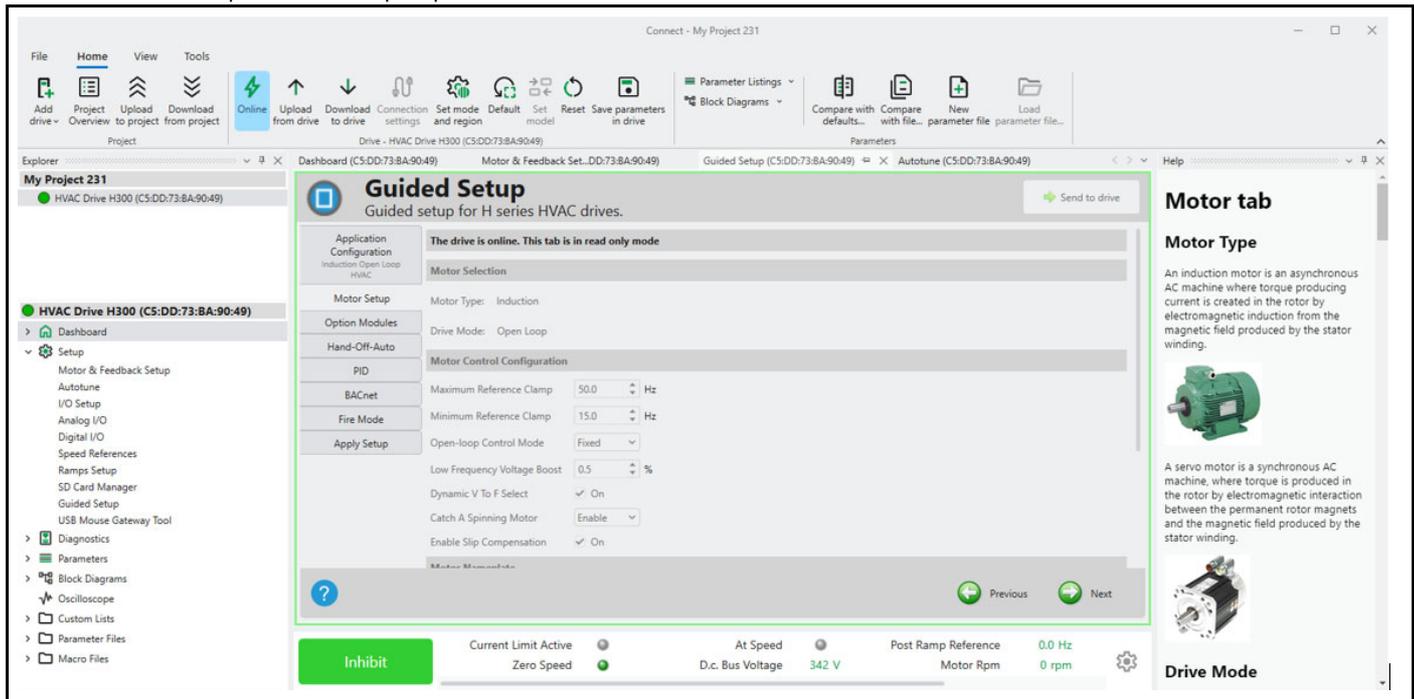
Mode
Open-Loop: This mode is suitable for 3 phase AC induction motors and other non-motor applications where a controllable 3 phase AC output is required.
RFC-A: For motor applications this mode is used where the actual shaft speed of the motor does not need to be accurate and can vary with load. This is usually the case for fan and pump loads. This mode is not suitable for systems where the low speed performance of the motor is important.
RFC-S: For motor applications, the speed of the motor is controlled by the output frequency and voltage of the drive. There will usually be a difference (slip) between the drive output frequency and the actual shaft speed. The slip will increase with load. Because the voltage applied to the motor is controlled with frequency the motor will not normally be subject to large starting currents.

Region
AC Supply Frequency: 50Hz
 Keep parameter values in option menus

Apply Cancel

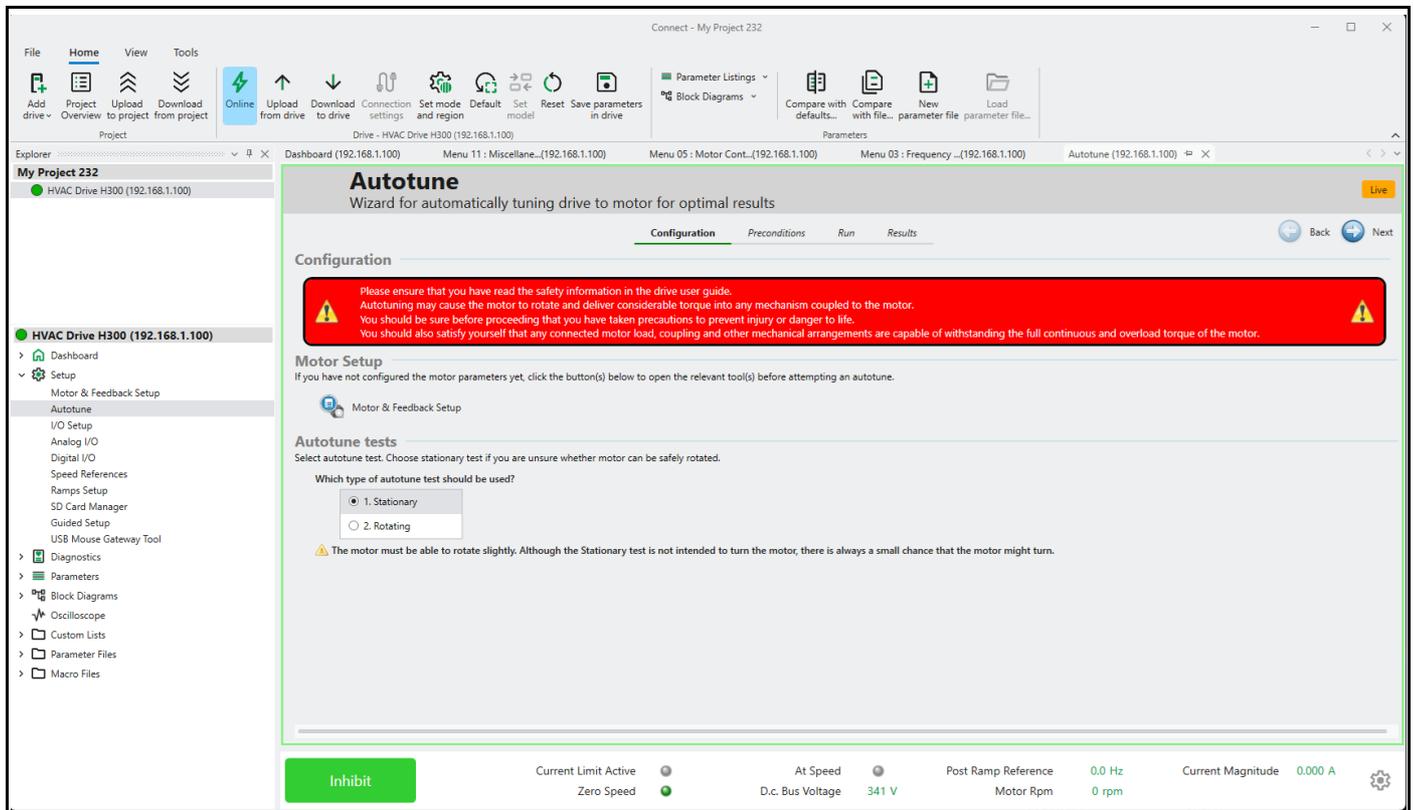
Inhibit
Current Limit Active
Zero Speed
At Speed
D.C. Bus Voltage 337 V
Post Ramp Ref
Motor

4. Select Default parameters from either the dashboard or the top line menu, this will set all parameters back to the Factory defaults.
5. Select Guided Setup and follow the prompts from there.



6. Please save all changes within the drive using the save option in the top line menu. Once the Guided set-up has been completed then consider using an Autotune for the Mode that the drive is set to via details within section 7.2 or via connect as per Figure 7-5 below.

Figure 7-5 Connect/Dashboard/Setup/Autotune.



7.5 Diagnostics

The Drive diagnostics screen can be shown as below selection this will provide the last 10 trips listed from the most recent these are also shown within Pr 10.020-10.029 Subtrips for Pr 10.020-10.029 are also listed on Pr 10.070 - Pr 10.079. Parameters Pr 10.001 through to Pr 10.019 provide additional drive status data some of these are also shown in the status bar at the bottom of the screen.

The screenshot displays the 'Drive Diagnostics' window in a software application. The interface includes a top toolbar with various icons for file operations and drive control. A left-hand navigation pane shows the project structure, with 'Diagnostics' and 'Drive Diagnostics' selected. The main area contains a table of trip history and a status bar at the bottom.

Current Status	History			
Trip	Trip Code	Sub-trip	Description	Timestamp*
Keypad Mode	34	0	Keypad has been removed when the drive is in keypad mode	Not available
Keypad Mode	34	0	Keypad has been removed when the drive is in keypad mode	Not available
Resistance	33	1	Stator resistance measurement failed or value exceeds the allowed range	Not available
Resistance	33	1	Stator resistance measurement failed or value exceeds the allowed range	Not available
Resistance	33	1	Stator resistance measurement failed or value exceeds the allowed range	01/01/2012 00:00:00
External Trip	6	3	External Trip has occurred	01/01/2012 00:00:00
External Trip	6	3	External Trip has occurred	01/01/2012 00:00:00
External Trip	6	3	External Trip has occurred	01/01/2012 00:00:00
External Trip	6	3	External Trip has occurred	01/01/2012 00:00:00
External Trip	6	3	External Trip has occurred	01/01/2012 00:00:00

* Timestamp is relative to the trip time depending the Date/Time Selector parameter (Pr6.019).
Keypad has been removed when the drive is in keypad mode

Suggested Actions

- Re-install keypad and reset.
- Change [P01.014] to select the reference from another source.

Clear Trip Log

Inhibit Current Limit Active Zero Speed At Speed D.c. Bus Voltage 336 V Post Ramp Reference 0.0 Hz Motor Rpm 0 rpm Current Magnitude 0.000 A

Refer to section 13 *Diagnostics* for additional information on Fault codes.

8 Optimization

This chapter takes the user through methods of optimizing the drive set-up and maximize the performance. The auto-tuning features of the drive simplify the optimization tasks.

8.1 Motor map parameters

8.1.1 Open loop motor control

Pr 00.020 {05.007} Rated Current	Defines the maximum continuous motor current
<ul style="list-style-type: none"> The rated current parameter must be set to the maximum continuous current of the motor. The motor rated current is used in the following: Current limits (see section 8.3 <i>Switching frequency</i> on page 187, for more information). Motor thermal overload protection (see section 8.2 <i>Motor thermal protection</i> on page 186, for more information) Vector mode voltage control (see <i>Open Loop Control Mode (00.014)</i>, later in this table) Slip compensation (see <i>Enable Slip Compensation (05.027)</i>, later in this table) Dynamic V/F control 	
Pr 00.018 {05.009} Rated Voltage	Defines the voltage applied to the motor at rated frequency
Pr 00.021 {05.006} Rated Frequency	Defines the frequency at which rated voltage is applied
<p>The <i>Rated Voltage (00.018)</i> and the <i>Rated Frequency (00.021)</i> are used to define the voltage to frequency characteristic applied to the motor (see <i>Open Loop Control Mode (00.014)</i>, later in this table). The <i>Rated Frequency (00.021)</i> is also used in conjunction with the motor rated speed to calculate the rated slip for slip compensation (see <i>Rated Speed (00.019)</i>, later in this table).</p>	
Pr 00.019 {05.008} Rated Speed	Defines the full load rated speed of the motor
Pr 00.017 {05.011} Number Of Motor Poles	Defines the number of motor poles
<p>The motor rated speed and the number of poles are used with the motor rated frequency to calculate the rated slip of induction machines in Hz.</p> $\text{Rated slip (Hz)} = \text{Motor rated frequency} - (\text{Number of pole pairs} \times [\text{Motor rated speed} / 60]) = \mathbf{00.021} = \left(\frac{\mathbf{00.017}}{2} \times \frac{\mathbf{00.019}}{60} \right)$ <p>If Pr 00.019 is set to 0 or to synchronous speed, slip compensation is disabled. If slip compensation is required this parameter should be set to the nameplate value, which should give the correct rpm for a hot machine. Sometimes it will be necessary to adjust this when the drive is commissioned because the nameplate value may be inaccurate. Slip compensation will operate correctly both below base speed and within the field-weakening region. Slip compensation is normally used to correct for the motor speed to prevent speed variation with load. The rated load rpm can be set higher than synchronous speed to deliberately introduce speed droop. This can be useful to aid load sharing with mechanically coupled motors.</p> <p>Pr 00.017 is also used in the calculation of the motor speed display by the drive for a given output frequency. When Pr 00.017 is set to 'Automatic', the number of motor poles is automatically calculated from the rated frequency Pr 00.021, and the motor rated speed Pr 00.019.</p> $\text{Number of poles} = 120 \times (\text{Rated Frequency (00.021)} / \text{Rated Speed (00.019)}) \text{ rounded to the nearest even number.}$	
Pr 05.010 Rated Power Factor	Defines the angle between the motor voltage and current
<p>The power factor is the true power factor of the motor, i.e. the angle between the motor voltage and current. The power factor is used in conjunction with the <i>Rated Current (00.020)</i>, to calculate the rated active current and magnetising current of the motor. The rated active current is used extensively to control the drive, and the magnetising current is used in vector mode stator resistance compensation. It is important that this parameter is set up correctly. The drive can measure the motor rated power factor by performing a rotating autotune (see Autotune (Pr 00.024), below).</p>	

Pr 00.024 {05.012} Autotune

There are two autotune tests available in open loop mode, a stationary and a rotating test. A rotating autotune should be used whenever possible so the measured value of power factor of the motor is used by the drive.

- A stationary autotune can be used when the motor is loaded and it is not possible to remove the load from the motor shaft. The stationary test measures the *Stator Resistance* (05.017) and *Transient Inductance* (05.024) which are required for good performance in vector control modes (see *Open Loop Control Mode* (00.014), later in this table). The stationary autotune does not measure the power factor of the motor so the value on the motor nameplate must be entered into Pr 05.010. To perform a Stationary autotune, set Pr 00.024 to 1, and provide the drive with both an enable signal (on terminal 29) and a run signal (on terminal 24).
- A rotating autotune should only be used if the motor is unloaded. A rotating autotune first performs a stationary autotune, as above, then a rotating test is performed in which the motor is accelerated with currently selected ramps up to a frequency of *Rated Frequency* (05.006) $\times \frac{2}{3}$, and the frequency is maintained at that level for 4 seconds. *Stator Inductance* (05.025) is measured and this value is used in conjunction with other motor parameters to calculate *Rated Power Factor* (05.010). To perform a Rotating autotune, set Pr 00.024 to 2, and provide the drive with both an enable signal (on terminal 29) and a run signal (on terminal 24).

Following the completion of an autotune test the drive will go into the inhibit state. The drive must be placed into a controlled disable condition before the drive can be made to run at the required reference. The drive can be put in to a controlled disable condition by removing the Safe Torque Off signal from terminal 29, setting the *Drive Enable* (06.015) to OFF (0) or disabling the drive via the *Control Word* (06.042) and *Control Word Enable* (06.043).

Pr 00.014 {05.014} Open Loop Control Mode

There are several voltage modes available which fall into two categories, vector control and fixed boost.

Vector control

Vector control mode provides the motor with a linear voltage characteristic from 0 Hz to motor *Rated Frequency* (00.021), and then a constant voltage above motor rated frequency. When the drive operates between motor rated frequency/50 and motor rated frequency/4, full vector based stator resistance compensation is applied. When the drive operates between motor rated frequency/4 and motor rated frequency/2 the stator resistance compensation is gradually reduced to zero as the frequency increases. For the vector modes to operate correctly the *Rated Power Factor* 05.010, *Stator Resistance* (05.017) and *Voltage Offset At Zero Current* (05.058) are all required to be set up accurately. The drive can be made to measure these by performing an autotune (see Pr 00.024 Autotune). The drive can also be made to measure the stator resistance and voltage offset automatically every time the drive is enabled or the first time the drive is enabled after it is powered up, by selecting one of the vector control voltage modes.

(0) **Ur S** = The stator resistance and the voltage offset are measured and the parameters for the selected motor map are over-written each time the drive is made to run. This test can only be done with a stationary motor where the flux has decayed to zero. Therefore this mode should only be used if the motor is guaranteed to be stationary each time the drive is made to run. To prevent the test from being done before the flux has decayed there is a period of 1 second after the drive has been in the ready state during which the test is not done if the drive is made to run again. In this case, previously measured values are used. Ur S mode ensures that the drive compensates for any change in motor parameters due to changes in temperature. The new values of stator resistance and voltage offset are not automatically saved to the drive's EEPROM.(4)

(4) **Ur I** = The stator resistance and voltage offset are measured when the drive is first made to run after each power-up. This test can only be done with a stationary motor. Therefore this mode should only be used if the motor is guaranteed to be stationary the first time the drive is made to run after each power-up. The new values of stator resistance and voltage offset are not automatically saved to the drive's EEPROM.

(1) **Ur** = The stator resistance and voltage offset are not measured. The user can enter the motor and cabling resistance into the *Stator Resistance* (05.017). However this will not include resistance effects within the drive inverter. Therefore if this mode is to be used, it is best to use an autotune test initially to measure the stator resistance and voltage offset.

(3) **Ur_Auto** = The stator resistance and voltage offset are measured once, the first time the drive is made to run. After the test has been completed successfully the *Open Loop Control Mode* (00.014) is changed to Ur mode. The *Stator Resistance* (05.017) and *Voltage Offset At Zero Current* (05.058) parameters are written to, and along with the *Open Loop Control Mode* (00.014), are saved in the drive's EEPROM. If the test fails, the voltage mode will stay set to Ur Auto and the test will be repeated next time the drive is made to run.

Fixed boost

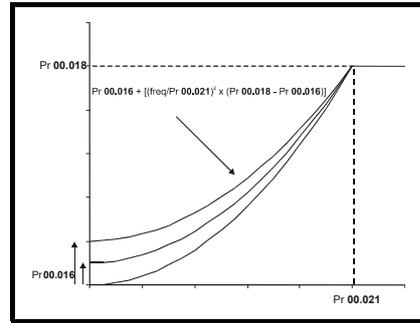
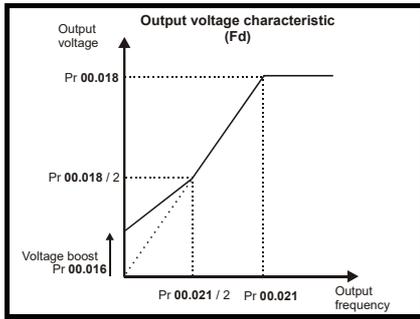
Neither the stator resistance nor the voltage offset are used in the control of the motor, instead a fixed characteristic with low frequency voltage boost as defined by Pr 00.016, is used. Fixed boost mode should be used when the drive is controlling multiple motors. There are two settings of fixed boost available:

(2) **Fixed** = This mode provides the motor with a linear voltage characteristic from 0 Hz to *Rated Frequency* (00.021), and then a constant voltage above rated frequency.

(5) **Square** = This mode provides the motor with a square law voltage characteristic from 0 Hz to *Rated Frequency* (00.021), and then a constant voltage above rated frequency. This mode is suitable for variable torque applications like fans and pumps where the load is proportional to the square of the speed of the motor shaft. This mode should not be used if a high starting torque is required.

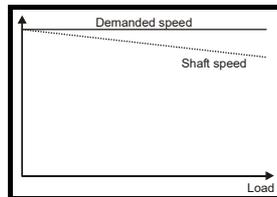
Pr 00.014 {05.014} Open Loop Control Mode (cont)

For both these modes, at low frequencies (from 0Hz to $\frac{1}{2}$ x Pr 00.021) a voltage boost is applied defined by Pr 00.016 as shown below:



Pr 05.027 Enable Slip Compensation

When a motor, being controlled in open loop mode, has load applied a characteristic of the motor is that the output speed drops in proportion to the load applied as shown:



In order to prevent the speed droop shown above slip compensation should be enabled. To enable slip compensation Pr 05.027 must be set to a 1 (this is the default setting), and the motor rated speed must be entered in Pr 00.019 (Pr 05.008).

The motor rated speed parameter should be set to the synchronous speed of the motor minus the slip speed. This is normally displayed on the motor nameplate, i.e. for a typical 18.5 kW, 50 Hz, 4 pole motor, the motor rated speed would be approximately 1465 rpm. The synchronous speed for a 50 Hz, 4 pole motor is 1500 rpm, so therefore the slip speed would be 35 rpm. If the synchronous speed is entered in Pr 00.019, slip compensation will be disabled. If too small a value is entered in Pr 00.019, the motor will run faster than the demanded frequency. The synchronous speeds for 50 Hz motors with different numbers of poles are as follows:

2 pole = 3000 rpm, 4 pole = 1500 rpm, 6pole =1000 rpm, 8 pole = 750 rpm

8.1.2 RFC-A Sensorless mode

Induction motor without position feedback

Pr 00.020 {05.007} Motor Rated Current	Defines the maximum motor continuous current
<p>The motor rated current parameter must be set to the maximum continuous current of the motor. The motor rated current is used in the following:</p> <ul style="list-style-type: none"> • Motor thermal overload protection (see section 8.2 <i>Motor thermal protection</i> on page 186, for more information) • Vector control algorithm 	
Pr 00.018 {05.009} Rated Voltage	Defines the voltage applied to the motor at rated frequency
Pr 00.021 {05.006} Rated Frequency	Defines the frequency at which rated voltage is applied
<p>The <i>Rated Voltage</i> (00.018) and the <i>Rated Frequency</i> (00.021) are used to define the voltage to frequency characteristic applied to the motor (see <i>Open Loop Control Mode</i> (00.014), later in this table). The motor rated frequency is also used in conjunction with the motor rated speed to calculate the rated slip for slip compensation (see motor <i>Rated Speed</i> (00.019), later in this table).</p>	
<p>The graph, titled 'Output voltage characteristic', plots Output voltage on the vertical axis against Output frequency on the horizontal axis. A solid line starts at the origin (0,0) and rises linearly to a point where the frequency is Pr 00.021 and the voltage is Pr 00.018. From this point, the line becomes horizontal, indicating constant voltage. A dashed line from the origin passes through a point where the frequency is Pr 00.021 / 2 and the voltage is Pr 00.018 / 2, showing that the voltage is proportional to frequency in the linear region.</p>	
Pr 00.019 {05.008} Rated Speed	Defines the full load rated speed of the motor
Pr 00.017 {05.011} Number Of Motor Poles	Defines the number of motor poles
<p>The motor rated speed and motor rated frequency are used to determine the full load slip of the motor which is used by the vector control algorithm. Incorrect setting of this parameter has the following effects:</p> <ul style="list-style-type: none"> • Reduced efficiency of motor operation • Reduction of maximum torque available from the motor • Reduced transient performance • Inaccurate control of absolute torque in torque control modes <p>The nameplate value is normally the value for a hot motor; however, some adjustment may be required when the drive is commissioned if the nameplate value is inaccurate. Either a fixed value can be entered in this parameter or an optimization system may be used to automatically adjust this parameter (see <i>Motor Parameter Adaptive Control</i> (05.016), later in this table).</p> <p>When Pr 00.017 is set to 'Automatic', the number of motor poles is automatically calculated from the motor <i>Rated Frequency</i> (00.021), and the motor <i>Rated Speed</i> (00.019).</p> <p>Number of poles = $120 \times (\text{Motor Rated Frequency } (00.021) / \text{Motor Rated Speed } (00.019))$ rounded to the nearest even number.</p>	
Pr 05.010 Rated Power Factor	Defines the angle between the motor voltage and current
<p>The power factor is the true power factor of the motor, i.e. the angle between the motor voltage and current. If the <i>Stator Inductance</i> (05.025) is set to zero then the power factor is used in conjunction with the motor <i>Rated Current</i> (00.020) and other motor parameters to calculate the rated active and magnetising currents of the motor, which are used in the vector control algorithm. If the stator inductance has a non-zero value this parameter is not used by the drive, but is continuously written with a calculated value of power factor. The stator inductance can be measured by the drive by performing a rotating autotune (see <i>Autotune</i> (Pr 00.024), later in this table).</p>	

Pr 00.024 {05.012} Autotune

There are two autotune tests available in RFC-A mode, a stationary test, and a rotating test. A stationary autotune will give moderate performance whereas a rotating autotune will give improved performance as it measures the actual values of the motor parameters required by the drive.

It is highly recommended that a rotating autotune is performed (Pr 00.024 set to 2).

Autotune test 1:

- A stationary autotune can be used when the motor is loaded and it is not possible to remove the load from the motor shaft. The stationary autotune measures the *Stator Resistance* (05.017) and *Transient Inductance* (05.024) of the motor. These are used to calculate the current loop gains, and at the end of the test the values in Pr 04.013 and Pr 04.014 are updated. A stationary autotune does not measure the power factor of the motor so the value on the motor nameplate must be entered into Pr 05.010. To perform a stationary autotune, set Pr 00.024 to 1, and provide the drive with both an enable signal (on terminal 29) and a run signal (on terminal 24).

Autotune test 2:

- A rotating autotune should only be used if the motor is unloaded. A rotating autotune first performs a stationary autotune, a rotating test is then performed in which the motor is accelerated with currently selected ramps up to a frequency of *Rated Frequency* (05.006) x 2/3, and the frequency is maintained at the level for up to 40 s. During the rotating autotune the *Stator Inductance* (05.025) is modified by the drive. The power factor is also modified for user information only, but is not used after this point as the stator inductance is used in the vector control algorithm instead. To perform a Rotating autotune, set Pr 00.024 to 2, and provide the drive with both an enable signal (on terminal 29) and a run signal (on terminal 24).

Following the completion of an autotune test the drive will go into the inhibit state. The drive must be placed into a controlled disable condition before the drive can be made to run at the required reference. The drive can be put in to a controlled disable condition by removing the Safe Torque Off signal from terminal 29, setting the *Drive Enable* (06.015) to OFF (0) or disabling the drive via the control word (Pr 06.042 & Pr 06.043)

Pr 04.013 / Pr 04.014 Current Loop Gains

The current loop gains proportional (Kp) and integral (Ki) gains control the response of the current loop to a change in current (torque) demand. The default values give satisfactory operation with most motors. However, for optimal performance in dynamic applications it may be necessary to change the gains to improve the performance. The *Current Controller Kp Gain* (04.013) is the most critical value in controlling the performance. The values for the current loop gains can be calculated by performing a stationary or rotating autotune (see *Autotune* Pr 00.024 earlier in this table) the drive measures the *Stator Resistance* (05.017) and *Transient Inductance* (05.024) of the motor and calculates the current loop gains.

This will give a step response with minimum overshoot after a step change of current reference. The proportional gain can be increased by a factor of 1.5 giving a similar increase in bandwidth; however, this gives a step response with approximately 12.5 % overshoot. The equation for the integral gain gives a conservative value. In some applications where it is necessary for the reference frame used by the drive to dynamically follow the flux very closely (i.e. high speed Sensorless RFC-A induction motor applications) the integral gain may need to have a significantly higher value.

Speed Loop Gains (Pr 00.014 {03.010}, Pr 00.015 {03.011}, Pr 00.016 {03.012})

The speed loop gains control the response of the speed controller to a change in speed demand. The speed controller includes proportional (Kp) and integral (Ki) feed forward terms, and a differential (Kd) feedback term.

Speed Controller Proportional Gain (Kp), Pr 00.014 {03.010}

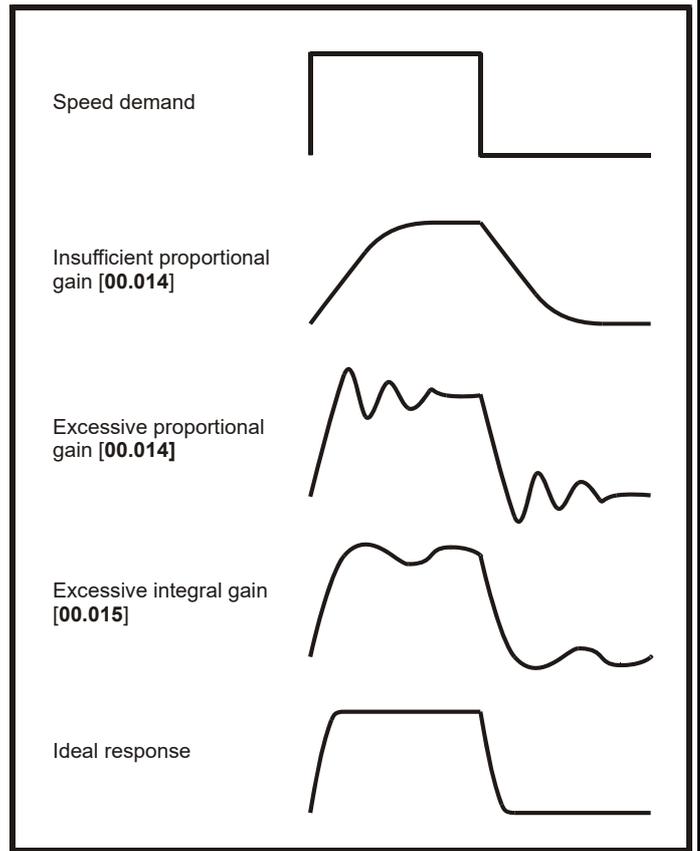
If the proportional gain has a value and the integral gain is set to zero the controller will only have a proportional term, and there must be a speed error to produce a torque reference. Therefore as the motor load increases there will be a difference between the reference and actual speeds. This effect, called regulation, depends on the level of the proportional gain, the higher the gain the smaller the speed error for a given load. If the proportional gain is too high either the acoustic noise produced by speed feedback quantization becomes unacceptable, or the stability limit is reached.

Speed Controller Integral Gain (Ki), Pr 00.015 {03.011}

The integral gain is provided to prevent speed regulation. The error is accumulated over a period of time and used to produce the necessary torque demand without any speed error. Increasing the integral gain reduces the time taken for the speed to reach the correct level and increases the stiffness of the system, i.e. it reduces the positional displacement produced by applying a load torque to the motor. Unfortunately increasing the integral gain also reduces the system damping giving overshoot after a transient. For a given integral gain the damping can be improved by increasing the proportional gain. A compromise must be reached where the system response, stiffness and damping are all adequate for the application. For RFC-A Sensorless mode, it is unlikely that the integral gain can be increased much above 0.50.

Differential Gain (Kd), Pr 00.016 {03.012}

The differential gain is provided in the feedback of the speed controller to give additional damping. The differential term is implemented in a way that does not introduce excessive noise normally associated with this type of function. Increasing the differential term reduces the overshoot produced by under-damping, however, for most applications the proportional and integral gains alone are sufficient.



8.1.3 RFC-S Sensorless mode

Permanent magnet motor without Position feedback

Pr 00.020 {05.007} Rated Current

Defines the maximum motor continuous current

The motor rated current parameter must be set to the maximum continuous current of the motor. The motor rated current is used in the following:

- Motor thermal overload protection (see section 8.2 *Motor thermal protection* on page 186, for more information)

Pr 00.017 {05.011} Number Of Motor Poles

Defines the number of motor poles

The number of motor poles parameter defines the number of electrical revolutions in one whole mechanical revolution of the motor. This parameter must be set correctly for the control algorithms to operate correctly. When Pr 00.017 is set to "Automatic" the number of poles is 6.

Pr 00.024 {05.012} Autotune

There are two autotune tests available in RFC-S sensorless mode, a stationary autotune and an inertia measurement test.

- Autotune test 1: Stationary Autotune

The stationary autotune can be used to measure all the necessary parameters for basic control. The tests measures *Stator Resistance (05.017)*, *Ld (05.024)* and *No Load Lq (05.068)*. The *Stator Resistance (05.017)* and *Ld (05.024)* are then used to set up *Current controller Kp Gain (04.013)* and *Current Controller Ki Gain (04.014)*. To perform a Stationary autotune, set Pr 00.024 to 1, and provide the drive with both an enable signal (on terminal 29) and a run signal (on terminal 24).

- Autotune test 2: Rotating Autotune

In sensorless mode, if Rotating autotune is selected (Pr 00.024 = 2), then a stationary autotune is performed.

- Autotune test 3: Locked rotor test for load dependant parameters

This test is not implemented at the time of writing.

Following the completion of an autotune test the drive will go into the inhibit state. The drive must be placed into a controlled disable condition before the drive can be made to run at the required reference. The drive can be put in to a controlled disable condition by removing the Safe Torque Off signal from terminal 29, setting the drive Enable Parameter (06.015) to OFF (0) or disabling the drive via the control word (Pr 06.042 & Pr 06.043).

Pr 03.079 Sensorless Mode Filter

When RFC-S sensorless mode is active the measured speed can include some ripple, which increases as the drive passes into field weakening. A filter is applied to the estimated speed and *Sensorless Mode Filter (03.079)* defines the time constant. The default time constant is 4 ms. This is particularly useful when using standard ramp or spinning start with a low friction high inertia load, and can prevent over voltage trips.

**Pr 00.040 {05.064} RFC Low Speed Mode /
Pr 00.041 {05.071} Low Speed Sensorless Mode Current**

(0) Injection mode

For low speed sensorless operation with signal injection (*RFC Low Speed Mode (05.064) = 0*) it is necessary to have a ratio of $L_q/L_d = 1.1$. Even if a motor has a larger ratio on no load, this ratio normally reduces as the q axis current is increased from zero. *Low Speed Sensorless Mode Current (05.071)* should be set at a level that is lower than the point where the inductance ratio falls to 1.1. The value of this parameter is used to define the drive current limits when signal injection is active and prevent loss of control of the motor.

(1) Non-salient mode

For low speed sensorless operation for non-salient motors (*RFC Low Speed Mode (05.064) = 1*) this defines a current applied in the d axis to aid starting. For most motors and application requiring up to 60 % torque on starting the default value is suitable. However the level of current may need to be increased to make the motor start.

(2) Current

This method, which applies a rotating current vector at the frequency defined by the speed reference, can be used with any motor with no saliency or moderate saliency. It should only be used with motors where more of the torque is produced in conjunction with the magnet flux rather than from saliency torque. This mode does not provide the same level of control at low speed as injection mode, but is easier to set up and more flexible than "Non-salient" mode. The following should be considered:

1. A current specified by *Low Speed Sensorless Mode Current (05.071)* is applied when low speed mode is active. This current should be sufficient to start the motor with the highest expected load. If the motor has some saliency with no-load applied, and a suitable saturation characteristic, the drive can detect the rotor position and apply the current at the correct angle to avoid starting transient. If the motor is non-salient as defined by the conditions for Inductance trip then the drive will not attempt to detect the rotor position and the current will be applied at an arbitrary angle. This could cause a starting transient if the level of current applied is high, and so *Low Speed Sensorless Mode Current (05.071)* should not be set to a higher level than necessary. To minimise the movement as a result of applying the current, it is increased over the period defined by *Sensorless Mode Current Ramp (05.063)* in the form of a squared characteristic (i.e. it is increased with a low rate of change at the beginning and the rate of change is gradually increased).
2. As the level of current when low speed mode is active is not dependent on the applied load, but is as defined by *Low Speed Sensorless Mode Current (05.071)*, and so the motor may become too hot if low speed mode is active for a prolonged period of time.
3. Generally *Low Speed Sensorless Mode Current (05.071)* should be set to a level higher than the expected maximum load, and can be set to a much higher level than the load if the saliency and saturation characteristic allow the position of the rotor to be detected on starting. However, *Low Speed Sensorless Mode Current (05.071)* should be matched more closely to the expected load under the following conditions: the load inertia is high compared to the motor inertia, or there is very little damping/loss in the load system, or where the q axis inductance of the motor changes significantly with load.

(3) Current no test

The "Current" method is used, but no attempt is made to determine the position of the rotor before applying the current. This can be selected for example, if the motor does not have a suitable saturation characteristic to allow the rotor position to be determined during starting, or if faster starting is required. The initial current vector angle will be at an arbitrary position with respect to the actual rotor position. As the vector sweeps round it must make the rotor start to rotate. If the ramp rate is too high the rotor may not keep up with the current vector and the motor may not start. If this is the case then the ramp rate should be reduced and/or the current used to start the motor should be increased.

Pr 04.012 Current Reference Filter 1 Time Constant

Current Reference Filter 1 Time Constant (04.012) defines the time constant of a first order filter that can be applied to the *Final Current Reference (04.004)*. The filter is provided to reduce acoustic noise and vibration produced as a result of position feedback quantisation. The filter introduces a lag in the speed controller loop, and so the speed controller gains may need to be reduced to maintain stability as the filter time constant is increased.

Pr 04.013 / Pr 04.014 Current Loop Gains

The current loop gains proportional (Kp) and integral (Ki) gains control the response of the current loop to a change in current (torque) demand. The default values give satisfactory operation with most motors. However, for optimal performance in dynamic applications it may be necessary to change the gains to improve the performance. The proportional gain (Pr **04.013**) is the most critical value in controlling the performance. The values for the current loop gains can be calculated by performing a stationary or rotating autotune (see *Autotune Pr 00.024*, earlier in this table) the drive measures the *Stator Resistance (05.017)* and *Transient Inductance (05.024)* of the motor and calculates the current loop gains.

This will give a step response with minimum overshoot after a step change of current reference. The proportional gain can be increased by a factor of 1.5 giving a similar increase in bandwidth; however, this gives a step response with approximately 12.5 % overshoot. The equation for the integral gain gives a conservative value. In some applications where it is necessary for the reference frame used by the drive to dynamically follow the flux very closely the integral gain may need to have a significantly higher value.

Speed Loop Gains (Pr 00.014 {03.010}, Pr 00.015 {03.011}, Pr 00.016 {03.012})

The speed loop gains control the response of the speed controller to a change in speed demand. The speed controller includes proportional (Kp) and integral (Ki) feed forward terms, and a differential (Kd) feedback term.

Speed Controller Proportional Gain (Kp), Pr 00.014 {03.010}

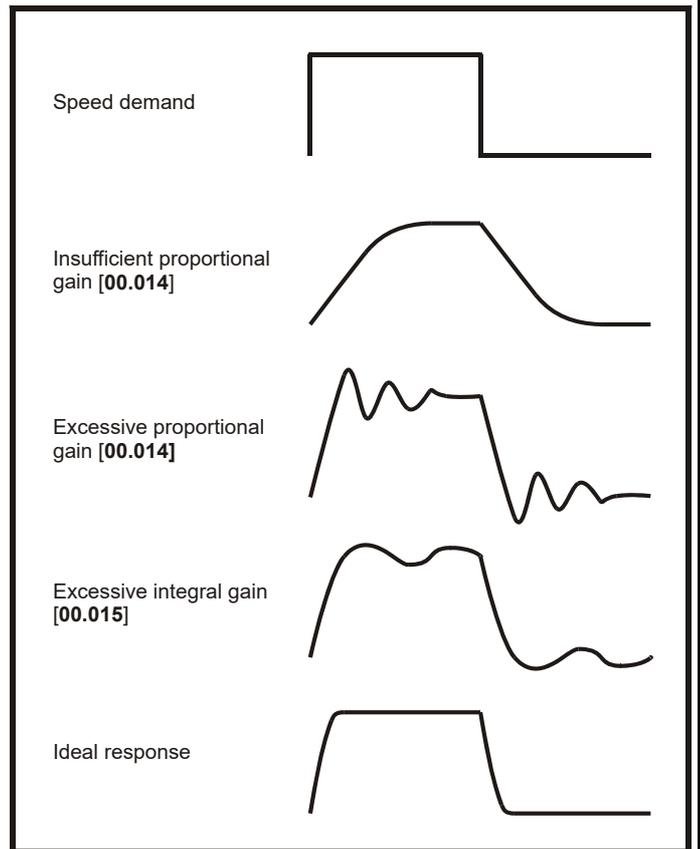
If the proportional gain has a value and the integral gain is set to zero the controller will only have a proportional term, and there must be a speed error to produce a torque reference. Therefore as the motor load increases there will be a difference between the reference and actual speeds. This effect, called regulation, depends on the level of the proportional gain, the higher the gain the smaller the speed error for a given load. If the proportional gain is too high either the acoustic noise produced by speed feedback quantization becomes unacceptable, or the stability limit is reached.

Speed Controller Integral Gain (Ki), Pr 00.015 {03.011}

The integral gain is provided to prevent speed regulation. The error is accumulated over a period of time and used to produce the necessary torque demand without any speed error. Increasing the integral gain reduces the time taken for the speed to reach the correct level and increases the stiffness of the system, i.e. it reduces the positional displacement produced by applying a load torque to the motor. Unfortunately increasing the integral gain also reduces the system damping giving overshoot after a transient. For a given integral gain the damping can be improved by increasing the proportional gain. A compromise must be reached where the system response, stiffness and damping are all adequate for the application.

Differential Gain (Kd), Pr 00.016 {03.012}

The differential gain is provided in the feedback of the speed controller to give additional damping. The differential term is implemented in a way that does not introduce excessive noise normally associated with this type of function. Increasing the differential term reduces the overshoot produced by under-damping, however, for most applications the proportional and integral gains alone are sufficient.



8.2 Motor thermal protection

A dual time constant thermal model is provided to estimate the motor temperature as a percentage of its maximum allowed temperature.

The motor thermal protection is modelled using losses in the motor. The losses in the motor are calculated as a percentage value, so that under these conditions the *Motor Protection Accumulator* (**04.019**) would eventually reach 100 %.

Percentage losses = 100 % x [Load related losses + Iron losses]

Where:

$$\text{Load related losses} = (1 - K_{fe}) \times (I / (K_1 \times I_{Rated}))^2$$

$$\text{Iron losses} = K_{fe} \times (w / w_{Rated})^{1.6}$$

Where:

I = Current Magnitude (**04.001**)

I_{Rated} = Rated Current (**05.007**)

K_{fe} = Rated Iron Losses As Percentage Of Losses (**04.039**) / 100 %

The *Motor Protection Accumulator* (**04.019**) is given by:

$$Pr \text{ 04.019} = \text{Percentage Losses} \times [(1 - K_2) (1 - e^{-t/\tau_1}) + K_2 (1 - e^{-t/\tau_2})]$$

Where:

T = Motor Protection Accumulator (**04.019**)

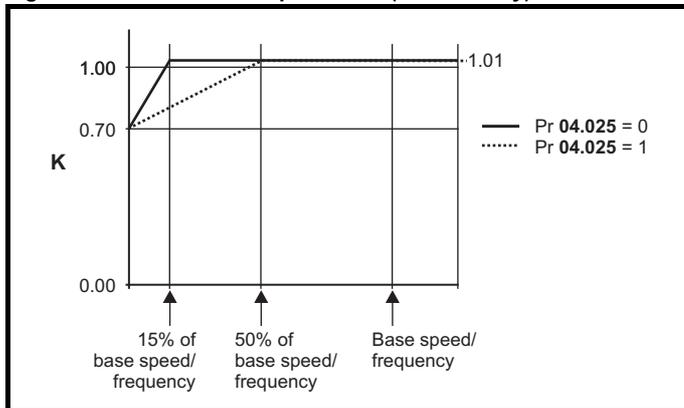
K_2 = Motor Thermal Time Constant 2 Scaling (**04.038**) / 100 %

τ_1 = Motor Thermal Time Constant 1 (**04.015**)

τ_2 = Motor Thermal Time Constant 2 (**04.037**)

K_1 = Varies, see below

Figure 8-1 Motor thermal protection (Normal Duty)



Both settings of Pr **04.025** are intended for motors where the cooling effect of the motor fan reduces with reduced motor speed, but with different speeds below which the cooling effect is reduced. If Pr **04.025** is 0 the characteristic is intended for motors where the cooling effect reduces with motor speed below 15 % of base speed/frequency. If Pr **04.025** is 1 the characteristic is intended for motors where the cooling effect reduces with motor speed below 50 % of base speed/frequency. The maximum value for K_1 is 1.01, so that above the knee of the characteristics the motor can operate continuously up to 101 % current.

When the estimated temperature in Pr **04.019** reaches 100 % the drive takes some action depending on the setting of Pr **04.016**. If Pr **04.016** is 0, the drive trips when Pr **04.019** reaches 100 %. If Pr **04.016** is 1, the current limit is reduced to $(K - 0.05) \times 100 \%$ when Pr **04.019** reaches 100 %.

The current limit is set back to the user defined level when Pr **04.019** falls below 95 %. The thermal model temperature accumulator is reset to zero at power-up and accumulates the temperature of the motor while them drive remains powered-up. If the rated current defined by Pr **05.007** is altered, the accumulator is reset to zero.

The default setting of the thermal time constant (Pr **04.015**) is 89 s which is equivalent to an overload of 110 % for 165 s from cold.

8.3 Switching frequency

The default switching frequency is 3 kHz, however this can be increased up to a maximum of 16 kHz by Pr **05.018** (dependent on drive size). The available switching frequencies are shown below.

Table 8-1 Available switching frequencies

Drive size	Model	2 kHz	3 kHz	4 kHz	6 kHz	8 kHz	12 kHz	16 kHz
3	All	✓	✓	✓	✓	✓	✓	✓
4								
5								
6								
7								
8								
9								
10								
11	400 V	✓	✓	✓	✓	✓		
11	575 and 690 V	✓	✓	✓				
12	All	✓	✓	✓	✓	✓		

If the switching frequency is increased from 3 kHz the following apply:

1. Increased heat loss in the drive, which means that derating to the output current must be applied.
See the derating tables for switching frequency and ambient temperature in *section 12.1.1 Power and current ratings (Derating for switching frequency and temperature)* on page 279.
2. Reduced heating of the motor - due to improved output waveform quality.
3. Reduced acoustic noise generated by the motor.
4. Increased sample rate on the speed and current controllers. A trade off must be made between motor heating, drive heating and the demands of the application with respect to the sample time required.

Table 8-2 Sample rates for various control tasks at each switching frequency

	3, 6, 12 kHz	2, 4, 8, 16 kHz	Open loop	RFC-A RFC-S
Level 1	3 kHz = 167µs 6 kHz = 83 µs 12 kHz = 83 µs	2 kHz = 250 µs 4 kHz = 125 µs 8 kHz = 62.5 µs 16 kHz = 62.5 µs	Peak limit	Current controllers
Level 2	250 µs	2 kHz - 500 µs 4 kHz - 250 µs 8 kHz - 125 µs 16 kHz - 125 µs	Current limit and ramps	Speed controller and ramps
Level 3	1 ms		Voltage controller	
Level 4	4 ms		Time critical user interface	
Background			Non-time critical user interface	

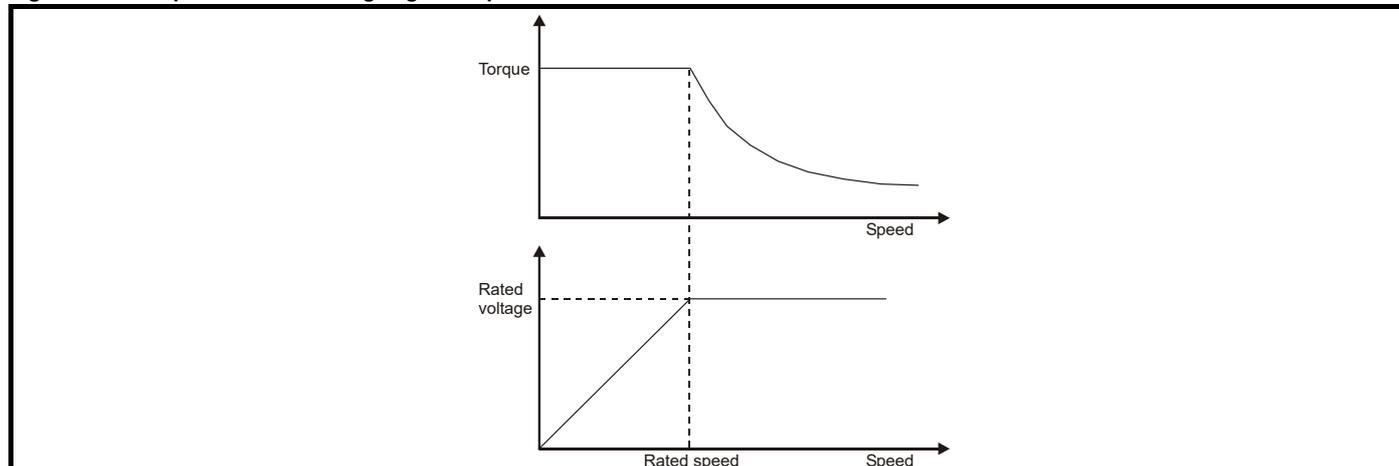
8.4 High speed operation

8.4.1 Field weakening (constant power) operation

(Open loop and RFC-A mode only)

The drive can be used to run an induction machine above synchronous speed into the constant power region. The speed continues to increase and the available shaft torque reduces. Figure 8-2 shows the torque and output voltage characteristics as the speed is increased above the rated value.

Figure 8-2 Torque and rated voltage against speed



Care must be taken to ensure the torque available above base speed is sufficient for the application to run satisfactorily.

8.4.2 Permanent magnet motor high speed operation

High speed servo mode is enabled by setting Pr **05.022** = 1. Care must be taken when using this mode with permanent magnet motor to avoid damaging the drive. The voltage produced by the permanent magnet motor magnets is proportional to speed. For high speed operation the drive must apply currents to the motor to counter-act the flux produced by the magnets. It is possible to operate the motor at very high speeds that would give a very high motor terminal voltage, but this voltage is prevented by the action of the drive.

If however, the drive is disabled (or tripped) when the motor voltages would be higher than the rating of the drive without the currents to counter-act the flux from the magnets, it is possible to damage the drive. If high speed mode is enabled the motor speed must be limited to the levels given in the table below unless an additional hardware protection system is used to limit the voltages applied to the drive output terminals to a safe level.

Drive voltage rating	Maximum motor speed (rpm)	Maximum safe line to line voltage at the motor terminals (V rms)
200	$400 \times 1000 / (K_e \times \sqrt{2})$	$400 / \sqrt{2}$
400	$800 \times 1000 / (K_e \times \sqrt{2})$	$800 / \sqrt{2}$
575	$955 \times 1000 / (K_e \times \sqrt{2})$	$955 / \sqrt{2}$
690	$1145 \times 1000 / (K_e \times \sqrt{2})$	$1145 / \sqrt{2}$

K_e is the ratio between r.m.s. line to line voltage produced by the motor and the speed in V/1000 rpm. Care must also be taken not to de-magnetize the motor. The motor manufacturer should always be consulted before using this mode.

By default, high speed operation is disabled (Pr **05.022** = 0).

It is also possible to enable high speed operation, and allow the drive to automatically limit the motor speed to the levels specified in the tables and generate an Overspeed. 1 trip if the levels are exceeded (Pr **05.022** = -1)

8.4.3 Maximum speed / frequency

In all operating modes (Open loop, RFC-A and RFC-S) the maximum output frequency is limited to 550 Hz. However, in RFC-S mode the speed is also limited by the voltage constant (K_e) of the motor. K_e is a specific constant for the servo motor being used. It can normally be found on the motor data sheet in V/k rpm (volts per 1,000 rpm).

8.4.4 Quasi-Square wave (open-loop only)

The maximum output voltage level of the drive is normally limited to an equivalent of the drive input voltage minus voltage drops within the drive (the drive will also retain a few percent of the voltage in order to maintain current control). If the motor rated voltage is set at the same level as the supply voltage, some pulse deletion will occur as the drive output voltage approaches the rated voltage level. If Pr **05.020** (Quasi-square wave enable) is set to 1 the modulator will allow over modulation, so that as the output frequency increases beyond the rated frequency the voltage continues to increase above the rated voltage. The modulation depth will increase beyond unity; first producing trapezoidal and then quasi-square waveforms.

This can be used for example:

- To obtain high output frequencies with a low switching frequency which would not be possible with space vector modulation limited to unity modulation depth,

or

- In order to maintain a higher output voltage with a low supply voltage.

The disadvantage is that the machine current will be distorted as the modulation depth increases above unity, and will contain a significant amount of low order odd harmonics of the fundamental output frequency. The additional low order harmonics cause increased losses and heating in the motor.

8.4.5 Fire mode

Fire Mode is a configurable override function that is used to alter the operation of the drive based upon external inputs, typically a discrete digital input from a Building Management Fire Protection system.



Fire Mode - Important Warning.

When Fire Mode is active the motor overload and thermal protection are disabled, as well as a number of drive protection functions. Fire Mode is provided for use only in emergency situations where the safety risk from disabling protection is less than the risk from the drive tripping - typically in smoke extraction operation to permit evacuation of a building. The use of Fire Mode itself causes a risk of fire from overloading of the motor or drive, so it must only be used after careful consideration of the balance of risks.

Care must be taken to prevent inadvertent activation or de-activation of Fire Mode. Fire Mode is indicated by a flashing display text warning "Fire mode active".

Care must be taken to ensure that parameters Pr **01.053** or Pr **01.054** are not inadvertently re-allocated to different inputs or variables. It should be noted that, by default, Pr **01.054** is controlled from digital input 4 and changing Pr **08.024** can re-allocate this digital input to another parameter. These parameters are at access level 2 in order to minimize the risk of inadvertent or unauthorized changes. It is recommended that User Security be applied to further reduce the risk (see section 5.9 *Parameter access level and security* on page 144). These parameters may also be changed via serial communications so adequate precautions should be taken if this functionality is utilized.

01.053		Fire mode reference									
RW	Uni										US
OL	↕	SPEED_FREQ_MAX						⇒		0.0 Hz	
RFC		Hz/rpm								0.0 rpm	

01.054		Fire mode activation									
RO	Bit									NC	US
↕		OFF (0) or On (1)						⇒			

Emergency ventilation or fire mode allows for the purging of air from a structure during a fire. It is enabled if Pr **01.053** is set to a non zero value and activated when Pr **01.054** is set to one. When activated, the pre-ramp reference (Pr **01.003**) is set to the value of Pr **01.053** and the normal drive controls are overridden as follows:

1. Drive enable is only controlled by the Enable input (Pr **06.015**). The control word (Pr **06.043**) cannot be used to disable the drive.
2. The internal run command is forced to be active. The normal drive sequencing bits (Pr **06.030** to Pr **6.034**) and the control word have no effect.
3. The limit switch functions (Pr **06.035** and Pr **06.036**) have no effect and will not stop the motor.
4. The hard speed reference is forced to zero. The hard speed reference should not be used when fire mode is likely to be activated as this will cause an abrupt change of speed.
5. The hand/off/auto function is disabled. If this system is in the hand state when fire mode is activated it will be forced to the off state, so that hand state is not active when fire mode is de-activated.
6. Keypad mode is disabled.
7. All latching mode states are reset.

When Pr **01.054** is subsequently set to zero the drive returns to normal operation.

Pr **01.054** can only be changed from a digital input and the default configuration allocates this to digital input 4.



Care should be taken when modifying parameters as setting Pr **01.053** to zero inhibits the fire mode function and changing Pr **08.024** (*Digital Input 4 source*) could result in digital input 4 source to be allocated to a parameter other than Pr **01.054**.

If fire mode is activated when the drive is in a tripped state then the trip is reset.

Only the trips listed in the following table can be initiated while fire mode is active.

Trip number	String	Cause of trip
2	Over Volts	DC bus over-voltage
3	OI ac	AC instantaneous over-current
4	OI brake	Braking resistor instantaneous over current
5	PSU	Drive power supply fault
9	PSU 24V	24 V internal power supply overload
21	Oht inverter	Power device over temperature based on thermal model
31	EEPROM	EEPROM failure
36	User Save	User parameter save error
37	Power Down Save	Power down save parameter error
109	OI dc	Power module over current detected from on state voltage monitoring
200	Slot1 HF	Slot 1 option module failure
205	Slot2 HF	Slot 2 option module failure
210	Slot2 HF	Slot 3 option module failure
217 to 249	HF17 to HF32	Hardware faults
250	Slot4 HF	Slot 4 factory fit option failure



It is possible for the drive or motor to become damaged when operating in fire mode because some of the drive thermal protection trips are disabled.

8.4.6 Advanced process PID

The Advanced Process PID comprises two PID controllers. PID 1 can be configured to operate as follows (refer to Pr **14.059** for details).

- Single setpoint and single feedback
- Single setpoint and dual feedback
- Dual setpoints and dual feedback

PID 2 always operates as a single setpoint, single feedback controller.

When a feedback signal requires square root conversion (e.g. airflow), square root scaling can be applied to PID 1 feedback (see Pr **14.058**, Pr **14.060**, Pr **14.061** and Pr **14.062**). PID 1 also includes a pre-sleep boost level facility (see Pr **14.028** and Pr **14.029**) to reduce frequent transitions into sleep mode when the PID is used.

The PID system is always active even when the output destination parameters are not set to a valid destination parameter. This allows the PID controllers to be used independently from the drive via a building automation network.

14.001	PID 1 output												
14.031	PID 2 output												
RW	Bi									NC	PT		
⇅	±100.00						⇒						

Pr **14.001** is the output (limited by Pr **14.013** and Pr **14.014**) from PID 1 before scaling (Pr **14.015**) is applied. It is derived from the following algorithm:

$$\text{Output} = \text{Error} \times [\text{Kp} + \text{Ki/s} + \text{Kds}/(0.064\text{s} + 1)]$$

Where:

Error = Reference (Pr **14.003**, Pr **14.025**) - Feedback (Pr **14.004**)

Kp = proportional gain (Pr **14.010**)

Ki = integral gain (Pr **14.011**)

Kd = differential gain (Pr **14.012**)

Therefore with an error of 100% and Kp = 1.000, the output produced by the proportional term is 100%. With an error of 100% and Ki = 1.000 the output produced by the integral term will increase linearly by 100% every second. With an error that is increasing by 100% per second and Kd = 1.000 the output produced by the differential term will be 100%. A filter with a 64 ms time constant is applied to the differential term to reduce noise.

14.002	PID main reference source parameter												
RW	Uni										PT	US	
⇅	Pr 0.000 to Pr 59.999						⇒	Pr 0.000					

14.003	PID 1 reference source parameter												
14.033	PID 2 reference source parameter												
RW	Uni										PT	US	
⇅	Pr 0.000 to Pr 59.999						⇒	Pr 0.000					

The PID reference is the sum of the digital reference (Pr **14.025**) and the value from the location defined by the source parameter (Pr **14.003**). Before the reference is applied to the controller algorithm, it can be scaled by setting Pr **14.023** to a value other than one and/or inverted by setting Pr **14.005** = 1.

14.004	PID 1 feedback source parameter												
14.034	PID 2 feedback source parameter												
RW	Uni										PT	US	
⇅	Pr 0.000 to Pr 59.999						⇒	Pr 0.000					

The feedback is the sum of the digital feedback (Pr **14.026**) and the value from the location defined by the source parameter (Pr **14.004**). Before the reference is applied to the controller algorithm, it can be scaled by setting Pr **14.024** to a value other than one and/or inverted by setting Pr **14.006** = 1.

14.005	PID 1 reference invert												
14.035	PID 2 reference invert												
RW	Bit												US
⇅	OFF (0) or On (1)						⇒	OFF (0)					

14.006	PID 1 feedback invert												
14.036	PID 2 feedback invert												
RW	Bit												US
⇅	OFF (0) or On (1)						⇒	OFF (0)					

14.007	PID 1 reference slew-rate limit												
14.037	PID 2 reference slew-rate limit												
RW	Uni												US
⇅	0.0 to 3200.0 s						⇒	0.0					

Pr **14.007** defines the time taken for the reference input to ramp from 0 to 100% following a 0 to 100% step change in input.

14.008	PID 1 enable												
RW	Bit												US
⇅	OFF (0) or On (1)						⇒	OFF (0)					

PID 1 is enabled when Pr **14.008** = 1 and both the parameter sources defined by Pr **14.009** and Pr **14.027** have a value of one. (The source value for Pr **14.009** or Pr **14.027** appears as one if the parameter is set to 0.0.) By default, Pr **14.009** is set to **10.001** (Drive Heathy) so that the PID controller is disabled if the drive is tripped. When the PID controller is disabled the output is zero and all the internal state variables (i.e. integrator accumulator etc.) are held at zero.

14.009	PID 1 optional enable source parameter 1												
RW	Uni											PT	US
⇅	Pr 0.000 to Pr 50.099						⇒	Pr 0.000					

14.010	PID 1 proportional gain												
14.040	PID 2 proportional gain												
RW	Uni												US
⇅	0.000 to 4.000						⇒	0.500					

14.011	PID 1 integral gain												
14.041	PID 2 integral gain												
RW	Uni												US
⇅	0.000 to 4.000						⇒	0.000					

14.012	PID 1 differential gain												
14.042	PID 2 differential gain												
RW	Uni												US
⇅	0.000 to 4.000						⇒	0.000					

14.013	PID 1 output upper limit												
14.043	PID 2 output upper limit												
RW	Uni												US
⇅	0.00 to 100.00 %						⇒	100.00 %					

14.014	PID 1 output lower limit												
14.044	PID 2 output lower limit												
RW	Uni												US
⇅	±100.00 %						⇒	-100.00 %					

If Pr **14.018** is zero, the upper limit (Pr **14.013**) defines the maximum positive output for the PID controller and the lower limit defines the minimum positive or maximum negative output. If symmetrical limits are selected, i.e. Pr **14.018** =c1, then the upper limit defines the maximum positive or negative magnitude for the PID output. When any of the limits is active then the integrator accumulator is held.

14.015	PID 1 output scaling												
14.045	PID 2 output scaling												
RW	Uni												US
⇅	0.000 to 4.000						⇒	1.000					

14.024	PID 1 feedback scaling												
14.054	PID 2 feedback scaling												
RW	Uni												US
⇅	0.000 to 4.000						⇒	1.000					

14.016	PID 1 output destination parameter												
14.046	PID 2 output destination parameter												
RW	Uni		DE					PT					US
⇅	Pr 0.000 to Pr 59.999						⇒	Pr 0.000					

14.025	PID 1 digital reference												
14.055	PID 2 digital reference												
RW	Bi									NC			
⇅	±100.00 %						⇒	0.00 %					

14.017	PID 1 integrator hold												
14.047	PID 2 integrator hold												
RW	Bit							NC					US
⇅	OFF (0) or On (1)						⇒	OFF (0)					

14.026	PID 1 digital feedback												
14.055	PID 2 digital feedback												
RW	Bi									NC			
⇅	±100.00 %						⇒	0.00 %					

When this parameter is set to OFF (0) the integrator operates normally. Setting this parameter to On (1) will cause the integrator value to be held. Setting this parameter does not prevent the integrator from being reset to zero if the PID controller is disabled.

14.027	PID 1 optional enable source parameter 2												
RW	Uni									PT			US
⇅	Pr 0.000 to 59.999						⇒	0.000					

14.018	PID 1 symmetrical limit enable												
14.048	PID 2 symmetrical limit enable												
RW	Bit												US
⇅	OFF (0) or On (1)						⇒	OFF (0)					

14.028	PID 1 pre-sleep boost level												
RW	Uni												US
⇅	0.00 to 100.00 %						⇒	0.00 %					

14.019	PID 1 main reference												
14.049	PID 2 main reference												
RO	Bi							NC	PT				US
⇅	±100.00 %						⇒						

14.029	Maximum boost time												
RW	Uni												US
⇅	0.0 to 250.0 s						⇒	0.0 s					

14.020	PID 1 reference												
14.050	PID 2 reference												
RO	Bi							NC	PT				US
⇅	±100.00 %						⇒						

14.030	PID 1 pre-sleep boost level enable												
RO	Bit									NC	PT		
⇅	OFF (0) or On (1)						⇒						

If PID is used to control the motor output via Menu 1 and sleep mode is enabled, then the drive will automatically stop the motor when the output drops below the sleep/wake threshold. The feedback may then fall causing the output and hence the feedback to rise again. Setting Pr 14.028 and Pr 14.029 to non zero values results in the value in Pr 14.028 being added to the PID reference for a length of time defined in Pr 14.029 when the drive attempts to enter sleep mode.. This will reduce the frequency of the transitions into sleep mode. Pr 14.030 indicates when the boost system is enabled.

14.021	PID 1 feedback												
14.051	PID 2 feedback												
RO	Bi							NC	PT				US
⇅	±100.00 %						⇒						

14.038	PID 2 enable												
RW	Uni												US
⇅	Off (0) or On (1)						⇒	Off (0)					

14.022	PID 1 error												
14.052	PID 2 error												
RO	Bi							NC	PT				US
⇅	±100.00 %						⇒						

14.058	PID 1 feedback output scaling												
RW	Uni												US
0.000 to 4.000						1.000							

14.023	PID 1 reference scaling												
14.053	PID 2 reference scaling												
RW	Uni												US
⇅	0.000 to 4.000						⇒	1.000					

Pr 14.058 allows scaling to be applied to the combined feedback signal from PID controller 1 and PID controller 2 after the square root function has been applied.

14.060		PID 1 Square root enable										
14.061		PID 2 Square root enable										
RW	Bit											US
OFF (0) or On (1)						OFF (0)						

14.062		Combined PID square root enable										
RW	Uni											US
OFF (0) or On (1)						OFF (0)						

The square root functions in the feedback paths are enabled or disabled with Pr 14.060, Pr 14.061 and Pr 14.062.

When the square root function is enabled, the following algorithm is applied to the feedback.

$$\text{Square root function output} = \text{Sign}(\text{Feedback}) \times 100.00\% \times \sqrt{|\text{Feedback}| / 100.00\%}$$

where Sign(Feedback) is 1 if the feedback is positive or -1 if the feedback is negative.

14.059		PID mode selector										
RW	Uni											US
0 to 7						0						

Single setpoint, single feedback (Pr 14.059 = 0 or 1)

The two PID controllers operate independently. The feedback for PID2 is always from the PID2 feedback input. PID1 feedback can select one of two sensors as shown in the table below.

Parameter 14.059	Final PID1 feedback
0	PID1 feedback
1	PID2 feedback

Single setpoint, dual feedback (Pr 14.059 = 2 to 5)

PID1 feedback is from two sensors, which can be configured as shown in the table below.

Parameter 14.059	Final PID1 feedback
2	PID1 feedback + PID2 feedback
3	Lowest of PID1 feedback and PID2 feedback
4	Highest of PID1 feedback and PID2 feedback
5	(PID1 feedback + PID2 feedback) / 2

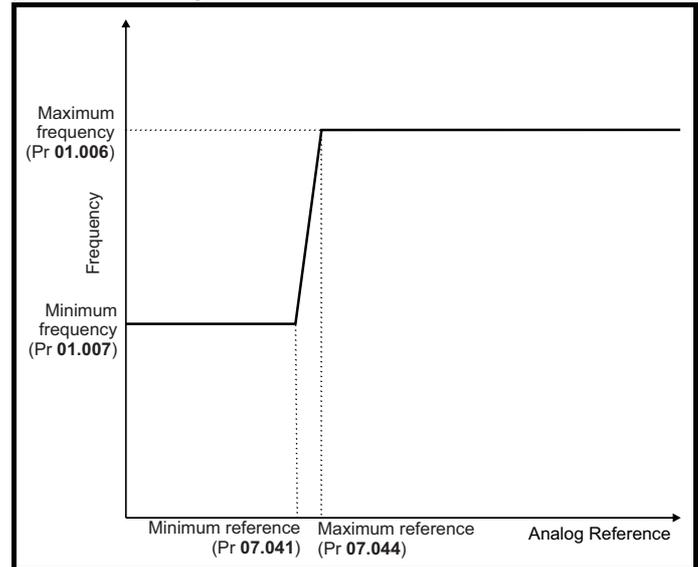
Dual setpoint, dual feedback (Pr 14.059 = 6 to 7)

When PID mode 6 or 7 is selected the controller operates in a dual zone mode. In this mode the reference and feedback quantities from each PID controller are used to calculate two controller errors. These two errors are then checked and the zone with the larger or smaller absolute value of error (depending upon mode selected) is used as the error signal to the PID1 controller.

Parameter 14.059	PID1 Error
6	Lowest of PID1 Error or PID2 Error
7	Highest of PID1 Error or PID2 Error

8.4.7 Analog reference profile

If analog input 2 is used as a reference, then the following reference profile can be configured.



For example, if the following is required:

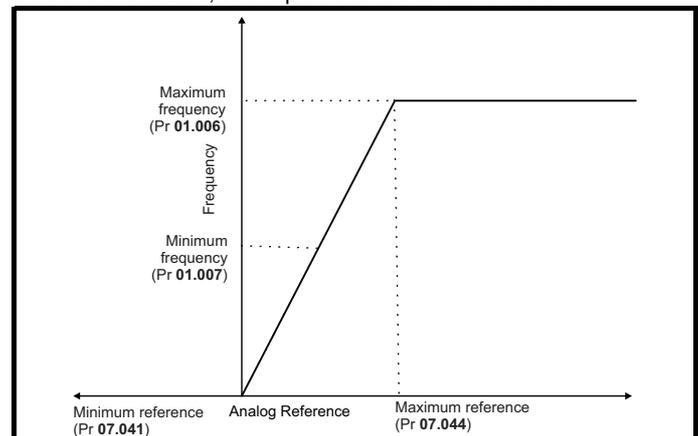
- Output frequency = 20 Hz when analog reference < 25%,
- Output frequency = 60 Hz when analog reference > 75%,
- Output frequency = linear ramp between 20 and 60 Hz when analog reference is between 25 and 75 %, then the parameters should be set as follows:
 - Pr 01.006 = 60
 - Pr 01.007 = 20
 - Pr 07.041 = 25
 - Pr 07.044 = 75

NOTE

If Pr 07.041 is greater than or equal to Pr 07.044, analog input 2 (Pr 07.002) will be forced to 0%, so the output frequency will always be equal to the value in Pr 01.007.

NOTE

If Pr 07.041 is negative and Pr 07.044 positive, the minimum reference will be forced to zero, so the profile will be as shown below.



NOTE

Parameters Pr 07.041 and Pr 07.044 are 8 bit parameters so these only have a resolution of 1%.

9 NV Media Card Operation

9.1 Introduction

The Non-Volatile Media Card feature enables simple configuration of parameters, parameter back-up, storing / reading PLC programs and drive copying using a SMARTCARD or SD card storing / reading PLC programs. The drive offers backward compatibility for an Affinity SMARTCARD.

SD card type supported:

SD or SDHC cards up to 32GB can be used and must be preformatted with the FAT32 file system.

The NV Media Card can be used for:

- Parameter copying between drives
- Saving drive parameter sets
- Saving an onboard program

The NV Media Card is located at the top of the module under the drive display (if installed) on the left-hand side.

Ensure the NV Media Card is inserted with the contacts facing the left-hand side of the drive.

The drive only communicates with the NV Media Card when commanded to read or write, meaning the card may be "hot swapped".

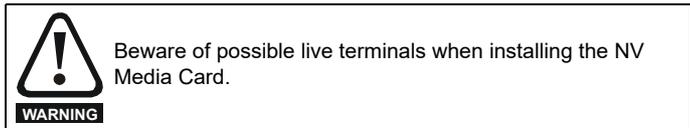
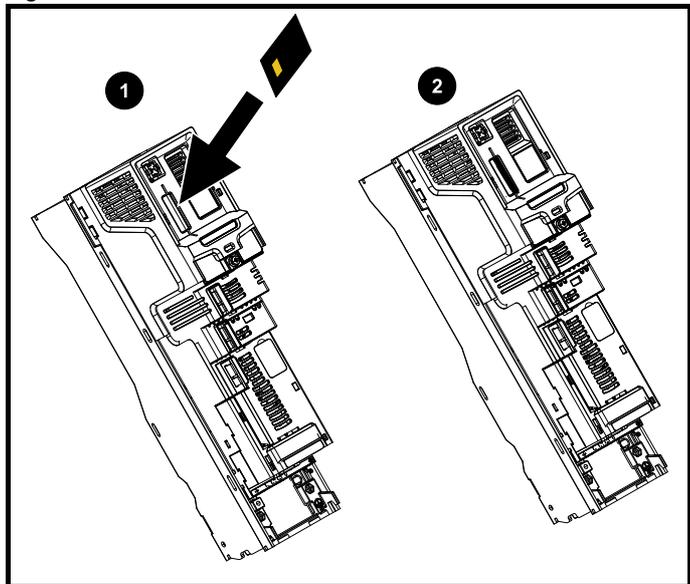


Figure 9-1 Installation of the NV Media Card



1. Installing the NV Media Card
2. NV Media Card installed

NV Media Card	Part number
SD Card Adaptor (memory card not included)	82400000016400
8 kB SMARTCARD	2214-4246
64 kB SMARTCARD	2214-1006

9.2 NV Media Card support

The NV Media Card can be used to store drive parameter sets and / or PLC programs set from the H300 in data blocks 001 to 499 on the card.

The H300 is compatible with an Affinity SMARTCARD, and is able to read and translate the Affinity parameter set into a compatible parameter set for H300. This is only possible if the Affinity parameter set was

transferred to the SMARTCARD using the difference from defaults transfer method (i.e. 4yyy transfer).

The HVAC drive H300 is not able to read any other type of Affinity data block on the card. Although it is possible to transfer difference from default data blocks from an Affinity into the HVAC drive H300, the following should be noted:

1. If a parameter from the source drive does not exist in the target drive then no data is transferred for that parameter.
2. If the data for the parameter in the target drive is out of range then the data is limited to the range of the target parameter.
3. If the target drive has a different rating to the source drive then the normal rules for this type of transfer apply.

Figure 9-2 Basic NV Media Card operation

Drive reads all parameters from the NV Media Card

Pr 00.033 = Read +

Programs all drive parameters to the NV Media Card

NOTE
Overwrites any data already in data block 1

Pr 00.033 = Program +

Drive automatically writes to the NV Media Card when a parameter save is performed

Auto Save

Pr 00.033 = Auto +

Drive boots from the NV Media Card on power up and automatically writes to the NV Media Card when a parameter save is performed

Auto Save

Pr 00.033 = Boot +

The whole card may be protected from accidental writing or erasing by setting the read-only flag as detailed in section 9.3.9 9888 / 9777 - *Setting and clearing the NV Media Card read only flag* on page 195.

The card should not be removed during data transfer, as the drive will produce a trip. If this occurs then either the transfer should be reattempted or in the case of a card to drive transfer, default parameters should be loaded.

9.3 Transferring data

Data transfer, erasing and protecting the information is performed by entering a code in Pr **mm.000** and then resetting the drive as shown in Table 9-1.

Table 9-1 SMARTCARD and SD card codes

Code	Operation	SMARTCARD	SD card
2001	Transfer the drive parameters to parameter file 001 and sets the block as bootable. This will include the parameters from attached option modules.	✓	✓
4yyy	Transfer the drive parameters to parameter file yyy. This will include the parameters from attached option modules.	✓	✓
5yyy	Transfer the onboard user program to onboard user program file yyy. On Board user program not supported on H300	✓	✓
6yyy	Load the drive parameters from parameter file yyy	✓	✓
7yyy	Erase file yyy.	✓	✓
8yyy	Compare the data in the drive with file yyy. If the files are the same then <i>Pr mm.000 (mm.000)</i> is simply reset to 0 when the compare is complete. If the files are different a 'Card Compare' trip is initiated. All other NV media card trips also apply.	✓	✓
9555	Clear the warning suppression flag	✓	✓
9666	Set the warning suppression flag	✓	✓
9777	Clear the read-only flag	✓	✓
9888	Set the read-only flag	✓	✓
9999	Erase and format the NV media card	✓	

Where yyy indicates the block number 001 to 999.

NOTE

If the read only flag is set then only codes 6yyy or 9777 are effective.

9.3.1 Writing to the NV Media Card

4yyy - Writes defaults differences to the NV Media Card

The data block only contains the parameter differences from the last time default settings were loaded.

All parameters except those with the NC (Not copied) coding bit set are transferred to the NV Media Card. In addition to these parameters all menu 20 parameters (except Pr **20.000**), can be transferred to the NV Media Card.

Writing a parameter set to the NV Media Card (Pr 11.042 = Program (2))

Setting Pr **11.042** to Program (2) and resetting the drive will save the parameters to the NV Media Card, i.e. this is equivalent to writing 4001 to Pr **mm.000**. All NV Media Card trips apply except 'Card Change'. If the data block already exists it is automatically overwritten. When the action is complete this parameter is automatically reset to None (0).

9.3.2 Reading from the NV Media Card

6yyy - Reading from NV Media Card

When the data is transferred back to the drive, using 6yyy in Pr **mm.000**, it is transferred to the drive RAM and the EEPROM. A parameter save is not required to retain the data after-power down. Set up data for any option modules installed stored on the card are transferred to the drive. If the option modules installed are different between source and destination drives, the menus for the option module slots where the option module categories are different are not updated from the card and will contain their default values after the copying action. The drive will produce a 'Card Option' trip if the option module installed to the source and the destination drives are different or are in different slots. If the data is being transferred to the drive with different voltage or current rating a 'Card Rating' trip will occur.

The following drive rating dependant parameters (RA coding bit set) will not be transferred to the destination drive by a NV Media Card when the voltage rating of the destination drive is different from the source drive and the file is a parameter file.

However, drive rating dependent parameters will be transferred if only the current rating is different. If drive rating dependant parameters are not transferred to the destination drive they will contain their default values.

Pr **02.008** *Standard Ramp Voltage*

Pr **04.005** to Pr **04.007** *Motoring Current Limits*

Pr **04.024**, *User Current Maximum Scaling*

Pr **05.007** *Rated Current*

Pr **05.009** *Rated Voltage*

Pr **05.010** *Rated Power Factor*

Pr **05.017** *Stator Resistance*

Pr **05.018** *Maximum Switching Frequency*

Pr **05.024** *Transient Inductance*

Pr **05.025** *Stator Inductance*

Pr **06.006** *Injection Braking Level*

Pr **06.048** *Supply Loss Detection Level*

Pr **06.065** *Standard Under Voltage Threshold*

Pr **06.066** *Low Under Voltage Threshold*

Reading a parameter set from the NV Media Card (Pr 11.042 = Read (1))

Setting Pr 11.042 to Read (1) and resetting the drive will transfer the parameters from the card into the drive parameter set and the drive EEPROM, i.e. this is equivalent to writing 6001 to Pr mm.000.

All NV Media Card trips apply. Once the parameters are successfully copied this parameter is automatically reset to None (0). Parameters are saved to the drive EEPROM after this action is complete.

9.3.3 Auto saving parameter changes (Pr 11.042 = Auto (3))

This setting causes the drive to automatically save any changes made to menu 0 parameters on the drive to the NV Media Card. The latest menu 0 parameter set in the drive is therefore always backed up on the NV Media Card. Changing Pr 11.042 to Auto (3) and resetting the drive will immediately save the complete parameter set from the drive to the card, i.e. all parameters except parameters with the NC coding bit set. Once the whole parameter set is stored only the individual modified menu 0 parameter setting is updated.

Advanced parameter changes are only saved to the NV Media Card when Pr mm.000 is set to 'Save Parameters' or 1001 and the drive reset.

All NV Media Card trips apply, except 'Card Change'. If the data block already contains information it is automatically overwritten.

If the card is removed when Pr 11.042 is set to 3 Pr 11.042 is then automatically set to None (0).

When a new NV Media Card is installed Pr 11.042 must be set back to Auto (3) by the user and the drive reset so the complete parameter set is rewritten to the new NV Media Card if auto mode is still required.

When Pr 11.042 is set to Auto (3) and the parameters in the drive are saved, the NV Media Card is also updated, and therefore the NV Media Card becomes a copy of the drives stored configuration.

At power up, if Pr 11.042 is set to Auto (3), the drive will save the complete parameter set to the NV Media Card. The drive will display 'Card Write' during this operation. This is done to ensure that if a user puts a new NV Media Card in during power down the new NV Media Card will have the correct data.

NOTE

When Pr 11.042 is set to Auto (3) the setting of Pr 11.042 itself is saved to the drive EEPROM but not the NV Media Card.

9.3.4 Booting up from the NV Media Card on every power up (Pr 11.042 = Boot (4))

When Pr 11.042 is set to Boot (4) the drive operates the same as Auto mode except when the drive is powered-up. The parameters on the NV Media Card will be automatically transferred to the drive at power up if the following are true:

- A card is inserted in the drive
- Parameter data block 1 exists on the card
- The data in block 1 is type 1 to 4 (as defined in Pr 11.038)
- Pr 11.042 on the card set to Boot (4)

The drive will display 'Booting Parameters' during this operation. If the drive mode is different from that on the card, the drive gives a 'Card Drive Mode' trip and the data is not transferred.

If 'Boot' mode is stored on the copying NV Media Card this makes the copying NV Media Card the master device. This provides a very fast and efficient way of re-programming a number of drives.

NOTE

'Boot' mode is saved to the card, but when the card is read, the value of Pr 11.042 is not transferred to the drive.

9.3.5 Booting up from the NV Media Card on every power up (Pr mm.000 = 2001)

It is possible to create a bootable parameter data block by setting Pr mm.000 to 2001 and initiating a drive reset. This data block is created in one operation and is not updated when further parameter changes are made.

Setting Pr mm.000 to 2001 will overwrite the data block 1 on the card if it already exists.

9.3.6 8yyy - Comparing the drive full parameter set with the NV Media Card values

Setting 8yyy in Pr mm.000, will compare the NV Media Card file with the data in the drive. If the compare is successful Pr mm.000 is simply set to 0. If the compare fails a 'Card Compare' trip is initiated.

9.3.7 7yyy / 9999 - Erasing data from the NV Media Card values

Data can be erased from the NV Media Card either one block at a time or all blocks in one go.

- Setting 7yyy in Pr mm.000 will erase NV Media Card data block yyy
- Setting 9999 in Pr mm.000 will erase all the data blocks on a SMARTCARD, but not on an SD Card.

9.3.8 9666 / 9555 - Setting and clearing the NV Media Card warning suppression flag

If the option modules installed to the source and destination drive are different or are in different slots the drive will produce a 'Card Option' trip. If the data is being transferred to a drive of a different voltage or current rating a 'Card Rating' trip will occur. It is possible to suppress these trips by setting the warning suppression flag. If this flag is set the drive will not trip if the option module(s) or drive ratings are different between the source and destination drives. The options module or rating dependent parameters will not be transferred.

- Setting 9666 in Pr mm.000 will set the warning suppression flag
- Setting 9555 in Pr mm.000 will clear the warning suppression flag

9.3.9 9888 / 9777 - Setting and clearing the NV Media Card read only flag

The NV Media Card may be protected from writing or erasing by setting the read only flag. If an attempt is made to write or erase a data block when the read only flag is set, a 'Card Read Only' trip is initiated. When the read only flag is set only codes 6yyy or 9777 are effective.

- Setting 9888 in Pr mm.000 will set the read only flag
- Setting 9777 in Pr mm.000 will clear the read only flag

9.4 Data block header information

Each data block stored on a NV Media Card has header information detailing the following:

- NV Media Card File Number (11.037)
- NV Media Card File Type (11.038)
- NV Media Card File Version (11.039)
- NV Media Card File Checksum (11.040)

The header information for each data block which has been used can be viewed in Pr 11.038 to Pr 11.040 by increasing or decreasing the data block number set in Pr 11.037. If there is no data on the card Pr 11.037 can only have a value of 0.

9.5 NV Media Card parameters

Table 9-2 Key to parameter table coding

RW	Read / Write	ND	No default value
RO	Read only	NC	Not copied
Num	Number parameter	PT	Protected parameter
Bit	Bit parameter	RA	Rating dependant
Txt	Text string	US	User save
Bin	Binary parameter	PS	Power-down save
FI	Filtered	DE	Destination

11.036 {00.032} NV Media Card File Previously Loaded	
RO	Num
OL	
RFC-A	⇕
RFC-S	

0 to 999 → 0

This parameter shows the number of the data block last transferred from a NV Media Card to the drive. If defaults are subsequently reloaded this parameter is set to 0.

11.037 NV Media Card File Number	
RW	Num
OL	
RFC-A	⇕
RFC-S	

0 to 999 → 0

This parameter should have the data block number which the user would like the information displayed in Pr 11.038, Pr 11.039 and Pr 11.040.

11.038 NV Media Card File Type	
RO	Txt
OL	
RFC-A	⇕
RFC-S	

None (0), Open-loop (1), RFC-A (2), RFC-S (3), Regen (4), User Prog (5), Option App (6) →

Displays the type/mode of the data block selected with Pr 11.037.

Pr 11.038	String	Type / mode
0	None	No file selected
1	Open-loop	Open-loop mode parameter file
2	RFC-A	RFC-A mode parameter file
3	RFC-S	RFC-S mode parameter file
4	Regen	Regen mode parameter file
5	User Prog	Onboard user program file
6	Option App	Option module application file

11.039 NV Media Card File Version	
RO	Num
OL	
RFC-A	⇕
RFC-S	

0 to 9999 →

Displays the version number of the file selected in Pr 11.037.

11.040 NV Media Card File Checksum	
RO	Num
OL	
RFC-A	⇕
RFC-S	

0 to 0 → 0

Displays the checksum of the data block selected in Pr 11.037.

11.042 {00.033} Parameter Cloning	
RW	Txt
OL	
RFC-A	⇕
RFC-S	

None (0), Read (1), Program (2), Auto (3), Boot (4) → None (0)

* Only a value of 3 or 4 in this parameter is saved.

NOTE

If Pr 11.042 is equal to 1 or 2, this value is not transferred to the drive or saved to the EEPROM. If Pr 11.042 is set to 3 or 4 the value is saved to the EEPROM

None (0) = Inactive

Read (1) = Read parameter set from the NV Media Card

Program (2) = Program a parameter set to the NV Media Card

Auto (3) = Auto save

Boot (4) = Boot mode

11.072 NV Media Card Create Special File	
RW	Num
OL	
RFC-A	⇕
RFC-S	

0 to 1 → 0

If NV Media Card Create Special File (11.072) = 1 when a parameter file is transferred to an NV media card the file is created as a macro file. NV Media Card Create Special File (11.072) is reset to 0 after the file is created or the transfer fails.

11.073 NV Media Card Type	
RO	Txt
OL	
RFC-A	⇕
RFC-S	

None (0), SMART Card (1), SD Card (2) →

This will display the type of media card inserted; it will contain one of the following values:

"None" (0) - No NV Media Card has been inserted.

"SMART Card" (1) - A SMARTCARD has been inserted.

"SD Card" (2) - A FAT formatted SD card has been inserted.

11.075 NV Media Card Read-only Flag	
RO	Bit
OL	
RFC-A	⇕
RFC-S	

Off (0) or On (1) →

NV Media Card Read-only Flag (11.075) shows the state of the read-only flag for the currently installed card.

11.076		NV Media Card Warning Suppression Flag						
RO	Bit				ND	NC	PT	
OL	⇕	Off (0) or On (1)			⇒			
RFC-A								
RFC-S								

NV Media Card Warning Suppression Flag (11.076) shows the state of the warning flag for the currently installed card.

11.077		NV Media Card File Required Version						
RW	Num				ND	NC	PT	
OL	⇕	0 to 9999			⇒			
RFC-A								
RFC-S								

The value of NV Media Card File Required Version (11.077) is used as the version number for a file when it is created on an NV Media Card. NV Media Card File Required Version (11.077) is reset to 0 when the file is created or the transfer fails.

11.078		NV Media Card Action Status						
RW	Txt				ND	NC	PT	
OL	⇕	None (0), Active (1), Card Slot 1 (2), Card Slot 2 (3), Card Slot 3 (4), Card Slot 4 (5), Card Product (6), Card User Prog (7), Card Busy (8), Card Data Exists (9), Card Option (10), Card Read Only (11), Card Error (12), Card No Data (13), Card Full (14), Card File Error (15), Card Rating (16), Card File Data (17), Card Derivative (18)			⇒			
RFC-A								
RFC-S								

This parameter shows the status of any action on an NV media card that is initiated by setting a value in parameter mm.000. When the action starts this parameter changes to Active (1) and if the action completes successfully it changes back to None (0). If however, the action fails this parameter changes to another value to show the cause. Non-critical failures, i.e. an error that is detected when writing to a card, do not cause drive trips as these may disable the drive and disturb the wider system, and so this parameter is a way to find the cause of a non-critical error.

9.6 NV Media Card trips

After an attempt to read, write or erase data from a NV Media Card a trip is initiated if there has been a problem with the command.

See Chapter 13 *Diagnostics* on page 307 for more information on NV Media Card trips.

10 Building Automation

10.1 Introduction

The HVAC drive H300 supports the following protocols:

- Modbus RTU
- BACnet MSTP

As standard the H300 Drive is provided with a 2 wire EIA-485 interface located beneath the control terminals (see Figure 10-1). All two protocols use this communication interface.

Figure 10-1 Location of the comms connector

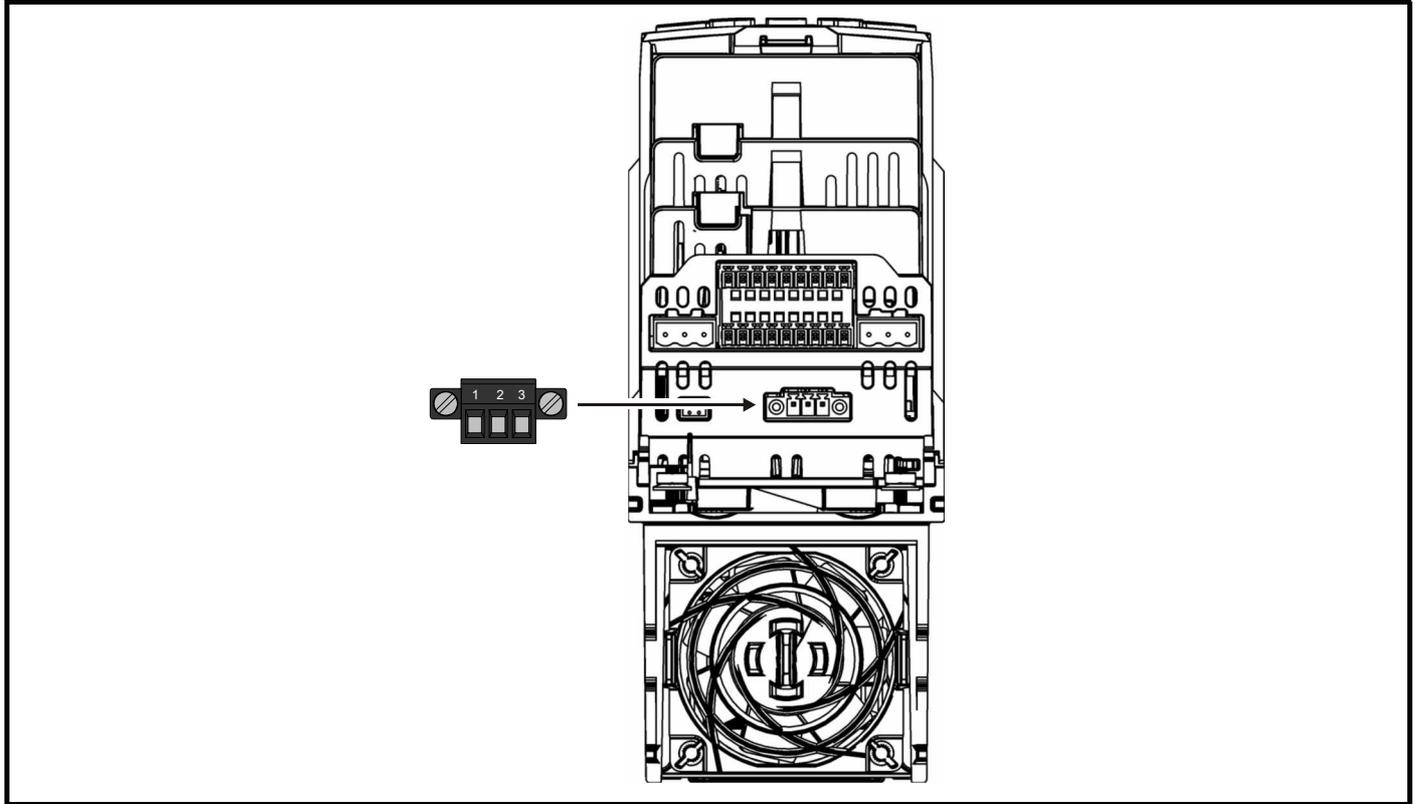


Table 10-1 Serial communication port pin-outs

Pin	Function
1	RX TX
2	Isolated 0V
3	RX\ TX\

10.2 Building automation network communications set up parameters

10.2.1 Serial Address

Serial Address (Pr 11.023) selects the MAC/Node Address for all protocols.

Table 10-2 Protocols

Protocol	Master / Slave	Allowable MAC Address Values		
		Minimum	Maximum	Broadcast
Modbus RTU	Slave	1	247	0
BACnet*	Master	0	127	255

If a MAC address is selected that is greater than or less than those allowed by the currently selected protocol then the actual address used will be the maximum valid address value. The parameter value will change to reflect the value being used.

*The BACnet module is a master device. As such it will instigate an *I-Am* broadcast message onto the BACnet network at power-up and on each subsequent drive reset. BACnet module act as a Master on the Data Link Layer over MS/TP.

10.2.2 Serial Mode

Serial Mode (Pr 11.024) defines the data format used by the serial comms interface. The bits in the value of Serial Mode define the data format as follows:

Table 10-3 Serial mode bits

Bits	3	2	1 and 0
Format	Number of data bits 0 = 8 bits 1 = 7 bits	Register mode 0 = Standard 1 = Modified	Stop bits and Parity 0 = 2 stop bits, no parity 1 = 1 stop bit, no parity 2 = 1 stop bit, even parity 3 = 1 stop bit, odd parity

For the Modbus RTU protocol bit, 3 should always be set to 0 as 8 data bits are required. The parameter value can be extended with the remaining communication protocols if required.

Bit 2 selects either standard or modified register mode. The menu and parameter numbers are derived for each mode as given in the table below. Standard mode is compatible with Unidrive SP. Modified mode is provided to allow register numbers up to 255 to be addressed.

Table 10-4 Register mode

Register mode	Register address
Standard	(mm x 100) + ppp - 1 where mm ≤ 162 and ppp ≤ 99
Modified	(mm x 256) + ppp - 1 where mm ≤ 63 and ppp ≤ 255

Table 10-5 Serial mode

Pr 11.024	Description
0	8 2 NP
1	8 1 NP
2	8 1 EP
3	8 1 OP
4	8 2 NP M
5	8 1 NP M
6	8 1 OP M
7	8 1 OP M
8	7 2 NP
9	7 1 NP
10	7 1 EP
11	7 1 OP
12	7 2 NP M
13	7 1 NP M
14	7 1 EP M
15	7 1 OP M

Changing the parameters does not immediately change the serial communications settings. Revised values will only be used after the next power-up or if *Reset Serial Communications* (Pr 11.020) is set to one.

10.2.3 Serial baud rate

Serial Baud Rate (Pr 11.025) defines the baud rate used by the serial comms interface. BACnet module only supports 9600, 19200 and 38400 baud rates

Table 10-6 Serial baud rate

Pr 11.025	Description
0	300
1	600
2	1200
3	2400
4	4800
5	9600
6	19200
7	38400
8	57600
9	76800
10	115200

Revised values will only be used after the next power-up or if *Reset Serial Communications* (Pr 11.020) is set to one.

10.2.4 Building automation network (BAN) protocol selection

Building automation network (BAN) protocol selection (Pr 29.001) selects the network protocol:

Table 10-7 BAN protocol

Pr 29.001	Protocol
0	Modbus RTU
1	BACnet MSTP

The following process should be followed to change the communication protocol:

1. Select the required protocol in Pr 29.001.
2. Perform a parameter save.
3. Power cycle the drive.

10.2.5 BACnet MS/TP Maximum Master MAC Address

(Pr 29.003) BACnet use only

This is highest address that the drive will use when looking for the next master on the network with which token passing can be achieved.

If a value greater than 127 is entered then the value used will be 127. The parameter value will change to 127 to reflect this.

10.2.6 Device Object Identifier

(Pr 29.004) BACnet use only

This number uniquely defines this device on the entire network.

10.2.7 Communications lost detection time-out period

Communications Lost Detection Time-Out Period (Pr 29.005) sets the period in seconds that the drive will wait to see a valid communications frame on the network before taking the action specified in *Communications Lost Action* (Pr 29.006).

10.2.8 Communications lost action

Communications Lost Action (Pr 29.006) determines the drive action when communication is lost.

BACnet

The network is monitored for the presence of an active token; should this token disappear for the time specified, the drive will take the configured action.

The following action is taken when loss of communication is recognized:

Table 10-8 Communications lost action

Pr 29.006	Action	Comment
0	Do nothing	The drive will continue as it was before communications was lost
1	Trip the drive	The drive will trip when communications is lost (sub trip 50)
2	Move to a fixed speed	Preset speed 8 is used to define this speed, see below

The move to fixed speed option will only operate if the drive is configured to use preset speed 1 as the reference at the time communications is lost.

Every time there is a transition from the communications healthy state to the communications lost state the reference value set in preset speed 8 will be transferred to preset speed 1 causing the drive to run at the speed defined in preset speed 8.

The drive will continue to run at this speed until such time as the user manually changes preset speed 1 via the keypad or communications returns and a new speed reference is provided via the building automation network

10.3 CT Modbus RTU specification (EIA-485)

This section describes the adaptation of the MODBUS RTU protocol offered on Control Techniques' products.

MODBUS RTU is a master slave system with half-duplex message exchange. The Control Techniques (CT) implementation supports the core function codes to read and write registers. A scheme to map between MODBUS registers and CT parameters is defined. The CT implementation also defines a 32 bit extension to the standard 16 bit register data format.

10.3.1 MODBUS RTU

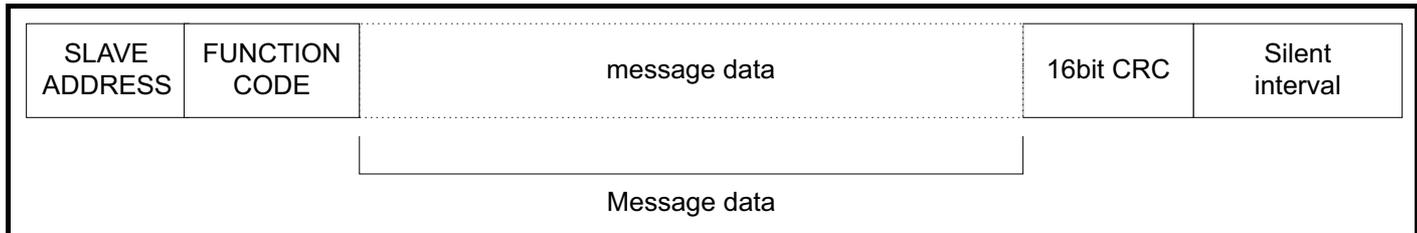
Physical layer

Attribute	Description
Normal physical layer for multi-drop operation	EIA-485 2 wire
Bit stream	Standard UART asynchronous symbols with Non Return to Zero (NRZ)
Symbol	Each symbol consists of:- 1 start bit 8 data bits (transmitted least significant bit first) 2 stop bits*
Baud rates	300, 600, 1200, 2400, 4800, 9600, 19200, 38400, 57600, 76800, 115200

* The drive will accept a packet with 1 or 2 stop bits but will always transmit 2 stop bits

RTU framing

The frame has the following basic format

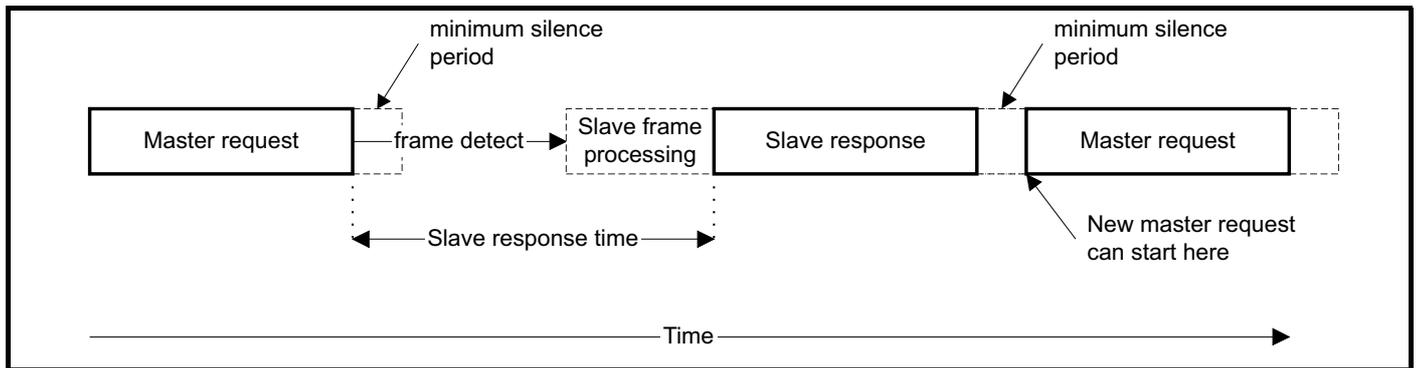


The frame is terminated with a minimum silent period of 3.5 character times (for example, at 19200 baud the minimum silent period is 2 ms). Nodes use the terminating silence period to detect the end of frame and begin frame processing. All frames must therefore be transmitted as a continuous stream without any gaps greater or equal to the silence period. If an erroneous gap is inserted then receiving nodes may start frame processing early in which case the CRC will fail and the frame will be discarded.

MODBUS RTU is a master slave system. All master requests, except broadcast requests, will lead to a response from an individual slave. The slave will respond (i.e. start transmitting the response) within the quoted maximum slave response time (this time is quoted in the data sheet for all Control Techniques products). The minimum slave response time is also quoted but will never be less than the minimum silent period defined by 3.5 character times.

If the master request was a broadcast request then the master may transmit a new request once the maximum slave response time has expired.

The master must implement a message time out to handle transmission errors. This time out period must be set to the maximum slave response time + transmission time for the response.



10.3.2 Slave address

The first byte of the frame is the slave node address. Valid slave node addresses are 1 through 247 decimal. In the master request this byte indicates the target slave node; in the slave response this byte indicates the address of the slave sending the response.

Global addressing

Address zero addresses all slave nodes on the network. Slave nodes suppress the response messages for broadcast requests.

10.3.3 MODBUS registers

The MODBUS register address range is 16 bit (65536 registers) which at the protocol level is represented by indexes 0 through 65535.

PLC registers

Modicon PLCs typically define 4 register 'files' each containing 65536 registers. Traditionally, the registers are referenced 1 through 65536 rather than 0 through 65535. The register address is therefore decremented on the master device before passing to the protocol.

File type	Description	Supported
1	Read only bits ("coil")	Use register
2	Read / write bits ("coil")	Use register
3	Read only 16bit register	Yes
4	Read / write 16bit register	Yes

The register *file* type code is NOT transmitted by MODBUS and all register files can be considered to map onto a single register address space. However, specific function codes are defined in MODBUS to support access to the "coil" registers. All standard CT drive parameters are mapped to register file '4' and the coil function codes are not required.

CT parameter mapping

The Modbus register address is 16 bits in size, of which the upper two bits are used for data type selection leaving 14 bits to represent the parameter address, taking into account the slave increments the address value by 1, this results in a theoretical maximum parameter address of Pr **163.84** (limited to Pr **162.99** in software) when the default standard addressing mode (see *Serial Mode* Pr **11.024**) is used.

To access a parameter number above 99 in any drive menu then the modified addressing mode must be used (see *Serial Mode* Pr **11.024**), this will allow access to parameter numbers up to 255 but also limit the maximum menu number to 63.

The Modbus slave device increments the register address by 1 before processing the command, this effectively prevents access to parameter Pr **00.000** in the drive or option module.

The tables below shows how the start register address is calculated for both addressing modes.

Parameter	Addressing mode	Protocol register
0.mm.ppp	Standard	mm x 100 + ppp - 1
	Modified	mm x 256 + ppp - 1

Examples					
		16-bit		32-bit	
		Decimal	Hex	Decimal	Hex
0.01.021	Standard	120	0x00 78	16504	0x40 78
	Modified	276	0x01 14	16660	0x41 14
0.01.000	Standard	99	0x00 63	16483	0x40 63
	Modified	255	0x00 FF	16639	0x40 FF
0.03.161	Standard	N/A	N/A	N/A	N/A
	Modified	928	0x03 A0	17312	0x43 A0

Data types

The MODBUS protocol specification defines registers as 16 bit signed integers. All CT devices support this data size. Refer to the section 10.3.7 *Extended data types* on page 205 for detail on accessing 32 bit register data.

10.3.4 Data consistency

All CT devices support a minimum data consistency of one parameter (16 bit or 32 bit data). Some devices support consistency for a complete multiple register transaction.

10.3.5 Data encoding

MODBUS RTU uses a 'big-endian' representation for addresses and data items (except the CRC, which is 'little-endian'). This means that when a numerical quantity larger than a single byte is transmitted, the MOST significant byte is sent first. So for example

16 - bits 0x1234 would be sent as 0x12, 0x34

32 - bits 0x12345678 would be sent as 0x12, 0x34, 0x56, 0x78

10.3.6 Function codes

The function code determines the context and format of the message data. Bit 7 of the function code is used in the slave response to indicate an exception.

The following function codes are supported:

Code	Description
3	Read multiple 16 bit registers
6	Write single register
16	Write multiple 16 bit registers
23	Read and write multiple 16 bit registers

FC03 Read multiple

Read a contiguous array of registers. The slave imposes an upper limit on the number of registers, which can be read. If this is exceeded the slave will issue an exception code 2.

Table 10-9 Master request

Byte	Description
0	Slave destination node address 1 through 247, 0 is global (broadcast)
1	Function code 0x03
2	Start register address MSB
3	Start register address LSB
4	Number of 16 bit registers MSB
5	Number of 16 bit registers LSB
6	CRC LSB
7	CRC MSB

Table 10-10 Slave response

Byte	Description
0	Slave source node address
1	Function code 0x03
2	Length of register data in read block (in bytes)
3	Register data 0 MSB
4	Register data 0 LSB
3+byte count	CRC LSB
4+byte count	CRC MSB

FC06 Write single register

Writes a value to a single 16 bit register. The normal response is an echo of the request, returned after the register contents have been written. The register address can correspond to a 32 bit parameter but only 16 bits of data can be sent.

Table 10-11 Master request

Byte	Description
0	Slave node address 1 through 247, 0 is global (broadcast)
1	Function code 0x06
2	Register address MSB
3	Register address LSB
4	Register data MSB
5	Register data LSB
6	CRC LSB
7	CRC MSB

Table 10-12 Slave response

Byte	Description
0	Slave source node address
1	Function code 0x06
2	Register address MSB
3	Register address LSB
4	Register data MSB
5	Register data LSB
6	CRC LSB
7	CRC MSB

FC16 Write multiple

Writes a contiguous array of registers. The slave imposes an upper limit on the number of registers which can be written. If this is exceeded the slave will discard the request and the master will time out.

Table 10-13 Master request

Byte	Description
0	Slave node address 1 through 247, 0 is global (broadcast)
1	Function code 0x10
2	Start register address MSB
3	Start register address LSB
4	Number of 16 bit registers MSB
5	Number of 16 bit registers LSB
6	Length of register data to write (in bytes)
7	Register data 0 MSB
8	Register data 0 LSB
7+byte count	CRC LSB
8+byte count	CRC MSB

Table 10-14 Slave response

Byte	Description
0	Slave source node address
1	Function code 0x10
2	Start register address MSB
3	Start register address LSB
4	Number of 16 bit registers written MSB
5	Number of 16 bit registers written LSB
6	CRC LSB
7	CRC MSB

FC23 Read/Write multiple

Writes and reads two contiguous arrays of registers. The slave imposes an upper limit on the number of registers which can be written. If this is exceeded the slave will discard the request and the master will time out.

Table 10-15 Master request

Byte	Description
0	Slave node address 1 through 247, 0 is global (broadcast)
1	Function code 0x17
2	Start register address to read MSB
3	Start register address to read LSB
4	Number of 16 bit registers to read MSB
5	Number of 16 bit registers to read LSB
6	Start register address to write MSB
7	Start register address to write LSB
8	Number of 16 bit registers to write MSB
9	Number of 16 bit registers to write LSB
10	Length of register data to write (in bytes)
11	Register data 0 MSB
12	Register data 0 LSB
11+byte count	CRC LSB
12+byte count	CRC MSB

Table 10-16 Slave response

Byte	Description
0	Slave source node address
1	Function code 0x17
2	Length of register data in read block (in bytes)
3	Register data 0 MSB
4	Register data 0 LSB
3+byte count	CRC LSB
4+byte count	CRC MSB

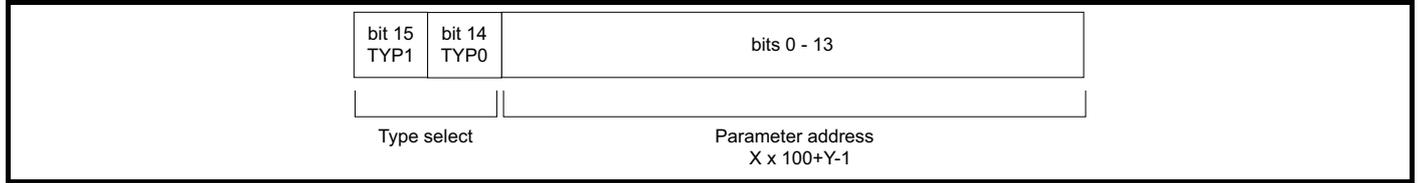
10.3.7 Extended data types

Standard MODBUS registers are 16bit and the standard mapping maps a single Pr **xx.yyy** (e.g.Pr **01.021**) to a single MODBUS register. To support 32 bit data types (integer and float) the MODBUS multiple read and write services are used to transfer a contiguous array of 16 bit registers.

Slave devices typically contain a mixed set of 16 bit and 32 bit registers. To permit the master to select the desired 16 bit or 32 bit access the top two bits of the register address are used to indicate the selected data type.

NOTE

The selection is applied for the whole block access.



The 2bit type field selects the data type according to the table below:

Type field bits 15-14	Selected data type	Comments
00	INT16	backward compatible
01	INT32	-
10	Float32	Not supported
11	Reserved	-

If a 32 bit data type is selected then the slave uses two consecutive 16 bit MODBUS registers (in 'big endian'). The master must also set the correct 'number of 16 bit registers'.

Example, read Pr **20.021** through Pr **20.024** as 32 bit parameters using FC03 from node 8:

Table 10-17 Master request

Byte	Value (Hex)	Description
0	0x08	Slave destination node address
1	0x03	FC03 multiple read
2	0x47	Start register address Pr 20.021
3	0xE4	(16384 + 2021 - 1) = 18404 = 0x47E4
4	0x00	Number of 16bit registers to read
5	0x08	Pr 20.021 through Pr 20.024 is 4x32 bit registers = 8x16 bit registers
6	CRC LSB	CRC
7	CRC MSB	CRC

Table 10-18 Slave response

Byte	Value (Hex)	Description
0	0x08	Slave destination node address
1	0x03	FC03 multiple read
2	0x10	Length of data (bytes) = 4x32 bit registers = 16 bytes
3-6	-	Pr 20.021 data
7-10	-	Pr 20.022 data
11-14	-	Pr 20.023 data
15-18	-	Pr 20.024 data
19	CRC LSB	CRC
20	CRC MSB	CRC

Reads when actual parameter type is different from selected

The slave will send the least significant word of a 32 bit parameter if that parameter is read as part of a 16 bit access.

The slave will sign extend the least significant word if a 16 bit parameter is accessed as a 32 bit parameter. The number of 16 bit registers must be even during a 32 bit access.

Example, if Pr **01.028** is a 32 bit parameter with a value of 0x12345678, Pr **01.029** is a signed 16 bit parameter with a value of 0xABCD, and Pr **01.030** is a signed 16 bit parameter with a value of 0x0123.

Read	Start register address	Number of 16 bit registers	Response (Hex)	Comments
Pr 01.028	127	1	0x5678	Standard 16 bit access to a 32 bit register will return low 16 bit word of truncated data
Pr 01.028	16511*	2	0x12345678	Full 32 bit access
Pr 01.028	16511*	1	Exception 2	Number of words must be even for 32 bit access
Pr 01.029	128	1	0xABCD	Standard 16 bit access to a 32 bit register will return low 16 bit word of data
Pr 01.029	16512*	2	0xFFFFABCD	32 bit access to a 16 bit register will return 32 bit sign extended data
Pr 01.030	16513*	2	0x00000123	32 bit access to a 16 bit register will return 32 bit sign extended data
Pr 01.028 to Pr 01.029	127	2	0x5678, 0xABCD	Standard 16 bit access to a 32 bit register will return low 16 bit word of truncated data
Pr 01.028 to Pr 01.029	16511*	4	0x12345678, 0xFFFFABCD	Full 32 bit access

* Bit 14 is set to allow 32 bit access.

Writes when actual parameter type is different from selected

The slave will allow writing a 32 bit value to a 16 bit parameter as long as the 32 bit value is within the normal range of the 16 bit parameter.

The slave will allow a 16 bit write to a 32 bit parameter. The slave will sign extend the written value, therefore the effective range of this type of write will be -32768 to +32767.

Examples, if Pr **01.028** has a range of ± 100000 , and Pr **01.029** has a range of ± 10000 .

Write	Start register address	Number of 16bit registers	Data (Hex)	Comments
Pr 01.028	127	1	0x1234	Standard 16 bit write to a 32bit register. Value written = 0x00001234
Pr 01.028	127	1	0xABCD	Standard 16 bit write to a 32bit register. Value written = 0xFFFFABCD
Pr 01.028	16511	2	0x00001234	Value written = 0x00001234
Pr 01.029	128	1	0x0123	Value written = 0x0123
Pr 01.029	16512	2	0x00000123	Value written = 0x00000123

* Bit 14 is set to allow 32 bit access

10.3.8 Exceptions

The slave will respond with an exception response if an error is detected in the master request. If a message is corrupted and the frame is not received or the CRC fails then the slave will not issue an exception. In this case the master device will time out. If a write multiple (FC16 or FC23) request exceeds the slave maximum buffer size then the slave will discard the message. No exception will be transmitted in this case and the master will time out.

Exception message format

The slave exception message has the following format.

Byte	Description
0	Slave source node address
1	Original function code with bit 7 set
2	Exception code
3	CRC LSB
4	CRC MSB

Exception codes

The following exception codes are supported.

Code	Description
1	Function code not supported
2	Register address out of range, or request to read too many registers

Parameter over range during block write FC16

The slave processes the write block in the order the data is received. If a write fails due to an out of range value then the write block is terminated. However, the slave does not raise an exception response, rather the error condition is signalled to the master by the number of successful writes field in the response.

Parameter over range during block read/write FC23

There will be no indication that there has been a value out of range during a FC23 access.

10.3.9 CRC

The CRC is a 16 bit cyclic redundancy check using the standard CRC-16 polynomial $x^{16} + x^{15} + x^2 + 1$. The 16 bit CRC is appended to the message and transmitted LSB first.

The CRC is calculated on ALL the bytes in the frame.

10.3.10 Device compatibility parameters

All devices have the following compatibility parameters defined:

Parameter	Description
Device ID	Unique device identification code
Minimum slave response time	The minimum delay between the end of a message from the master and the time at which the master is ready to receive a response from the slave.
Maximum slave response time	When global addressing, the master must wait for this time before issuing a new message. In a network of devices, the slowest time must be used
Baud rate	Baud rate used by Modbus RTU
32 bit float data type supported	If this data type is not supported then an over range error will be raised if this data type is used
Maximum buffer size	Determines the maximum block size.

10.4 BACnet specification

This section describes the support for BACnet MS/TP Master device.

H300 BACnet derivative support "BACnet-Application Specific Controller (B-ASC)" profile and it is compliance to BACnet protocol Version 1 Revision15.

H300 BACnet drive act as Master on Data Link Layer over MS/TP for data communication. Device supports three standard Baud rate **9600, 19200, 38400**.

10.4.1 BACnet Interoperability Building Blocks (BIBBs)

The BACnet Interoperability Building Blocks (BIBBs) are collections of one or more BACnet services. They are prescribed in terms of an "A" and a "B" device. Both of these devices are nodes on a BACnet network.

Here "A" node will act as the user of data (Client) and "B" node will be the provider of this data.

HVAC H300 device support following BIBBs

10.4.2 Data Sharing Services: These BIBBs prescribe the BACnet capabilities required to interoperable perform the data sharing functions.

- Data Sharing-ReadProperty-B (DS-RP-B)**

The B device is a provider of data to device A.

BACnet Service	Initiate	Execute
Read Property		X

This property has the following three fields

Object ID	Property	ArrayIndex
-----------	----------	------------

'ArrayIndex' field is required while reading an 'Array' property.

- Date Sharing-WriteProperty-B(DS-RW-B)**

The B device allows a value to be changed by device A.

BACnet Service	Initiate	Execute
Write Property		X

This property has the following five fields

Object ID	Property	ArrayIndex	Value	Priority
-----------	----------	------------	-------	----------

'ArrayIndex' is required while writing an 'Array' property.

'Priority' is required while writing to 'Commandable' property.

10.4.3 Device and Network Management Services: These BIBBs prescribe the BACnet capabilities required to interoperable perform the Device Management and Network Management functions.

- Device Management-Dynamic Device Building-B (DM-DDB-B)**

The B device provides information about its device attributes and responds to requests to identify itself. This is an unconfirmed service.

BACnet Service	Initiate	Execute
Who-Is		X
I-Am	X	

Structure of Who-Is service is as below; Both the fields are optional

Low Limit	High Limit
-----------	------------

- Device Management-Dynamic Object Building-B (DM-DOB-B)**

The B device provides address information about its objects upon request. This is an unconfirmed service.

BACnet Service	Initiate	Execute
Who-Has		X
I-Have	X	

Structure of 'Who-Has' service primitive is as below. The limit fields are optional.

Low Limit	High Limit	Object ID	Object Name
-----------	------------	-----------	-------------

Refer the 'H300 BACnet Objects list with ID and Name' table below.

10.4.4 Device Management-Reinitialize Device-B (DM-RD-B)

The B device performs reinitialization requests from the A device. The optional password field shall be ignored.

BACnet Service	Initiate	Execute
Reinitialize Device		X

Structure of 'ReinitializeDevice' service primitive is as below.

The password field is an optional.

State	Password

H300 BACnet Drive supports the following two states.

- 'Cold Start' (Reboot itself).
- 'Warm Start' (Reset itself to some predefined initial state).

Password field is an optional hence ignored.

10.4.5 Device Management-TimeSynchronization-B (DM-RD-B)

The B device interprets time synchronization messages from the A device. This service may be broadcast, multicast, or addressed to a single recipient.

BACnet Service	Initiate	Execute
TimeSynchronization		X

Structure of 'TimeSynchronization' service primitive is as below.

Date	Time

Valid 'Date' range: Minimum: January 1, 2012; Maximum: December 31, 2079.

10.4.6 Device Management-DeviceCommunicationControl-B (DM-DCC-B)

The B device instructed to stop initiating and optionally stop responding to all APDUs (except DeviceCommunicationControl or, if supported, ReinitializeDevice). This is confirmed service request.

BACnet Service	Initiate	Execute
DeviceCommunicationControl		X

Structure of 'DeviceCommunicationControl' service primitive is as below'

Time	Enable/Disable	Password

'Password' field is an optional hence ignored.

Only 'indefinite' time duration is supported therefore 'Time' field must be kept 'blank' and communication must be re-enabled by a 'DeviceCommunicationControl' or 'ReinitializeDevice' service.

10.4.7 Object/Property Support Matrix

The following table summarizes the Object Types / Properties supported:

Property	Object Type						
	Device	Analog Input	Analog Output	Analog Value	Binary Input	Binary Output	Binary Value
Object Identifier	✓	✓	✓	✓	✓	✓	✓
Object Name	✓	✓	✓	✓	✓	✓	✓
Object Type	✓	✓	✓	✓	✓	✓	✓
Property List	✓	✓	✓	✓	✓	✓	✓
System Status	✓						
Vendor Name	✓						
Vendor Identifier	✓						
Model Name	✓						
Firmware Revision	✓						
Application Software Revision	✓						
Protocol Version	✓						
Protocol Revision	✓						
Services Supported	✓						
Object Types Supported	✓						
Object List	✓						

Property	Object Type						
	Device	Analog Input	Analog Output	Analog Value	Binary Input	Binary Output	Binary Value
Max APDU Length	✓						
Segmentation Support	✓						
Local Date	✓						
Local Time	✓						
APDU Timeout	✓						
Number APDU Retries	✓						
Max Master	✓						
Max Info Frames	✓						
Device Address Binding	✓						
Database Revision	✓						
Present Value		✓	✓	✓	✓	✓	✓
Status Flags		✓	✓	✓	✓	✓	✓
Event State		✓	✓	✓	✓	✓	✓
Reliability		✓		✓**			
Out-of-Service		✓	✓	✓	✓	✓	✓
Units		✓	✓	✓			
Priority Array			✓*	✓*		✓*	✓*
Relinquish Default			✓*	✓*		✓*	✓*
Polarity					✓***	✓***	

* These properties are for commandable objects only.

** Not all the AV objects have this property.

*** Polarities are changed by the drive parameters. For BACnet they are read-only.

10.4.8 Detailed BACnet Objects

The tables in the following sections describe the BACnet objects that are available on the drive. The device object is also produced when queried by a master on the network.

The Present Value property of each of the objects can be accessed in the manner indicated in the right-hand column of each of the object tables. The three access types are as follows:

Code	Type	Description
RO	Read Only	The present value of these objects can only be read.
RW	Read/Write	The present value property of these objects can be both read from and written to. Writes from different BACnet devices will overwrite each other.
C	Commanded	The present value property of these objects can be both read from and written to. Writes are accompanied by a priority level in the range 1 to 16, the underlying drive parameter is set to the value written at the highest priority level. All commandable objects support a writeable relinquish default property. The value of this property becomes the present value when no priority is provided.

Device Object

Device Object Properties
Object Identifier
Object Name
Object Type
Property List
System Status
Vendor Name
Vendor Identifier
Model Name
Firmware Revision
Application Software Revision
Protocol Version
Protocol Revision
Services Supported
Object Types Supported
Object List
Max APDU Length
Segmentation Support
Local Date
Local Time
APDU Timeout
Number APDU Retries
Max Master
Max Info Frames
Device Address Binding
Database Revision

Analog Input Objects

Instance ID	Object Name	Description	Units	Access R=Read, W=Read/Write, C=Commandable
1	#AI_01 Drive Analog IP1	Analog Input 1 on Drive	Percent	R
2	#AI_02 Drive Analog IP2	Analog Input 2 on Drive	Percent	R

Analog Output Objects

Instance ID	Object Name	Description	Units	Access R=Read, W=Read/Write, C=Commandable
1	#AO_01 Drive Analog OP1	Analog Output 1 on Drive	Percent	C
2	#AO_02 Drive Analog OP2	Analog Output 2 on Drive	Percent	C

Analog Value Objects

Instance ID	Object Name	Description	Units	Access R=Read, W=Read/Write, C=Commandable
4	#AV_04 Speed Ref	The required output frequency/speed reference	Hertz	C
5	#AV_05 Max Speed Ref	The maximum reference clamp value	Hertz	W
6	#AV_06 Output Current	Motor output current magnitude	Amperes	R
7	#AV_07 Output Torque	Motor output torque as a percent of full load	Percent	R
8	#AV_08 Output Frequency	Drive output frequency	Hertz	R
9	#AV_09 Output Speed	Motor Speed	RPM	R
10	#AV_10 Output Power	Drive Output Power	kW	R
11	#AV_11 Drive Status Wd	Drive Status Word	No Units	R
12	#AV_12 User Trip Param	User trip	No Units	W
13	#AV_13 Last Trip	Last Drive Trip	No Units	R
14	#AV_14 Filtr Change(dt)	Time between filter changes	Hours	W
15	#AV_15 Nxt Filtr ChTime	Time before filter change due	Hours	R
16	#AV_16 Enrgy Meter(MWh)	Energy meter (MWh)	MWh	R
17	#AV_17 Enrgy Meter(kWh)	Energy meter (kWh)	kWh	R
18	#AV_18 PID1 Dig Ref	Digital reference for PID 1	Percent	C
19	#AV_19 PID1 Dig Fback	Digital feedback for PID 1	Percent	C
20	#AV_20 PID1 Ref	Sum of all reference inputs to PID 1	Percent	R
21	#AV_21 PID1 Fback	Sum of all feedback inputs to PID 1	Percent	R
22	#AV_22 PID1 Output	The output from PID 1	Percent	R
23	#AV_23 PID2 Dig Ref	Digital reference for PID 2	Percent	C
24	#AV_24 PID2 Dig Fback	Digital feedback for PID 2	Percent	C
25	#AV_25 PID2 Ref	Sum of all reference inputs to PID 2	Percent	R
26	#AV_26 PID2 Fback	Sum of all feedback inputs to PID 2	Percent	R
27	#AV_27 PID2 Output	The output from PID 2	Percent	R
28	#AV_28 User Sel 29.010	User selectable parameter 1	No Units	R/W
29	#AV_29 User Sel 29.011	User selectable parameter 2	No Units	R/W
30	#AV_30 User Sel 29.012	User selectable parameter 3	No Units	R/W
31	#AV_31 User Sel 29.013	User selectable parameter 4	No Units	R/W
32	#AV_32 User Sel 29.014	User selectable parameter 5	No Units	R/W
33	#AV_33 User Sel 29.015	User selectable parameter 6	No Units	R/W
34	#AV_34 User Sel 29.016	User selectable parameter 7	No Units	R/W
35	#AV_35 User Sel 29.017	User selectable parameter 8	No Units	R/W
36	#AV_36 User Sel 29.018	User selectable parameter 9	No Units	R/W
37	#AV_37 User Sel 29.019	User selectable parameter 10	No Units	R/W

NOTE

Analog Value 28 to 37 are the objects where any drive parameter can be mapped and controlled using BACnet communication. The Access control for that object will be as per the drive parameters access.

Binary Input Objects

Instance ID	Object Name	Description	Access R=Read, W=Read/Write, C=Commandable
1	#BI_01 Drive Binary IP1	Digital Input 1 on Drive (bi-directional)	R
2	#BI_02 Drive Binary IP2	Digital Input 2 on Drive (bi-directional)	R
3	#BI_03 Drive Binary IP3	Digital Input 3 on Drive (bi-directional)	R
4	#BI_04 Drive Binary IP4	Digital Input 4 on Drive	R
5	#BI_05 Drive Binary IP5	Digital Input 5 on Drive	R
6	#BI_06 Drive Binary IP6	Digital Input 6 on Drive	R
7	#BI_07 Drive Binary IP7	Drive enable input	R

Binary Output Objects

Instance ID	Object Name	Description	Access R=Read, W=Read/Write, C=Commandable
1	#BO_01 Drive Binary OP1	Digital Output 1 on Drive (bi-directional)	C
2	#BO_02 Drive Binary OP2	Digital Output 2 on Drive (bi-directional)	C
3	#BO_03 Drive Binary OP3	Digital Output 2 on Drive (bi-directional)	C
4	#BO_04 Drive Binary OP4	24V Output	C
5	#BO_05 Drive Binary RI1	Drive Relay 1	C
6	#BO_06 Drive Binary RI2	Drive Relay 2	C

NOTE

Binary Input and Output objects 1 to 3 are bi-directional points - They can be either Input or Output at a time.

Binary Value Objects

Instance ID	Object Name	Description	Access R=Read, W=Read/Write, C=Commandable
1	#BV_01 Reset Enrgy Metr	Digital Output 1 on Drive (bi-directional)	W
2	#BV_02 Filtr Change Rqd	Digital Output 2 on Drive (bi-directional)	W*
3	#BV_03 Drive Run Fwrd	Digital Output 2 on Drive (bi-directional)	C
4	#BV_04 Drive Healthy	24V Output	R
5	#BV_05 Drive Warning	Drive Relay 1	R
6	#BV_06 Drive Reset	Drive Relay 2	W**

* Can only be set to INACTIVE.

** Can only be set to ACTIVE from INACTIVE.

NOTE

The object instantiation in H300 drive is STATIC. i.e. No object can be created or deleted at runtime.

11 Advanced parameters

This is a quick reference to all parameters in the drive showing units, ranges limits etc, with block diagrams to illustrate their function. Full descriptions of the parameters can be found in the *Parameter Reference Guide*.



These advanced parameters are listed for reference purposes only. The lists in this chapter do not include sufficient information for adjusting these parameters. Incorrect adjustment can affect the safety of the system, and damage the drive and or external equipment. Before attempting to adjust any of these parameters, refer to the *Parameter Reference Guide*.

WARNING

Table 11-1 Menu descriptions

Menu	Description
0	Commonly used basic set up parameters for quick / easy programming
1	Frequency / Speed reference
2	Ramps
3	Speed feedback and speed control
4	Torque and current control
5	Motor control
6	Sequencer and clock
7	Analog I/O, Temperature monitoring
8	Digital I/O
9	Programmable logic, motorized pot, binary sum, timers and scope
10	Status and trips
11	Drive set-up and identification, serial communications
12	Threshold detectors and variable selectors
13	Standard motion control
14	User PID controller
15	Option module slot 1 set-up menu
16	Option module slot 2 set-up menu
17	Option module slot 3 set-up menu
18	General option module application menu 1
19	General option module application menu 2
20	General option module application menu 3
22	Menu 0 set-up
23	Not allocated
28	Reserved menu
29	Building Automation Network Setup
Slot 1	Slot 1 option menus*
Slot 2	Slot 2 option menus*
Slot 3	Slot 3 option menus*

* Only displayed when the option modules are installed.

Operation mode abbreviations:

Open-loop:

Sensorless control for induction motors

RFC-A Sensorless:

Asynchronous Rotor Flux Sensorless Control for induction motors

RFC-S Sensorless: Synchronous Rotor Flux Sensorless Control for synchronous motors including permanent magnet motors.

Default abbreviations:

Standard default value (50 Hz AC supply frequency)

USA default value (60 Hz AC supply frequency)

NOTE

Parameter numbers shown in brackets {...} are the equivalent Menu 0 parameters. Some Menu 0 parameters appear twice since their function depends on the operating mode.

The Range - RFC-A / S column applies to both RFC-A and RFC-S. For some parameters, this column applies to only one of these modes, this is indicated accordingly in the Default columns.

In some cases, the function or range of a parameter is affected by the setting of another parameter. The information in the lists relates to the default condition of any parameters affected in this way.

Table 11-2 Key to parameter table coding

Coding	Attribute
RW	Read/Write: can be written by the user
RO	Read only: can only be read by the user
Bit	1 bit parameter: 'On' or 'Off' on the display
Num	Number: can be uni-polar or bi-polar
Txt	Text: the parameter uses text strings instead of numbers.
Bin	Binary parameter
IP	IP Address parameter
Mac	Mac Address parameter
Date	Date parameter
Time	Time parameter
Chr	Character parameter
FI	Filtered: some parameters which can have rapidly changing values are filtered when displayed on the drive keypad for easy viewing.
DE	Destination: This parameter selects the destination of an input or logic function.
RA	Rating dependent: this parameter is likely to have different values and ranges with drives of different voltage and current ratings. Parameters with this attribute will be transferred to the destination drive by non-volatile storage media when the rating of the destination drive is different from the source drive and the file is a parameter file. However, the values will be transferred if only the current rating is different and the file is a difference from default type file.
ND	No default: The parameter is not modified when defaults are loaded
NC	Not copied: not transferred to or from non-volatile media during copying.
PT	Protected: cannot be used as a destination.
US	User save: parameter saved in drive EEPROM when the user initiates a parameter save.
PS	Power-down save: parameter automatically saved in drive EEPROM when the under volts (UV) trip occurs.

Table 11-3 Feature look-up table

Feature	Related parameters (Pr)												
Acceleration rates	02.010	02.011 to 02.019		02.032	02.033	02.034	02.002						
Analog speed reference 1	01.036	07.010	07.001	07.007	07.008	07.009	07.025	07.026	07.030				
Analog speed reference 2	01.037	07.014	01.041	07.002	07.011	07.012	07.013	07.028	07.031				
Analog I/O	Menu 7												
Analog input 1	07.001	07.007	07.008	07.009	07.010	07.025	07.026	07.028	07.030	07.040	07.043	07.051	
Analog input 2	07.002	07.011	07.012	07.013	07.014	07.022	07.023	07.027	07.031	07.041	07.044		
Analog output 1	07.019	07.020	07.021	07.033									
Analog output 2	07.022	07.023	07.024										
Application menu	Menu 18			Menu 19		Menu 20							
At speed indicator bit	03.006	03.007	03.009	10.006	10.005	10.007							
Auto reset	10.034	10.035	10.036	10.001									
Autotune	05.010	05.012	05.017	05.024	05.025								
Catch a spinning motor	06.009	05.040											
Coast to stop	06.001												
Comms	11.023 to 11.026												
Copying	11.042	11.036 to 11.040											
Cost - per kWh electricity	06.016	06.017	06.024	06.025	06.026	06.040							
Current controller	04.013	04.014											
Current feedback	04.001	04.002	04.017	04.004	04.012	04.020	04.023	04.024	04.026	10.008	10.009	10.017	
Current limits	04.005	04.006	04.007	04.018	04.015	04.019	04.016	05.007	05.010	10.008	10.009	10.017	
DC bus voltage	05.005	02.008											
DC injection braking	06.006	06.007	06.001										
Deceleration rates	02.020	02.021 to 02.029		02.004	02.035 to 02.037		02.002	02.008	06.001	10.030	10.031	10.039	02.009
Defaults	11.043	11.046											
Digital I/O	Menu 8												
Digital I/O read word	08.020												
Digital I/O T22	08.001	08.011	08.021	08.031									
Digital I/O T23	08.002	08.012	08.022	08.032									
Digital I/O T24	08.003	08.013	08.023	08.033									
Digital input T25	08.004	08.014	08.024										
Digital input T26	08.005	08.015	08.025	08.039									
Digital input T27	08.006	08.016	08.026	08.039									
Digital output T3	08.008	08.018	08.028										
Direction	10.013	06.030	06.031	01.003	10.014	02.001	03.002	08.003	08.004	10.040			
Drive active	10.002	10.040											
Drive derivative	11.028												
Drive Healthy	10.001	08.027	08.007	08.017	10.036	10.040							
Dynamic performance	05.026												
Dynamic V/F	05.013												
Enable	06.015	08.009	08.010										
External trip	10.032	08.010	08.007										
Fan speed	06.045												
Fast disable	06.029												
Field weakening - induction motor	01.006	05.028											
Field weakening - PM motor	05.022	01.006	05.009										
Fire mode	01.053	01.054											
Filter change	06.019	06.018											
Frequency reference selection	01.014	01.015											
High stability space vector modulation	05.019												
I/O sequencer	06.004	06.030	06.031	06.032	06.033	06.034	06.042	06.043	06.041				
Inertia compensation	02.038	05.012	04.022	03.018									
Keypad reference	01.017	01.014	01.043	01.051	06.012	06.013							
Line power supply loss	06.003	10.015	10.016	05.005									
Logic function 1	09.001	09.004	09.005	09.006	09.007	09.008	09.009	09.010					
Logic function 2	09.002	09.014	09.015	09.016	09.017	09.018	09.019	09.020					
Maximum speed	01.006												
Menu 0 set-up	Menu 22												
Minimum speed	01.007	10.004											
Modules - number of	11.035												
Motor map	05.006	05.007	05.008	05.009	05.010	05.011							
Motorized potentiometer	09.021	09.022	09.023	09.024	09.025	09.026	09.027	09.028					

Feature	Related parameters (Pr)												
Offset speed reference	01.004	01.038	01.009										
Onboard PLC	11.047 to 11.051												
Open loop vector mode	05.014	05.017	05.023										
Operating mode	00.048	11.031	03.024	05.014									
Output	05.001	05.002	05.003	05.004									
Overspeed threshold	03.008												
PID controller	Menu 14												
Positive logic	08.029												
Power up parameter	11.022	11.021											
Preset speeds	01.015	01.021 to 01.028		01.016	01.014	01.042	01.045 to 01.048		01.050				
Programmable logic	Menu 9												
Quasi square operation	05.020												
Ramp (accel / decel) mode	02.004	02.008	06.001	02.002	02.003	10.030	10.031	10.039					
Rated speed	05.008												
Regenerating	10.010	10.011	10.030	10.031	06.001	10.012	10.039	10.040					
Relay outputs	08.007	08.017	08.027	8.045	8.055	8.065							
Reset	10.033	08.002	08.022	10.034	10.035	10.036	10.001						
RFC-A Sensorless	03.024	03.042	04.012										
S ramp	02.006	02.007											
Sample rates	05.018												
Safe Torque Off input	08.009	08.010											
Security code	11.030	11.044											
Serial comms	11.023 to 11.026												
Skip speeds	01.029	01.030	01.031	01.032	01.033	01.034	01.035						
Slip compensation	05.027	05.008											
NV media card	11.036 to 11.040			11.042									
Firmware version	11.029	11.034											
Speed controller	03.010 to 03.017			03.019	03.020	03.021							
Speed feedback	03.002	03.003	03.004										
Speed feedback - drive	03.026												
Speed reference selection	01.014	01.015	01.049	01.050	01.001								
Status word	10.040												
Supply	06.044	05.005											
Switching frequency	05.018	05.035	07.034	07.035									
Thermal protection - drive	05.018	05.035	07.004	07.005	07.006	07.032	07.035	10.018					
Thermal protection - motor	04.015	05.007	04.019	04.016	04.025	07.015							
Thermistor inputs	7.007	7.001	7.053	7.011	7.002	7.058							
Threshold detector 1	12.001	12.003 to 12.007											
Threshold detector 2	12.002	12.023 to 12.027											
Time - filter change	06.019	06.018											
Time - powered up log	06.020	06.021	06.028										
Time - run log	06.022	06.023	06.028										
Torque	04.003	04.026	05.032										
Torque mode	04.008	04.011	04.009	04.010									
Trip detection	10.037	10.038	10.020 to 10.029										
Trip log	10.020 to 10.029			10.041 to 10.051		06.028	10.070 to 10.079						
Under voltage	05.005	10.016	10.015										
V/F mode	05.015	05.014											
Variable selector 1	12.008 to 12.015												
Variable selector 2	12.028 to 12.035												
Velocity feed forward	01.039	01.040											
Voltage controller	05.031												
Voltage mode	05.014	05.017	05.023	05.015									
Voltage rating	11.033	05.009	05.005										
Voltage supply	06.044	05.005											
Warning	10.019	10.012	10.017	10.018	10.040								

11.1 Parameter ranges and Variable minimum/maximums:

Some parameters in the drive have a variable range with a variable minimum and a variable maximum values which is dependent on one of the following:

- The settings of other parameters
- The drive rating
- The drive mode
- Combination of any of the above

The tables below give the definition of variable minimum/maximum and the maximum range of these.

VM_AC_VOLTAGE		Range applied to parameters showing AC voltage
Units	V	
Range of [MIN]	0	
Range of [MAX]	0 to 930	
Definition	VM_AC_VOLTAGE[MAX] is drive voltage rating dependent. See Table 11-4 VM_AC_VOLTAGE[MIN] = 0	

VM_AC_VOLTAGE_SET		Range applied to the AC voltage set-up parameters
Units	V	
Range of [MIN]	0	
Range of [MAX]	0 to 690	
Definition	VM_AC_VOLTAGE_SET[MAX] is drive voltage rating dependent. See Table 11-4 VM_AC_VOLTAGE_SET[MIN] = 0	

VM_ACCEL_RATE		Maximum applied to the ramp rate parameters
Units	s / 100 Hz, s / 1000 rpm, s / 1000 mm/s	
Range of [MIN]	Open-loop: 0.0 RFC-A, RFC-S: 0.000	
Range of [MAX]	Open-loop: 0.0 to 3200.0 RFC-A, RFC-S: 0.000 to 3200.000	
Definition	<p>A maximum needs to be applied to the ramp rate parameters because the units are a time for a change of speed from zero to a defined level or to maximum speed. The defined level is 100 Hz for Open-loop mode and 1000 rpm or 1000 mm/s for RFC-A and RFC-S modes. If the change of speed is to the maximum speed then changing the maximum speed changes the actual ramp rate for a given ramp rate parameter value. The variable maximum calculation ensures that longest ramp rate (parameter at its maximum value) is not slower than the rate with the defined level, i.e. 3200.00 s / Hz for Open-loop mode, and 3200.000 s / 1000 rpm or 3200.000 s / 1000 mm/s for RFC-A and RFC-S modes.</p> <p>The maximum frequency/speed is taken from <i>Maximum Reference Clamp (01.006)</i> if <i>Select Motor 2 Parameters (11.045)</i> = 0, or <i>M2 Maximum Reference Clamp (21.001)</i> if <i>Select Motor 2 Parameters (11.045)</i> = 1.</p> <p>Open-loop mode VM_ACCEL_RATE[MIN] = 0.0</p> <p>If Ramp Rate Units (02.039) = 0: VM_ACCEL_RATE[MAX] = 3200.0 Otherwise: VM_ACCEL_RATE[MAX] = 3200.0 x Maximum frequency / 100.0</p> <p>RFC-A, RFC-S modes VM_ACCEL_RATE[MIN] = 0.000</p> <p>If Ramp Rate Units (02.039) = 0: VM_ACCEL_RATE[MAX] = 3200.000 Otherwise: VM_ACCEL_RATE[MAX] = 3200.000 x Maximum speed / 1000.0</p>	

VM_DC_VOLTAGE		Range applied to parameters showing DC voltage
Units	V	
Range of [MIN]	0	
Range of [MAX]	0 to 1190	
Definition	<p>VM_DC_VOLTAGE[MAX] is the full scale DC bus voltage feedback (over voltage trip level) for the drive. This level is drive voltage rating dependent. See Table 11-4</p> <p>VM_DC_VOLTAGE[MIN] = 0</p>	

VM_DC_VOLTAGE_SET		Range applied to DC voltage reference parameters
Units	V	
Range of [MIN]	0	
Range of [MAX]	0 to 1150	
Definition	<p>VM_DC_VOLTAGE_SET[MAX] is drive voltage rating NV dependent. See Table 11-4</p> <p>VM_DC_VOLTAGE_SET[MIN] = 0</p>	

VM_DRIVE_CURRENT		Range applied to parameters showing current in A
Units	A	
Range of [MIN]	-99999.999 to 0.000	
Range of [MAX]	0.000 to 99999.999	
Definition	<p>VM_DRIVE_CURRENT[MAX] is equivalent to the full scale (over current trip level) or Kc value for the drive and is given by <i>Full Scale Current Kc (11.061)</i>.</p> <p>VM_DRIVE_CURRENT[MIN] = - VM_DRIVE_CURRENT[MAX]</p>	

VM_DRIVE_CURRENT_UNIPOLAR		Unipolar version of VM_DRIVE_CURRENT
Units	A	
Range of [MIN]	0.000	
Range of [MAX]	0.000 to 99999.999	
Definition	<p>VM_DRIVE_CURRENT_UNIPOLAR[MAX] = VM_DRIVE_CURRENT[MAX]</p> <p>VM_DRIVE_CURRENT_UNIPOLAR[MIN] = 0.000</p>	

VM_HIGH_DC_VOLTAGE		Range applied to parameters showing high DC voltage
Units	V	
Range of [MIN]	0	
Range of [MAX]	0 to 1500	
Definition	<p>VM_HIGH_DC_VOLTAGE[MAX] is the full scale DC bus voltage feedback for the high DC bus voltage measurement which can measure the voltage if it goes above the normal full scale value. This level is drive voltage rating dependent. See Table 11-4</p> <p>VM_HIGH_DC_VOLTAGE[MIN] = 0</p>	

VM_LOW_UNDER_VOLTS		Range applied the low under-voltage threshold
Units	V	
Range of [MIN]	24	
Range of [MAX]	24 to 1150	
Definition	<p>If <i>Back-up Mode Enable (06.068)</i> = 0: VM_LOW_UNDER_VOLTS[MAX] = VM_STD_UNDER_VOLTS[MIN]</p> <p>If <i>Back-up Mode Enable (06.068)</i> = 1: VM_LOW_UNDER_VOLTS[MAX] = VM_STD_UNDER_VOLTS[MIN] / 1.1.</p> <p>VM_LOW_UNDER_VOLTS[MIN] = 24.</p>	

VM_MIN_SWITCHING_FREQUENCY		Range applied to the minimum switching frequency parameter
Units	User units	
Range of [MIN]	0	
Range of [MAX]	0 to 6	
Definition	VM_MIN_SWITCHING_FREQUENCY[MAX] = <i>Maximum Switching Frequency (05.018)</i> VM_MIN_SWITCHING_FREQUENCY[MIN] = 0 for motor control modes	

VM_MOTOR1_CURRENT_LIMIT VM_MOTOR2_CURRENT_LIMIT		Range applied to current limit parameters
Units	%	
Range of [MIN]	0.0	
Range of [MAX]	0.0 to 1000.0	
Definition	VM_MOTOR1_CURRENT_LIMIT[MIN] = 0.0 Open-loop VM_MOTOR1_CURRENT_LIMIT[MAX] = $(I_{Tlimit} / I_{Trated}) \times 100 \%$ Where: $I_{Tlimit} = I_{MaxRef} \times \cos(\sin^{-1}(I_{Mrated} / I_{MaxRef}))$ $I_{Mrated} = Pr \ 05.007 \sin \phi$ $I_{Trated} = Pr \ 05.007 \times \cos \phi$ $\cos \phi = Pr \ 05.010$ I_{MaxRef} is 0.7 x Pr 11.061 when the motor rated current set in Pr 05.007 is the lower of 0.7 x Pr 11.061 or 1.1 x Pr 11.060 (i.e. Normal duty). RFC-A VM_MOTOR1_CURRENT_LIMIT[MAX] = $(I_{Tlimit} / I_{Trated}) \times 100 \%$ Where: $I_{Tlimit} = I_{MaxRef} \times \cos(\sin^{-1}(I_{Mrated} / I_{MaxRef}))$ $I_{Mrated} = Pr \ 05.007 \times \sin \phi_1$ $I_{Trated} = Pr \ 05.007 \times \cos \phi_1$ $\phi_1 = \cos^{-1}(Pr \ 05.010) + \phi_2$. ϕ_1 is calculated during an autotune. See the variable minimum / maximum calculations in the <i>Parameter Reference Guide</i> for more information regarding ϕ_2 . I_{MaxRef} is 0.9 x Pr 11.061 when the motor rated current set in Pr 05.007 is the lower of 0.9 x Pr 11.061 or 1.1 x Pr 11.060 (i.e. Normal duty). RFC-S VM_MOTOR1_CURRENT_LIMIT[MAX] = $(I_{MaxRef} / Pr \ 05.007) \times 100 \%$ Where: I_{MaxRef} is 0.9 x Pr 11.061 when the motor rated current set in Pr 05.007 is the lower of 0.9 x Pr 11.061 or 1.1 x Pr 11.060 (i.e. Normal duty).	

VM_NEGATIVE_REF_CLAMP1 VM_NEGATIVE_REF_CLAMP2		Limits applied to the negative frequency or speed clamp																	
Units	Open-loop: Hz RFC-A, RFC-S: rpm or mm/s																		
Range of [MIN]	Open-loop: -550.0 to 0.0 RFC-A, RFC-S: -50000.0 to 0.0																		
Range of [MAX]	Open-loop: 0.0 to 550.0 RFC-A, RFC-S: 0.0 to 50000.0																		
Definition	<table border="1"> <thead> <tr> <th>Negative Reference Clamp Enable (01.008)</th> <th>Bipolar Reference Enable (01.010)</th> <th>VM_NEGATIVE_REF_CLAMP1[MIN]</th> <th>VM_NEGATIVE_REF_CLAMP1[MAX]</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>0</td> <td>0.0</td> <td>Pr 01.006</td> </tr> <tr> <td>0</td> <td>1</td> <td>0.0</td> <td>0.0</td> </tr> <tr> <td>1</td> <td>X</td> <td>-VM_POSITIVE_REF_CLAMP[MAX]</td> <td>0.0</td> </tr> </tbody> </table>	Negative Reference Clamp Enable (01.008)	Bipolar Reference Enable (01.010)	VM_NEGATIVE_REF_CLAMP1[MIN]	VM_NEGATIVE_REF_CLAMP1[MAX]	0	0	0.0	Pr 01.006	0	1	0.0	0.0	1	X	-VM_POSITIVE_REF_CLAMP[MAX]	0.0		
Negative Reference Clamp Enable (01.008)	Bipolar Reference Enable (01.010)	VM_NEGATIVE_REF_CLAMP1[MIN]	VM_NEGATIVE_REF_CLAMP1[MAX]																
0	0	0.0	Pr 01.006																
0	1	0.0	0.0																
1	X	-VM_POSITIVE_REF_CLAMP[MAX]	0.0																

VM_POSITIVE_REF_CLAMP1 VM_POSITIVE_REF_CLAMP2		Limits applied to the positive frequency or speed reference clamp										
Units	Open-loop: Hz RFC-A, RFC-S: rpm or mm/s											
Range of [MIN]	Open-loop: 0.0 RFC-A, RFC-S: 0.0											
Range of [MAX]	Open-loop: 550.0 RFC-A, RFC-S: 0.0 to 50000.0											
Definition	<p>VM_POSITIVE_REF_CLAMP1[MAX] defines the range of the positive reference clamp, <i>Maximum Reference Clamp (01.006)</i>, which in turn limit the references. In RFC-A and RFC-S modes a limit is applied so that the position feedback does not exceed the speed where the drive can no longer interpret the feedback signal correctly as given in the table below. The limit is based on the position feedback device selected with <i>Motor Control Feedback Select (03.026)</i>. It is possible to disable this limit if the <i>RFC Feedback Mode (03.024)</i> ≥ 1 so that the motor can be operated at a speed above the level where the drive can interpret the feedback in sensorless mode. It should be noted that the position feedback device itself may have a maximum speed limit that is lower than those given in the table. Care should be taken not to exceed a speed that would cause damage to the position feedback device.</p> <table border="1"> <thead> <tr> <th>Feedback device</th> <th>VM_POSITIVE_REF_CLAMP1[MAX]</th> </tr> </thead> <tbody> <tr> <td>AB, AB Servo</td> <td>(500 kHz x 60 / rotary lines per revolution) rpm (500 kHz / linear line pitch in mm) mm/s</td> </tr> <tr> <td>FD, FR, FD Servo, FR Servo</td> <td>(500 kHz x 60 / rotary lines per revolution)/2 rpm (500 kHz / linear line pitch in mm)/2 mm/s</td> </tr> <tr> <td>SC, SC Hiper, SC EnDat, SC SSI, SC Servo</td> <td>(500 kHz x 60 / sine waves per revolution) rpm (500 kHz x linear line pitch in mm) mm/s</td> </tr> <tr> <td>Any other device</td> <td>50000.0 rpm or mm/s</td> </tr> </tbody> </table> <p>In open-loop mode VM_POSITIVE_REF_CLAMP1[MAX] is fixed at 550.0 Hz In RFC mode a limit is applied to the speed reference of 550 x 60 / Motor pole pairs. Therefore, with a 4 pole motor the limit for VM_POSITIVE_REF_CLAMP1[MAX] will be 16,500 rpm. VM_POSITIVE_REF_CLAMP1[MIN] = 0.0 VM_POSITIVE_REF_CLAMP2 is defined in the same way as VM_POSITIVE_REF_CLAMP1 except VM_POSITIVE_REF_CLAMP2[MAX] defines the range of the positive reference clamp, <i>M2 Maximum Reference Clamp (21.001)</i>, which in turn limits the references.</p>		Feedback device	VM_POSITIVE_REF_CLAMP1[MAX]	AB, AB Servo	(500 kHz x 60 / rotary lines per revolution) rpm (500 kHz / linear line pitch in mm) mm/s	FD, FR, FD Servo, FR Servo	(500 kHz x 60 / rotary lines per revolution)/2 rpm (500 kHz / linear line pitch in mm)/2 mm/s	SC, SC Hiper, SC EnDat, SC SSI, SC Servo	(500 kHz x 60 / sine waves per revolution) rpm (500 kHz x linear line pitch in mm) mm/s	Any other device	50000.0 rpm or mm/s
	Feedback device	VM_POSITIVE_REF_CLAMP1[MAX]										
	AB, AB Servo	(500 kHz x 60 / rotary lines per revolution) rpm (500 kHz / linear line pitch in mm) mm/s										
	FD, FR, FD Servo, FR Servo	(500 kHz x 60 / rotary lines per revolution)/2 rpm (500 kHz / linear line pitch in mm)/2 mm/s										
	SC, SC Hiper, SC EnDat, SC SSI, SC Servo	(500 kHz x 60 / sine waves per revolution) rpm (500 kHz x linear line pitch in mm) mm/s										
	Any other device	50000.0 rpm or mm/s										

VM_POWER		Range applied to parameters that either set or display power
Units	kW	
Range of [MIN]	-99999.999 to 0.000	
Range of [MAX]	0.000 to 99999.999	
Definition	<p>VM_POWER[MAX] is rating dependent and is chosen to allow for the maximum power that can be output by the drive with maximum a.c. output voltage, at maximum controlled current and unity power factor.</p> $VM_POWER[MAX] = \sqrt{3} \times VM_AC_VOLTAGE[MAX] \times VM_DRIVE_CURRENT[MAX] / 1000$ <p>VM_POWER[MIN] = -VM_POWER[MAX]</p>	

VM_RATED_CURRENT		Range applied to rated current parameters
Units	A	
Range of [MIN]	0.000	
Range of [MAX]	0.000 to 99999.999	
Definition	<p>VM_RATED_CURRENT [MAX] = <i>Maximum Rated Current (11.060)</i> and is dependent on the drive rating. This is the Normal Duty rating of the drive.</p> <p>VM_RATED_CURRENT [MIN] = 0.00</p>	

VM_SPEED		Range applied to parameters showing speed
Units	Open-loop, RFC-A, RFC-S: rpm or mm/s	
Range of [MIN]	Open-loop, RFC-A, RFC-S: -50000.0 to 0.0	
Range of [MAX]	Open-loop, RFC-A, RFC-S: 0.0 to 50000.0	
Definition	<p>This variable minimum/maximum defines the range of speed monitoring parameters. To allow headroom for overshoot the range is set to twice the range of the speed references.</p> <p>$VM_SPEED[MAX] = 2 \times VM_SPEED_FREQ_REF[MAX]$</p> <p>$VM_SPEED[MIN] = 2 \times VM_SPEED_FREQ_REF[MIN]$</p>	

VM_SPEED_FREQ_KEYPAD_REF		Range applied Keypad Control Mode Reference (01.017)	
Units	Open-loop: Hz RFC-A, RFC-S: rpm or mm/s		
Range of [MIN]	Open-loop: -550.0 to 550.0 RFC-A, RFC-S: -50000.0 to 50000.0		
Range of [MAX]	Open-loop: 0.0 to 550.0 RFC-A, RFC-S: 0.0 to 50000.0		
Definition	<p>This variable maximum is applied to <i>Keypad Control Mode Reference (01.017)</i>. The maximum applied to these parameters is the same as other frequency reference parameters.</p> <p>$VM_SPEED_FREQ_USER_REFS [MAX] = VM_SPEED_FREQ_REF[MAX]$</p> <p>However the minimum is dependent on <i>Negative Reference Clamp Enable (01.008)</i> and <i>Bipolar Reference Enable (01.010)</i>.</p>		
	Negative Reference Clamp Enable (01.008)	Bipolar Reference Enable (01.010)	VM_SPEED_FREQ_USER_REFS[MIN]
	0	0	If <i>Select Motor 2 Parameters (11.045) = 0</i> <i>Minimum Reference Clamp (01.007)</i> , otherwise <i>M2 Minimum Reference Clamp (21.002)</i>
	0	1	$-VM_SPEED_FREQ_REF[MAX]$
	1	0	0.0
1	1	$-VM_SPEED_FREQ_REF[MAX]$	

VM_SPEED_FREQ_REF		Range applied to the frequency or speed reference parameters	
Units	Open-loop: Hz RFC-A, RFC-S: rpm or mm/s		
Range of [MIN]	Open-loop: -550.0 to 0.0 RFC-A, RFC-S: -50000.0 to 0.0		
Range of [MAX]	Open-loop: 0.0 to 550.0 RFC-A, RFC-S: 0.0 to 50000.0		
Definition	This variable minimum/maximum is applied throughout the frequency and speed reference system so that the references can vary in the range from the minimum to maximum clamps.		
	Negative Reference Clamp Enable (01.008)	VM_SPEED_FREQ_REF[MAX] if Select Motor 2 Parameters (11.045) = 0	VM_SPEED_FREQ_REF[MAX] if Select Motor 2 Parameters (11.045) = 1
	0	Maximum Reference Clamp (01.006)	M2 Maximum Reference Clamp (21.001)
	1	Maximum Reference Clamp (01.006) or Minimum Reference Clamp (01.007) whichever the larger	M2 Maximum Reference Clamp (21.001) or M2 Minimum Reference Clamp (21.002) whichever the larger
VM_SPEED_FREQ_REF[MIN] = -VM_SPEED_FREQ_REF[MAX].			

VM_SPEED_FREQ_REF_UNIPOLAR		Unipolar version of VM_SPEED_FREQ_REF	
Units	Open-loop: Hz RFC-A, RFC-S: rpm or mm/s		
Range of [MIN]	Open-loop: 0.0 RFC-A, RFC-S: 0.0		
Range of [MAX]	Open-loop: 0.0 to 550.0 RFC-A, RFC-S: 0.0 to 50000.0		
Definition	VM_SPEED_FREQ_REF_UNIPOLAR[MAX] = VM_SPEED_FREQ_REF[MAX] VM_SPEED_FREQ_REF_UNIPOLAR[MIN] = 0.0		

VM_SPEED_FREQ_USER_REFS		Range applied to some analog reference parameters	
Units	Open-loop: Hz RFC-A, RFC-S: rpm or mm/s		
Range of [MIN]	Open-loop: -550.00 to 550.00 RFC-A, RFC-S: -50000.0 to 50000.0		
Range of [MAX]	Open-loop: 0.00 to 550.00 RFC-A, RFC-S: 0.0 to 50000.0		
Definition	VM_SPEED_FREQ_USER_REFS[MAX] = VM_SPEED_FREQ_REF[MAX]		
	Negative Reference Clamp Enable (01.008)	Bipolar Reference Enable (01.010)	VM_SPEED_FREQ_USER_REFS [MIN]
	0	0	Pr 01.007
	0	1	-VM_SPEED_FREQ_REF[MAX]
	1	0	0.0
1	1	-VM_SPEED_FREQ_REF[MAX]	

VM_STD_UNDER_VOLTS		Range applied the standard under-voltage threshold	
Units	V		
Range of [MIN]	0 to 1150		
Range of [MAX]	0 to 1150		
Definition	VM_STD_UNDER_VOLTS[MAX] = VM_DC_VOLTAGE_SET / 1.1 VM_STD_UNDER_VOLTS[MIN] is voltage rating dependent. See Table 11-4		

VM_SUPPLY_LOSS_LEVEL		Range applied to the supply loss threshold
Units	V	
Range of [MIN]	0 to 1150	
Range of [MAX]	0 to 1150	
Definition	<p>VM_SUPPLY_LOSS_LEVEL[MAX] = VM_DC_VOLTAGE_SET[MAX]</p> <p>VM_SUPPLY_LOSS_LEVEL[MIN] is drive voltage rating dependent. See Table 11-4</p>	

VM_SWITCHING_FREQUENCY		Range applied to the maximum switching frequency parameters
Units	User units	
Range of [MIN]	0	
Range of [MAX]	0 to 6	
Definition	<p>VM_SWITCHING_FREQUENCY[MAX] = Power stage dependent</p> <p>VM_SWITCHING_FREQUENCY[MIN] = 0 for motor control modes</p>	

VM_TORQUE_CURRENT		Range applied to torque and torque producing current parameters						
Units	%							
Range of [MIN]	-1000.0 to 0.0							
Range of [MAX]	0.0 to 1000.0							
Definition	<table border="1"> <thead> <tr> <th>Select Motor 2 Parameters (11.045)</th> <th>VM_TORQUE_CURRENT [MAX]</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>VM_MOTOR1_CURRENT_LIMIT[MAX]</td> </tr> <tr> <td>1</td> <td>VM_MOTOR2_CURRENT_LIMIT[MAX]</td> </tr> </tbody> </table> <p>VM_TORQUE_CURRENT[MIN] = -VM_TORQUE_CURRENT[MAX]</p>		Select Motor 2 Parameters (11.045)	VM_TORQUE_CURRENT [MAX]	0	VM_MOTOR1_CURRENT_LIMIT[MAX]	1	VM_MOTOR2_CURRENT_LIMIT[MAX]
Select Motor 2 Parameters (11.045)	VM_TORQUE_CURRENT [MAX]							
0	VM_MOTOR1_CURRENT_LIMIT[MAX]							
1	VM_MOTOR2_CURRENT_LIMIT[MAX]							

VM_TORQUE_CURRENT_UNIPOLAR		Unipolar version of VM_TORQUE_CURRENT
Units	%	
Range of [MIN]	0.0	
Range of [MAX]	0.0 to 1000.0	
Definition	<p>VM_TORQUE_CURRENT_UNIPOLAR[MAX] = VM_TORQUE_CURRENT[MAX]</p> <p>VM_TORQUE_CURRENT_UNIPOLAR[MIN] = 0.0</p> <p><i>User Current Maximum Scaling (04.024)</i> defines the variable maximum/minimums VM_USER_CURRENT and VM_USER_CURRENT_HIGH_RES which are applied to <i>Percentage Load (04.020)</i>, <i>Torque Reference (04.008)</i> and <i>Torque Offset (04.009)</i>. This is useful when routing these parameters to an analog output as it allows the full scale output value to be defined by the user. This maximum is subject to a limit of MOTOR1_CURRENT_LIMIT or MOTOR2_CURRENT_LIMIT depending on which motor map is currently active.</p> <p>The maximum value (VM_TORQUE_CURRENT_UNIPOLAR [MAX]) varies between drive sizes with default parameters loaded. For some drive sizes the default value may be reduced below the value given by the parameter range limiting.</p>	

VM_USER_CURRENT		Range applied to torque reference and percentage load parameters with one decimal place
Units	%	
Range of [MIN]	-1000.0 to 0.0	
Range of [MAX]	0.0 to 1000.0	
Definition	<p>VM_USER_CURRENT[MAX] = <i>User Current Maximum Scaling (04.024)</i></p> <p>VM_USER_CURRENT[MIN] = -VM_USER_CURRENT[MAX]</p> <p><i>User Current Maximum Scaling (04.024)</i> defines the variable maximum/minimums VM_USER_CURRENT and VM_USER_CURRENT_HIGH_RES which are applied to <i>Percentage Load (04.020)</i>, <i>Torque Reference (04.008)</i> and <i>Torque Offset (04.009)</i>. This is useful when routing these parameters to an analog output as it allows the full scale output value to be defined by the user. This maximum is subject to a limit of MOTOR1_CURRENT_LIMIT or MOTOR2_CURRENT_LIMIT depending on which motor map is currently active.</p> <p>The maximum value (VM_TORQUE_CURRENT_UNIPOLAR [MAX]) varies between drive sizes with default parameters loaded. For some drive sizes the default value may be reduced below the value given by the parameter range limiting.</p>	

VM_USER_CURRENT_HIGH_RES		Range applied to torque reference and percentage load parameters with two decimal places
Units	%	
Range of [MIN]	-1000.00 to 0.00	
Range of [MAX]	0.00 to 1000.00	
Definition	<p>VM_USER_CURRENT_HIGH_RES[MAX] = <i>User Current Maximum Scaling (04.024)</i> with an additional decimal place</p> <p>VM_USER_CURRENT_HIGH_RES[MIN] = -VM_USER_CURRENT_HIGH_RES[MAX]</p> <p><i>User Current Maximum Scaling (04.024)</i> defines the variable maximum/minimums VM_USER_CURRENT and VM_USER_CURRENT_HIGH_RES which are applied to <i>Percentage Load (04.020)</i>, <i>Torque Reference (04.008)</i> and <i>Torque Offset (04.009)</i>. This is useful when routing these parameters to an analog output as it allows the full scale output value to be defined by the user. This maximum is subject to a limit of MOTOR1_CURRENT_LIMIT or MOTOR2_CURRENT_LIMIT depending on which motor map is currently active.</p> <p>The maximum value (VM_TORQUE_CURRENT_UNIPOLAR [MAX]) varies between drive sizes with default parameters loaded. For some drive sizes the default value may be reduced below the value given by the parameter range limiting.</p>	

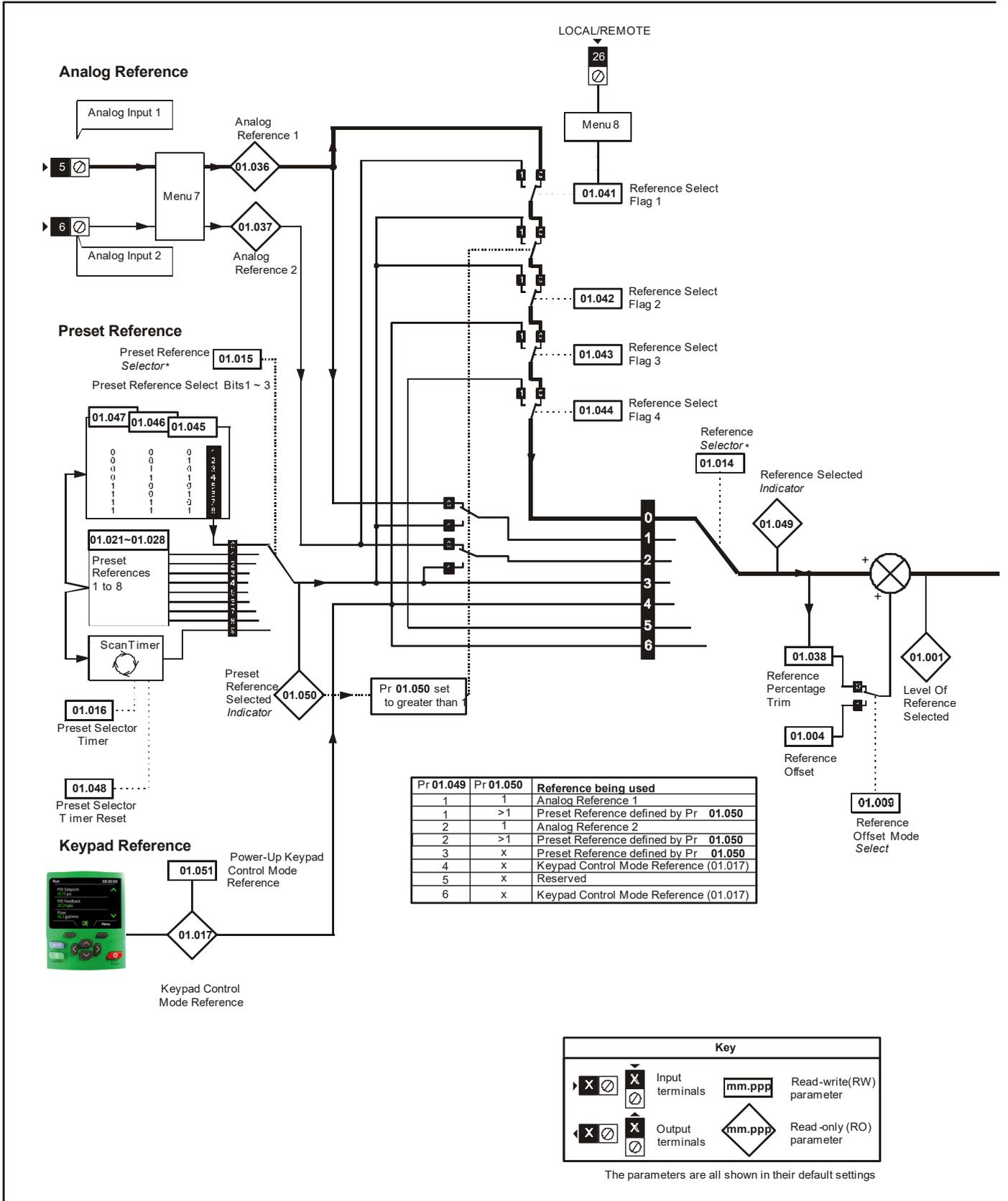
Table 11-4 Voltage ratings dependant values

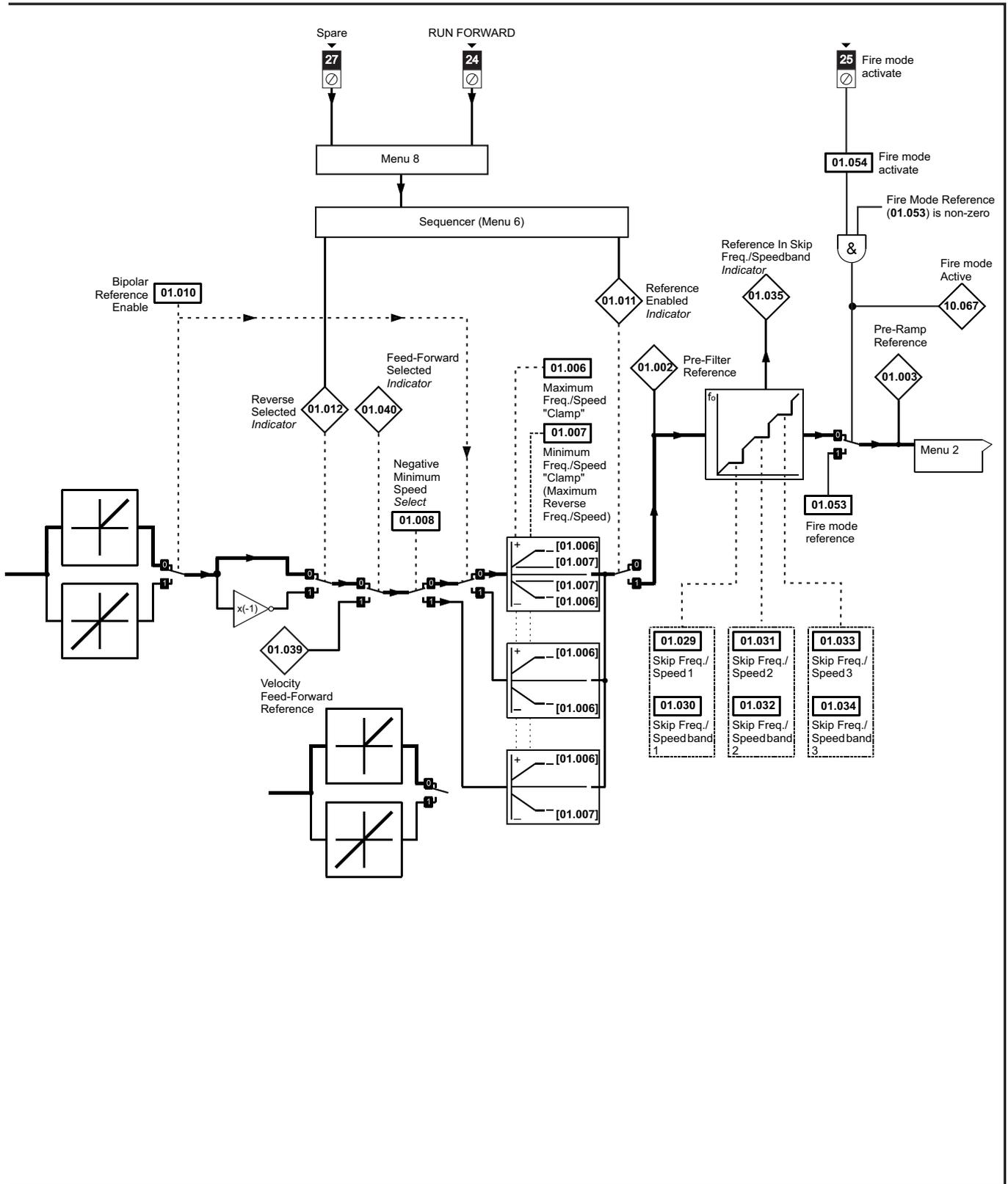
Variable min/max	Voltage level (V)			
	200 V	400 V	575 V	690 V
VM_DC_VOLTAGE_SET[MAX]	400	800	955	1150
VM_DC_VOLTAGE[MAX]	415	830	990	1190
VM_AC_VOLTAGE_SET[MAX]	265	530	635	765
VM_AC_VOLTAGE[MAX]	325	650	780	930
VM_STD_UNDER_VOLTS[MIN]	175	330	435	435
VM_SUPPLY_LOSS_LEVEL[MIN]	205	410	540	540
VM_HIGH_DC_VOLTAGE	1500	1500	1500	1500

Safety information	Product information	Mechanical installation	Electrical installation	Getting started	Basic parameters	Running the motor	Optimization	NV Media Card Operation	Building Automation	Advanced parameters	Technical data	Diagnostics	UL listing information
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11.2 Menu 1: Frequency / speed reference

Figure 11-1 Menu 1 logic diagram





Parameter		Range(⇄)		Default(⇄)			Type						
		OL	RFC-A / S	OL	RFC-A	RFC-S							
01.001	Reference Selected	VM_SPEED_FREQ_REF Hz	VM_SPEED_FREQ_REF rpm				RO	Num	ND	NC	PT		
01.002	Pre-Skip Filter Reference	VM_SPEED_FREQ_REF Hz	VM_SPEED_FREQ_REF rpm				RO	Num	ND	NC	PT		
01.003	Pre-Ramp Reference	VM_SPEED_FREQ_REF Hz	VM_SPEED_FREQ_REF rpm				RO	Num	ND	NC	PT		
01.004	Reference Offset	VM_SPEED_FREQ_REF Hz	VM_SPEED_FREQ_REF rpm	0.0			RW	Num					US
01.006	Maximum Reference Clamp	VM_POSITIVE_REF_CLAMP1 Hz	VM_POSITIVE_REF_CLAMP1 rpm	50Hz: 50.0 60Hz: 60.0	50Hz: 1500.0 60Hz: 1800.0	3000.0	RW	Num					US
01.007	Minimum Reference Clamp	VM_NEGATIVE_REF_CLAMP1 Hz	VM_NEGATIVE_REF_CLAMP1 rpm	15 Hz	450 rpm		RW	Num					US
01.008	Negative Reference Clamp Enable	Off (0) or On (1)		Off (0)			RW	Bit					US
01.009	Reference Offset Select	Off (0) or On (1)		Off (0)			RW	Bit					US
01.010	Bipolar Reference Enable	Off (0) or On (1)		Off (0)			RW	Bit					US
01.011	Reference On	Off (0) or On (1)					RO	Bit	ND	NC	PT		
01.012	Reverse Select	Off (0) or On (1)					RO	Bit	ND	NC	PT		
01.014	Reference Selector	A1 A2 (0), A1 Preset (1), A2 Preset (2) Preset (3), Keypad (4) Keypad Ref (6)		A1 A2 (0)			RW	Txt	ND				US
01.015	Preset Selector	Select By Flags (0), Preset Ref 1 (1), Preset Ref 2 (2), Preset Ref 3 (3), Preset Ref 4 (4), Preset Ref 5 (5), Preset Ref 6 (6), Preset Ref 7 (7), Preset Ref 8 (8), Select By Timer (9)		Select By Flags (0)			RW	Num					US
01.016	Preset Selector Time	0.0 to 400.0 s		10.0 s			RW	Num					US
01.017	Keypad Control Mode Reference	VM_SPEED_FREQ_USER_REFS		0.0			RO	Num		NC	PT	PS	
01.021	Preset Reference 1	VM_SPEED_FREQ_REF		0.0			RW	Num					US
01.022	Preset Reference 2	VM_SPEED_FREQ_REF		0.0			RW	Num					US
01.023	Preset Reference 3	VM_SPEED_FREQ_REF		0.0			RW	Num					US
01.024	Preset Reference 4	VM_SPEED_FREQ_REF		0.0			RW	Num					US
01.025	Preset Reference 5	VM_SPEED_FREQ_REF		0.0			RW	Num					US
01.026	Preset Reference 6	VM_SPEED_FREQ_REF		0.0			RW	Num					US
01.027	Preset Reference 7	VM_SPEED_FREQ_REF		0.0			RW	Num					US
01.028	Preset Reference 8	VM_SPEED_FREQ_REF		0.0			RW	Num					US
01.029	Skip Reference 1	0.0 to 550.0 Hz	0 to 33000 rpm	0.0	0		RW	Num					US
01.030	Skip Reference Band 1	0.0 to 25.0 Hz	0 to 250 rpm	0.0	0		RW	Num					US
01.031	Skip Reference 2	0.0 to 550.0 Hz	0 to 33000 rpm	0.0	0		RW	Num					US
01.032	Skip Reference Band 2	0.0 to 25.0 Hz	0 to 250 rpm	0.0	0		RW	Num					US
01.033	Skip Reference 3	0.0 to 550.0 Hz	0 to 33000 rpm	0.0	0		RW	Num					US
01.034	Skip Reference Band 3	0.0 to 25.0 Hz	0 to 250 rpm	0.0	0		RW	Num					US
01.035	Reference In Rejection Zone	Off (0) or On (1)					RO	Bit	ND	NC	PT		
01.036	Analog Reference 1	VM_SPEED_FREQ_USE_R_REFS Hz	VM_SPEED_FREQ_USE_R_REFS rpm	0.00	0.0		RO	Num		NC			
01.037	Analog Reference 2	±VM_SPEED_FREQ_US_ER_REFS Hz	±VM_SPEED_FREQ_USE_R_REFS rpm	0.00	0.0		RO	Num		NC			
01.038	Percentage Trim	±100.00 %		0.00 %			RW	Num		NC			
01.039	Speed Feed-forwards	VM_SPEED_FREQ_REF					RO	Num	ND	NC	PT		
01.040	Speed Feed-forwards Select	Off (0) or On (1)					RO	Bit	ND	NC	PT		
01.041	Reference Select Flag 1	Off (0) or On (1)		Off (0)			RW	Bit		NC	PT		
01.042	Reference Select Flag 2	Off (0) or On (1)		Off (0)			RW	Bit		NC	PT		
01.043	Reference Select Flag 3	Off (0) or On (1)		Off (0)			RW	Bit		NC	PT		
01.044	Reference Select Flag 4	Off (0) or On (1)		Off (0)			RW	Bit		NC	PT		
01.045	Preset Select Flag 1	Off (0) or On (1)		Off (0)			RW	Bit		NC	PT		
01.046	Preset Select Flag 2	Off (0) or On (1)		Off (0)			RW	Bit		NC	PT		
01.047	Preset Select Flag 3	Off (0) or On (1)		Off (0)			RW	Bit		NC	PT		
01.048	Preset Selector Timer Reset	Off (0) or On (1)		Off (0)			RW	Bit		NC	PT		
01.049	Reference Selected Indicator	1 to 6					RO	Num	ND	NC	PT		
01.050	Preset Selected Indicator	1 to 8					RO	Num	ND	NC	PT		
01.051	Power-up Keypad Control Mode Reference	Reset (0), Last (1), Preset (2)		Reset (0)			RW	Txt					US
01.052	Hand / Off / Auto operating mode	0 to 3		1			RW	Num					US

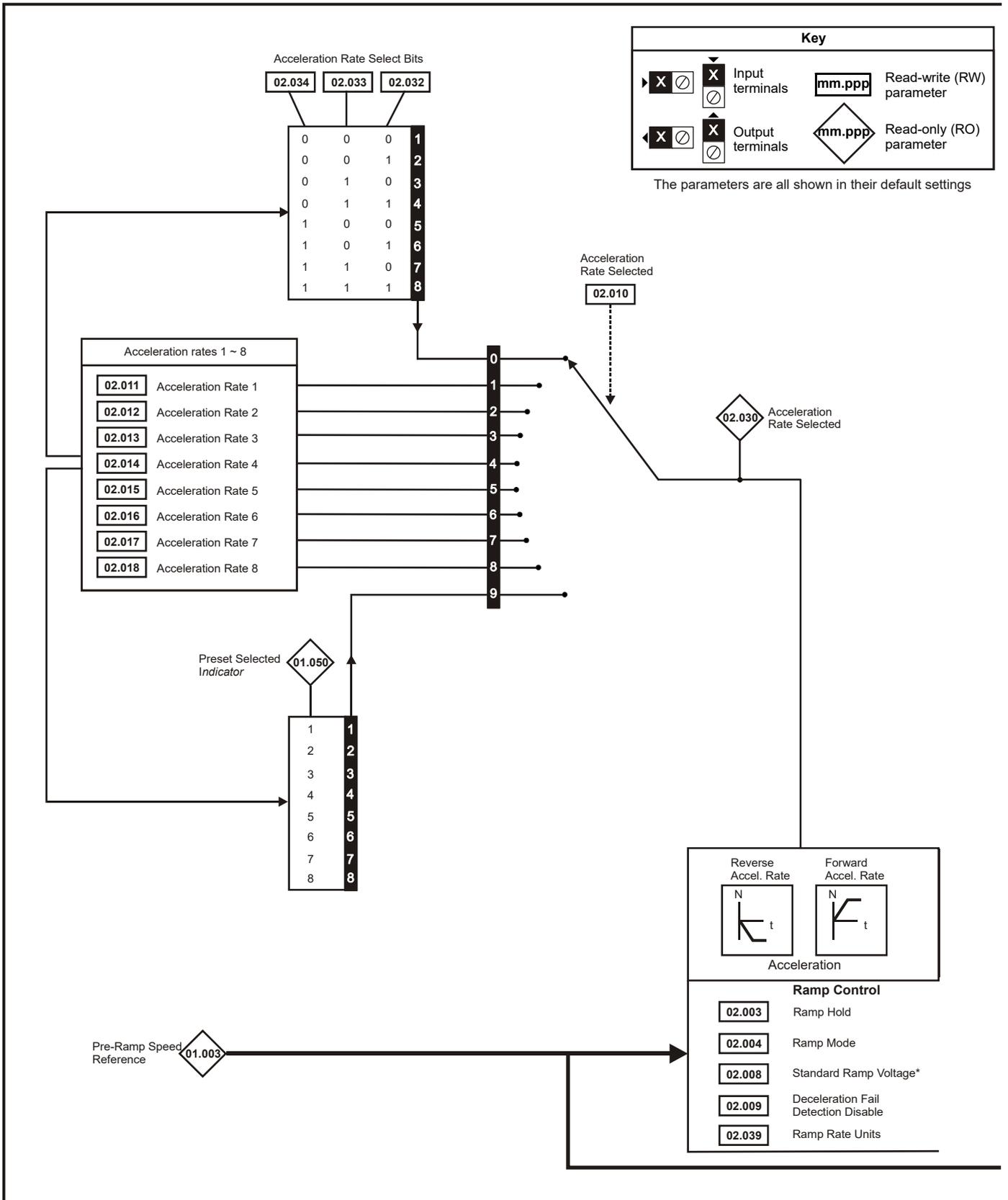
Safety information	Product information	Mechanical installation	Electrical installation	Getting started	Basic parameters	Running the motor	Optimization	NV Media Card Operation	Building Automation	Advanced parameters	Technical data	Diagnostics	UL listing information
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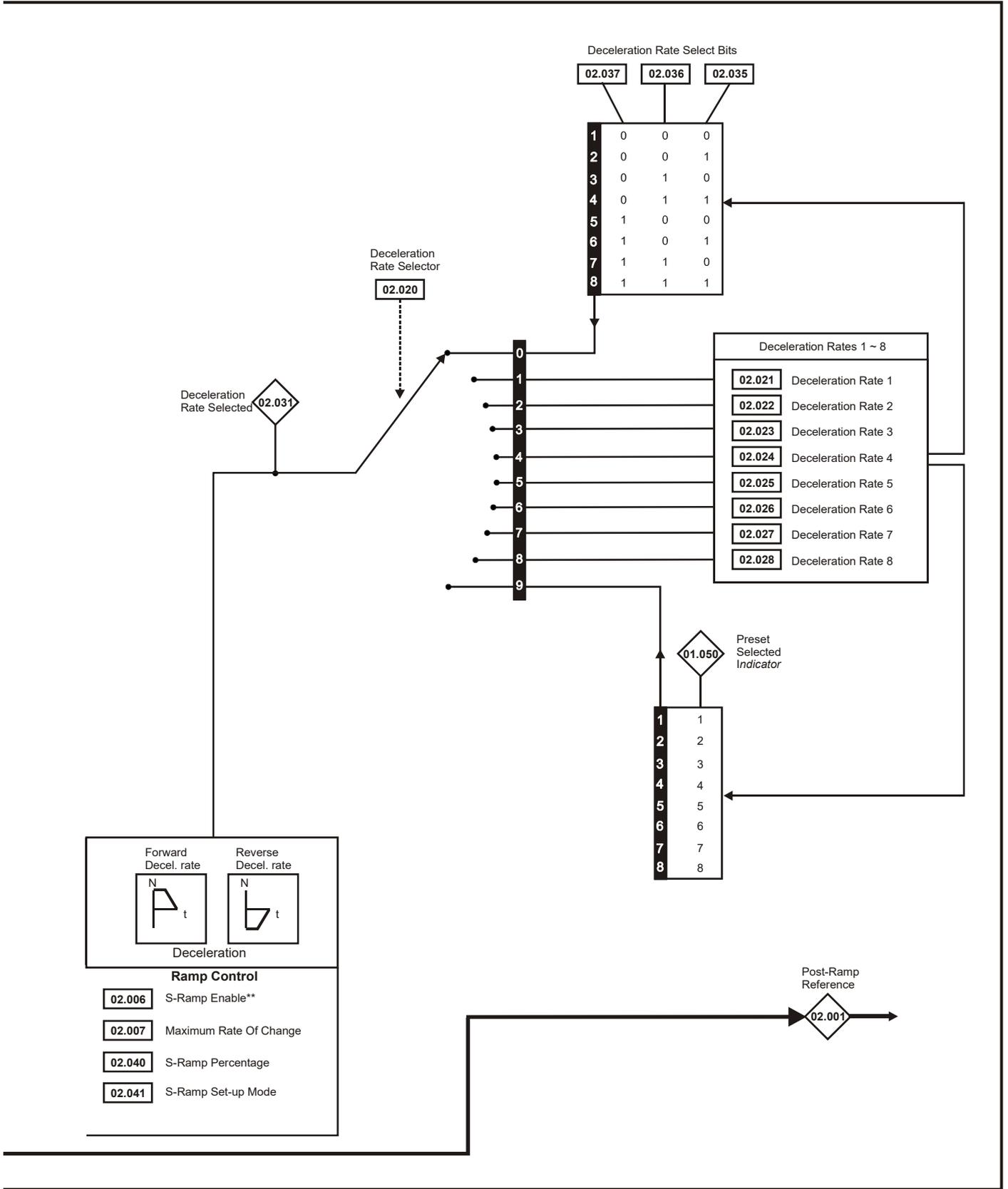
Parameter	Range(↕)		Default(⇒)			Type					
	OL	RFC-A / S	OL	RFC-A	RFC-S	RW	Num		NC	US	
01.053 Fire mode reference	VM_SPEED_FREQ_REF		0.0			RW	Num				US
01.054 Fire mode activate	Off (0) or On (1)		Off (0)			RO	Bit		NC		

RW	Read / Write	RO	Read only	Num	Number parameter	Bit	Bit parameter	Txt	Text string	Bin	Binary parameter	Fl	Filtered
ND	No default value	NC	Not copied	PT	Protected parameter	RA	Rating dependent	US	User save	PS	Power-down save	DE	Destination

11.3 Menu 2: Ramps

Figure 11-2 Menu 2 logic diagram





Parameter	Range(⇅)		Default(⇄)			Type					
	OL	RFC-A / S	OL	RFC-A	RFC-S	RO	Num	ND	NC	PT	US
02.001 Post Ramp Reference	VM_SPEED_FREQ_REF Hz	VM_SPEED_FREQ_REF rpm				RO	Num	ND	NC	PT	US
02.003 Ramp Hold	Off (0) or On (1)		Off (0)			RW	Bit				US
02.004 Ramp Mode	Standard (1), Std boost (2)	Standard (1)	Standard (1)			RW	Txt				US
02.006 S Ramp Enable	Off (0) or On (1)		Off (0)			RW	Bit				US
02.007 Maximum Rate Of Change Of Acceleration	0.0 to 300.0 s ² /100 Hz	0.000 to 100.000 s ² /1000 rpm	3.1	1.500	0.030	RW	Num				US
02.008 Standard Ramp Voltage	VM_DC_VOLTAGE_SET V		200 V drive: 375 V 400 V drive 50 Hz: 750 V 400 V drive 60 Hz: 775 V 575 V drive: 895 V 690 V: 1075 V			RW	Num		RA		US
02.009 Deceleration Fail Detection Disable	Off (0) or On (1)		Off (0)			RW	Bit				US
02.010 Acceleration Rate Selector	0 to 9		0			RW	Num				US
02.011 Acceleration Rate 1	0.0 to VM_ACCEL_RATE s	0.000 to VM_ACCEL_RATE s	10.0 s	10.000 s		RW	Num				US
02.012 Acceleration Rate 2	0.0 to VM_ACCEL_RATE s	0.000 to VM_ACCEL_RATE s	20.0 s	20.000 s		RW	Num				US
02.013 Acceleration Rate 3	0.0 to VM_ACCEL_RATE s	0.000 to VM_ACCEL_RATE s	20.0 s	20.000 s		RW	Num				US
02.014 Acceleration Rate 4	0.0 to VM_ACCEL_RATE s	0.000 to VM_ACCEL_RATE s	20.0 s	20.000 s		RW	Num				US
02.015 Acceleration Rate 5	0.0 to VM_ACCEL_RATE s	0.000 to VM_ACCEL_RATE s	20.0 s	20.000 s		RW	Num				US
02.016 Acceleration Rate 6	0.0 to VM_ACCEL_RATE s	0.000 to VM_ACCEL_RATE s	20.0 s	20.000 s		RW	Num				US
02.017 Acceleration Rate 7	0.0 to VM_ACCEL_RATE s	0.000 to VM_ACCEL_RATE s	20.0 s	20.000 s		RW	Num				US
02.018 Acceleration Rate 8	0.0 to VM_ACCEL_RATE s	0.000 to VM_ACCEL_RATE s	20.0 s	20.000 s		RW	Num				US
02.020 Deceleration Rate Selector	0 to 9		0			RW	Num				US
02.021 Deceleration Rate 1	0.0 to VM_ACCEL_RATE s	0.000 to VM_ACCEL_RATE s	10.0 s	10.000 s		RW	Num				US
02.022 Deceleration Rate 2	0.0 to VM_ACCEL_RATE s	0.000 to VM_ACCEL_RATE s	20.0 s	20.000 s		RW	Num				US
02.023 Deceleration Rate 3	0.0 to VM_ACCEL_RATE s	0.000 to VM_ACCEL_RATE s	20.0 s	20.000 s		RW	Num				US
02.024 Deceleration Rate 4	0.0 to VM_ACCEL_RATE s	0.000 to VM_ACCEL_RATE s	20.0 s	20.000 s		RW	Num				US
02.025 Deceleration Rate 5	0.0 to VM_ACCEL_RATE s	0.000 to VM_ACCEL_RATE s	20.0 s	20.000 s		RW	Num				US
02.026 Deceleration Rate 6	0.0 to VM_ACCEL_RATE s	0.000 to VM_ACCEL_RATE s	20.0 s	20.000 s		RW	Num				US
02.027 Deceleration Rate 7	0.0 to VM_ACCEL_RATE s	0.000 to VM_ACCEL_RATE s	20.0 s	20.000 s		RW	Num				US
02.028 Deceleration Rate 8	0.0 to VM_ACCEL_RATE s	0.000 to VM_ACCEL_RATE s	20.0 s	20.000 s		RW	Num				US
02.030 Acceleration Rate Selected	0 to 8					RO	Num	ND	NC	PT	
02.031 Deceleration Rate Selected	0 to 8					RO	Num	ND	NC	PT	
02.032 Acceleration Rate Select Bit 0	Off (0) or On (1)		Off (0)			RW	Bit		NC		
02.033 Acceleration Rate Select Bit 1	Off (0) or On (1)		Off (0)			RW	Bit		NC		
02.034 Acceleration Rate Select Bit 2	Off (0) or On (1)		Off (0)			RW	Bit		NC		
02.035 Deceleration Rate Select Bit 0	Off (0) or On (1)		Off (0)			RW	Bit		NC		
02.036 Deceleration Rate Select Bit 1	Off (0) or On (1)		Off (0)			RW	Bit		NC		
02.037 Deceleration Rate Select Bit 2	Off (0) or On (1)		Off (0)			RW	Bit		NC		
02.039 Ramp Rate Units	Off (0) = 100 Hz or On (1) = Maximum frequency	Off (0) = 1000 rpm or 1000 mm/s (0) or On (1) = Maximum speed	On (1) = Maximum frequency	On (1) = Maximum speed		RW	Bit				US
02.040 S Ramp Percentage	0.0 to 50.0 %		0.0 %			RW	Num				US
02.041 S Ramp Set-up Mode	Single (0), Percentage (1)		Single (0)			RW	Txt				US

RW	Read / Write	RO	Read only	Num	Number parameter	Bit	Bit parameter	Txt	Text string	Bin	Binary parameter	FI	Filtered
ND	No default value	NC	Not copied	PT	Protected parameter	RA	Rating dependent	US	User save	PS	Power-down save	DE	Destination

11.4 Menu 3: Speed feedback and speed control

Figure 11-3 Menu 3 Open-loop logic diagram

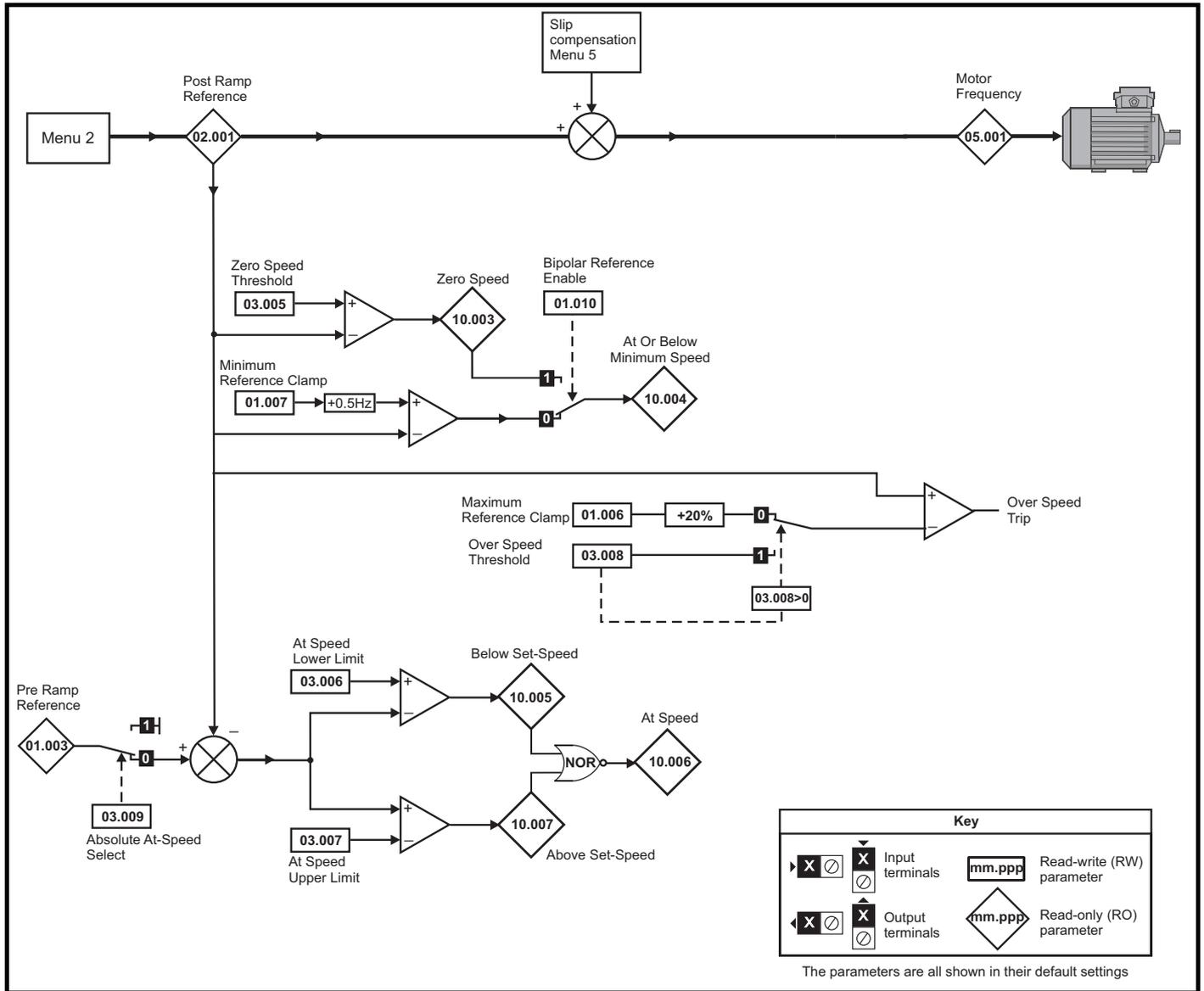
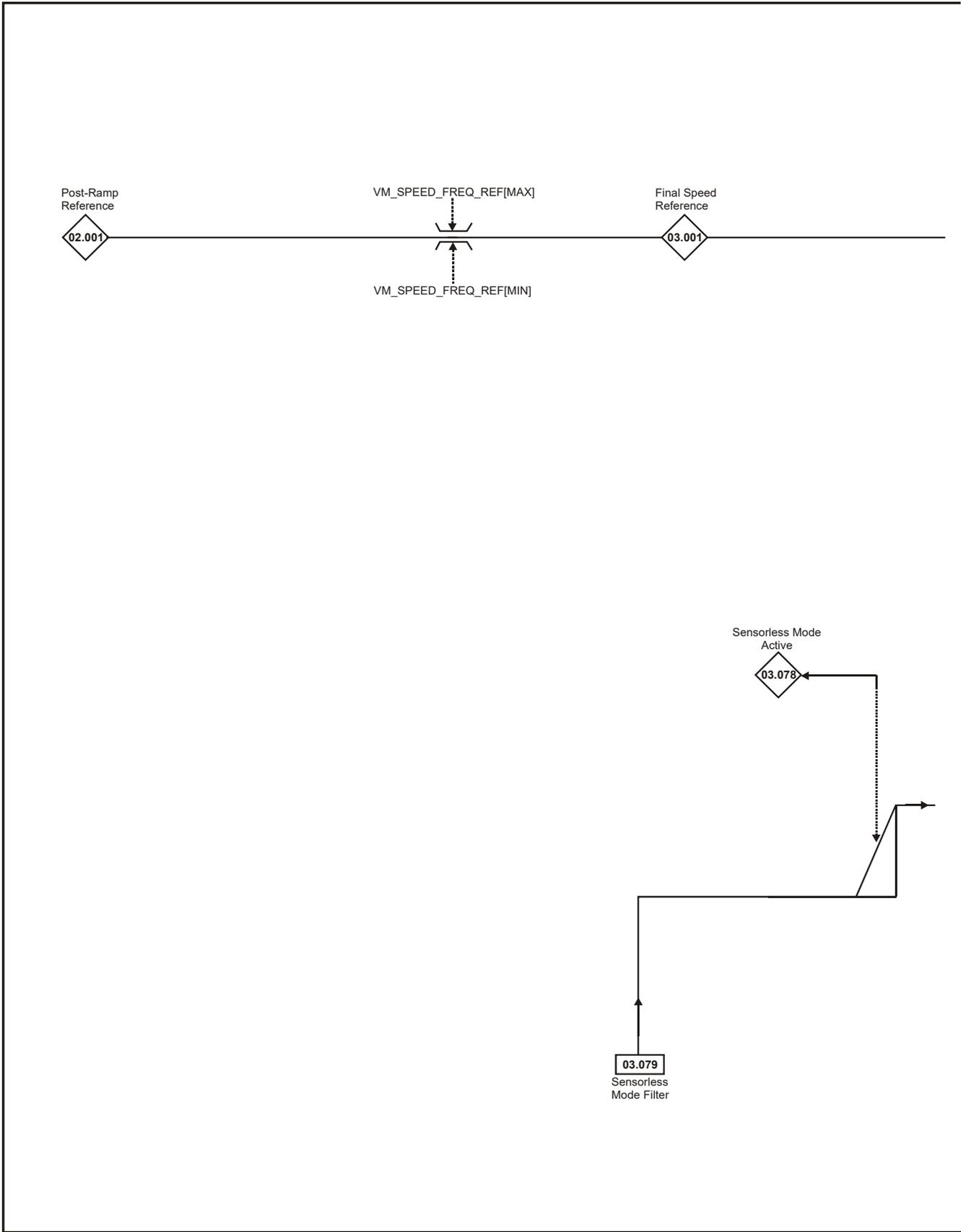
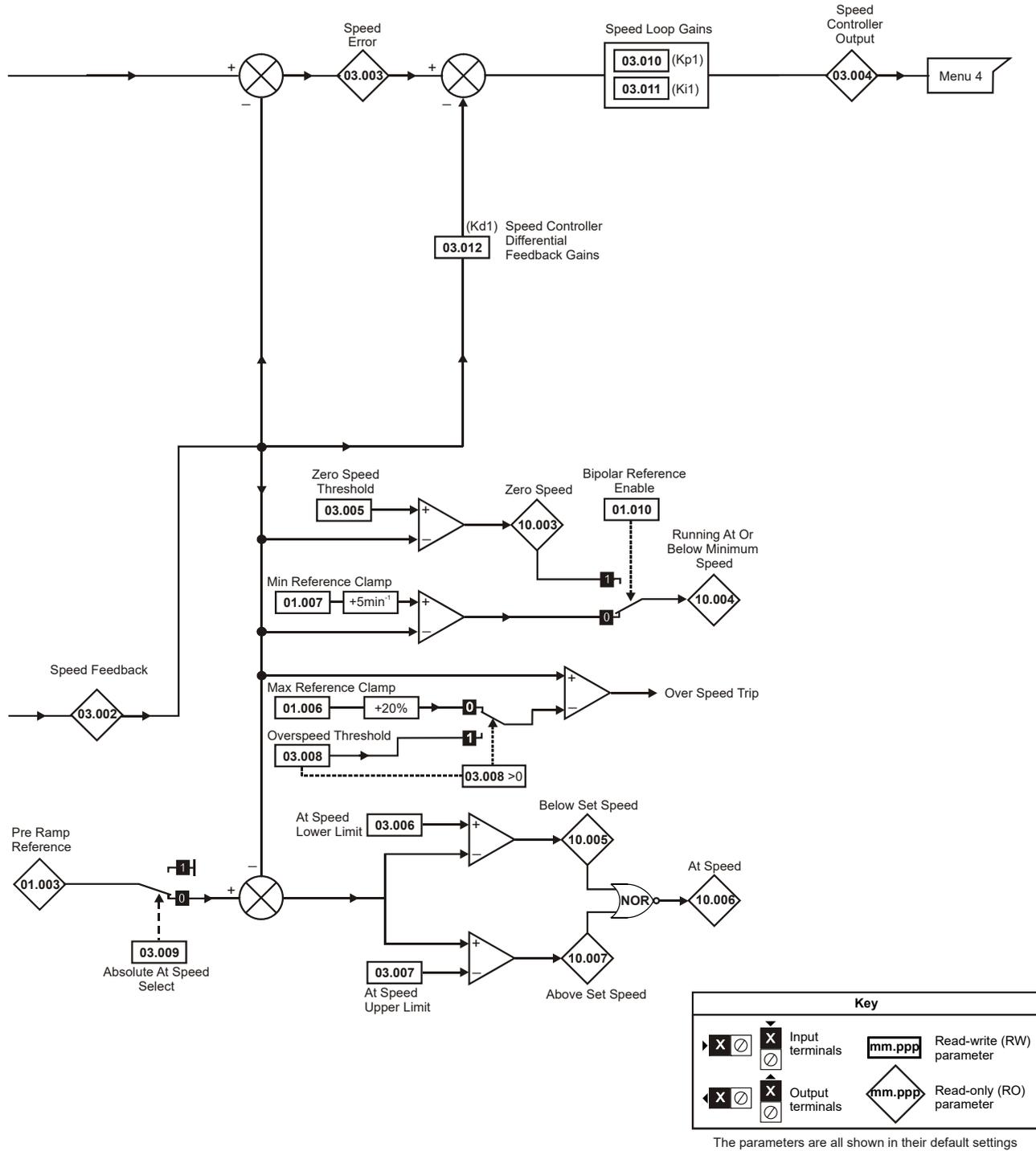


Figure 11-4 Menu 3 RFC-A, RFC-S logic diagram



NOTE

* Automatic change over if the relevant 'bit' of *Position Feedback Initialized* (03.076) is 0.



Parameter		Range			Default			Type					
		OL	RFC-A	RFC-S	OL	RFC-A	RFC-S						
03.001	Final Speed Reference		VM_SPEED					RO	Num	ND	NC	PT	FI
03.002	Speed Feedback		VM_SPEED					RO	Num	ND	NC	PT	FI
03.003	Speed Error		VM_SPEED					RO	Num	ND	NC	PT	FI
03.004	Speed Controller Output		VM_TORQUE_CURRENT %					RO	Num	ND	NC	PT	FI
03.005	Zero Speed Threshold	0.0 to 20.0 Hz	0 to 200 rpm		1.0 Hz	5 rpm		RW	Num				US
03.006	At Speed Lower Limit	0.0 to 550.0 Hz	0 to 33000 rpm		1.0 Hz	5 rpm		RW	Num				US
03.007	At Speed Upper Limit	0.0 to 550.0 Hz	0 to 33000 rpm		1.0 Hz	5 rpm		RW	Num				US
03.008	Over Speed Threshold	0.0 to 550.0 Hz	0 to 40000 rpm		0.0 Hz	0 rpm		RW	Num				US
03.009	Absolute At Speed Select	Off (0) or On (1)			Off (0)			RW	Bit				US
03.010	Speed Controller Proportional Gain Kp1		0.0000 to 200.0000 s/rad			0.0300 s/rad		RW	Num				US
03.011	Speed Controller Integral Gain Ki1		0.00 to 655.35 s ² /rad			0.10 s ² /rad		RW	Num				US
03.012	Speed Controller Differential Feedback Gain Kd1		0.00000 to 0.65535 1/rad			0.00000 1/rad		RW	Num				US
03.078	Sensorless Mode Active		Off (0) or On (1)					RO	Bit	ND	NC	PT	
03.079	Sensorless Mode Filter		4 (0), 8 (1), 16 (2), 32 (3), 64 (4) ms			4 (0) ms		RW	Txt				US

RW	Read / Write	RO	Read only	Num	Number parameter	Bit	Bit parameter	Txt	Text string	Bin	Binary parameter	FI	Filtered
ND	No default value	NC	Not copied	PT	Protected parameter	RA	Rating dependent	US	User save	PS	Power-down save	DE	Destination

11.5 Menu 4: Torque and current control

Figure 11-5 Menu 4 Open loop logic diagram

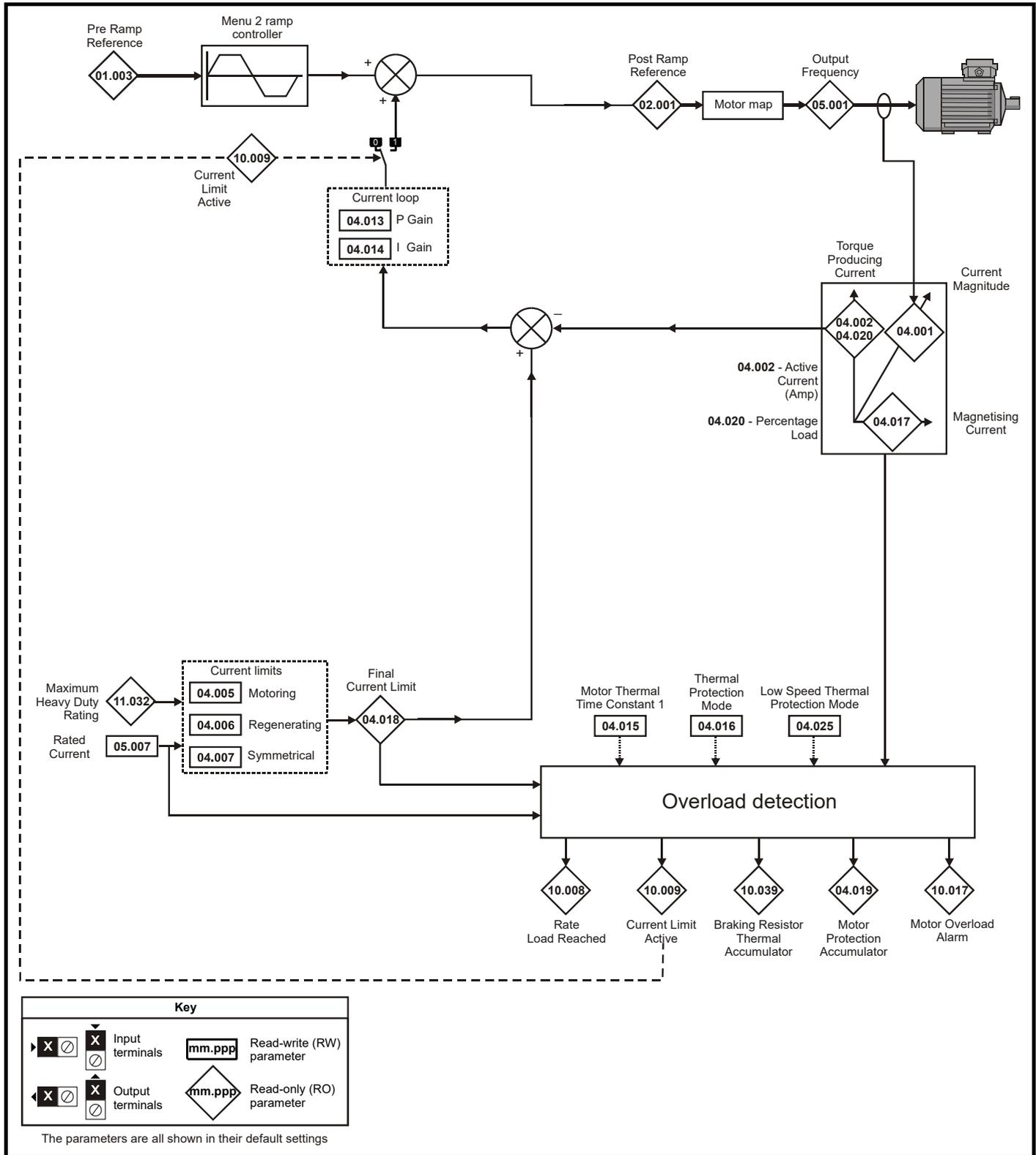
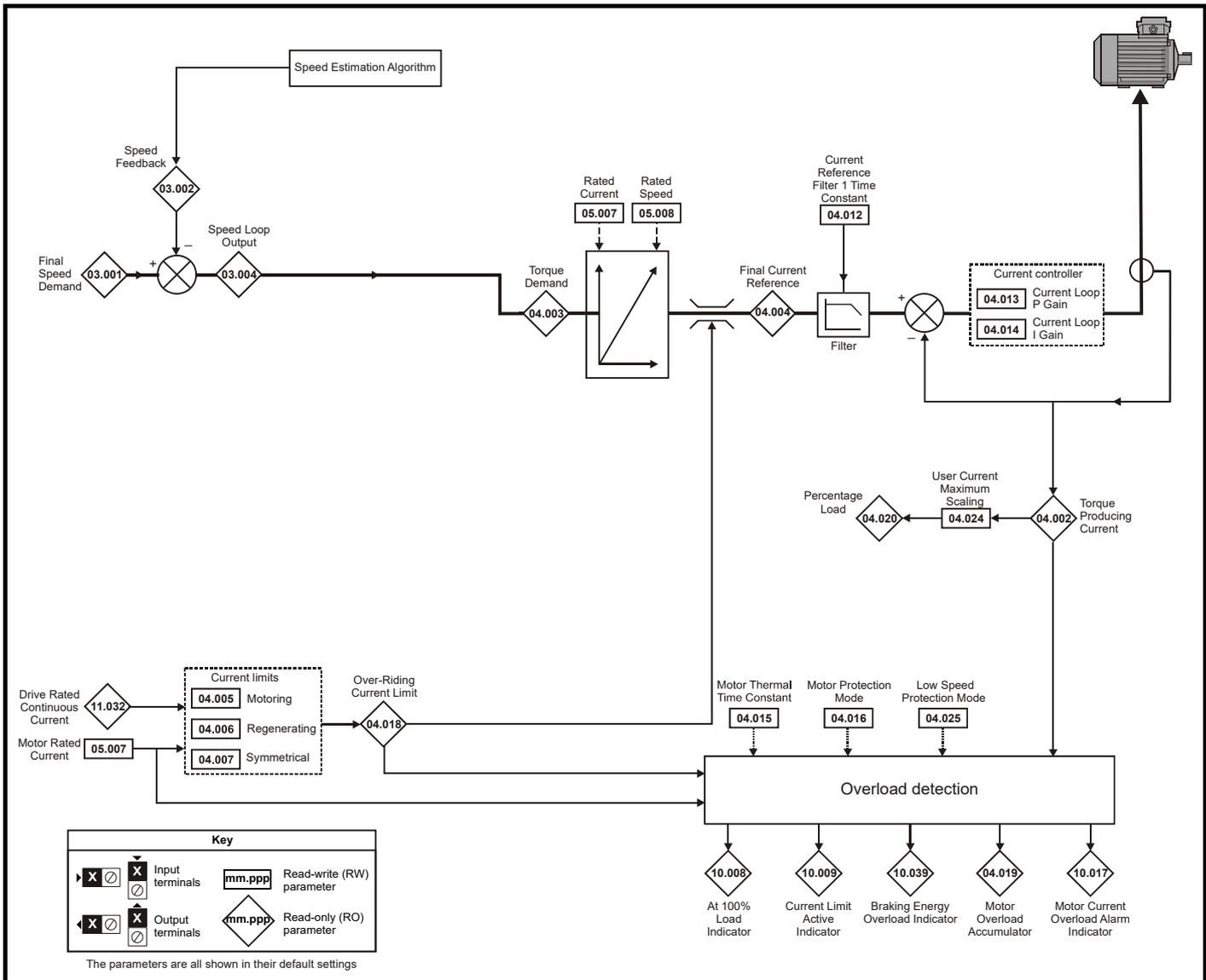


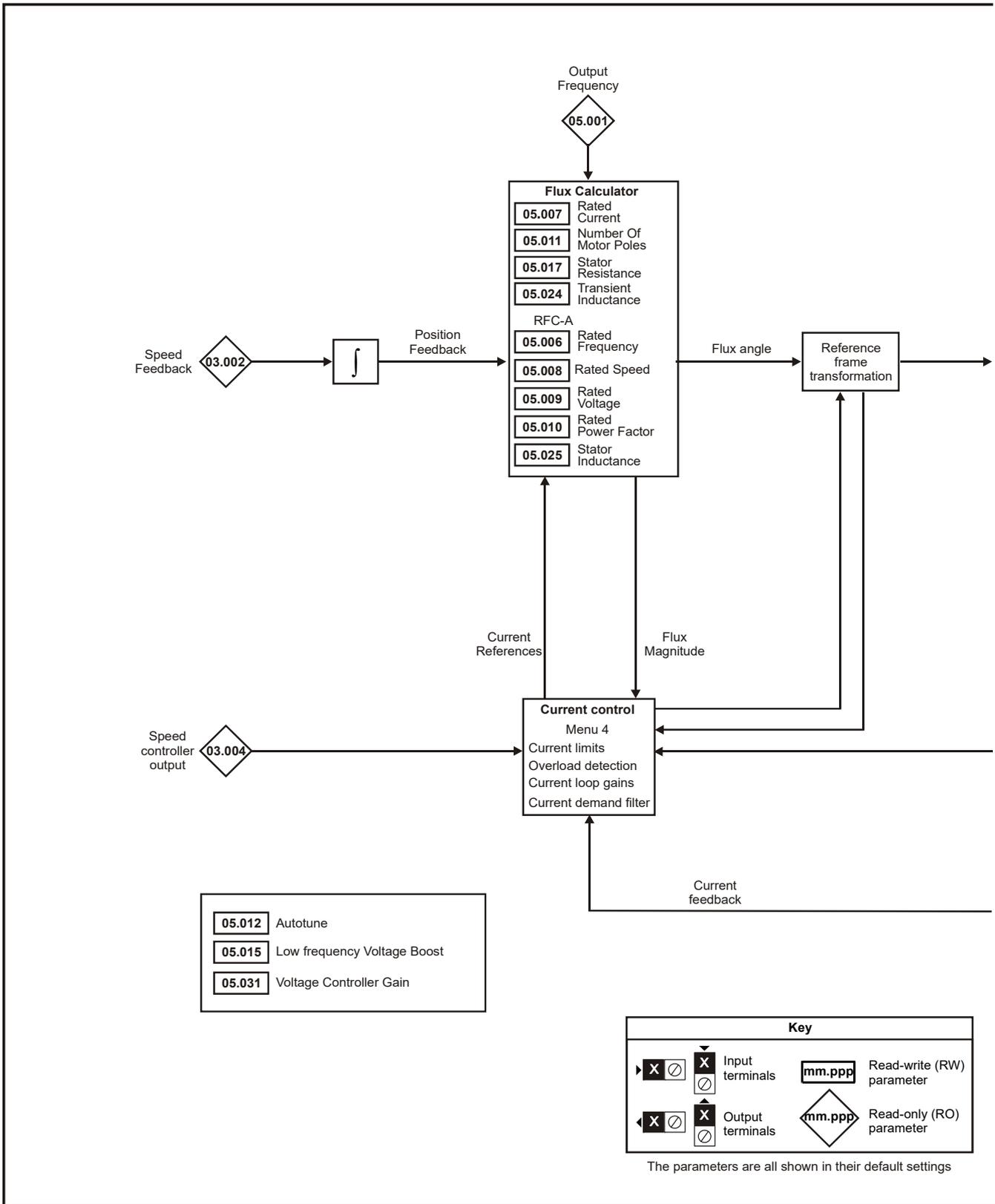
Figure 11-7 Menu 4 RFC-S logic diagram

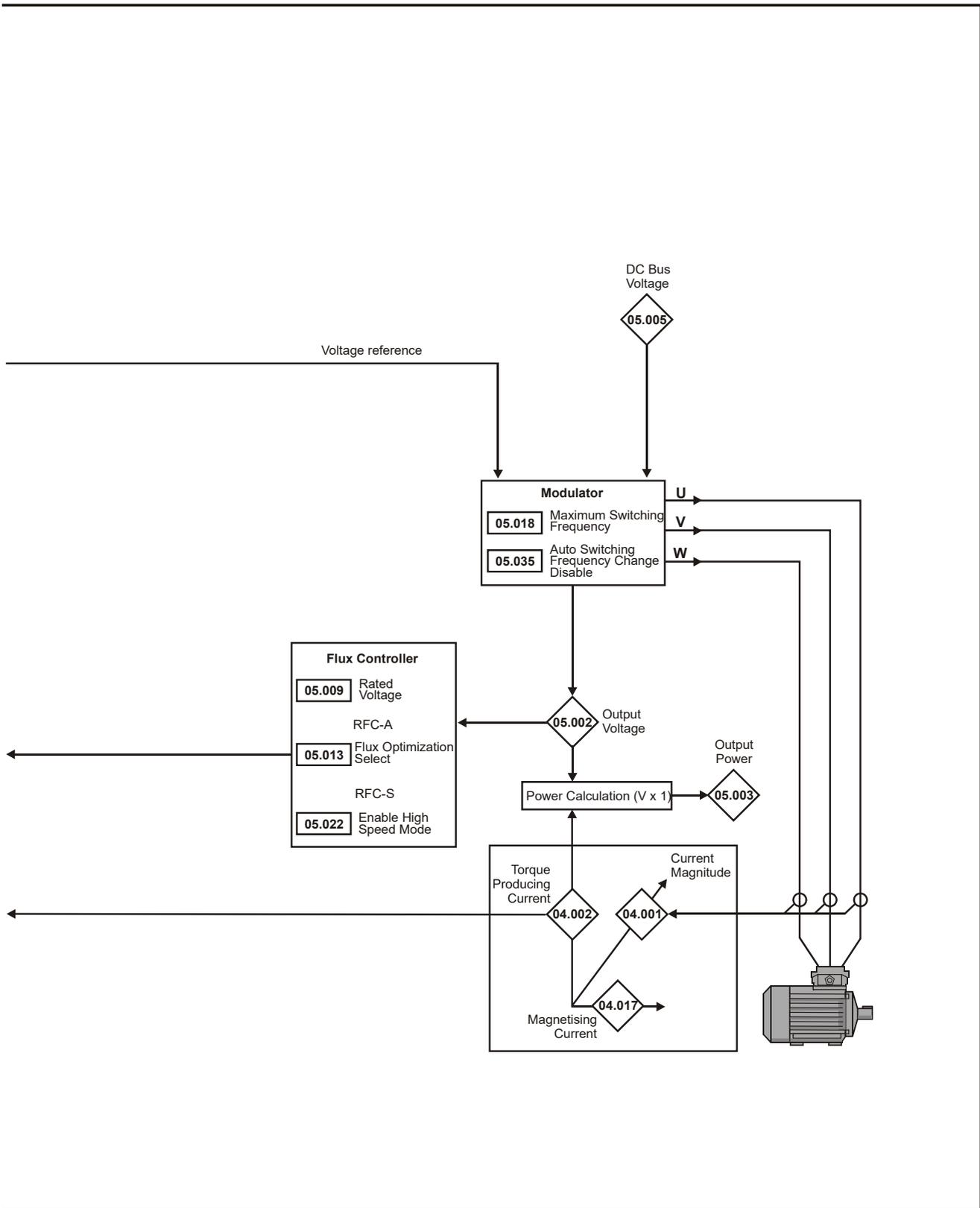


Parameter		Range(⇅)		Default(⇄)			Type					
		OL	RFC-A / S	OL	RFC-A	RFC-S						
04.001	Current Magnitude	0.000 to VM_DRIVE_CURRENT_UNIPOLAR A					RO	Num	ND	NC	PT	FI
04.002	Torque Producing Current / Iq	VM_DRIVE_CURRENT A					RO	Num	ND	NC	PT	FI
04.003	Final Torque Reference	VM_TORQUE_CURRENT %					RO	Num	ND	NC	PT	FI
04.004	Final Current Reference	VM_TORQUE_CURRENT %					RO	Num	ND	NC	PT	FI
04.005	Motoring Current Limit	0.0 to VM_MOTOR1_CURRENT_LIMIT %				110.0 %	RW	Num		RA		US
04.006	Regenerating Current Limit	0.0 to VM_MOTOR1_CURRENT_LIMIT %				110.0 %	RW	Num		RA		US
04.007	Symmetrical Current Limit	0.0 to VM_MOTOR1_CURRENT_LIMIT %				110.0 %	RW	Num		RA		US
04.012	Current Reference Filter 1 Time Constant		0.0 to 25.0 ms			1.0 ms	RW	Num				US
04.013	Current Controller Kp Gain	0 to 30000		20		150	RW	Num				US
04.014	Current Controller Ki Gain	0 to 30000		40		2000	RW	Num				US
04.015	Motor Thermal Time Constant 1	1.0 to 3000.0 s				89.0 s	RW	Num				US
04.016	Thermal Protection Mode	Motor Trip (0), Motor Limit (1), Drive Limit (2), Both Limit (3), Disabled (4)				Motor Limit (1)	RW	Bin				US
04.017	Magnetising Current / Id	VM_DRIVE_CURRENT A					RO	Num	ND	NC	PT	FI
04.018	Final Current Limit	VM_TORQUE_CURRENT %					RO	Num	ND	NC	PT	
04.019	Motor Protection Accumulator	0.0 to 100.0 %					RO	Num	ND	NC	PT	PS
04.020	Percentage Load	VM_USER_CURRENT %					RO	Num	ND	NC	PT	FI
04.021	Current feedback filter disable	Off (0) or On (1)				Off (0)	RW	Bit				US
04.024	User Current Maximum Scaling	0.0 to VM_TORQUE_CURRENT_UNIPOLAR				110.0 %	RW	Num		RA		US
04.025	Low Speed Thermal Protection Mode	0 to 1				0	RW	Num				US
04.026	Percentage Torque	0.0 to VM_USER_CURRENT %					RO	Num	ND	NC	PT	FI
04.027	Low load detection level	0.0 to 100%				0.0 %	RW	Num				US
04.028	Low load detection speed / frequency threshold	VM_SPEED_FREQ_REF_UNIPOLAR		0.0 Hz		0.0 rpm	RW	Num				US
04.029	Enable trip on low load	Off (0) or On (1)				Off (0)	RW	Bit				US
04.036	Motor Protection Accumulator Power-Up Value	Power down (0), Zero (1), Real time (2)				Power down (0)	RW	Txt				US
04.037	Motor Thermal Time Constant 2	1.0 to 3000.0 s				89.0 s	RW	Num				US
04.038	Motor Thermal Time Constant 2 Scaling	0 to 100 %				0 %	RW	Num				US
04.039	Rated Iron Losses As Percentage Of Losses	0 to 100 %				0 %	RW	Num				US
04.041	Rated Torque	0.00 to 50000.00 Nm				0.00 Nm	RW	Num				US
04.042	Torque Estimation Minimum Frequency	0 to 100 %				5 %	RW	Num				US
04.049	Magnetising Current Limit		0.0 to 100.0 %			100.0 %	RW	Num				US

RW	Read / Write	RO	Read only	Num	Number parameter	Bit	Bit parameter	Txt	Text string	Bin	Binary parameter	FI	Filtered
ND	No default value	NC	Not copied	PT	Protected parameter	RA	Rating dependent	US	User save	PS	Power-down save	DE	Destination

Figure 11-9 Menu 5 RFC-A, RFC-S logic diagram





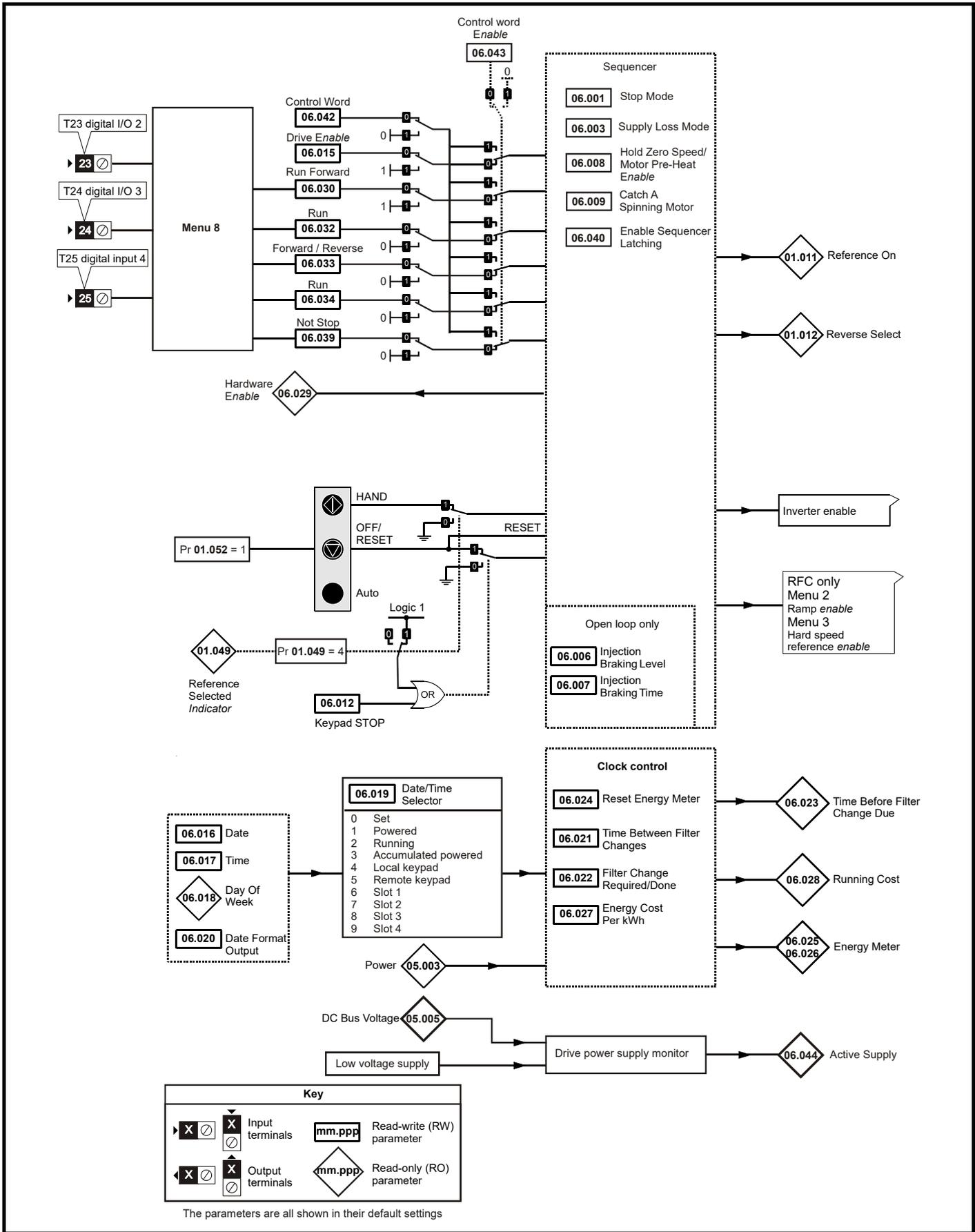
Parameter		Range(φ)			Default(⇔)			Type					
		OL	RFC-A	RFC-S	OL	RFC-A	RFC-S						
05.001	Output Frequency	VM_SPEED_FREQ_REF Hz	±2000.0 Hz					RO	Num	ND	NC	PT	FI
05.002	Output Voltage	0 to VM_AC_VOLTAGE V						RO	Num	ND	NC	PT	FI
05.003	Output Power	VM_POWER kW						RO	Num	ND	NC	PT	FI
05.004	Motor Rpm	±180000 rpm						RO	Num	ND	NC	PT	FI
05.005	D.C. Bus Voltage	0 to VM_DC_VOLTAGE V						RO	Num	ND	NC	PT	FI
05.006	Rated Frequency	0.0 to 550.0 Hz			50Hz: 50.0 60Hz: 60.0		RW	Num					US
05.007	Rated Current	0.000 to VM_RATED_CURRENT A			Maximum Rated Current 11.060			RW	Num		RA		US
05.008	Rated Speed	0 to 33000 rpm	0.00 to 33000.00 rpm		50Hz - 1500 rpm 60Hz - 1800 rpm	50Hz - 1450.00 rpm 60Hz - 1750.00 rpm	3000.00 rpm	RW	Num				US
05.009	Rated Voltage	0 to VM_AC_VOLTAGE_SET V			200 V drive: 230 V Eur - 400 V drive: 400 V USA - 400 V drive: 460 V 575 V drive: 575 V 690 V drive: 690 V			RW	Num		RA		US
05.010	Rated Power Factor	0.000 to 1.000			Default Power Factor		RW	Num		RA		US	
05.011	Number Of Motor Poles	Automatic (0) to 480 Poles (240)			Automatic (0)		8 Poles (4)	RW	Txt				US
05.012	Autotune	None (0), Basic (1), Improved (2)		None (0), Stationary (1), Rotating (2)	0			RW	Num		NC		
05.013	Open Loop> Dynamic V To F Select	Off (0) or On (1)			On (1)			RW	Bit				US
	RFC-A> Flux Optimization Select		Off (0) or On (1)			Off (0)		RW	Bit				US
05.014	Open-loop Control Mode	Ur S (0), Ur (1), Fixed (2), Ur Auto (3), Ur I (4), Square (5), Sync Motor (6)			Fixed (2)			RW	Txt				US
05.015	Open-loop / RFC-A > Low Frequency Voltage Boost	0.0 to 25.0 %			0.5 %			RW	Num				US
	RFC-S> Minimal Movement Phasing Test Current			1% (0), 2% (1), 3% (2), 6% (3), 12% (4), 25% (5), 50% (6), 100% (7)			1% (0)	RW	Num				US
05.016	Minimal Movement Phasing Test Angle		0.00 to 25.00 °				0.00 °	RW	Num				US
05.017	Stator Resistance	0.000000 to 1000.000000 Ω			0.000000 Ω			RW	Num		RA		US
05.018	Maximum Switching Frequency	0 to VM_SWITCHING_FREQUENCY kHz			3 kHz (1)			RW	Txt		RA		US
05.019	High Stability Space Vector Modulation	Off (0) or On (1)			Off (0)			RW	Bit				US
05.020	Quasi-square Enable	Off (0) or On (1)			Off (0)			RW	Bit				US
05.022	Enable High Speed Mode			Limit (-2), Limit (Servo) (-1), Disable (0), Enable (Servo) (1), Enable (2)			Limit Servo (-1)	RW	Bit				US
05.024	Transient Inductance / Ld	0.000 to 500.000 mH			0.000 mH			RW	Num		RA		US
05.025	Stator Inductance	0.00 to 5000.00 mH			0.00 mH			RW	Num		RA		US
05.027	Open-Loop> Enable Slip Compensation	Off (0) or On (1)			On (1)			RW	Bit				US
	RFC-A Flux Control Gain		±10.0			1		RW	Bit				US
05.028	Torque Linearisation Disable			Off (0) or On (1)			Off (0)	RW	Bit				US
05.031	Voltage Controller Gain	1 to 30			1			RW	Num				US
05.033	Volts per 1000 rpm		0 to 10000 V				98 V	RW	Num				US
05.034	Percentage Flux		0.0 to 150.0 %					RO	Num	ND	NC	PT	FI
05.035	Auto-switching Frequency Change	Enabled (0), Disabled (1), No Ripple Detect (2)			Enabled (0)			RW	Txt				US

Parameter	Range(↕)			Default(⇒)			Type								
	OL	RFC-A	RFC-S	OL	RFC-A	RFC-S									
05.036	Auto-switching Frequency Step Size			1 to 2			2			RW	Num				US
05.037	Switching Frequency			2 kHz (0), 3 kHz (1), 4 kHz (2), 6 kHz (3), 8 kHz (4), 12 kHz (5), 16 kHz (6)						RO	Txt	ND	NC	PT	
05.038	Minimum Switching Frequency			0 to VM_MIN_SWITCHING_FREQUENCY kHz			2 kHz (0)			RW	Txt				US
05.039	Maximum Inverter Temperature Ripple			20 to 60 °C			60 °C			RW	Num				US
05.040	Spin Start Boost			0.0 to 10.0			1.0			RW	Num				US
05.041	Voltage Headroom			0 to 20 %			0 % 10 %			RW	Num				US
05.042	Reverse Output Phase Sequence			Off (0) or On (1)			Off (0)			RW	Bit				US
05.063	Sensorless Mode Current Ramp			0.00 to 1.00 s			0.20 s			RW	Num				US
05.064	RFC Low Speed Mode			Non-salient (-1), Injection (0), Current (1), Current (2), Current No Test (3), Current Step (4), Current Only (5)			Current (2)			RW	Txt				US
05.065	Saliency Torque Control Select			Disabled (0), Low (1), High (2), Auto (3)			Disabled (0)			RW	Txt				US
05.066	Active Saliency Torque Mode			Disabled (0), Low (1), High (2), Sync Reluctance (3)						RO	Txt	ND	NC	PT	
05.067	Required Over-current Trip Level			0 to 100 %			0 %			RW	Num				US
05.068	Actual Over-current Trip Level			0 to 500 %						RO	Num	ND	NC	PT	
05.069	Over-current Trip Level as Percentage of Rated Current			0 to 1000 %			0 %			RW	Num				US
05.070	Inverted Saturation Characteristic			Off (0) or On (1)			Off (0)			RW	Bit				US
05.071	Low Speed Sensorless Mode Current Limit			0.0 to 1000.0 %			100.0 %			RW	Num		RA		US
05.072	No-load Lq			0.000 to 500.000 mH			0.000 mH			RW	Num		RA		US
05.075	Iq Test Current For Inductance Measurement			0 to 200 %			100 %			RW	Num				US
05.077	Phase Offset At Iq Test Current			±90.0 °			0.0 °			RW	Num		RA		US
05.078	Lq At The Defined Iq Test Current			0.000 to 500.000 mH			0.000 mH			RW	Num		RA		US
05.082	Id Test Current for Inductance Measurement			-100 to 0 %			-100 %			RW	Num				US
05.084	Lq At The Defined Id Test Current			0.000 to 500.000 mH			0.000 mH			RW	Num		RA		US
05.088	Estimated Lq			0.000 to 500.000 mH						RO	Num	ND	NC	PT	FI
05.089	Rated Torque Angle			0 to 90 °						RO	Num	ND	NC	PT	
05.090	Maximum Torque Angle			45° to 90°			80°			RW	Num				US

RW	Read / Write	RO	Read only	Num	Number parameter	Bit	Bit parameter	Txt	Text string	Bin	Binary parameter	FI	Filtered
ND	No default value	NC	Not copied	PT	Protected parameter	RA	Rating dependent	US	User save	PS	Power-down save	DE	Destination

11.7 Menu 6: Sequencer and clock

Figure 11-10 Menu 6 logic diagram



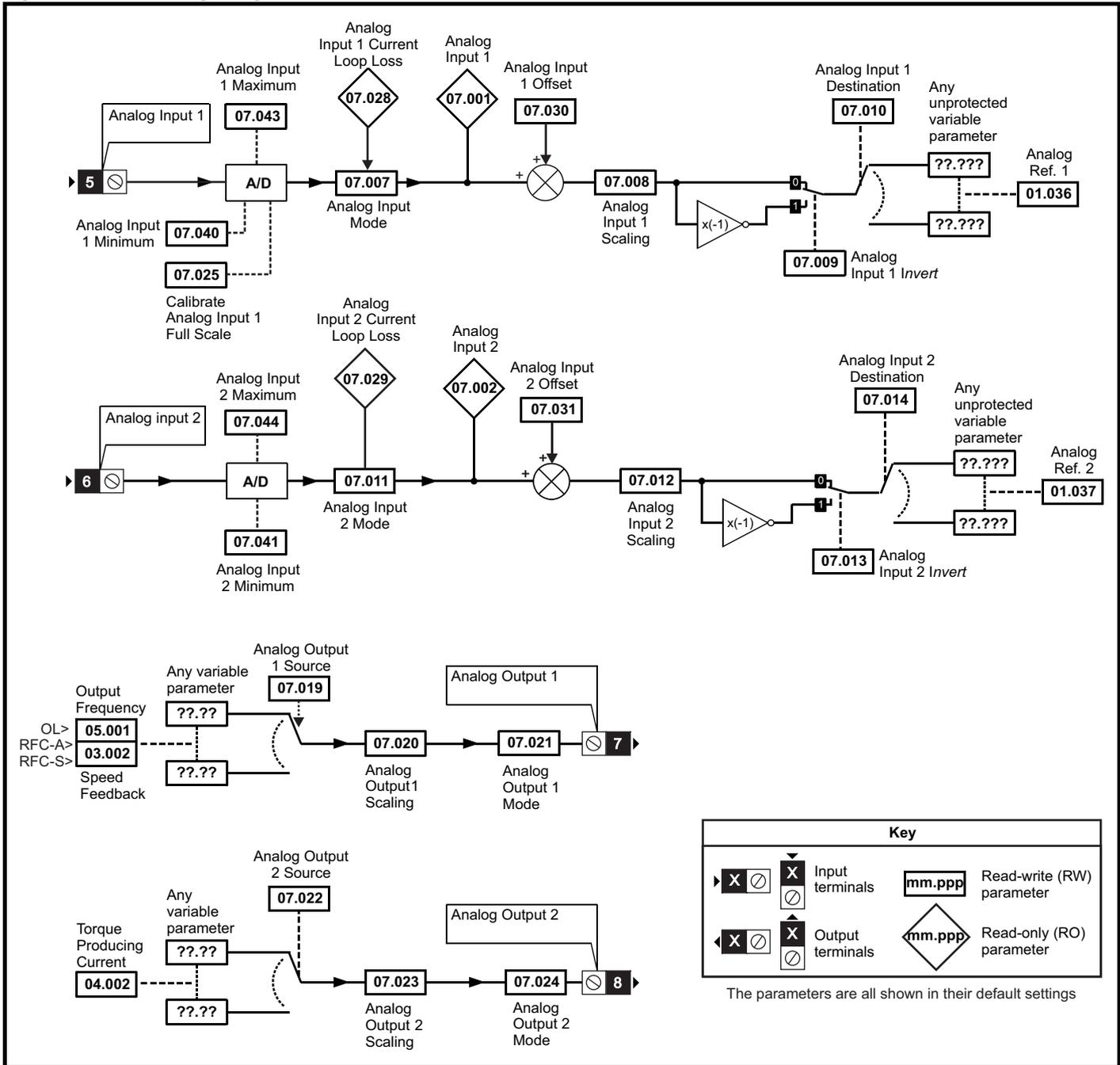
Parameter		Range(†)		Default(⇔)			Type							
		OL	RFC-A / S	OL	RFC-A	RFC-S								
06.001	Stop Mode	Coast (0), Ramp (1), Ramp dc I (2), dc I (3), Timed dc I (4)		Coast (0), Ramp (1),		Ramp (1)			RW	Txt				US
06.003	Supply Loss Mode	Disable (0), Ramp Stop (1), Ride Thru (2)		Disable (0), Ramp Stop (1), Ride Thru (2), Limit Stop (3)		Disable (0)			RW	Txt				US
06.006	Injection Braking Level	0.0 to 150.0 %				100.0 %				RW	Num		RA	US
06.007	Injection Braking Time	0.0 to 100.0 s				1.0 s				RW	Num			US
06.008	Hold Zero Speed	Off (0) or On (1)				Off (0)			RW	Bit				US
06.009	Catch A Spinning Motor	Disable (0), Enable (1), Fwd Only (2), Rev Only (3)				Enable (1)			RW	Txt				US
06.010	Enable Conditions	000000000000 to 111111111111							RO	Bin	ND	NC	PT	
06.011	Sequencer State Machine Inputs	0000000 to 1111111							RO	Bin	ND	NC	PT	
06.015	Drive Enable	Off (0) or On (1)				On (1)			RW	Bit				US
06.016	Date	00-00-00 to 31-12-99							RW	Date	ND	NC	PT	
06.017	Time	00:00:00 to 23:59:59							RW	Time	ND	NC	PT	
06.018	Day Of Week	Sunday (0), Monday (1), Tuesday (2), Wednesday (3), Thursday (4), Friday (5), Saturday (6)							RO	Txt	ND	NC	PT	
06.019	Date/Time Selector	Set (0), Powered (1), Running (2), Acc Powered (3), Local Keypad (4), Remote Keypad (5), Slot 1 (6), Slot 2 (7), Slot 3 (8), Slot 4 (9)				Local Keypad (4)			RW	Txt				US
06.020	Date Format	Std (0) or US (1)				Std (0)			RW	Txt				Us
06.021	Time Between Filter Changes	0 to 30000 Hours				0 Hours			RW	Num				US
06.022	Filter Change Required / Change Done	Off (0) or On (1)							RW	Bit	ND	NC		
06.023	Time Before Filter Change Due	0 to 30000 Hours							RO	Num	ND	NC	PT	PS
06.024	Reset Energy Meter	Off (0) or On (1)				Off (0)			RW	Bit				
06.025	Energy Meter: MWh	±999.0 MWh							RO	Num	ND	NC	PT	PS
06.026	Energy Meter: kWh	±99.99 kWh							RO	Num	ND	NC	PT	PS
06.027	Energy Cost Per kWh	0.0 to 600.0				0.0			RW	Num				US
06.028	Running Cost	±32000							RO	Num	ND	NC	PT	
06.029	Hardware Enable	Off (0) or On (1)							RO	Bit	ND	NC	PT	
06.030	Run Forward	Off (0) or On (1)				Off (0)			RW	Bit		NC		
06.032	Run Reverse	Off (0) or On (1)				Off (0)			RW	Bit		NC		
06.033	Forward/Reverse	Off (0) or On (1)				Off (0)			RW	Bit		NC		
06.034	Run	Off (0) or On (1)				Off (0)			RW	Bit		NC		
06.039	Not Stop	Off (0) or On (1)				Off (0)			RW	Bit		NC		
06.040	Enable Sequencer Latching	Off (0) or On (1)				Off (0)			RW	Bit				US
06.041	Drive Event Flags	00 to 11				00			RW	Bin		NC		
06.042	Control Word	00000000000000 to 11111111111111				00000000000000			RW	Bin		NC		
06.043	Control Word Enable	Off (0) or On (1)				Off (0)			RW	Bit				US
06.044	Active Supply	Off (0) or On (1)							RO	Bit	ND	NC	PT	
06.045	Cooling Fan control	0 to 11				10			RW	Num				US
06.046	Cooling Fan Speed	-10 to 10							RO	Num	ND	NC	PT	
06.047	Input Phase Loss Detection Mode	Full (0), Ripple Only (1), Disabled (2)				Full (0)			RW	Txt				US
06.048	Supply Loss Detection Level	0 to VM_SUPPLY_LOSS_LEVEL				200 V drive: 205 V 400 V drive: 410 V 575 V drive: 540 V 690 V drive: 540 V			RW	Num		RA		US
06.051	Hold Supply Loss Active	Off (0) or On (1)				Off (0)			RW	Bit		NC		
06.052	Motor Pre-heat Current Magnitude	0 to 100 %				0 %			RW	Num				US
06.053	Sleep / Wake Threshold	±VM_SPEED_FREQ_REF_UNIPOLAR				0.0			RW	Num				US
06.054	Sleep Time	0.0 to 250.0 s				10.0 s			RW	Num				US
06.055	Wake Time	0.0 to 250.0 s				10.0 s			RW	Num				US
06.056	Sleep Required	Off (0) or On (1)							RO	Bit	ND	NC	PT	
06.057	Sleep Active	Off (0) or On (1)							RO	Bit	ND	NC	PT	
06.058	Output Phase Loss Detection Time	0.5 s (0), 1.0 s (1), 2.0 s (2), 4.0 s (3)				0.5 s (0)			RW	Txt				US
06.059	Output Phase Loss Detection Enable	Disabled (0), Phases (1), Devices (2), Low Noise (3)				Disabled (0)			RW	Bit				US

Parameter	Range(⌘)		Default(⇄)			Type					
	OL	RFC-A / S	OL	RFC-A	RFC-S						
06.060	Standby Mode Enable	Off (0) or On (1)	Off (0)			RW	Bit				US
06.061	Standby Mode Mask	0000000 to 1111111	0000000			RW	Bin				US
06.065	Standard Under Voltage Threshold	VM_STD_UNDER_VOLTS	200 V drive: 175 V 400 V drive: 330 V 575 V drive: 435 V 690 V drive: 435 V			RW	Num		RA		US
06.066	Low Voltage Under Voltage Threshold	24 to VM_LOW_UNDER_VOLTS	200 V drive: 175 V 400 V drive: 330 V 575 V drive: 435 V 690 V drive: 435 V			RW	Num		RA		US
06.067	Low Under Voltage Threshold Select	Off (0) or On (1)	Off (0)			RW	Bit				US
06.068	Back Up Supply Mode Enable	Off (0) or On (1)	Off (0)			RW	Bit				US
06.069	Under-Voltage System Contactor Close	Off (0) or On (1)				RO	Bit	ND	NC	PT	
06.070	Under-Voltage System Contactor Closed	Off (0) or On (1)	Off (0)			RW	Bit				
06.071	Slow Rectifier Charge Rate Enable	Off (0) or On (1)	Off (0)			RW	Bit				US
06.072	User Supply Select	Off (0) or On (1)	Off (0)			RW	Bit				US
06.084	Date And Time Offset	±12.00 Hours	0.00 Hours			RW	Num				US
06.085	Control Word Override	000000000000000 to 111111111111111	000000000000000			RW	Bin		NC		
06.086	Control Override Enable	Disabled (0), Control Word (1), Enabled (2)	Disabled (0)			RW	Txt		NC		

RW	Read / Write	RO	Read only	Num	Number parameter	Bit	Bit parameter	Txt	Text string	Bin	Binary parameter	FI	Filtered
ND	No default value	NC	Not copied	PT	Protected parameter	RA	Rating dependent	US	User save	PS	Power-down save	DE	Destination
IP	IP address	Mac	Mac address	Date	Date parameter	Time	Time parameter	SMP	Slot,menu,parameter	Chr	Character parameter	Ver	Version number

11.8 Menu 7: Analog I/O

Figure 11-11 Menu 7 logic diagram



Parameter	Range(⊕)		Default(⇒)			Type							
	OL	RFC-A / S	OL	RFC-A	RFC-S								
07.001	Analog Input 1	±100.00 %				RO	Num	ND	NC	PT	FI		
07.002	Analog Input 2	±100.00 %				RO	Num	ND	NC	PT	FI		
07.004	Monitored Temperature 1	±250 °C				RO	Num	ND	NC	PT			
07.005	Monitored Temperature 2	±250 °C				RO	Num	ND	NC	PT			
07.006	Monitored Temperature 3	±250 °C				RO	Num	ND	NC	PT			
07.007	Analog Input 1 Mode	4-20 mA Low (-4), 20-4 mA Low (-3), 4-20 mA Hold (-2), 20-4 mA Hold (-1), 0-20 mA (0), 20-0 mA (1), 4-20 mA Trip (2), 20-4 mA Trip (3), 4-20 mA (4), 20-4 mA (5), Volt (6), Therm Short Cct (7), Thermistor (8), T herm No Trip (9)		4-20 mA (4)		RW	Txt						US
07.008	Analog Input 1 Scaling	0.000 to 10.000		1.000		RW	Num						US
07.009	Analog Input 1 Invert	Off (0) or On (1)		Off (0)		RW	Bit						US
07.010	Analog Input 1 Destination	0.000 to 59.999		1.036		RW	Num	DE			PT		US
07.011	Analog Input 2 Mode	4-20 mA Low (-4), 20-4 mA Low (-3), 4-20 mA Hold (-2), 20-4 mA Hold (-1), 0-20 mA (0), 20-0 mA (1), 4-20 mA Trip (2), 20-4 mA Trip (3), 4-20 mA (4), 20-4 mA (5), Volt (6), Therm Short Cct (7), Thermistor (8), Therm No Trip (9)		Volt (6)		RW	Txt						US
07.012	Analog Input 2 Scaling	0.000 to 10.000		1.000		RW	Num						US
07.013	Analog Input 2 Invert	Off (0) or On (1)		Off (0)		RW	Bit						US
07.014	Analog Input 2 Destination	0.000 to 59.999		1.037		RW	Num	DE			PT		US
07.019	Analog Output 1 Source	0.000 to 59.999		5.001	3.002	RW	Num				PT		US
07.020	Analog Output 1 Scaling	0.000 to 10.000		1.000		RW	Num						US
07.021	Analog Output 1 Mode	Volts (0), 0-20 mA (1), 20-0 mA (2), 4-20 mA (3), 20-4 mA (4)		Volts (0)		RW	Txt						US
07.022	Analog Output 2 Source	0.000 to 59.999		4.002		RW	Num				PT		US
07.023	Analog Output 2 Scaling	0.000 to 10.000		1.000		RW	Num						US
07.024	Analog Output 2 Mode	Volts (0), 0-20 mA (1), 20-0 mA (2), 4-20 mA (3), 20-4 mA (4)		Volts (0)		RW	Txt						US
07.025	Calibrate Analog Input 1 Full Scale	Off (0) or On (1)		Off (0)		RW	Bit		NC				
07.026	Analog Input 1 Fast Update Active	Off (0) or On (1)				RO	Bit	ND	NC	PT			
07.027	Analog Input 1 Fast Update Active	Off (0) or On (1)				RO	Bit	ND	NC	PT			
07.028	Analog Input 1 Current Loop Loss	Off (0) or On (1)				RO	Bit	ND	NC	PT			
07.029	Analog Input 2 Current Loop Loss	Off (0) or On (1)				RO	Bit	ND	NC	PT			
07.030	Analog Input 1 Offset	±100.00 %		0.00 %		RW	Num						US
07.031	Analog Input 2 Offset	±100.00 %		0.00 %		RW	Num						US
07.033	Power Output	±100.0 %				RO	Num	ND	NC	PT			
07.034	Inverter Temperature	±250 °C				RO	Num	ND	NC	PT			
07.035	Percentage Of d.c. Bus Thermal Trip Level	0 to 100 %				RO	Num	ND	NC	PT			
07.036	Percentage Of Drive Thermal Trip Level	0 to 100 %				RO	Num	ND	NC	PT			
07.037	Temperature Nearest To Trip Level	0 to 29999				RO	Num	ND	NC	PT			
07.038	Temperature Monitor Select 1	00000 to 10000		01001		RW	Num						US
07.039	Temperature Monitor Select 2	00000 to 10000		01002		RW	Num						US
07.040	Analog Input 1 Minimum	±100.00 %		-100.00 %		RW	Num						US
07.041	Analog Input 2 Minimum	±100.00 %		-100.00 %		RW	Num						US
07.043	Analog Input 1 Maximum	±100.00 %		100.00 %		RW	Num						US
07.044	Analog Input 2 Maximum	±100.00 %		100.00 %		RW	Num						US
07.051	Analog Input 1 Full Scale	0 to 65535				RO	Num	ND	NC	PT	PS		
07.052	Temperature Monitor Select 3	0 to 1999		1		RW	Num						US
07.053	Analog Input 1 Thermistor Type	DIN44082 (0), KTY84 (1), PT100 (2), PT1000 (3), PT2000 (4), NI1000 (5)		DIN44082 (0)		RW	Txt						US
07.054	Analog Input 1 Thermistor Feedback	0 to 5000 Ω				RO	Num	ND	NC	PT			
07.055	Analog Input 1 Thermistor Trip Threshold	0 to 5000 Ω		3300 Ω		RW	Num						US
07.056	Analog Input 1 Thermistor Reset Threshold	0 to 5000 Ω		1800 Ω		RW	Num						US
07.057	Analog Input 1 Thermistor Temperature	-50 to 300 °C				RO	Num	ND	NC	PT			
07.058	Analog Input 2 Thermistor Type	DIN44082 (0), KTY84 (1), PT100 (2), PT1000 (3), PT2000 (4), NI1000 (5)		DIN44082 (0)		RW	Txt						US
07.059	Analog Input 2 Thermistor Feedback	0 to 5000 Ω				RO	Num	ND	NC	PT			
07.060	Analog Input 2 Thermistor Trip Threshold	0 to 5000 Ω		3300 Ω		RW	Num						US

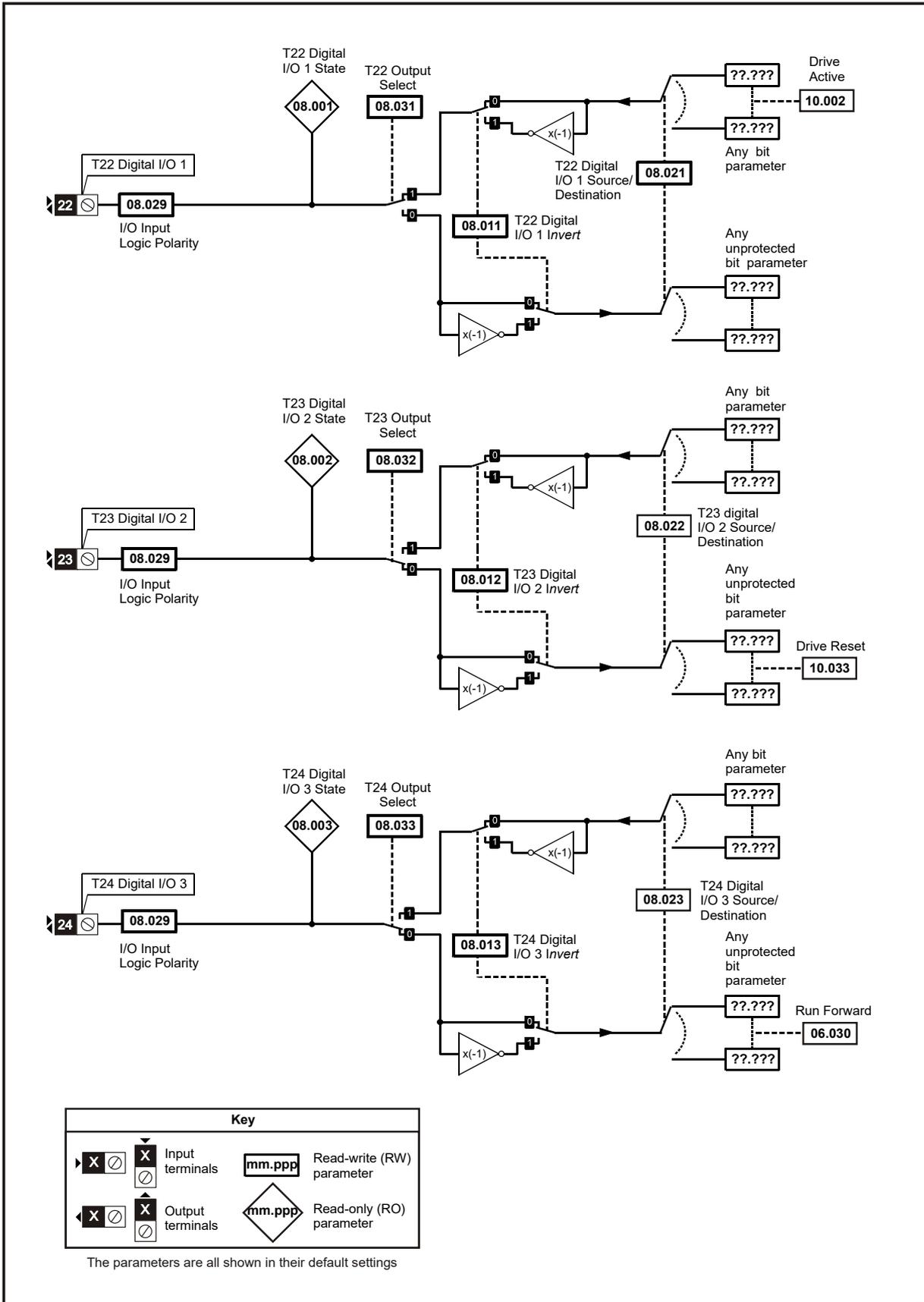
Safety information	Product information	Mechanical installation	Electrical installation	Getting started	Basic parameters	Running the motor	Optimization	NV Media Card Operation	Building Automation	Advanced parameters	Technical data	Diagnostics	UL listing information
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Parameter	Range(⇅)		Default(⇒)			Type					
	OL	RFC-A / S	OL	RFC-A	RFC-S						
07.061 Analog Input 2 Thermistor Reset Threshold	0 to 5000 Ω		1800 Ω			RW	Num				US
07.062 Analog Input 2 Thermistor Temperature	-50 to 300 °C					RO	Num	ND	NC	PT	
07.063 Analog Input 1 Filter Time Constant (T5)	Disabled (0), 500 μs (1), 1ms (2), 2ms (3), 4ms (4), 8ms (5), 16ms (6)		Disabled (0)			RW	Txt				US
07.064 Analog Input 2 Filter Time Constant (T6)	Disabled (0), 500 μs (1), 1ms (2), 2ms (3), 4ms (4), 8ms (5), 16ms (6)		Disabled (0)			RW	Txt				US

RW	Read / Write	RO	Read only	Num	Number parameter	Bit	Bit parameter	Txt	Text string	Bin	Binary parameter	FI	Filtered
ND	No default value	NC	Not copied	PT	Protected parameter	RA	Rating dependent	US	User save	PS	Power-down save	DE	Destination

11.9 Menu 8: Digital I/O

Figure 11-12 Menu 8 logic diagram



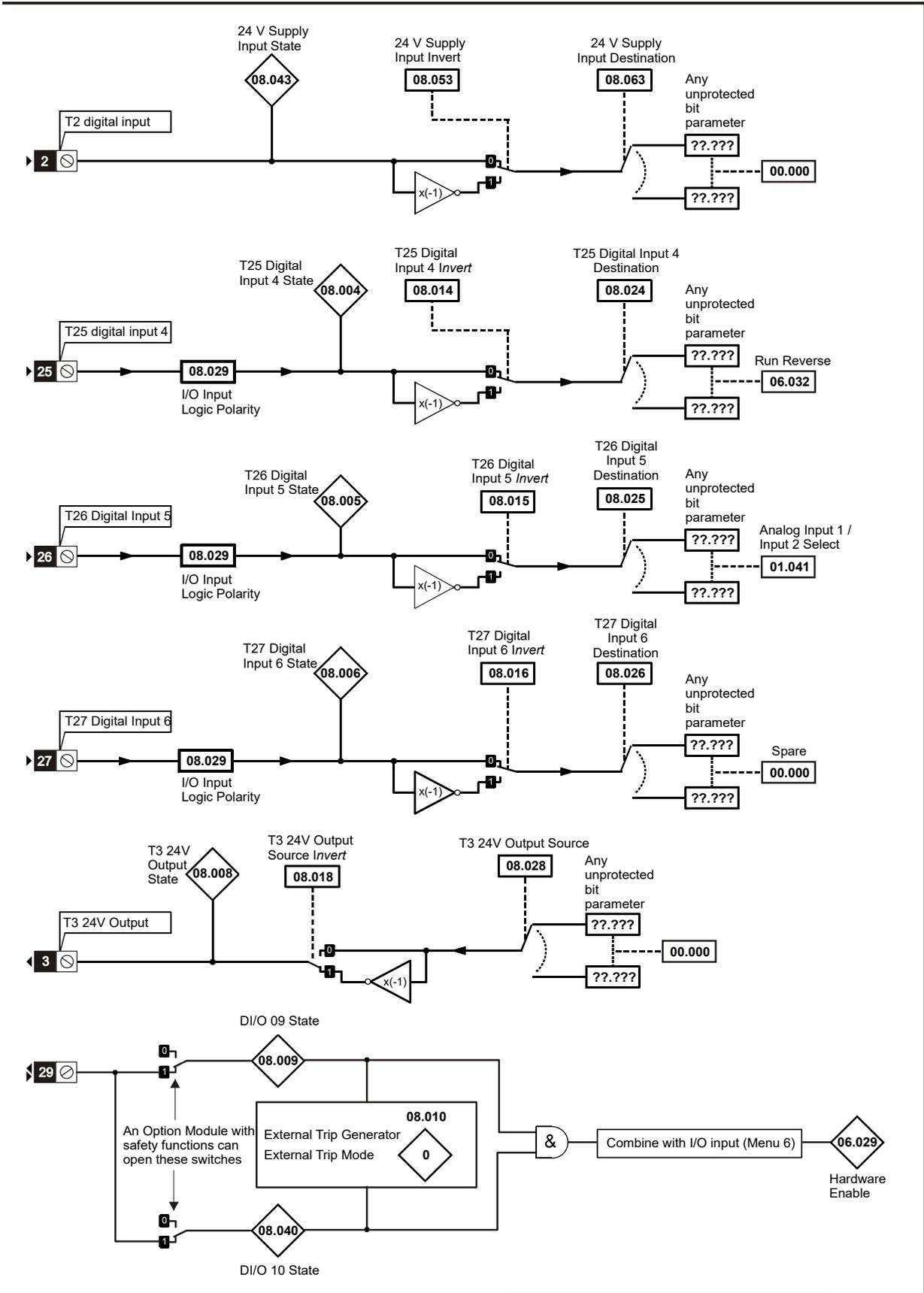


Figure 11-13 Menu 8 logic (cont)

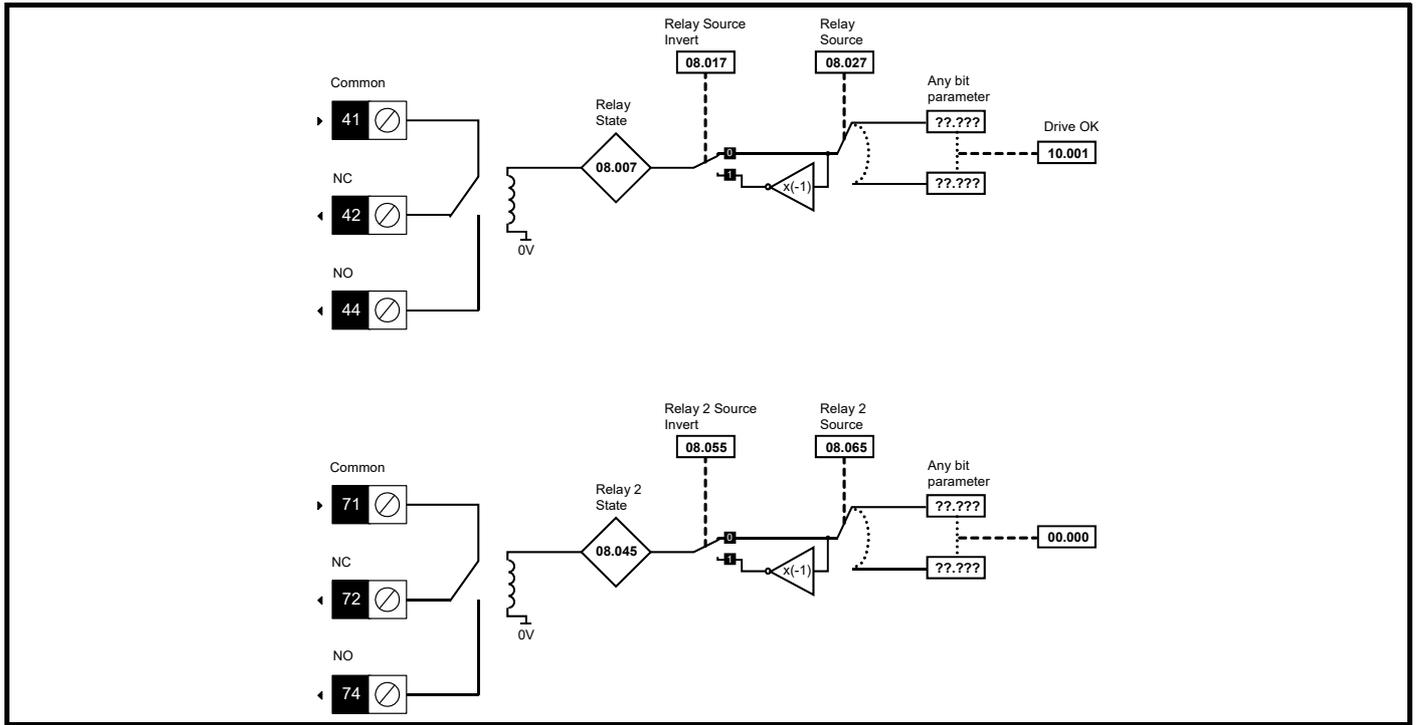
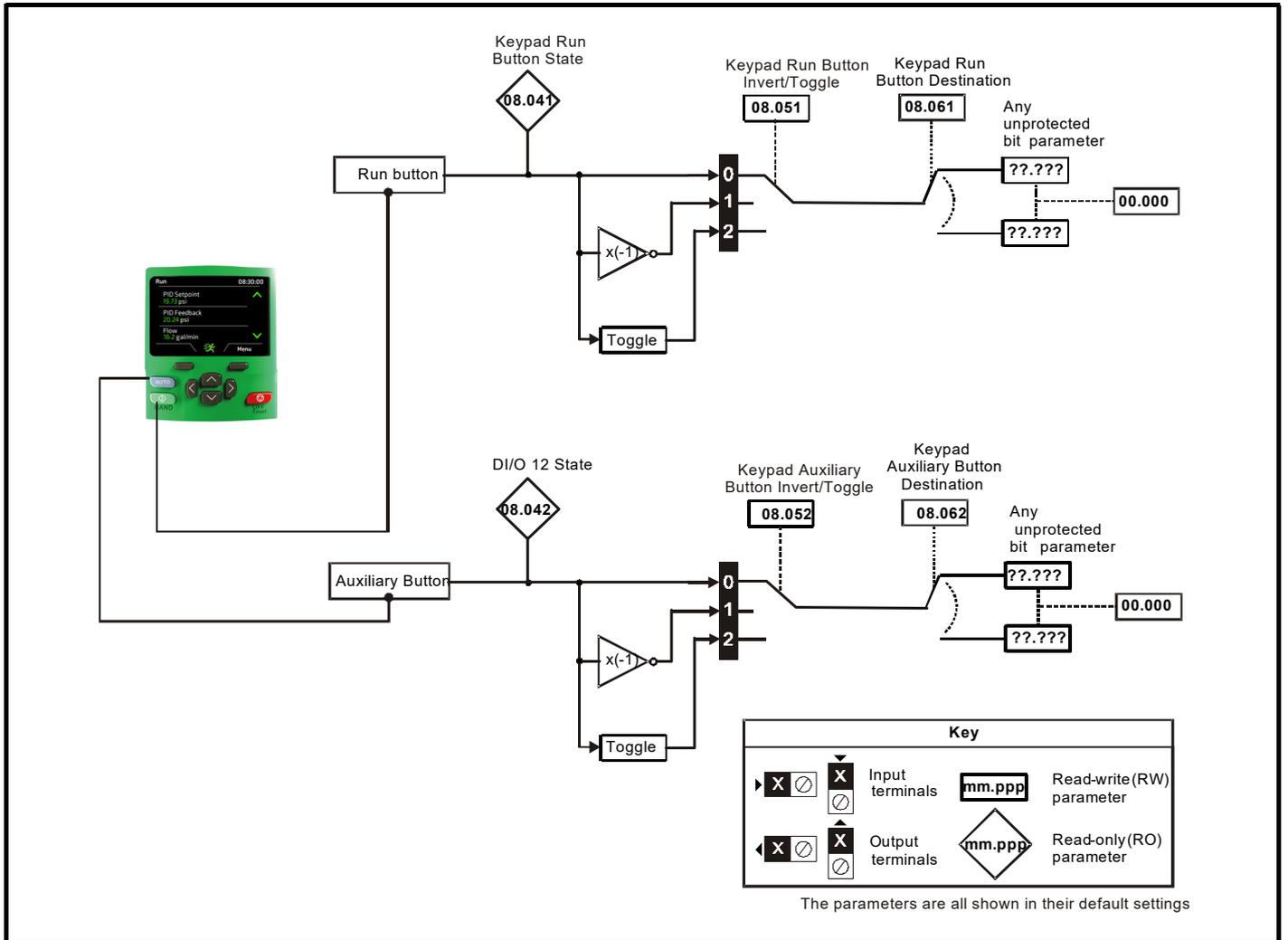


Figure 11-14 Menu 8 logic (cont)



Parameter	Range(⌘)		Default(⇒)			Type						
	OL	RFC-A / S	OL	RFC-A	RFC-S							
08.001	Digital I/O 01 State	Off (0) or On (1)				RO	Bit	ND	NC	PT		
08.002	Digital I/O 02 State	Off (0) or On (1)				RO	Bit	ND	NC	PT		
08.003	Digital I/O 03 State	Off (0) or On (1)				RO	Bit	ND	NC	PT		
08.004	Digital Input 04 State	Off (0) or On (1)				RO	Bit	ND	NC	PT		
08.005	Digital Input 05 State	Off (0) or On (1)				RO	Bit	ND	NC	PT		
08.006	Digital Input 06 State	Off (0) or On (1)				RO	Bit	ND	NC	PT		
08.007	Relay Output State	Off (0) or On (1)				RO	Bit	ND	NC	PT		
08.008	24V Supply Output State	Off (0) or On (1)				RO	Bit	ND	NC	PT		
08.009	STO Input 01 State	Off (0) or On (1)				RO	Bit	ND	NC	PT		
08.010	External Trip Mode	Disable (0), STO 1 (1), STO 2 (2), STO 1 OR STO 2 (3)			Disable (0)	RW	Txt					U S
08.011	Digital I/O 01 Invert	Not Invert (0), Invert (1)			Not Invert (0)	RW	Txt					U S
08.012	Digital I/O 02 Invert	Not Invert (0), Invert (1)			Not Invert (0)	RW	Txt					U S
08.013	Digital I/O 03 Invert	Not Invert (0), Invert (1)			Not Invert (0)	RW	Txt					U S
08.014	Digital Input 04 Invert	Not Invert (0), Invert (1)			Not Invert (0)	RW	Txt					U S
08.015	Digital Input 05 Invert	Not Invert (0), Invert (1)			Not Invert (0)	RW	Txt					U S
08.016	Digital Input 06 Invert	Not Invert (0), Invert (1)			Not Invert (0)	RW	Txt					U S
08.017	Relay Invert	Not Invert (0), Invert (1)			Not Invert (0)	RW	Txt					U S
08.018	24V Supply Output Invert	Not Invert (0), Invert (1)			Invert (1)	RW	Txt					U S
08.020	Digital I/O Read Word	0 to 511				RO	Num	ND	NC	PT		
08.021	Digital I/O 01 Source/ Destination	0.000 to 59.999			10.002	RW	Num	DE		PT		U S
08.022	Digital I/O 02 Source/ Destination	0.000 to 59.999			10.033	RW	Num	DE		PT		U S
08.023	Digital I/O 03 Source/ Destination	0.000 to 59.999			6.030	RW	Num	DE		PT		U S
08.024	Digital Input 04 Destination	0.000 to 59.999			1.054	RW	Num	DE		PT		U S
08.025	Digital Input 05 Destination	0.000 to 59.999			1.041	RW	Num	DE		PT		U S
08.026	Digital Input 06 Destination	0.000 to 59.999			0.000	RW	Num	DE		PT		U S
08.027	Relay Output Source	0.000 to 59.999			10.001	RW	Num			PT		U S
08.028	24V Supply Output Source	0.000 to 59.999			0.000	RW	Num			PT		U S
08.029	Input Logic Polarity	Negative Logic (0) or Positive Logic (1)			Positive Logic (1)	RW	Txt					U S
08.031	Digital I/O 01 Output Select	Off (0) or On (1)			On (1)	RW	Bit					U S
08.032	Digital I/O 02 Output Select	Off (0) or On (1)			Off (0)	RW	Bit					U S
08.033	Digital I/O 03 Output Select	Off (0) or On (1)				RW	Bit					
08.040	STO Input 02 State	Off (0) or On (1)				RO	Bit	ND	NC	PT		
08.041	Keypad Run Button State	Off (0) or On (1)				RO	Bit	ND	NC	PT		
08.042	Keypad Auxiliary Button State	Off (0) or On (1)				RO	Bit	ND	NC	PT		
08.043	24V Supply Input State	Off (0) or On (1)				RO	Bit	ND	NC	PT		
08.044	Keypad Stop Button State	Off (0) or On (1)				RO	Bit	ND	NC	PT		
08.045	Relay 2 Output State	Off (0) or On (1)				RO	Bit	ND	NC	PT		
08.051	Keypad Run Button Invert/ Toggle	Not Invert (0), Invert (1) or Toggle (2)			Not Invert (0)	RW	Txt					U S
08.052	Keypad Auxiliary Button Invert/ Toggle	Not Invert (0), Invert (1) or Toggle (2)			Not Invert (0)	RW	Txt					U S
08.053	24V Supply Input Invert	Not Invert (0), Invert (1)			Not Invert (0)	RW	Txt					U S
08.055	Relay 2 Invert	Not Invert (0), Invert (1)			Not Invert (0)	RW	Txt					U S

Safety information	Product information	Mechanical installation	Electrical installation	Getting started	Basic parameters	Running the motor	Optimization	NV Media Card Operation	Building Automation	Advanced parameters	Technical data	Diagnostics	UL listing information			
08.061	Keypad Run Button Destination				0.000 to 59.999				0.000		RW	Num	DE		PT	U S
08.062	Keypad Auxiliary Button Destination				0.000 to 59.999				0.000		RW	Num	DE		PT	U S
08.063	24V Supply Input Source				0.000 to 59.999				0.000		RW	Num			PT	U S
08.065	Relay 2 Source				0.000 to 59.999				0.000		RW	Num			PT	U S
08.071	DI/O Output Enable Register 1				0000000000000000 to 1111111111111111				0000000000000000		RW	Bin			PT	U S
08.072	DI/O Input Register 1				0000000000000000 to 1111111111111111						RO	Bin			PT	
08.073	DI/O Output Register 1				0000000000000000 to 1111111111111111				0000000000000000		RW	Bin			PT	

RW	Read / Write	RO	Read only	Num	Number parameter	Bit	Bit parameter	Txt	Text string	Bin	Binary parameter	FI	Filtered
ND	No default value	NC	Not copied	PT	Protected parameter	RA	Rating dependent	US	User save	PS	Power-down save	DE	Destination

11.10 Menu 9: Programmable logic, motorized pot, binary sum and timers

Figure 11-15 Menu 9 logic diagram: Programmable logic

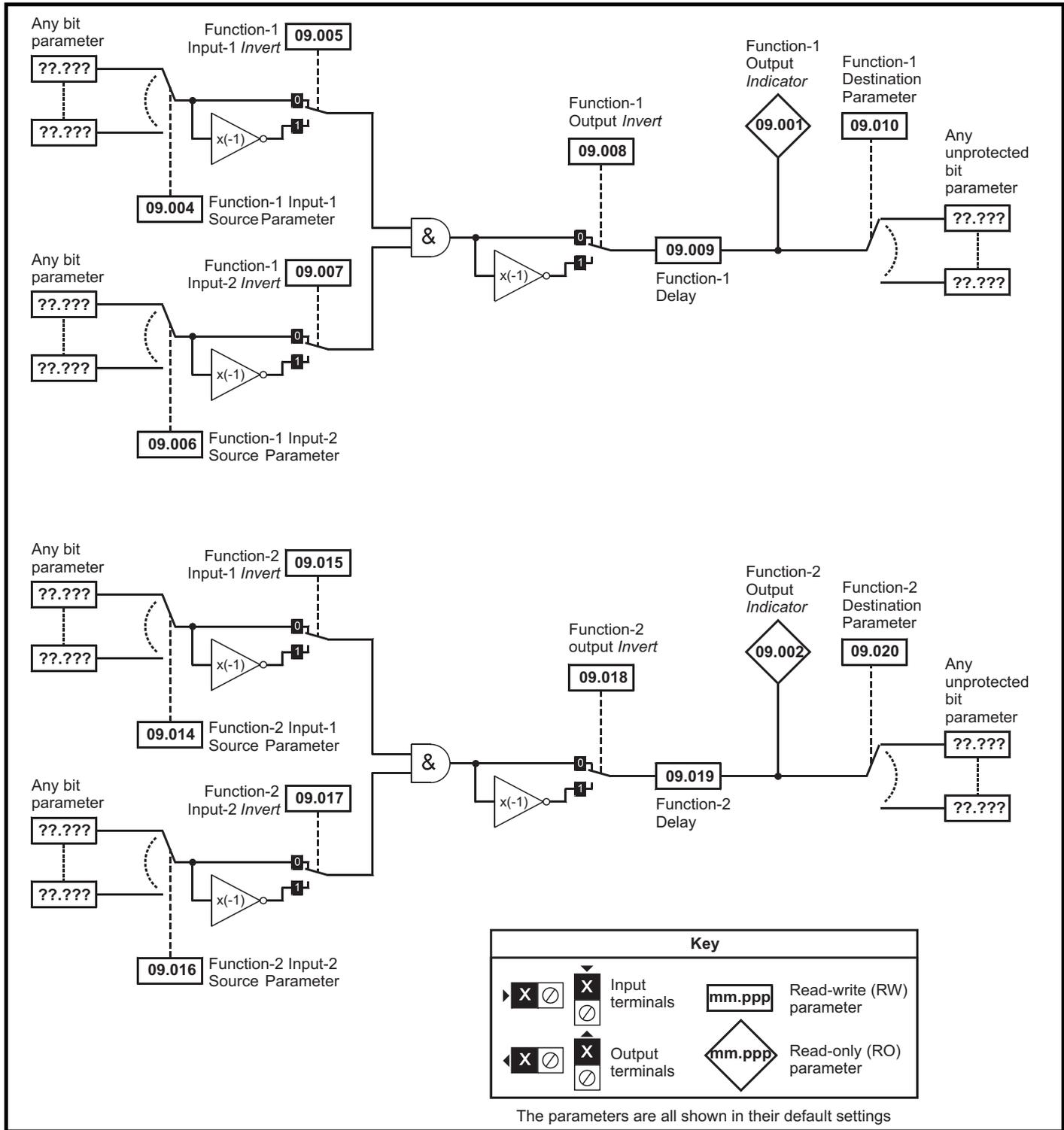


Figure 11-16 Menu 9 logic diagram: Motorized pot and binary sum

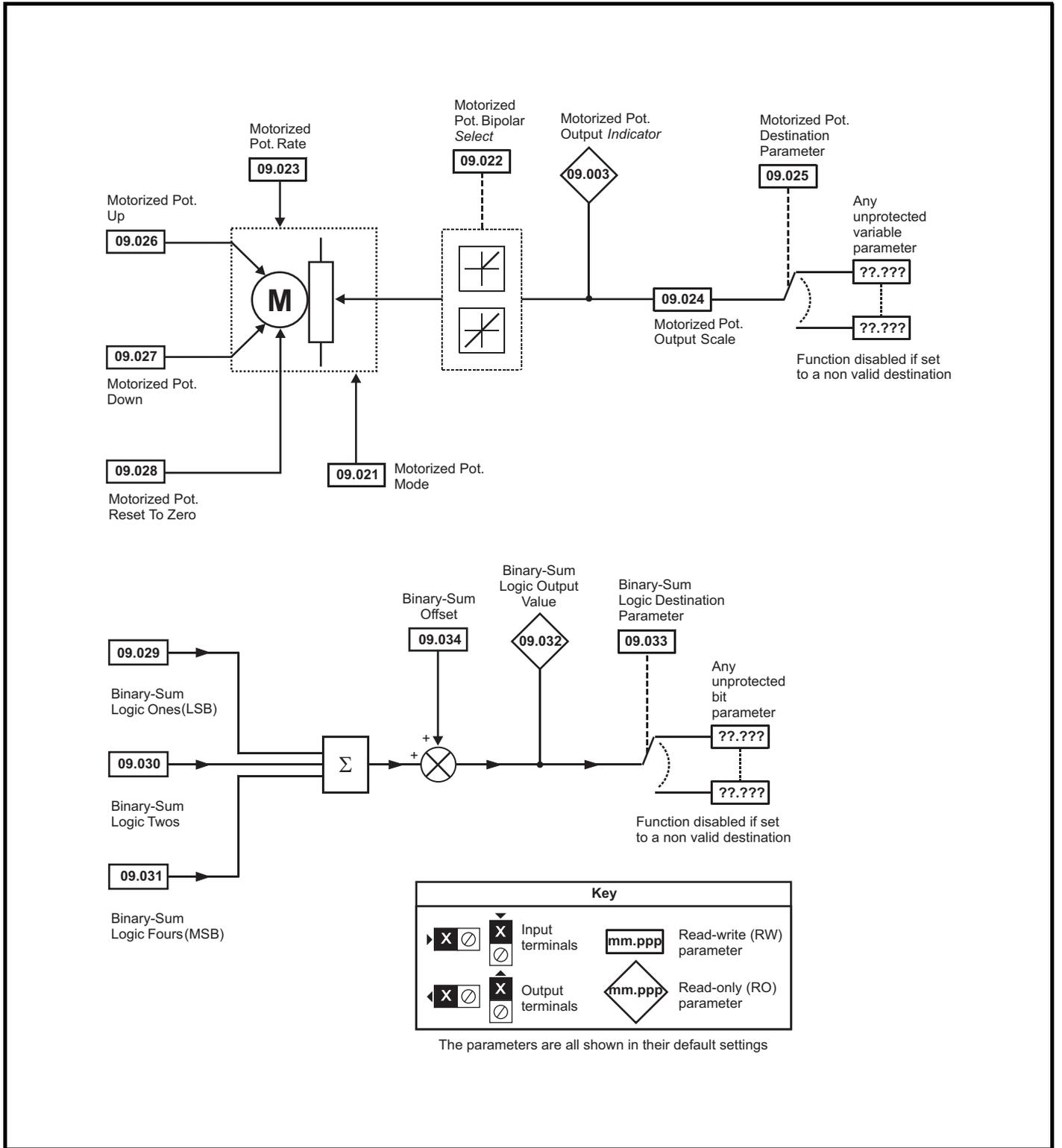


Figure 11-17 Menu 9 logic diagram: Timers

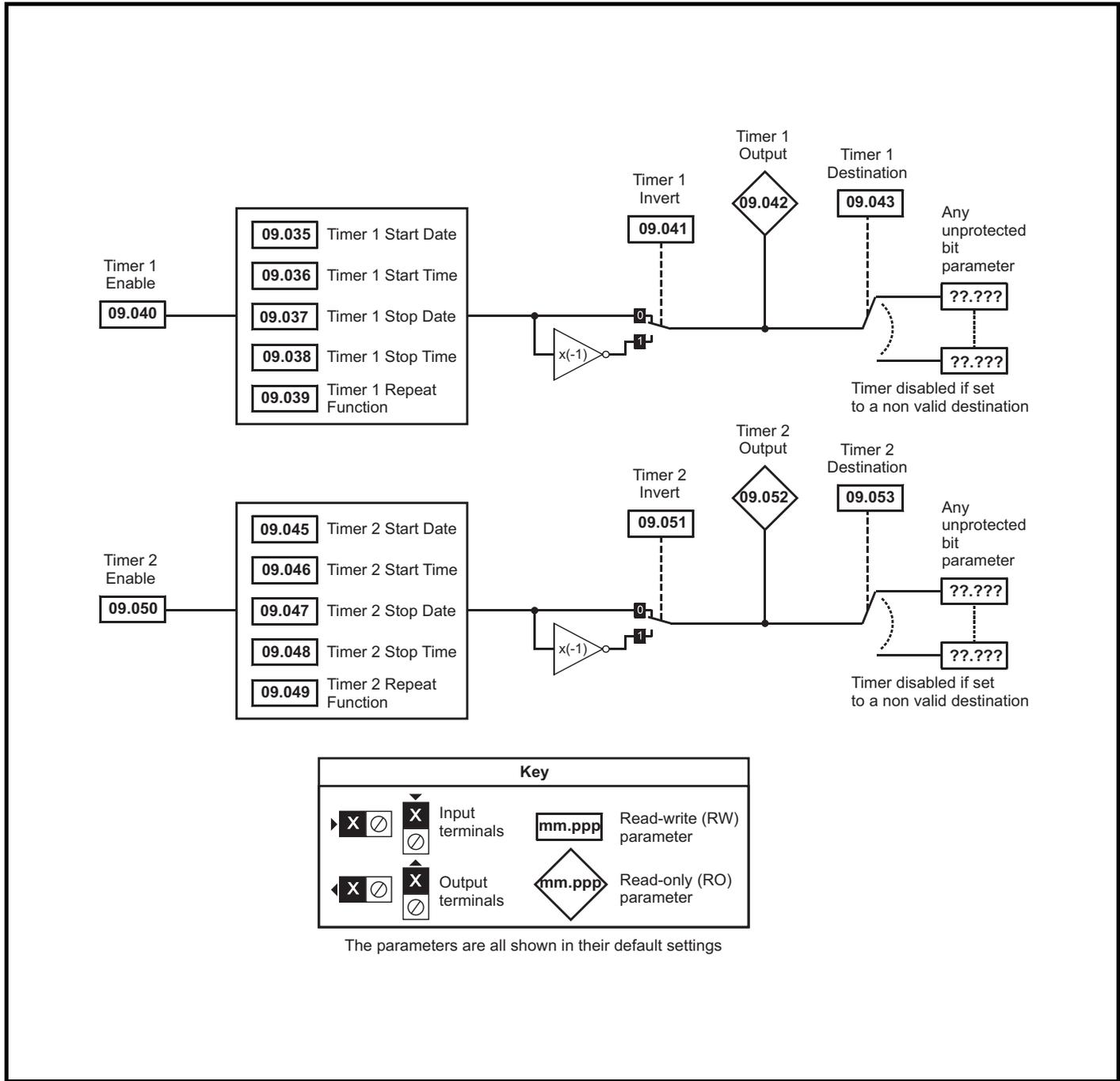
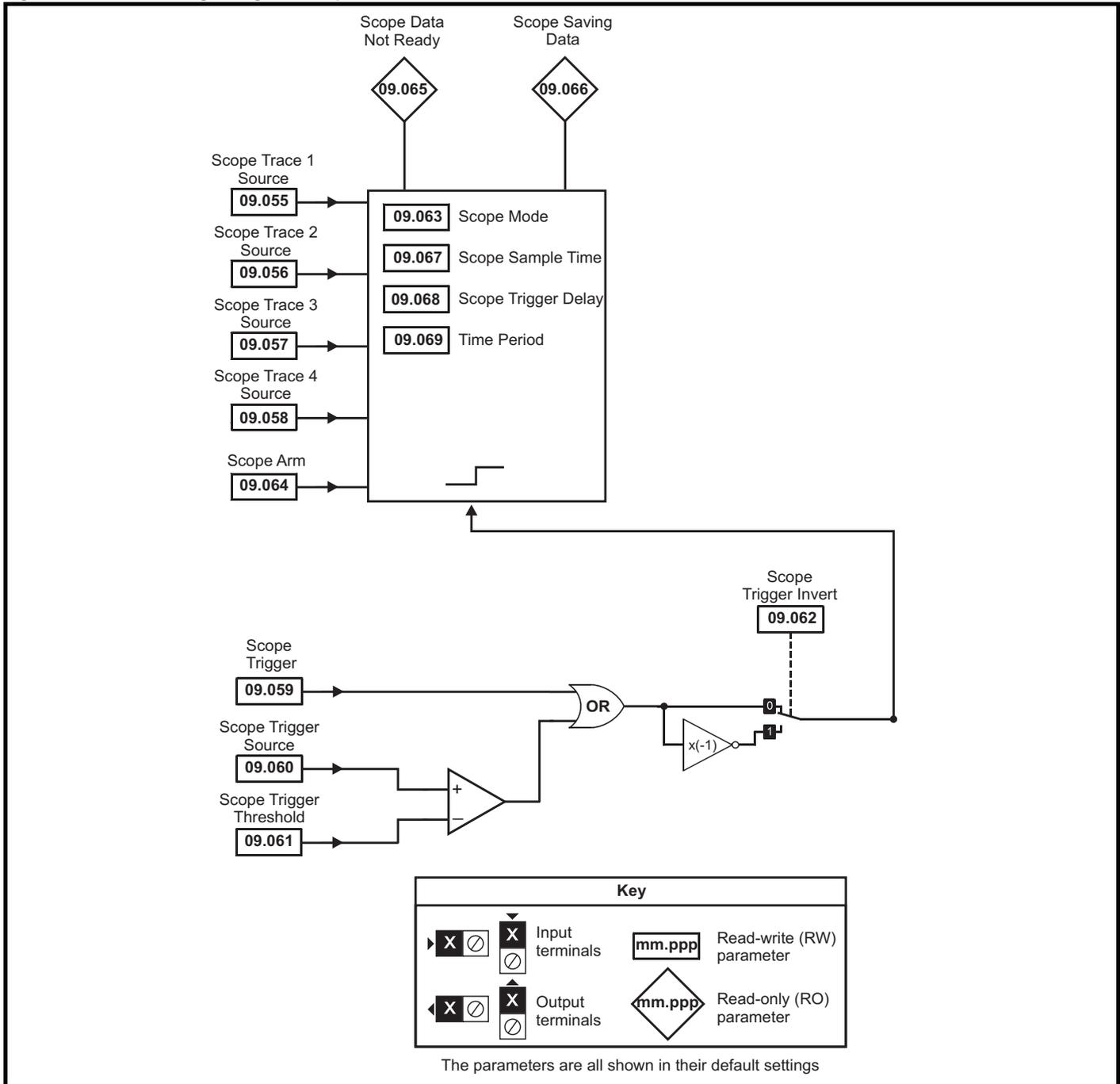


Figure 11-18 Menu 9 logic diagram: Scope function



Parameter	Range(⌘)		Default(⇒)			Type						
	OL	RFC-A / S	OL	RFC-A	RFC-S							
09.001	Logic Function 1 Output	Off (0) or On (1)				RO	Bit	ND	NC	PT		
09.002	Logic Function 2 Output	Off (0) or On (1)				RO	Bit	ND	NC	PT		
09.003	Motorized Pot Output	±100.00 %				RO	Num	ND	NC	PT	PS	
09.004	Logic Function 1 Source 1	0.000 to 59.999		0.000		RW	Num			PT	US	
09.005	Logic Function 1 Source 1 Invert	Off (0) or On (1)		Off (0)		RW	Bit				US	
09.006	Logic Function 1 Source 2	0.000 to 59.999		0.000		RW	Num			PT	US	
09.007	Logic Function 1 Source 2 Invert	Off (0) or On (1)		Off (0)		RW	Bit				US	
09.008	Logic Function 1 Output Invert	Off (0) or On (1)		Off (0)		RW	Bit				US	
09.009	Logic Function 1 Delay	±25.0 s		0.0 s		RW	Num				US	
09.010	Logic Function 1 Destination	0.000 to 59.999		0.000		RW	Num	DE		PT	US	
09.014	Logic Function 2 Source 1	0.000 to 59.999		0.000		RW	Num			PT	US	
09.015	Logic Function 2 Source 1 Invert	Off (0) or On (1)		Off (0)		RW	Bit				US	
09.016	Logic Function 2 Source 2	0.000 to 59.999		0.000		RW	Num			PT	US	
09.017	Logic Function 2 Source 2 Invert	Off (0) or On (1)		Off (0)		RW	Bit				US	
09.018	Logic Function 2 Output Invert	Off (0) or On (1)		Off (0)		RW	Bit				US	
09.019	Logic Function 2 Delay	±25.0 s		0.0 s		RW	Num				US	
09.020	Logic Function 2 Destination	0.000 to 59.999		0.000		RW	Num	DE		PT	US	
09.021	Motorized Pot Mode	0 to 4		0		RW	Num				US	
09.022	Motorized Pot Bipolar Select	Off (0) or On (1)		Off (0)		RW	Bit				US	
09.023	Motorized Pot Rate	0 to 250 s		20 s		RW	Num				US	
09.024	Motorized Pot Scaling	0.000 to 4.000		1.000		RW	Num				US	
09.025	Motorized Pot Destination	0.000 to 59.999		0.000		RW	Num	DE		PT	US	
09.026	Motorized Pot Up	Off (0) or On (1)		Off (0)		RW	Bit		NC			
09.027	Motorized Pot Down	Off (0) or On (1)		Off (0)		RW	Bit		NC			
09.028	Motorized Pot Reset	Off (0) or On (1)		Off (0)		RW	Bit		NC			
09.029	Binary Sum Ones	Off (0) or On (1)		Off (0)		RW	Bit		NC			
09.030	Binary Sum Twos	Off (0) or On (1)		Off (0)		RW	Bit		NC			
09.031	Binary Sum Fours	Off (0) or On (1)		Off (0)		RW	Bit		NC			
09.032	Binary Sum Output	0 to 255				RO	Num	ND	NC	PT		
09.033	Binary Sum Destination	0.000 to 59.999		0.000		RW	Num	DE		PT	US	
09.034	Binary Sum Offset	0 to 248		0		RW	Num				US	
09.035	Timer 1 Start Date	00-00-00 to 31-12-99		00-00-00		RW	Date				US	
09.036	Timer 1 Start Time	00:00:00 to 23:59:59		00:00:00		RW	Time				US	
09.037	Timer 1 Stop Date	00-00-00 to 31-12-99		00-00-00		RW	Date				US	
09.038	Timer 1 Stop Time	00:00:00 to 23:59:59		00:00:00		RW	Time				US	
09.039	Timer 1 Repeat Function	None (0), Hour (1), Day (2), Week (3), Month (4), Year (5), One off (6), Minute (7)		None (0)		RW	Txt				US	
09.040	Timer 1 Enable	Off (0) or On (1)		Off (0)		RW	Bit				US	
09.041	Timer 1 Invert	Off (0) or On (1)		Off (0)		RW	Bit				US	
09.042	Timer 1 Output	Off (0) or On (1)				RO	Bit	ND	NC	PT		
09.043	Timer 1 Destination	0.000 to 59.999		0.000		RW	DE			PT	US	
09.045	Timer 2 Start Date	00-00-00 to 31-12-99		00-00-00		RW	Date				US	
09.046	Timer 2 Start Time	00:00:00 to 23:59:59		00:00:00		RW	Time				US	
09.047	Timer 2 Stop Date	00-00-00 to 31-12-99		00-00-00		RW	Date				US	
09.048	Timer 2 Stop Time	00:00:00 to 23:59:59		00:00:00		RW	Time				US	
09.049	Timer 2 Repeat Function	None (0), Hour (1), Day (2), Week (3), Month (4), Year (5), One off (6), Minute (7)		None (0)		RW	Txt				US	
09.050	Timer 2 Enable	Off (0) or On (1)		Off (0)		RW	Bit				US	
09.051	Timer 2 Invert	Off (0) or On (1)		Off (0)		RW	Bit				US	
09.052	Timer 2 Output	Off (0) or On (1)				RO	Bit	ND	NC	PT		
09.053	Timer 2 Destination	0.000 to 59.999		0.000		RW	DE			PT	US	
09.055	Scope Trace 1 Source	0.000 to 59.999		0.000		RW	Num			PT	US	
09.056	Scope Trace 2 Source	0.000 to 59.999		0.000		RW	Num			PT	US	
09.057	Scope Trace 3 Source	0.000 to 59.999		0.000		RW	Num			PT	US	
09.058	Scope Trace 4 Source	0.000 to 59.999		0.000		RW	Num			PT	US	

Parameter		Range(⇅)		Default(⇄)			Type						
		OL	RFC-A / S	OL	RFC-A	RFC-S							
09.059	Scope Trigger	Off (0) or On (1)		Off (0)			RW	Bit					
09.060	Scope Trigger Source	0.000 to 59.999		0.000			RW	Num				PT	US
09.061	Scope Trigger Threshold	-2147483648 to 2147483647		0			RW	Num					US
09.062	Scope Trigger Invert	Off (0) or On (1)		Off (0)			RW	Bit					US
09.063	Scope Mode	Single (0), Normal (1), Auto (2)		Single (0)			RW	Txt					US
09.064	Scope Arm	Off (0) or On (1)		Off (0)			RW	Bit		NC			
09.065	Scope Data Not Ready	Off (0) or On (1)					RO	Bit	ND	NC	PT		
09.066	Scope Saving Data	Off (0) or On (1)					RO	Bit	ND	NC	PT		
09.067	Scope Sample Time	1 to 200		1			RW	Num					US
09.068	Scope Trigger Delay	0 to 100 %		0 %			RW	Num					US
09.069	Scope Time Period	0.00 to 200000.00 ms					RO	Num	ND	NC	PT		
09.070	Scope Auto-save Mode	Disabled (0), Overwrite (1), Keep (2)		Disabled (0)			RW	Txt					US
09.071	Scope Auto-save File Number	0 to 99		0			RO	Num					PS
09.072	Scope Auto-save Reset	Off (0) or On (1)		Off (0)			RW	Bit					
09.073	Scope Auto-save Status	Disabled (0), Active (1), Stopped (2), Failed (3)		Disabled (0)			RO	Txt					PS

RW	Read / Write	RO	Read only	Num	Number parameter	Bit	Bit parameter	Txt	Text string	Bin	Binary parameter	FI	Filtered
ND	No default value	NC	Not copied	PT	Protected parameter	RA	Rating dependent	US	User save	PS	Power-down save	DE	Destination
IP	IP address	Mac	Mac address	Date	Date parameter	Time	Time parameter	SMP	Slot,menu,parameter	Chr	Character parameter	Ver	Version number

11.11 Menu 10: Status and trips

Parameter	Range(⇅)		Default(⇒)			Type					
	OL	RFC-A / S	OL	RFC-A	RFC-S						
10.001	Drive Heathy	Off (0) or On (1)				RO	Bit	ND	NC	PT	
10.002	Drive Active	Off (0) or On (1)				RO	Bit	ND	NC	PT	
10.003	Zero Speed	Off (0) or On (1)				RO	Bit	ND	NC	PT	
10.004	Running At Or Below Minimum Speed	Off (0) or On (1)				RO	Bit	ND	NC	PT	
10.005	Below Set Speed	Off (0) or On (1)				RO	Bit	ND	NC	PT	
10.006	At Speed	Off (0) or On (1)				RO	Bit	ND	NC	PT	
10.007	Above Set Speed	Off (0) or On (1)				RO	Bit	ND	NC	PT	
10.008	Rated Load Reached	Off (0) or On (1)				RO	Bit	ND	NC	PT	
10.009	Current Limit Active	Off (0) or On (1)				RO	Bit	ND	NC	PT	
10.010	Regenerating	Off (0) or On (1)				RO	Bit	ND	NC	PT	
10.011	Braking IGBT Active	Off (0) or On (1)				RO	Bit	ND	NC	PT	
10.012	Braking Resistor Alarm	Off (0) or On (1)				RO	Bit	ND	NC	PT	
10.013	Reverse Direction Commanded	Off (0) or On (1)				RO	Bit	ND	NC	PT	
10.014	Reverse Direction Running	Off (0) or On (1)				RO	Bit	ND	NC	PT	
10.015	Supply Loss	Off (0) or On (1)				RO	Bit	ND	NC	PT	
10.016	Under Voltage Active	Off (0) or On (1)				RO	Bit	ND	NC	PT	
10.017	Motor Overload Alarm	Off (0) or On (1)				RO	Bit	ND	NC	PT	
10.018	Drive Over-temperature Alarm	Off (0) or On (1)				RO	Bit	ND	NC	PT	
10.019	Drive Warning	Off (0) or On (1)				RO	Bit	ND	NC	PT	
10.020	Trip 0	0 to 255				RO	Txt	ND	NC	PT	PS
10.021	Trip 1	0 to 255				RO	Txt	ND	NC	PT	PS
10.022	Trip 2	0 to 255				RO	Txt	ND	NC	PT	PS
10.023	Trip 3	0 to 255				RO	Txt	ND	NC	PT	PS
10.024	Trip 4	0 to 255				RO	Txt	ND	NC	PT	PS
10.025	Trip 5	0 to 255				RO	Txt	ND	NC	PT	PS
10.026	Trip 6	0 to 255				RO	Txt	ND	NC	PT	PS
10.027	Trip 7	0 to 255				RO	Txt	ND	NC	PT	PS
10.028	Trip 8	0 to 255				RO	Txt	ND	NC	PT	PS
10.029	Trip 9	0 to 255				RO	Txt	ND	NC	PT	PS
10.030	Braking Resistor Rated Power	0.000 to 99999.999 kW			0.000 kW	RW	Num				US
10.031	Braking Resistor Thermal Time Constant	0.000 to 1500.000 s			0.000 s	RW	Num				US
10.032	External Trip	Off (0) or On (1)			Off (0)	RW	Bit		NC		
10.033	Drive Reset	Off (0) or On (1)			Off (0)	RW	Bit		NC		
10.034	Number Of Auto-reset Attempts	None (0), 1 (1), 2 (2), 3 (3), 4 (4), 5 (5), Infinite (6)			5 (5)	RW	Txt				US
10.035	Auto-reset Delay	0.0 to 600.0 s			5.0 s	RW	Num				US
10.036	Auto-reset Hold Drive Heathy	Off (0) or On (1)			Off (0)	RW	Bit				US
10.037	Action On Trip Detection	00000 to 11111			00000	RW	Bin				US
10.038	User Trip	0 to 255				RW	Num	ND	NC		
10.039	Braking Resistor Thermal Accumulator	0.0 to 100.0 %				RO	Num	ND	NC	PT	
10.040	Status Word	0000000000000000 to 1111111111111111				RO	Bin	ND	NC	PT	
10.041	Trip 0 Date	00-00-00 to 31-12-99				RO	Date	ND	NC	PT	PS
10.042	Trip 0 Time	00:00:00 to 23:59:59				RO	Time	ND	NC	PT	PS
10.043	Trip 1 Date	00-00-00 to 31-12-99				RO	Date	ND	NC	PT	PS
10.044	Trip 1 Time	00:00:00 to 23:59:59				RO	Time	ND	NC	PT	PS
10.045	Trip 2 Date	00-00-00 to 31-12-99				RO	Date	ND	NC	PT	PS
10.046	Trip 2 Time	00:00:00 to 23:59:59				RO	Time	ND	NC	PT	PS
10.047	Trip 3 Date	00-00-00 to 31-12-99				RO	Date	ND	NC	PT	PS
10.048	Trip 3 Time	00:00:00 to 23:59:59				RO	Time	ND	NC	PT	PS
10.049	Trip 4 Date	00-00-00 to 31-12-99				RO	Date	ND	NC	PT	PS
10.050	Trip 4 Time	00:00:00 to 23:59:59				RO	Time	ND	NC	PT	PS
10.051	Trip 5 Date	00-00-00 to 31-12-99				RO	Date	ND	NC	PT	PS
10.052	Trip 5 Time	00:00:00 to 23:59:59				RO	Time	ND	NC	PT	PS
10.053	Trip 6 Date	00-00-00 to 31-12-99				RO	Date	ND	NC	PT	PS

Safety information	Product information	Mechanical installation	Electrical installation	Getting started	Basic parameters	Running the motor	Optimization	NV Media Card Operation	Building Automation	Advanced parameters	Technical data	Diagnostics	UL listing information
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Parameter	Range(⌘)		Default(⇄)			Type						
	OL	RFC-A / S	OL	RFC-A	RFC-S	RO	Time	ND	NC	PT	PS	
10.054	Trip 6 Time	00:00:00 to 23:59:59				RO	Time	ND	NC	PT	PS	
10.055	Trip 7 Date	00-00-00 to 31-12-99				RO	Date	ND	NC	PT	PS	
10.056	Trip 7 Time	00:00:00 to 23:59:59				RO	Time	ND	NC	PT	PS	
10.057	Trip 8 Date	00-00-00 to 31-12-99				RO	Date	ND	NC	PT	PS	
10.058	Trip 8 Time	00:00:00 to 23:59:59				RO	Time	ND	NC	PT	PS	
10.059	Trip 9 Date	00-00-00 to 31-12-99				RO	Date	ND	NC	PT	PS	
10.060	Trip 9 Time	00:00:00 to 23:59:59				RO	Time	ND	NC	PT	PS	
10.061	Braking Resistor Resistance	0.00 to 10000.00 Ω			0.00 Ω	RW	Num					US
10.062	Low Load Detected Alarm	Off (0) or On (1)				RO	Bit	ND	NC	PT		
10.063	Local Keypad Battery Low	Off (0) or On (1)				RO	Bit	ND	NC	PT		
10.064	Remote Keypad Battery Low	Off (0) or On (1)				RO	Bit	ND	NC	PT		
10.065	Auto-tune Active	Off (0) or On (1)				RO	Bit	ND	NC	PT		
10.067	Fire Mode Active	Off (0) or On (1)				RO	Bit	ND	NC	PT		
10.068	Hold Drive Healthy On Under Voltage	Off (0) or On (1)			Off (0)	RW	Bit					US
10.069	Additional Status Bits	0000000000 to 1111111111				RO	Bin	ND	NC	PT		
10.070	Trip 0 Sub-trip Number	0 to 65535				RO	Num	ND	NC	PT	PS	
10.071	Trip 1 Sub-trip Number	0 to 65535				RO	Num	ND	NC	PT	PS	
10.072	Trip 2 Sub-trip Number	0 to 65535				RO	Num	ND	NC	PT	PS	
10.073	Trip 3 Sub-trip Number	0 to 65535				RO	Num	ND	NC	PT	PS	
10.074	Trip 4 Sub-trip Number	0 to 65535				RO	Num	ND	NC	PT	PS	
10.075	Trip 5 Sub-trip Number	0 to 65535				RO	Num	ND	NC	PT	PS	
10.076	Trip 6 Sub-trip Number	0 to 65535				RO	Num	ND	NC	PT	PS	
10.077	Trip 7 Sub-trip Number	0 to 65535				RO	Num	ND	NC	PT	PS	
10.078	Trip 8 Sub-trip Number	0 to 65535				RO	Num	ND	NC	PT	PS	
10.079	Trip 9 Sub-trip Number	0 to 65535				RO	Num	ND	NC	PT	PS	
10.080	Stop Motor	Off (0) or On (1)				RO	Bit	ND	NC	PT		
10.081	Phase Loss	Off (0) or On (1)				RO	Bit	ND	NC	PT		
10.101	Drive Status	Inhibit (0), Ready (1), Stop (2), Scan (3), Run (4), Supply Loss (5), Deceleration (6), dc Injection (7), Position (8), Trip (9), Active (10), Off (11), Hand (12), Auto (13), Heat (14), Under Voltage (15), Phasing (16)				RO	Txt	ND	NC	PT		
10.102	Trip Reset Source	0 to 1023				RO	Num	ND	NC	PT	PS	
10.103	Trip Time Identifier	-2147483648 to 2147483647 ms				RO	Num	ND	NC	PT		
10.104	Active Alarm	None (0), Brake Resistor (1), Motor Overload (2), Ind Overload (3), Drive Overload (4), Auto Tune (5), Limit Switch (6), Fire Mode (7), Low Load (8), Option Slot 1 (9), Option Slot 2 (10), Option Slot 3 (11), Option Slot 4 (12)				RO	Txt	ND	NC	PT		
10.105	Hand Off Auto state	Not Active (0), OFF (1), Hand (2), Auto (3)				RO	Txt	ND	NC	PT	PS	
10.106	Potential Drive Damage Conditions	0000 to 1111				RO	Bin	ND	NC	PT	PS	
10.107	Auto-tune State	Not Active (0), Resistance (1), pLs (2), Ls (3), Flux (4), Flux Repeat (5), Ld Lq No-load (6), Lq (7), Ke (8), Inertia (9)				RO	Txt	ND	NC	PT		

RW	Read / Write	RO	Read only	Num	Number parameter	Bit	Bit parameter	Txt	Text string	Bin	Binary parameter	FI	Filtered
ND	No default value	NC	Not copied	PT	Protected parameter	RA	Rating dependent	US	User save	PS	Power-down save	DE	Destination
IP	IP address	Mac	Mac address	Date	Date parameter	Time	Time parameter	SMP	Slot,menu,parameter	Chr	Character parameter	Ver	Version number

Table 11-5 Defaults for Pr 10.030, Pr 10.031 and Pr 10.061

Drive size	Pr 10.030	Pr 10.031	Pr 10.061
3	50 W	3.3 s	75 Ω
4 and 5	100 W	2.0 s	38 Ω
All other ratings and frame sizes	0.000		0.00

11.12 Menu 11: General drive set-up

Parameter	Range(⇩)		Default(⇨)			Type					
	OL	RFC-A / S	OL	RFC-A	RFC-S						
11.018	Status Mode Parameter 1	0.000 to 59.999	0.000			RW	Num			PT	US
11.019	Status Mode Parameter 2	0.000 to 59.999	0.000			RW	Num			PT	US
11.020	Reset Serial Communications	Off (0) or On (1)				RW	Bit	ND	NC		
11.021	Parameter 00.030 Scaling	0.000 to 10.000	1.000			RW	Num				US
11.022	Parameter Displayed At Power-up	0.000 to 0.080	0.001			RW	Num			PT	US
11.023	Serial Address	1 to 255	1			RW	Num				US
11.024	Serial Mode	8 2 NP (0), 8 1 NP (1), 8 1 EP (2), 8 1 OP (3), 8 2 NP M (4), 8 1 NP M (5), 8 1 EP M (6), 8 1 OP M (7), 7 2 NP (8), 7 1 NP (9), 7 1 EP (10), 7 1 OP (11), 7 2 NP M (12), 7 1 NP M (13), 7 1 EP M (14), 7 1 OP M (15)	8 2 NP (0)			RW	Txt				US
11.025	Serial Baud Rate	300 (0), 600 (1), 1200 (2), 2400 (3), 4800 (4), 9600 (5), 19200 (6), 38400 (7), 57600 (8), 76800 (9), 115200 (10)	19200 (6)			RW	Txt				US
11.026	Minimum Comms Transmit Delay	0 to 250 ms	2 ms			RW	Num				US
11.027	Silent Period	0 to 250 ms	0 ms			RW	Num				US
11.028	Drive Derivative	0 to 255				RO	Num	ND	NC	PT	
11.029	Software Version	00.00.00.00 to 99.99.99.99				RO	Num	ND	NC	PT	
11.030	User Security Code	0 to 2147483647				RW	Num	ND	NC	PT	
11.031	User Drive Mode	Open-loop (1), RFC-A (2), RFC-S (3)	Open-loop (1)	RFC-A (2)	RFC-S (3)	RW	Txt	ND	NC	PT	
11.033	Drive Rated Voltage	200 V (0), 400 V (1), 575 V (2), 690 V (3)				RO	Txt	ND	NC	PT	
11.034	Software Sub-version	0 to 99				RO	Num	ND	NC	PT	
11.035	Number Of Power Modules Test	-1 to 20	-1			RW	Num				US
11.036	NV Media Card File Previously Loaded	0 to 999	0			RO	Num		NC	PT	
11.037	NV Media Card File Number	0 to 999	0			RW	Num				
11.038	NV Media Card File Type	None (0), Open-loop (1), RFC-A (2), RFC-S (3), Regen (4), User Prog (5), Option App (6)				RO	Txt	ND	NC	PT	
11.039	NV Media Card File Version	0 to 9999				RO	Num	ND	NC	PT	
11.040	Customer Specific Parameter	0	0			RO			NC	PT	
11.041	NV Media Card Disable Booting	Off (0) On (1)	Off (0)								
11.042	Parameter Cloning	None (0), Read (1), Program (2), Auto (3), Boot (4)	None (0)			RW	Txt		NC		US
11.043	Load Defaults	None (0), Standard (1), US (2)				RW	Txt		NC		
11.044	User Security Status	Menu 0 (0), All Menus (1), Read-only Menu 0 (2), Read-only (3), Status Only (4), No Access (5)				RW	Txt	ND		PT	
11.046	Defaults Previously Loaded	0 to 2000				RO	Num	ND	NC	PT	US
11.047	Onboard User Program: Enable	Reset And Run (-1), Stop (0), Run (1)	Run (1)			RW	Txt				US
11.048	Onboard User Program: Status	Stopped (0), Running (1), Exception (2), No Program (3)				RO	Num	ND	NC	PT	
11.049	Onboard User Program: Programming Events	0 to 65535				RO	Num	ND	NC	PT	
11.050	Onboard User Program: Freewheeling Tasks Per Second	0 to 65535				RO	Num	ND	NC	PT	
11.051	Onboard User Program: Clock Task Time Used	0.0 to 100.0 %				RO	Num	ND	NC	PT	
11.052	Serial Number LS	000000000 to 999999999				RO	Num	ND	NC	PT	
11.053	Serial Number MS	0 to 999999999				RO	Num	ND	NC	PT	
11.054	Drive Date Code	0 to 65535				RO	Num	ND	NC	PT	
11.055	Onboard User Program: Clock Task Scheduled Interval	0 to 262140 ms				RO	Num	ND	NC	PT	

Parameter		Range(⇄)		Default(⇄)			Type						
		OL	RFC-A / S	OL	RFC-A	RFC-S							
11.056	Option Slot Identifiers	1234 (0), 1243 (1), 1324 (2), 1342 (3), 1423 (4), 1432 (5), 4123 (6), 3124 (7), 4132 (8), 2134 (9), 3142 (10), 2143 (11), 3412 (12), 4312 (13), 2413 (14), 4213 (15), 2314 (16), 3214 (17), 2341 (18), 2431 (19), 3241 (20), 3421 (21), 4231 (22), 4321 (23)		1234 (0)			RW	Txt				PT	
11.059	Minimum No-overload Current	0.000 to 99999.999 A					RO	Num	ND	NC	PT		
11.060	Maximum Rated Current	0.000 to 99999.999 A					RO	Num	ND	NC	PT		
11.061	Full Scale Current Kc	0.000 to 99999.999 A					RO	Num	ND	NC	PT		
11.062	Power Board Software Version Number	0.00 to 99.99					RO	Num	ND	NC	PT		
11.063	Product Type	0 to 255					RO	Num	ND	NC	PT		
11.064	Product Identifier Characters	H300 (1295396912) to (2147483647)		H300			RO	Chr	ND	NC	PT		
11.065	Drive Rating And Configuration	00000000 to 999999999					RO	Num	ND	NC	PT		
11.066	Power Stage Identifier	0 to 255					RO	Num	ND	NC	PT		
11.067	Control Board Identifier	0.000 to 65.535					RO	Num	ND	NC	PT		
11.068	Internal I/O Identifier	0 to 255					RO	Num	ND	NC	PT		
11.069	Position Feedback Interface Identifier	0 to 255					RO	Num	ND	NC	PT		
11.070	Core Parameter Database Version	0.00 to 99.99					RO	Num	ND	NC	PT		
11.071	Number Of Power Modules Detected	0 to 20					RO	Num	ND	NC	PT	US	
11.072	NV Media Card Create Special File	0 to 1		0			RW	Num		NC			
11.073	NV Media Card Size	None (0), SMART Card (1), SD Card (2)					RO	Num	ND	NC	PT		
11.075	NV Media Card Read-only Flag	Off (0) or On (1)					RO	Bit	ND	NC	PT		
11.076	NV Media Card Warning Suppression Flag	Off (0) or On (1)					RO	Bit	ND	NC	PT		
11.077	NV Media Card File Required Version	0 to 9999					RW	Num	ND	NC	PT		
11.078	NV Media Card Action Status	None (0), Active (1), Card Slot 1 (2), Card Slot 2 (3), Card Slot 3 (4), Card Slot 4 (5), Card Product (6), Card User Prog (7), Card Busy (8), Card Data Exists (9), Card Option (10), Card Read Only (11), Card Error (12), Card No Data (13), Card Full (14), Card File Error (15), Card Rating (16), Card File Data (17), Card Derivative (18)					RO	Txt	ND	NC	PT		
11.079	Drive Name Characters 1-4	-2147483648 to 2147483647		0			RW	Chr			PT	US	
11.080	Drive Name Characters 5-8	-2147483648 to 2147483647		0			RW	Chr			PT	US	
11.081	Drive Name Characters 9-12	-2147483648 to 2147483647		0			RW	Chr			PT	US	
11.082	Drive Name Characters 13-16	-2147483648 to 2147483647		0			RW	Chr			PT	US	
11.084	Drive Mode	Open-loop (1), RFC-A (2), RFC-S (3)					RO	Txt	ND	NC	PT	US	
11.085	Security Status	None (0), Read-only (1), Status-only (2), No Access (3)					RO	Txt	ND	NC	PT	PS	
11.086	Menu Access Status	Menu 0 (0) or All Menus (1)					RO	Txt	ND	NC	PT	PS	
11.090	Keypad Port Serial Address	1 to 16		1			RW	Num				US	
11.091	Product Identifier Characters 1	-2147483648 to 2147483647					RO	Chr	ND	NC	PT		
11.092	Product Identifier Characters 2	-2147483648 to 2147483647					RO	Chr	ND	NC	PT		
11.093	Product Identifier Characters 3	-2147483648 to 2147483647					RO	Chr	ND	NC	PT		
11.095	Number Of Rectifiers Detected	0 to 9					RO	Num	ND	NC	PT		
11.096	Number Of Rectifiers Expected	0 to 9		0			RW	Num				US	

RW	Read / Write	RO	Read only	Num	Number parameter	Bit	Bit parameter	Txt	Text string	Bin	Binary parameter	FI	Filtered
ND	No default value	NC	Not copied	PT	Protected parameter	RA	Rating dependent	US	User save	PS	Power-down save	DE	Destination
IP	IP address	Mac	Mac address	Date	Date parameter	Time	Time parameter	SMP	Slot,menu,parameter	Chr	Character parameter	Ver	Version number

11.13 Menu 12: Threshold detectors and variable selectors

Figure 11-19 Menu 12 logic diagram

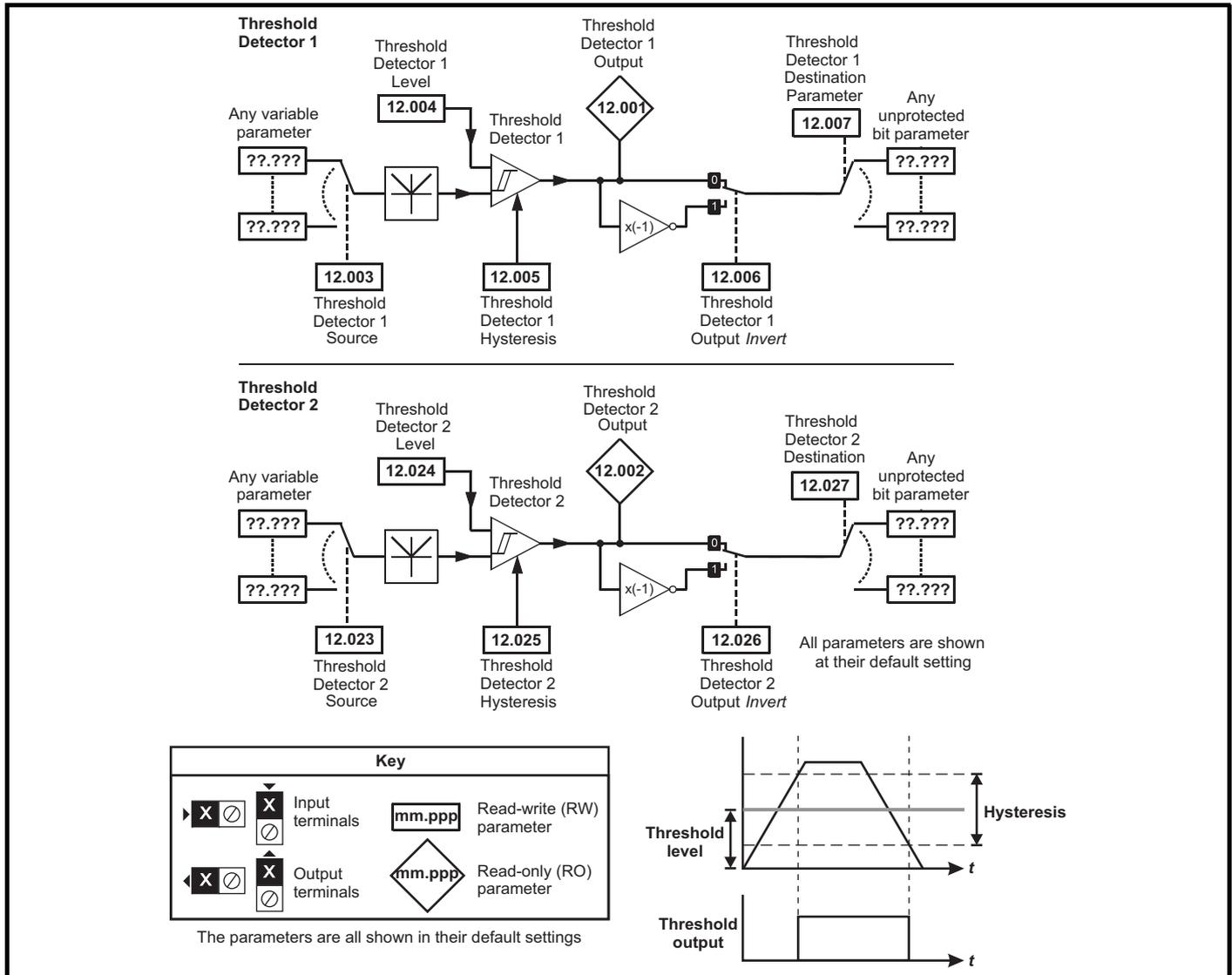
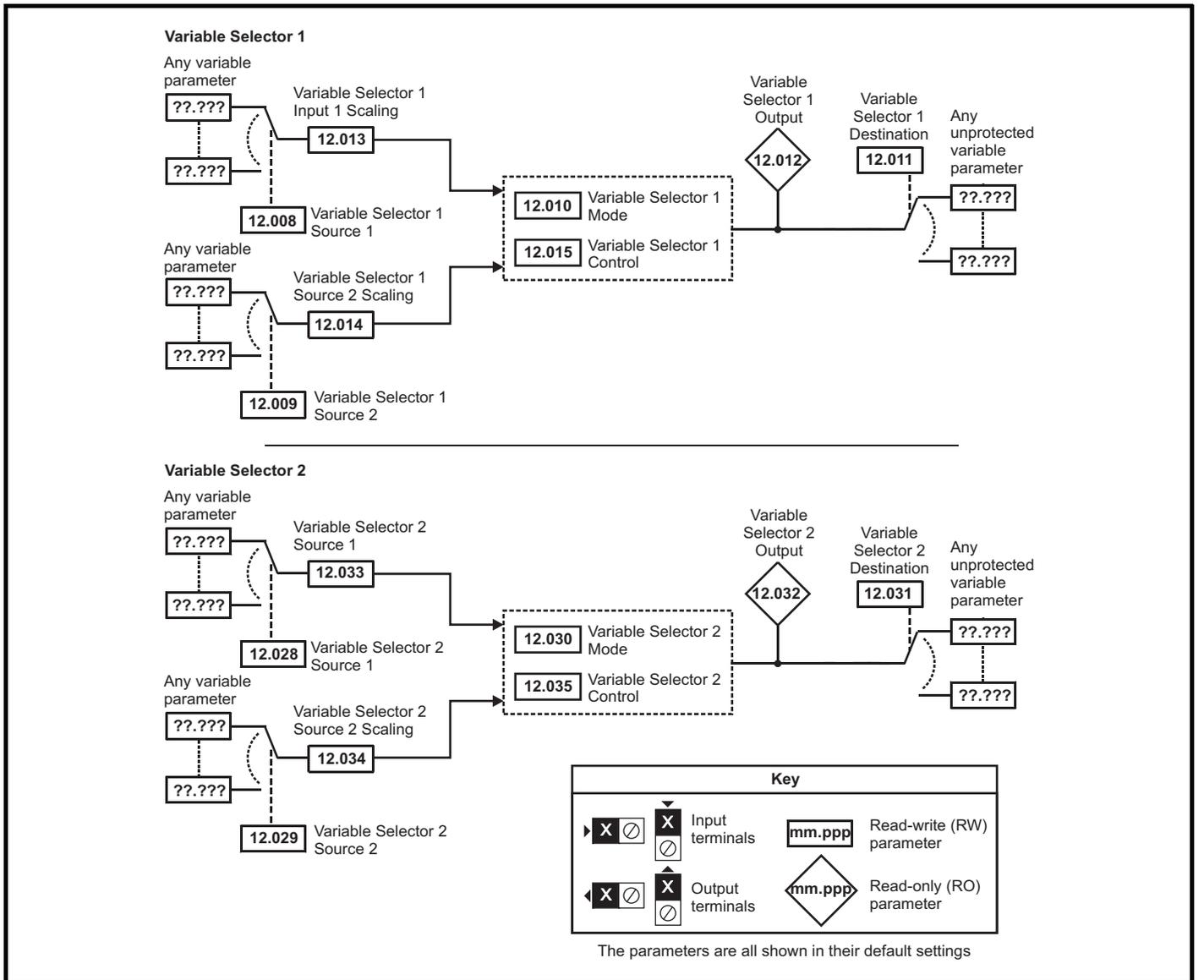


Figure 11-20 Menu 12 logic diagram (continued)

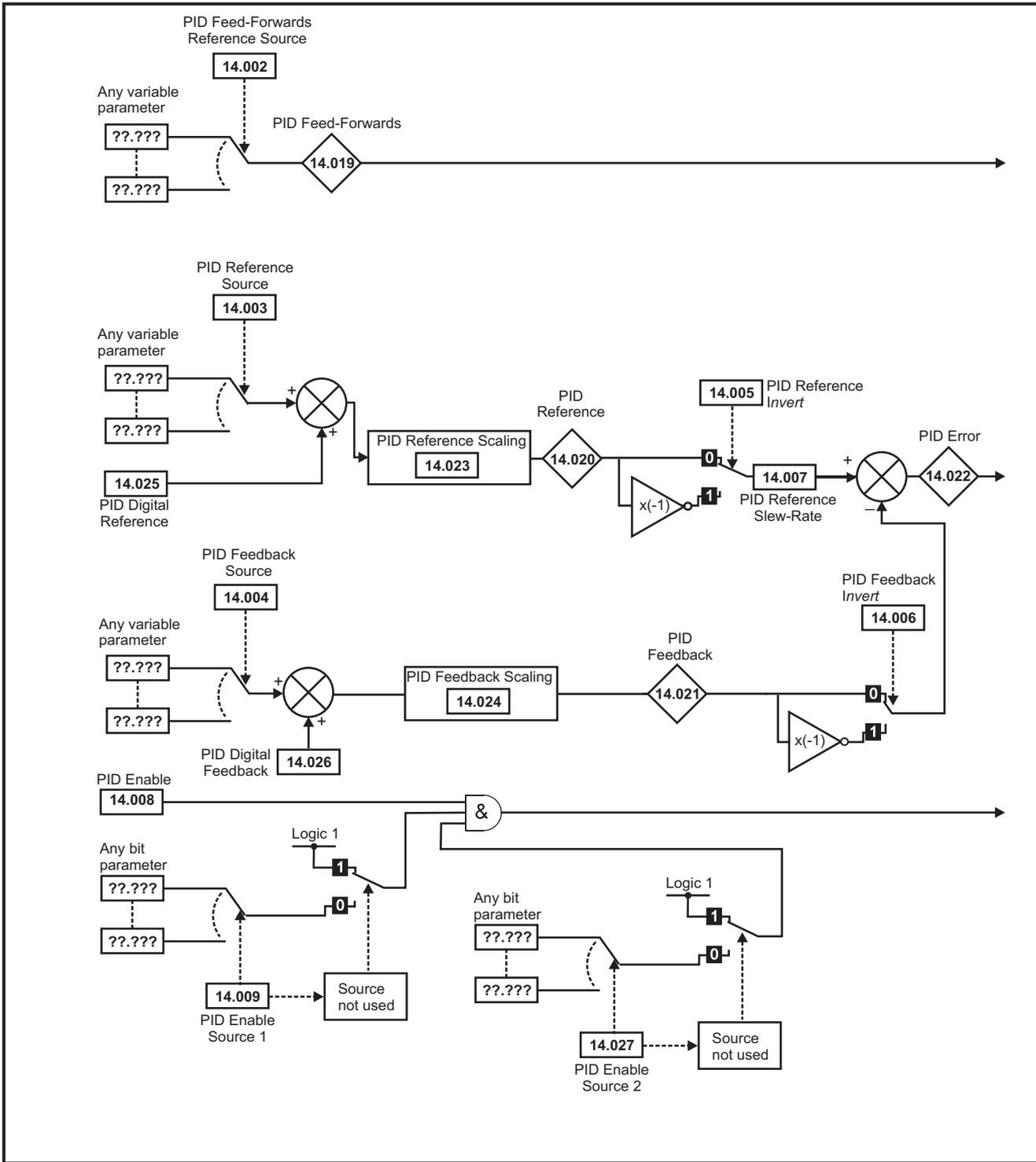


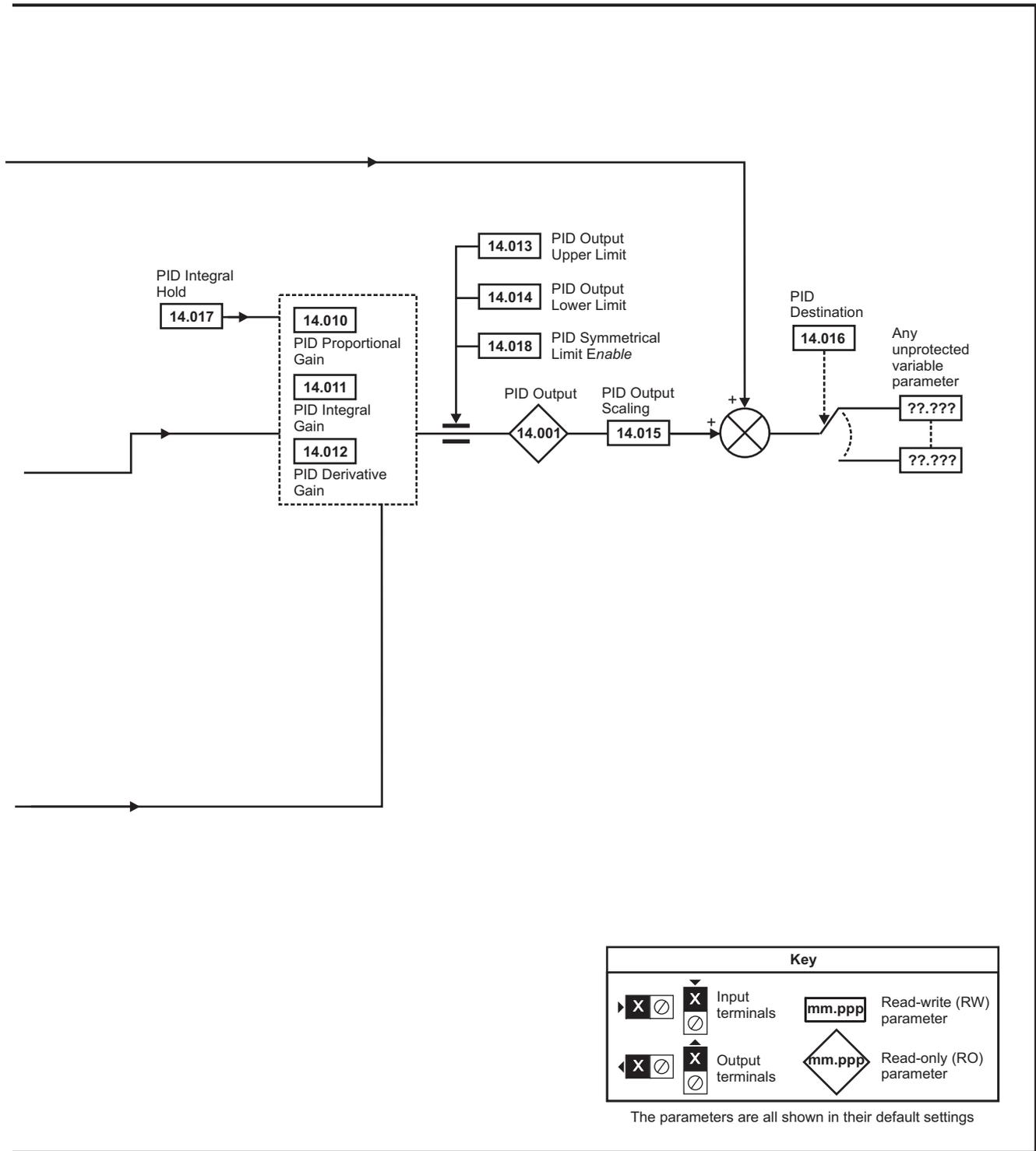
Parameter	Range(†)		Default(⇔)			Type						
	OL	RFC- A / S	OL	RFC-A	RFC-S							
12.001	Threshold Detector 1 Output	Off (0) or On (1)					RO	Bit	ND	NC	PT	
12.002	Threshold Detector 2 Output	Off (0) or On (1)					RO	Bit	ND	NC	PT	
12.003	Threshold Detector 1 Source	0.000 to 59.999		0.000			RW	Num			PT	US
12.004	Threshold Detector 1 Level	0.00 to 100.00 %		0.00 %			RW	Num				US
12.005	Threshold Detector 1 Hysteresis	0.00 to 25.00 %		0.00 %			RW	Num				US
12.006	Threshold Detector 1 Output Invert	Off (0) or On (1)		Off (0)			RW	Bit				US
12.007	Threshold Detector 1 Destination	0.000 to 59.999		0.000			RW	Num	DE		PT	US
12.008	Variable Selector 1 Source 1						RW	Num			PT	US
12.009	Variable Selector 1 Source 2						RW	Num			PT	US
12.010	Variable Selector 1 Mode	Input 1 (0), Input 2 (1), Add (2), Subtract (3), Multiply (4), Divide (5), Time Const (6), Ramp (7), Modulus (8), Powers (9), Sectional (10)		Input 1 (0)			RW	Txt				US
12.011	Variable Selector 1 Destination	0.000 to 59.999		0.000			RW	Num	DE		PT	US
12.012	Variable Selector 1 Output	±100.00 %					RO	Num	ND	NC	PT	
12.013	Variable Selector 1 Source 1 Scaling	±4.000		1.000			RW	Num				US
12.014	Variable Selector 1 Source 2 Scaling	±4.000		1.000			RW	Num				US
12.015	Variable Selector 1 Control	0.00 to 100.00		0.00			RW	Num				US
12.016	Variable Selector 1 Enable	Off (0) or On (1)		On (1)			RW	Bit				US
12.023	Threshold Detector 2 Source	0.000 to 59.999		0.000			RW	Num			PT	US
12.024	Threshold Detector 2 Level	0.00 to 100.00 %		0.00 %			RW	Num				US
12.025	Threshold Detector 2 Hysteresis	0.00 to 25.00 %		0.00 %			RW	Num				US
12.026	Threshold Detector 2 Output Invert	Off (0) or On (1)		Off (0)			RW	Bit				US
12.027	Threshold Detector 2 Destination	0.000 to 59.999		0.000			RW	Num	DE		PT	US
12.028	Variable Selector 2 Source 1	0.000 to 59.999		0.000			RW	Num			PT	US
12.029	Variable Selector 2 Source 2	0.000 to 59.999		0.000			RW	Num			PT	US
12.030	Variable Selector 2 Mode	Input 1 (0), Input 2 (1), Add (2), Subtract (3), Multiply (4), Divide (5), Time Const (6), Ramp (7), Modulus (8), Powers (9), Sectional (10)		Input 1 (0)			RW	Txt				US
12.031	Variable Selector 2 Destination	0.000 to 59.999		0.000			RW	Num	DE		PT	US
12.032	Variable Selector 2 Output	±100.00 %					RO	Num	ND	NC	PT	
12.033	Variable Selector 2 Source 1 Scaling	±4.000		1.000			RW	Num				US
12.034	Variable Selector 2 Source 2 Scaling	±4.000		1.000			RW	Num				US
12.035	Variable Selector 2 Control	0.00 to 100.00		0.00			RW	Num				US
12.036	Variable Selector 2 Enable	Off (0) or On (1)		On (1)			RW	Bit				US

RW	Read / Write	RO	Read only	Num	Number parameter	Bit	Bit parameter	Txt	Text string	Bin	Binary parameter	FI	Filtered
ND	No default value	NC	Not copied	PT	Protected parameter	RA	Rating dependent	US	User save	PS	Power-down save	DE	Destination

11.14 Menu 14: User PID controller

Figure 11-21 Menu 14 Logic diagram





Key	
	Input terminals
	Output terminals
	Read-write (RW) parameter
	Read-only (RO) parameter

The parameters are all shown in their default settings

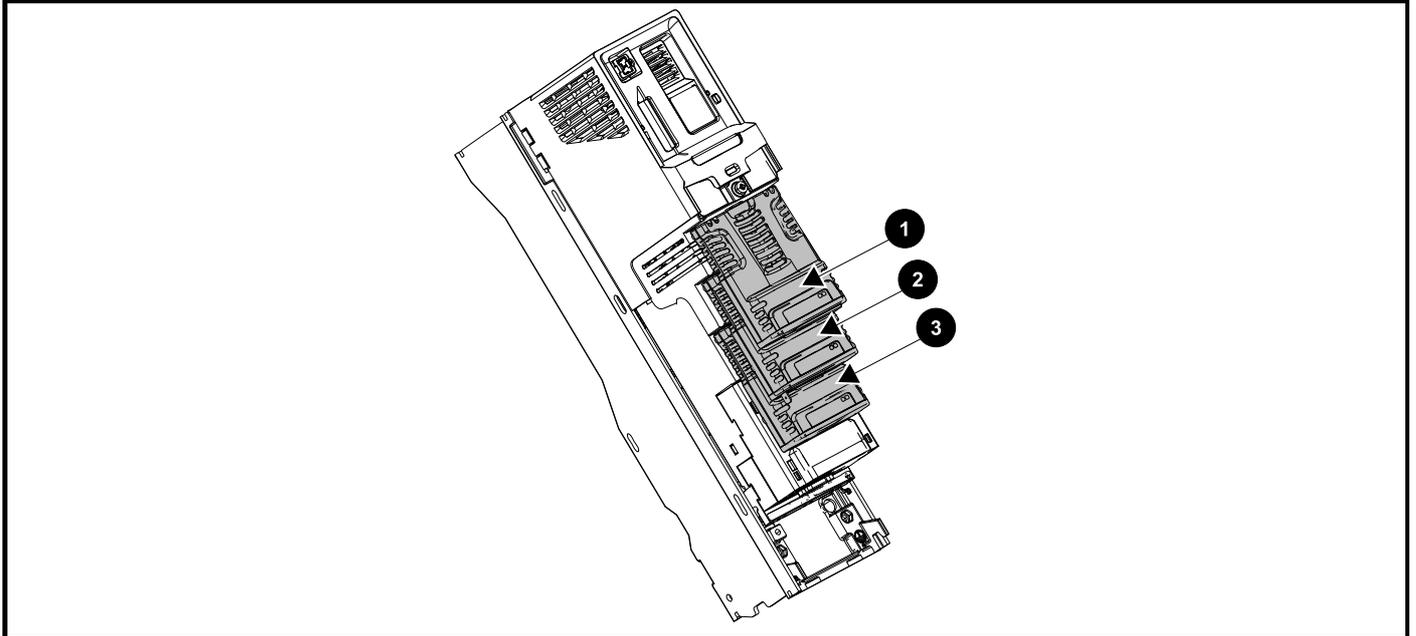
Parameter		Range(⇕)		Default(⇒)			Type					
		Open-Loop	RFC-A / S	Open-Loop	RFC-A	RFC-S						
14.001	PID1 Output	±100.00 %					RO	Num	ND	NC	PT	
14.002	PID1 Feed-forwards Reference Source	0.000 to 59.999		0.000			RW	Num			PT	US
14.003	PID1 Reference Source	0.000 to 59.999		0.000			RW	Num			PT	US
14.004	PID1 Feedback Source	0.000 to 59.999		0.000			RW	Num			PT	US
14.005	PID1 Reference Invert	Off (0) or On (1)		Off (0)			RW	Bit				US
14.006	PID1 Feedback Invert	Off (0) or On (1)		Off (0)			RW	Bit				US
14.007	PID1 Reference Slew Rate	0.0 to 3200.0 s		0.0 s			RW	Num				US
14.008	PID1 Enable	Off (0) or On (1)		Off (0)			RW	Bit				US
14.009	PID1 Enable Source 1	0.000 to 59.999		0.000			RW	Num			PT	US
14.010	PID1 Proportional Gain	0.000 to 4.000		1.000			RW	Num				US
14.011	PID1 Integral Gain	0.000 to 4.000		0.500			RW	Num				US
14.012	PID1 Differential Gain	0.000 to 4.000		0.000			RW	Num				US
14.013	PID1 Output Upper Limit	0.00 to 100.00 %		100.00 %			RW	Num				US
14.014	PID1 Output Lower Limit	±100.00 %		-100.00 %			RW	Num				US
14.015	PID1 Output Scaling	0.000 to 4.000		1.000			RW	Num				US
14.016	PID1 Destination	0.000 to 59.999		0.000			RW	Num	DE		PT	US
14.017	PID1 Integral Hold	Off (0) or On (1)		Off (0)			RW	Bit				US
14.018	PID1 Symmetrical Limit Enable	Off (0) or On (1)		Off (0)			RW	Bit				US
14.019	PID1 Feed-forwards Reference	±100.00 %					RO	Num	ND	NC	PT	
14.020	PID1 Reference	±100.00 %					RO	Num	ND	NC	PT	
14.021	PID1 Feedback	±100.00 %					RO	Num	ND	NC	PT	
14.022	PID1 Error	±100.00 %					RO	Num	ND	NC	PT	
14.023	PID1 Reference Scaling	0.000 to 4.000		1.000			RW	Num				US
14.024	PID1 Feedback Scaling	0.000 to 4.000		1.000			RW	Num				US
14.025	PID1 Digital Reference	±100.00 %		0.00 %			RW	Num				US
14.026	PID1 Digital Feedback	±100.00 %		0.00 %			RW	Num				US
14.027	PID1 Enable Source 2	0.000 to 59.999		0.000			RW	Num			PT	US
14.028	PID1 Pre-sleep Boost Level	0.00 to 100.00 %		0.00 %			RW	Num				US
14.029	PID1 Maximum Boost Time	0.0 to 250.0 s		0.0 s			RW	Num				US
14.030	PID1 Pre-sleep Boost Level Enable	Off (0) or On (1)					RO	Bit	ND	NC	PT	
14.031	PID2 Output	±100.00 %					RO	Num	ND	NC	PT	
14.032	PID2 Feed-forwards Reference Source	0.000 to 59.999		0.000			RW	Num			PT	US
14.033	PID2 Reference Source	0.000 to 59.999		0.000			RW	Num			PT	US
14.034	PID2 Feedback Source	0.000 to 59.999		0.000			RW	Num			PT	US
14.035	PID2 Reference Invert	Off (0) or On (1)		Off (0)			RW	Bit				US
14.036	PID2 Feedback Invert	Off (0) or On (1)		Off (0)			RW	Bit				US
14.037	PID2 Reference Slew Rate Limit	0.0 to 3200.0 s		0.0 s			RW	Num				US
14.038	PID2 Enable	Off (0) or On (1)		Off (0)			RW	Bit				US
14.039	PID2 Enable Source 1	0.000 to 59.999		0.000			RW	Num			PT	US
14.040	PID2 Proportional Gain	0.000 to 4.000		1.000			RW	Num				US
14.041	PID2 Integral Gain	0.000 to 4.000		0.500			RW	Num				US
14.042	PID2 Differential Gain	0.000 to 4.000		0.000			RW	Num				US
14.043	PID2 Output Upper Limit	0.00 to 100.00 %		100.00 %			RW	Num				US
14.044	PID2 Output Lower Limit	±100.00 %		-100.00 %			RW	Num				US
14.045	PID2 Output Scaling	0.000 to 4.000		1.000			RW	Num				US
14.046	PID2 Destination	0.000 to 59.999		0.000			RW	Num	DE		PT	US
14.047	PID2 Integral Hold	Off (0) or On (1)		Off (0)			RW	Bit				US
14.048	PID2 Symmetrical Limit Enable	Off (0) or On (1)		Off (0)			RW	Bit				US
14.049	PID2 Feed-forwards Reference	±100.00 %					RO	Num	ND	NC	PT	
14.050	PID2 Reference	±100.00 %					RO	Num	ND	NC	PT	
14.051	PID2 Feedback	±100.00 %					RO	Num	ND	NC	PT	
14.052	PID2 Error	±100.00 %					RO	Num	ND	NC	PT	
14.053	PID2 Reference Scaling	0.000 to 4.000		1.000			RW	Num				US
14.054	PID2 Feedback Scaling	0.000 to 4.000		1.000			RW	Num				US
14.055	PID2 Digital Reference	±100.00 %		0.00 %			RW	Num				US
14.056	PID2 Digital Feedback	±100.00 %		0.00 %			RW	Num				US
14.057	PID2 Enable Source 2	0.000 to 59.999		0.000			RW	Num			PT	US
14.058	PID1 Feedback Output Scaling	0.000 to 4.000		1.000			RW	Num				US

Parameter		Range(⇅)		Default(⇄)			Type						
		Open-Loop	RFC-A / S	Open-Loop	RFC-A	RFC-S							
14.059	PID1 Mode Selector	Fbk1 (0), Fbk2 (1), Fbk1 + Fbk2 (2), Min Fbk (3), Max Fbk (4), Av Fbk (5), Min Error (6), Max Error (7)		Fbk1 (0)			RW	Txt					US
14.060	PID1 Feedback Square Root Enable 1	Off (0) or On (1)		Off (0)			RW	Bit					US
14.061	PID2 Feedback Square Root Enable	Off (0) or On (1)		Off (0)			RW	Bit					US
14.062	PID1 Feedback Square Root Enable 2	Off (0) or On (1)		Off (0)			RW	Bit					US
14.070	PID1 Output With Feed-forwards	±100.00 %					RO	Num	ND	NC	PT		
14.071	PID1 Output Preset Enable	Off (0) or On (1)					RW	Bit	ND	NC			
14.072	PID1 Output Preset Level	±100.00 %		0.00 %			RW	Num					US
14.073	PID1 Digital Feed-forwards	±100.00 %		0.00 %			RW	Num					US
14.080	PID2 Output With Feed-forwards	±100.00 %					RO	Num	ND	NC	PT		
14.081	PID2 Output Preset Enable	Off (0) or On (1)					RW	Bit	ND	NC			
14.082	PID2 Output Preset Level	±100.00 %		0.00 %			RW	Num					US
14.083	PID2 Digital Feed-forwards	±100.00 %		0.00 %			RW	Num					US

RW	Read / Write	RO	Read only	Num	Number parameter	Bit	Bit parameter	Txt	Text string	Bin	Binary parameter	FI	Filtered
ND	No default value	NC	Not copied	PT	Protected parameter	RA	Rating dependent	US	User save	PS	Power-down save	DE	Destination

11.15 Menus 15, 16 and 17: Option module set-up

Figure 11-22 Location of option module slots and their corresponding menu numbers



1. Solutions Module Slot 1 - Menu 15
2. Solutions Module Slot 2 - Menu 16
3. Solutions Module Slot 3 - Menu 17

11.15.1 Parameters common to all categories

Parameter	Range(⇅)	Default(⇒)	Type					
mm.001	Module ID	0 to 65535	RO	Num	ND	NC	PT	
mm.002	Software Version	00.00.00.00 to 99.99.99.99	RO	Num	ND	NC	PT	
mm.003	Hardware Version	0.00 to 99.99	RO	Num	ND	NC	PT	
mm.004	Serial Number LS	0 to 99999999	RO	Num	ND	NC	PT	
mm.005	Serial Number MS		RO	Num	ND	NC	PT	
mm.006	Module Status	-2 to 3	RO	Num	ND	NC	PT	
mm.007	Module Reset	Off (0) to On (1)	RW	Bit		NC		

The option module ID indicates the type of module that is installed in the corresponding slot. See the relevant option module user guide for more information regarding the module.

Option module ID	Module	Category
0	No module installed	
209	SI-I/O	Automation (I/O Expansion)
304	SI-Applications Plus	Automation (Applications)
310	MCi210	
311	MCi200	
439	SI-BACnet IP	Fieldbus
443	SI-PROFIBUS	
447	SI-DeviceNet	
448	SI-CANopen	
433	SI-Ethernet	
432	SI-PROFINET RT	
434	SI-PROFINET V2	

11.16 Menu 18: Application menu 1

Parameter		Range(⌘)		Default(⇔)			Type						
		OL	RFC-A / S	OL	RFC-A	RFC-S							
18.001	Application Menu 1 Power-down Save Integer	-32768 to 32767		0			RW	Num					PS
18.002 to 18.010	Application Menu 1 Read-only Integer	-32768 to 32767					RO	Num	ND	NC			US
18.011 to 18.030	Application Menu 1 Read-write Integer	-32768 to 32767		0			RW	Num					US
18.031 to 18.050	Application Menu 1 Read-write bit	Off (0) or On (1)		Off (0)			RW	Bit					US
18.051 to 18.054	Application Menu 1 Power-down Save long Integer	-2147483648 to 2147483647		0			RW	Num					PS

RW	Read / Write	RO	Read only	Num	Number parameter	Bit	Bit parameter	Txt	Text string	Bin	Binary parameter	FI	Filtered
ND	No default value	NC	Not copied	PT	Protected parameter	RA	Rating dependent	US	User save	PS	Power-down save	DE	Destination

11.17 Menu 19: Application menu 2

Parameter		Range(⌘)		Default(⇔)			Type						
		OL	RFC-A / S	OL	RFC-A	RFC-S							
19.001	Application Menu 2 Power-down Save Integer	-32768 to 32767		0			RW	Num					PS
19.002 to 19.010	Application Menu 2 Read-only Integer	-32768 to 32767					RO	Num	ND	NC			US
19.011 to 19.030	Application Menu 2 Read-write Integer	-32768 to 32767		0			RW	Num					US
19.031 to 19.050	Application Menu 2 Read-write bit	Off (0) or On (1)		Off (0)			RW	Bit					US
19.051 to 19.054	Application Menu 2 Power-down Save long Integer	-2147483648 to 2147483647		0			RW	Num					PS

RW	Read / Write	RO	Read only	Num	Number parameter	Bit	Bit parameter	Txt	Text string	Bin	Binary parameter	FI	Filtered
ND	No default value	NC	Not copied	PT	Protected parameter	RA	Rating dependent	US	User save	PS	Power-down save	DE	Destination

11.18 Menu 20: Application menu 3

Parameter		Range(⌘)		Default(⇔)			Type						
		OL	RFC-A / S	OL	RFC-A	RFC-S							
20.001 to 20.020	Application Menu 3 Read-write Integer	-32768 to 32767		0			RW	Num					
20.021 to 20.040	Application Menu 3 Read-write Long Integer	-2147483648 to 2147483647		0			RW	Num					

RW	Read / Write	RO	Read only	Num	Number parameter	Bit	Bit parameter	Txt	Text string	Bin	Binary parameter	FI	Filtered
ND	No default value	NC	Not copied	PT	Protected parameter	RA	Rating dependent	US	User save	PS	Power-down save	DE	Destination

11.19 Menu 22: Additional Menu 0 set-up

Parameter	Range(⇅)			Default(⇄)			Type						
	OL	RFC-A	RFC-S	OL	RFC-A	RFC-S							
22.001	Parameter 00.001 Set-up	0.000 to 59.999		05.004	03.002		RW	Num			PT	US	
22.002	Parameter 00.002 Set-up				05.001		RW	Num			PT	US	
22.003	Parameter 00.003 Set-up				04.001		RW	Num			PT	US	
22.004	Parameter 00.004 Set-up				05.003		RW	Num			PT	US	
22.005	Parameter 00.005 Set-up				11.029		RW	Num			PT	US	
22.006	Parameter 00.006 Set-up				00.000		RW	Num			PT	US	
22.007	Parameter 00.007 Set-up				00.000		RW	Num			PT	US	
22.008	Parameter 00.008 Set-up				00.000		RW	Num			PT	US	
22.009	Parameter 00.009 Set-up				00.000		RW	Num			PT	US	
22.010	Parameter 00.010 Set-up				01.007		RW	Num			PT	US	
22.011	Parameter 00.011 Set-up				01.006		RW	Num			PT	US	
22.012	Parameter 00.012 Set-up				02.011		RW	Num			PT	US	
22.013	Parameter 00.013 Set-up				02.021		RW	Num			PT	US	
22.014	Parameter 00.014 Set-up				05.014	03.010		RW	Num			PT	US
22.015	Parameter 00.015 Set-up				05.013	03.011		RW	Num			PT	US
22.016	Parameter 00.016 Set-up				05.015	03.012		RW	Num			PT	US
22.017	Parameter 00.017 Set-up				05.011		RW	Num			PT	US	
22.018	Parameter 00.018 Set-up				05.009		RW	Num			PT	US	
22.019	Parameter 00.019 Set-up				05.008		RW	Num			PT	US	
22.020	Parameter 00.020 Set-up				05.007		RW	Num			PT	US	
22.021	Parameter 00.021 Set-up				05.006		05.033	RW	Num			PT	US
22.022	Parameter 00.022 Set-up				05.018			RW	Num			PT	US
22.023	Parameter 00.023 Set-up				06.009		00.000	RW	Num			PT	US
22.024	Parameter 00.024 Set-up				05.012			RW	Num			PT	US
22.025	Parameter 00.025 Set-up				07.007			RW	Num			PT	US
22.026	Parameter 00.026 Set-up				07.010			RW	Num			PT	US
22.027	Parameter 00.027 Set-up				07.011			RW	Num			PT	US
22.028	Parameter 00.028 Set-up				07.014			RW	Num			PT	US
22.029	Parameter 00.029 Set-up				07.058			RW	Num			PT	US
22.030	Parameter 00.030 Set-up				11.030			RW	Num			PT	US
22.031	Parameter 00.031 Set-up				11.044			RW	Num			PT	US
22.032	Parameter 00.032 Set-up				11.036			RW	Num			PT	US
22.033	Parameter 00.033 Set-up				11.042			RW	Num			PT	US
22.034	Parameter 00.034 Set-up				06.016			RW	Num			PT	US
22.035	Parameter 00.035 Set-up				06.017			RW	Num			PT	US
22.036	Parameter 00.036 Set-up				06.018			RW	Num			PT	US
22.037	Parameter 00.037 Set-up				06.019			RW	Num			PT	US
22.038	Parameter 00.038 Set-up				06.020			RW	Num			PT	US
22.039	Parameter 00.039 Set-up				00.000			RW	Num			PT	US
22.040	Parameter 00.040 Set-up				00.000		05.064	RW	Num			PT	US
22.041	Parameter 00.041 Set-up				00.000		05.071	RW	Num			PT	US
22.042	Parameter 00.042 Set-up				00.000		05.072	RW	Num			PT	US
22.043	Parameter 00.043 Set-up				00.000		05.075	RW	Num			PT	US
22.044	Parameter 00.044 Set-up				00.000		05.077	RW	Num			PT	US
22.045	Parameter 00.045 Set-up				00.000		05.078	RW	Num			PT	US
22.046	Parameter 00.046 Set-up				00.000		05.082	RW	Num			PT	US
22.047	Parameter 00.047 Set-up				00.000		05.084	RW	Num			PT	US
22.048	Parameter 00.048 Set-up				10.034			RW	Num			PT	US
22.049	Parameter 00.049 Set-up				10.035			RW	Num			PT	US
22.050	Parameter 00.050 Set-up				10.020			RW	Num			PT	US
22.051	Parameter 00.051 Set-up				10.021			RW	Num			PT	US
22.052	Parameter 00.052 Set-up				10.022			RW	Num			PT	US
22.053	Parameter 00.053 Set-up				10.023			RW	Num			PT	US
22.054	Parameter 00.054 Set-up				10.024			RW	Num			PT	US
22.055	Parameter 00.055 Set-up				10.025			RW	Num			PT	US
22.056	Parameter 00.056 Set-up				10.026			RW	Num			PT	US
22.057	Parameter 00.057 Set-up				10.027			RW	Num			PT	US

Safety information	Product information	Mechanical installation	Electrical installation	Getting started	Basic parameters	Running the motor	Optimization	NV Media Card Operation	Building Automation	Advanced parameters	Technical data	Diagnostics	UL listing information
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Parameter		Range(⇅)			Default(⇄)			Type					
		OL	RFC-A	RFC-S	OL	RFC-A	RFC-S						
22.058	Parameter 00.058 Set-up	0.000 to 59.999				10.028		RW	Num			PT	US
22.059	Parameter 00.059 Set-up					10.029		RW	Num			PT	US
22.060	Parameter 00.060 Set-up					10.041		RW	Num			PT	US
22.061	Parameter 00.061 Set-up					10.042		RW	Num			PT	US
22.062	Parameter 00.062 Set-up					10.043		RW	Num			PT	US
22.063	Parameter 00.063 Set-up					10.044		RW	Num			PT	US
22.064	Parameter 00.064 Set-up					10.045		RW	Num			PT	US
22.065	Parameter 00.065 Set-up					10.046		RW	Num			PT	US
22.066	Parameter 00.066 Set-up					10.047		RW	Num			PT	US
22.067	Parameter 00.067 Set-up					10.048		RW	Num			PT	US
22.068	Parameter 00.068 Set-up					10.049		RW	Num			PT	US
22.069	Parameter 00.069 Set-up					10.050		RW	Num			PT	US
22.070	Parameter 00.070 Set-up					10.051		RW	Num			PT	US
22.071	Parameter 00.071 Set-up					10.052		RW	Num			PT	US
22.072	Parameter 00.072 Set-up					10.053		RW	Num			PT	US
22.073	Parameter 00.073 Set-up					10.054		RW	Num			PT	US
22.074	Parameter 00.074 Set-up					10.055		RW	Num			PT	US
22.075	Parameter 00.075 Set-up					10.056		RW	Num			PT	US
22.076	Parameter 00.076 Set-up					10.057		RW	Num			PT	US
22.077	Parameter 00.077 Set-up					10.058		RW	Num			PT	US
22.078	Parameter 00.078 Set-up		10.059		RW	Num			PT	US			
22.079	Parameter 00.079 Set-up		10.060		RW	Num			PT	US			
22.080	Parameter 00.080 Set-up					00.000		RW	Num			PT	US

RW	Read / Write	RO	Read only	Num	Number parameter	Bit	Bit parameter	Txt	Text string	Bin	Binary parameter	FI	Filtered
ND	No default value	NC	Not copied	PT	Protected parameter	RA	Rating dependent	US	User save	PS	Power-down save	DE	Destination

11.20 Menu 29: Building Automation Network Setup

Parameter		Range	Default	Type						
29.001	BAN Protocol Selection	Modbus RTU (0), BACnet MSTP (1)	Modbus RTU (0)	RW	Txt					US
29.003	MS/TP Maximum Master MAC Address	0 to 127	127	RW	Num					US
29.004	Device Object Identifier	0 to 4194302	1	RW	Num					US
29.005	Communications Lost Detection Time-Out Period	5 to 60000 s	5 s	RW	Num					US
29.006	Communications Lost Action	0 to 2	0	RW	Num				PT	US
29.010	User Selectable Parameter 1	0.000 to 41.999	0.000	RW	Num				PT	US
29.011	User Selectable Parameter 2	0.000 to 41.999	0.000	RW	Num				PT	US
29.012	User Selectable Parameter 3	0.000 to 41.999	0.000	RW	Num				PT	US
29.013	User Selectable Parameter 4	0.000 to 41.999	0.000	RW	Num				PT	US
29.014	User Selectable Parameter 5	0.000 to 41.999	0.000	RW	Num				PT	US
29.015	User Selectable Parameter 6	0.000 to 41.999	0.000	RW	Num				PT	US
29.016	User Selectable Parameter 7	0.000 to 41.999	0.000	RW	Num				PT	US
29.017	User Selectable Parameter 8	0.000 to 41.999	0.000	RW	Num				PT	US
29.018	User Selectable Parameter 9	0.000 to 41.999	0.000	RW	Num				PT	US
29.019	User Selectable Parameter 10	0.000 to 41.999	0.000	RW	Num				PT	US
29.020	CRC Errors	0 to 65535		RW	Num	ND	NC	PT		
29.021	Token Interval	0.000 to 65.535 s		RO	Num	ND	NC	PT		
29.022	Received Message Counter	0 to 65535		RO	Num	ND	NC	PT		
29.023	Derivative Status	-1 to 3		RO	Num	ND	NC	PT		
29.024	Software Version	0 to 99999999		RO	Num	ND	NC	PT		

RW	Read / Write	RO	Read Only	Bit	Bit Parameter	Txt	Text String	Date	Date Parameter	Time	Time Parameter
Chr	Character Parameter	Bin	Binary Parameter	IP	IP Address	Mac	Mac Address	Ver	Version Number	SMP	Slot, menu, parameter
Num	Number Parameter	DE	Destination	ND	No Default Value	RA	Rating dependant	NC	Non- copyable	PT	Protected
Fl	Filtered	US	User Save	PS	Power-Down Save						

12 Technical data

12.1 Drive technical data

12.1.1 Power and current ratings (Derating for switching frequency and temperature)

For a full explanation of Normal Duty refer to Chapter 2.4 *Ratings* on page 17.

Table 12-1 Maximum permissible continuous output current @ 40 °C (104 °F) ambient

Model	Normal Duty								
	Nominal rating		Maximum permissible continuous output current (A) for the following switching frequencies						
	kW	hp	2 kHz	3 kHz	4 kHz	6 kHz	8 kHz	12 kHz	16 kHz
200 V									
03200066	1.1	1.5	6.6						
03200080	1.5	2.0	8.0						
03200110	2.2	3.0	11						10.2
03200127	3.0	3.0	12.7				12.1	10.2	
04200180	4.0	5.0	18						
04200250	5.5	7.5	25				24	22	
05200300	7.5	10	30				27.6	23.7	
06200500	11	15	50				42.3	24.5	
06200580	15	20	58			53	42.3	32.5	
07200750	18.5	25	75				74.3	59.7	
07200940	22	30	94				74.3	59.7	
07201170	30	40	117		114	96	74.3	59.7	
08201490	37	50	149			146	125.2	93	
08201800	45	60	180		160.2	148.8	126	93	
09202160	55	75	216			184	128	93	
09202660	75	100	266	258	218	184	128	93	
10203250	90	125	325		313	266	194	144	
10203600	110	150	360		313	266	194	144	
400 V									
03400034	1.1	2.0	3.4						
03400045	1.5	2.0	4.5						
03400062	2.2	3.0	6.2						5.0
03400077	3.0	5.0	7.7				6.2	5.0	
03400104	4.0	5.0	10.4				7.6	5.7	
03400123	5.5	7.5	12.3			10.5	7.6	5.8	
04400185	7.5	10	18.5				14.6	11.1	
04400240	11	15	24	21.8	19.2	14.6	11.2		
05400300	15	20	30		25.8	22.2	17.1	13.5	
06400380	18.5	25	38				31	24.3	
06400480	22	30	48			41	31	24.5	
06400630	30	40	63	57	48	41	31	24.5	
07400790	37	60	79				63	53.6	
07400940	45	60	94			80.6	63	53.6	
07401120	55	75	112	95.2	80.6	63	53.8		
08401550	75	100	155			132	98	77	
08401840	90	150	184		169	142	106.7	77	

Model	Normal Duty								
	Nominal rating		Maximum permissible continuous output current (A) for the following switching frequencies						
	kW	hp	2 kHz	3 kHz	4 kHz	6 kHz	8 kHz	12 kHz	16 kHz
09402210	110	150	221			192	159	108	77
09402660	132	200	266	255	231	192	160	109	77
10403200	160	250	320			285	238	173	124
10403610	200	300	361		339	285	238	173	126
11404370	225	350	437		415	336	272		
11404870	250	400	487	460	415	336	272		
11405070	280	400	507	460	415	336	272		
12404800	315	500	608	602	547	444	353		
12405660	355	550	660	660	614	488	389		
12406660	450	650	755	747	672	529	423		
12407200	500	700	865	787	709	554	441		

575 V										
05500039	2.2	3.0	3.9							
05500061	4.0	5.0	6.1							
05500100	5.5	7.5	10							
06500120	7.5	10.0	12							
06500170	11.0	15.0	17							14.8
06500220	15.0	20.0	22					20.5		15
06500270	18.5	25.0	27				26.2	20	16	
06500340	22.0	30.0	34		31	26.2	20	16.8		
06500430	30.0	40.0	43	39.6	31	26.2	20	16.8		
07500530	45	50	53			51.8	40.2	27.7	21.2	
07500730	55	60	73	71.5	51.8	40.2	27.7	21.2		
08500860	75	75	86				73.1	49.7	37.8	
08501080	90	100	108			91.8	73.1	49.7	37.8	
09501250	110	125	125				101	71	54	
09501500	110	150	150			126	100	70	54	
10502000	130	200	200	168	126	100	70	54		
11502480	185	250	248		220					
11502880	225	300	288	265	220					
11503150	250	350	315	265	220					

690 V										
07600230	18.5	25	23							21.2
07600300	22	30	30					27.9	21.2	
07600360	30	40	36						28.1	21.2
07600460	37	50	46				40.5	28.1	21.2	
07600520	45	60	52		51.5	40.6	28.1	21.2		
07600730	55	75	73	71.5	51.8	40.6	28.1	21.2		
08600860	75	100	86				72.2	49.7	37.8	
08601080	90	125	108			91.8	72.4	49.7	37.8	
09601250	110	150	125				100	71	54	
09601550	132	175	155			126	100	71	54	
10601720	160	200	172	169	126	100	71	55		

Model	Normal Duty									
	Nominal rating		Maximum permissible continuous output current (A) for the following switching frequencies							
	kW	hp	2 kHz	3 kHz	4 kHz	6 kHz	8 kHz	12 kHz	16 kHz	
10601970	185	250	197			154	114	75	55	
11602250	200	250	225		220					
11602750	250	300	275	265	220					
11603050	280	400	305	265	220					

Table 12-2 Maximum permissible continuous output current @ 40 °C (104 °F) ambient with high IP insert installed

Model	Normal Duty						
	Maximum permissible continuous output current (A) for the following switching frequencies						
	2 kHz	3 kHz	4 kHz	6 kHz	8 kHz	12 kHz	16 kHz
200 V							
03200066	6.6						
03200080	8.0						
03200110	11.0						9.7
03200127	12.3	11.9	11.1	10.0	9.0	6.4	4.7
04200180	14.5			13.5	12.2	10.5	9.6
04200250	14.5			13.5	12.2	10.5	9.6
05200300	25.5	25.2	24.9	24.3	23.7	22.5	21.6
400 V							
03400034	3.4						3.3
03400045	4.5			4.4	4.1	3.6	3.3
03400062	5.1	5.0	4.7	4.4	4.1	3.6	3.3
03400077	7.7		7.4	6.7	6.2	5.7	5.0
03400104	8.3			7.6	6.9	6.0	5.2
03400123	8.3			7.6	6.9	6.0	5.2
04400185	8.6					8.4	6.9
04400240	8.6					8.4	6.9
05400300	17.1	15.6	14.4	12.6	11.4	9.6	8.7
575 V							
05500039	3.9						
05500061	6.1						
05500100	10.0						

Table 12-3 Maximum permissible continuous output current @ 50 °C (122 °F)

Model	Normal Duty						
	Maximum permissible continuous output current (A) for the following switching frequencies						
	2 kHz	3 kHz	4 kHz	6 kHz	8 kHz	12 kHz	16 kHz
200 V							
03200066	6.6						
03200080	8.0						
03200110	11					10.5	9.1
03200127	12.7		12.6	12.2	11.7	10.5	9.1
04200180	18						
04200250	22.2						20.2
05200300	30				29.7	25.2	21.6
06200500	50				49	38	30
06200580	58			56	49	38	30.2
07200750	75					59.7	48.8
07200940	94			92.1	80	59.7	48.9
07201170	117		112	92.4	80	59.7	49.1
08201490	149			147	133	113	84
08201800	180		167	148	133	113	84
09202160	216			197	168	117	84
09202660	253	237	221	197	168	117	85
10203250	325	320	302	266	241	176	130
10203600	346	320	302	266	241	176	130
400 V							
03400034	3.4						
03400045	4.5						
03400062	6.2				5.9	5.4	4.4
03400077	7.6	7.2	6.9	6.4	5.9	5.4	4.4
03400104	10.4			9.3	8.5	6.9	5.1
03400123	11.9	11.2	10.5	9.3	8.5	6.9	5.2
04400185	18	17.5	17	16.3	15.8	12.2	9.3
04400240	18	17.5	17	16.3	15.8	12.2	9.3
05400300	25.5			23.6	20.4	15.6	12.3
06400380	38				37	28	21.4
06400480	48			43	36.5	27.4	21.4
06400630	63	58	52	43	37	28	21.4
07400790	79				73.5	57.7	49
07400940	94			86.5	73.3	58.3	49
07401120	112		109	87.4	72.8	58.3	49.3
08401550	155			146	123	93	69
08401840	184		180	146	123	93.8	69
09402210	221		213	175	144	97	69
09402660	253	237	213	176	144	98	69
10403200	320		300	259	217	154	112
10403610	343	321	300	260	217	155	112

Model	Normal Duty						
	Maximum permissible continuous output current (A) for the following switching frequencies						
	2 kHz	3 kHz	4 kHz	6 kHz	8 kHz	12 kHz	16 kHz
11404370	437	415	374	298	240		
11404870	462	415	374	298	240		
11405070	462	415	374	298	240		
575 V							
05500039	3.9						
05500061	6.1						
05500100	10						
06500120	12						
06500170	17						13.4
06500220	22					17.8	13.4
06500270	27				23.5	17.8	15
06500340	34			28.2	23.5	18	15
06500430	43.0	41.7	36.1	28	23.7	18	15
07500530	53			46.7	35.8	24.8	19
07500730	73		65	46.7	35.8	24.8	19
08500860	86			76.7	64.5	44.3	31.3
08501080	104	97.2	90.7	76.7	64.8	44.3	31.3
09501250	125			114	90	62	48
09501500	150			114	90	62	48
10502000	200	184	154	114	90	62	48
11502480	226		198				
11502880	262	241	198				
11503150	296	241	198				
690 V							
07600230	23						19
07600300	30					24.8	19
07600360	36				35.8	24.8	19
07600460	46				35.8	24.8	19
07600520	52			46.7	35.8	25	19
07600730	73		65	46.7	35.8	25	19
08600860	86			76.7	64.5	44.3	31.3
08601080	104	97.2	90.7	76.7	64.8	44.3	31.3
09601250	125			114	90	62	48
09601550	155		153	113	89	62	48
10601720	172		153	114	89	62	48
10601970	197		195	134	102	67	48
11602250	205		198				
11602750	250	241	198				
11603050	296	241	198				

NOTE

55 ° C ratings are available on request.

12.1.2 Power dissipation

Table 12-4 Losses @ 40° C (104° F) ambient

Model	Normal Duty								
	Nominal rating		Drive losses (W) taking into account any current derating for the given conditions						
	kW	hp	2 kHz	3 kHz	4 kHz	6 kHz	8 kHz	12 kHz	16 kHz
200 V									
03200066	1.1	1.5	88	93	95	99	104	113	122
03200080	1.5	2	95	100	102	107	113	122	133
03200110	2.2	3	117	123	126	133	139	151	146
03200127	3	3	129	136	141	149	158	168	157
04200180	4	5	171	180	187	201	216	244	273
04200250	5.5	7.5	227	239	248	266	284	308	314
05200300	7.5	10	280	291	302	324	344	356	342
06200500	11	15	375	394	413	452	490	480	485
06200580	15	20	442	463	484	528	522	481	486
07200750	18.5	25	533	570	597	650	703	885	894
07200940	22	30	671	718	751	815	881	890	899
07201170	30	40	851	911	951	1004	911	920	929
08201490	37	50	1339	1433	1536	1765	1943	1962	1982
08201800	45	60	1638	1753	1894	1914	1985	2005	2025
09202160 (9A)	55	75	2028	2170	2312	2596	2448	2160	2031
09202660 (9A)	75	100	2585	2754	2822	2623	2448	2156	2034
09202160 (9E)	55	75	1889	2031	2174	2458	2348	2112	2006
09202660 (9E)	75	100	2375	2554	2625	2482	2348	2108	2009
10203250	90	125	2478	2672	2867	3123	2952	2701	2554
10203600	110	150	2802	3016	3230	3126	2957	2706	2554
400 V									
03400034	1.1	1.5	76	80	84	94	103	123	141
03400045	1.5	2	84	88	92	104	115	137	160
03400062	2.2	3	99	104	112	125	139	167	157
03400077	3	5	108	114	122	137	153	149	147
03400104	4	5	138	145	158	186	212	201	197
03400123	5	7.5	155	163	179	209	208	201	200
04400185	7.5	10	214	225	244	283	322	325	310
04400240	11	15	269	283	307	325	329	325	315
05400300	15	20	295	324	353	356	355	359	362
06400380	18.5	25	378	417	456	532	613	652	645
06400480	22	30	469	515	561	657	651	646	650
06400630	30	40	616	656	659	650	646	643	649
07400790	37	50	745	830	907	1062	1218	1230	1242
07400940	45	60	896	999	1088	1264	1241	1253	1266
07401120	55	75	1033	1152	1247	1218	1170	1182	1194
08401550	75	100	1482	1652	1817	2154	2121	2142	2164
08401840	90	125	1798	2004	2191	2333	2279	2302	2325
09402210 (9A)	110	150	2431	2710	2989	3075	2992	2842	2833
09402660 (9A)	132	200	3016	3191	3143	3063	3000	2856	2828
09402210 (9E)	110	150	2286	2565	2844	2966	2917	2807	2815
09402660 (9E)	132	200	2806	2998	2984	2955	2925	2821	2811
10403200	160	250	3210	3582	3954	4148	4034	3939	3843
10403610	200	300	3703	4121	4226	4154	4038	3947	3874
11404370	225	350	4182	4576	4708	4444	4246		
11404870	250	400	4734	4843	4708	4444	4246		
11405070	280	400	4962	4843	4708	4444	4246		

Model	Normal Duty								
	Nominal rating		Drive losses (W) taking into account any current derating for the given conditions						
	kW	hp	2 kHz	3 kHz	4 kHz	6 kHz	8 kHz	12 kHz	16 kHz
575 V									
05500039	2.2	3	82	92	102	121	142	183	223
05500061	4	5	120	135	150	180	209	269	328
05500100	5.5	7.5	173	194	215	260	302	388	474
06500120	7.5	10	191	215	239	287	334	430	525
06500170	11	15	253	284	315	376	438	563	569
06500220	15	20	325	362	399	484	569	575	580
06500270	18.5	25	391	448	505	596	682	689	696
06500340	22	30	534	623	712	810	822	830	839
06500430	30	40	675	798	836	813	823	831	840
07500530	45	50	867	1004	1139	1358	1262	1275	1287
07500730	55	60	1078	1248	1375	1209	1122	1133	1145
08500860	75	75	1607	1861	2180	2814	2982	3012	3042
08501080	90	100	2050	2374	2753	2947	2963	2993	3023
09501250 (9A)	110	125	1707	1977	2247	2787	2723	2731	2859
09501500 (9A)	110	150	2087	2410	2734	2810	2692	2697	2859
09501250 (9E)	110	125	1595	1865	2135	2675	2644	2687	2831
09501500 (9E)	110	150	1933	2256	2580	2696	2616	2654	2831
10502000	130	200	2692	3137	2923	2696	2616	2654	2831
11502480	185	250	3391	3999	4097				
11502880	225	300	4004	4296	4097				
11503150	250	350	4439	4296	4097				
690 V									
07600230	18.5	25	363	428	491	617	743	793	970
07600300	22	30	468	551	631	791	952	962	971
07600360	30	40	560	660	754	941	1129	1140	1152
07600460	37	50	725	854	971	1206	1271	1284	1297
07600520	45	60	836	985	1117	1350	1275	1288	1301
07600730	55	75	1059	1248	1375	1209	1122	1133	1145
08600860	75	100	1579	1861	2180	2814	2945	2974	3004
08601080	90	125	2015	2374	2753	2947	2935	2964	2994
09601250 (9A)	110	150	1878	2213	2548	3218	3155	3266	3465
09601550 (9A)	132	175	2384	2797	3211	3232	3155	3267	3474
09601250 (9E)	110	150	1730	2065	2400	3070	3058	3215	3434
09601550 (9E)	132	175	2160	2573	2986	3083	3058	3216	3443
10601720	160	200	2420	2882	3270	3083	3052	3192	3472
10601970	185	250	2614	3132	3649	3667	3495	3633	3993
11602250	200	250	3225	3893	4497				
11602750	250	300	4023	4640	4497				
11603050	280	400	4576	4684	4540				

Table 12-5 Losses @ 40°C (104° F) ambient with high IP insert installed

Model	Normal Duty						
	Drive losses (W) taking into consideration any current derating for the given conditions						
	2 kHz	3 kHz	4 kHz	6 kHz	8 kHz	12 kHz	16 kHz
200 V							
03200066	88	93	95	99	104	113	122
03200080	95	100	102	107	113	122	133
03200110	117	123	126	133	140	158	157
03200127	122	128	124	122	118	98	84
04200180	138	145	151	151	146	142	146
04200250	204	215	205	194	189	187	199
05200300	188	194	201	212	222	240	262
400 V							
03400034	76	80	84	94	103	123	137
03400045	84	88	92	102	105	110	134
03400062	80	84	85	89	92	109	134
03400077	108	114	117	122	135	172	203
03400104	112	118	134	155	173	221	267
03400123	112	118	134	155	173	221	267
04400185	100	105	114	132	153	197	207
04400240	96	101	111	131	152	197	207
05400300	118	118	119	124	132	152	183
575 V							
05500039	32	42	52	71	92	133	173
05500061	70	85	100	130	159	219	278
05500100	123	144	165	210	252	338	424

Table 12-6 Losses @ 50° C (122° F) ambient

Model	Normal Duty						
	Drive losses (W) taking into account any current derating for the given conditions						
	2 kHz	3 kHz	4 kHz	6 kHz	8 kHz	12 kHz	16 kHz
200 V							
03200066	88	93	95	99	104	113	122
03200080	95	100	102	107	113	122	133
03200110	117	123	126	133	139	144	139
03200127	129	136	140	143	147	151	150
04200180	171	180	187	201	216	253	297
04200250	203	214	223	244	265	312	334
05200300	280	291	302	324	341	325	312
06200500	375	394	413	452	480	431	594
06200580	442	463	484	510	483	432	451
07200750	538	570	597	650	703	710	717
07200940	678	718	751	799	750	758	765
07201170	848	898	898	805	751	759	766
08201490	1353	1433	1536	1741	1770	1788	1806
08201800	1640	1737	1740	1759	1771	1789	1807
09202160 (9A)	2028	2170	2312	2354	2256	2010	1910
09202660 (9A)	2431	2405	2368	2358	2245	2015	1922
09202160 (9E)	1889	2031	2174	2240	2172	1970	1889
09202660 (9E)	2241	2239	2223	2243	2161	1975	1900
10203250	2478	2625	2641	2625	2671	2490	2379
10203600	2666	2629	2643	2629	2678	2495	2374
400 V							
03400034	76	80	84	118	103	123	141
03400045	84	88	92	104	115	137	160
03400062	99	104	112	125	132	146	155
03400077	106	106	109	114	117	145	155
03400104	138	145	158	175	194	225	225
03400123	152	152	160	175	194	225	230
04400185	213	213	227	262	300	323	325
04400240	212	212	227	262	300	318	321
05400300	251	275	300	326	326	328	330
06400380	378	417	456	532	597	589	568
06400480	469	515	561	589	580	571	568
06400630	616	604	601	582	583	581	567
07400790	744	830	907	1062	1141	1152	1164
07400940	895	999	1087	1163	1138	1149	1161
07401120	1018	1136	1200	1118	1074	1085	1096
08401550	1480	1652	1815	2016	1970	1990	2010
08401840	1754	1957	2114	1998	1979	1999	2019
09402210 (9A)	2431	2710	2872	2799	2737	2639	2652
09402660 (9A)	2837	2926	2870	2814	2737	2660	2665
09402210 (9E)	2286	2565	2738	2709	2675	2611	2638
09402660 (9E)	2648	2760	2735	2723	2675	2632	2651
10403200	3210	3582	3681	3765	3700	3597	3591

Model	Normal Duty						
	Drive losses (W) taking into account any current derating for the given conditions						
	2 kHz	3 kHz	4 kHz	6 kHz	8 kHz	12 kHz	16 kHz
10403610	3482	3598	3676	3776	3694	3625	3589
11404370	4182	4329	4228	3988	3843		
11404870	4456	4329	4228	3988	3843		
11405070	4456	4329	4228	3988	3843		
575 V							
05500039	82	92	102	121	142	183	223
05500061	120	135	150	180	209	269	328
05500100	173	194	215	260	302	388	474
06500120	191	215	239	287	334	430	525
06500170	253	284	315	376	438	563	515
06500220	325	362	399	482	569	500	519
06500270	391	448	505	596	612	613	652
06500340	534	623	712	737	737	747	749
06500430	675	774	763	734	742	748	750
07500530	936	988	1115	1225	1144	1155	1167
07500730	1161	1225	1228	1098	1030	1040	1051
08500860	1753	1850	2172	2540	2672	2699	2726
08501080	1980	2090	2291	2540	2684	2711	2738
09501250 (9A)	1707	1977	2247	2538	2456	2495	2699
09501500 (9A)	2087	2410	2734	2544	2456	2482	2676
09501250 (9E)	1595	1865	2135	2443	2392	2460	2674
09501500 (9E)	1933	2256	2580	2448	2392	2447	2652
10502000	2692	2841	2654	2448	2392	2447	2652
11502480	3191	3678	3532				
11502880	3965	3678	3532				
11503150	3965	3678	3632				
690 V							
07600230	359	428	491	617	743	750	758
07600300	463	551	631	791	958	968	977
07600360	554	660	754	944	1144	1155	1167
07600460	717	854	965	1206	1144	1155	1167
07600520	814	969	1094	1225	1144	1155	1167
07600730	1029	1225	1228	1098	1030	1040	1051
08600860	1553	1850	2172	2540	2672	2699	2726
08601080	1755	2090	2291	2540	2684	2711	2738
09601250 (9A)	1878	2213	2548	2933	2882	2974	3248
09601550 (9A)	2384	2797	3175	2918	2855	2974	3249
09601250 (9E)	1730	2065	2400	2810	2803	2934	3223
09601550 (9E)	2160	2573	2955	2796	2778	2934	3225
10601720	2420	2882	2947	2805	2789	2932	3229
10601970	2614	3132	3610	3243	3221	3420	3771
11602250	3225	3893	4048				
11602750	4023	4186	4048				
11603050	4421	4230	4091				

Table 12-7 Power losses from the front of the drive when through-panel mounted

Frame size	Power loss
3	≤ 50 W
4	≤ 75 W
5	≤ 100 W
6	≤ 100 W
7	≤ 204 W
8	≤ 347 W
9A/9E	≤ 480 W
10E/11E	≤ 480 W

12.1.3 Supply requirements

AC supply voltage:

200 V drive: 200 V to 240 V ±10 %

400 V drive: 380 V to 480 V ±10 %

575 V drive: 500 V to 575 V ±10 %

690 V drive: 500 V to 690 V ±10 %

Number of phases: 3

Maximum supply imbalance: 2 % negative phase sequence (equivalent to 3 % voltage imbalance between phases).

Frequency range: 45 to 66 Hz

For UL compliance only, the maximum supply symmetrical fault current must be limited to 100 kA.

12.1.4 Line reactors

Input line reactors reduce the risk of damage to the drive resulting from poor phase balance or severe disturbances on the supply network.

Where line reactors are to be used, reactance values of approximately 2 % are recommended. Higher values may be used if necessary, but may result in a loss of drive output (reduced torque at high speed) because of the voltage drop.

For all drive ratings, 2 % line reactors permit drives to be used with a supply unbalance of up to 3.5 % negative phase sequence (equivalent to 5 % voltage imbalance between phases).

Severe disturbances may be caused by the following factors, for example:

- Power factor correction equipment connected close to the drive.
- Large DC drives having no or inadequate line reactors connected to the supply.
- Across the line (DOL) started motor(s) connected to the supply such that when any of these motors are started, the voltage dip exceeds 20 %

Such disturbances may cause excessive peak currents to flow in the input power circuit of the drive. This may cause nuisance tripping, or in extreme cases, failure of the drive.

Drives of low power rating may also be susceptible to disturbance when connected to supplies with a high rated capacity.

Line reactors are particularly recommended for use with the following drive models when one of the above factors exists, or when the supply capacity exceeds 175 kVA:

03200066, 03200080, 03200110, 03200127

03400034, 03400045, 03400062, 03400077

Model sizes 03400104 to 07600730 have an internal DC choke and model sizes 08201490 to 0801080 and frame 9A have internal AC line chokes so they do not require AC line reactors except for cases of excessive phase unbalance or extreme supply conditions. Drive sizes 9E, 10E and 11E do not have internal input line reactors hence an external input line reactor must be used. For more information refer to section 4.2.3 *Drive model and input line reactor* on page 98.

When required, each drive must have its own reactor(s). Three individual reactors or a single three-phase reactor should be used.

When required each drive must have its own reactor(s). Three individual reactors or a single three-phase reactor should be used.

Reactor current ratings

The current rating of the line reactors should be as follows:

Continuous current rating:

Not less than the continuous input current rating of the drive

Repetitive peak current rating:

Not less than twice the continuous input current rating of the drive

12.1.5 Motor requirements

No. of phases: 3

Maximum voltage:

200 V drive: 265 V

400 V drive: 530 V

575 V drive: 635 V

690 V drive: 765 V

12.1.6 Temperature, humidity and cooling method

Ambient temperature operating range:

-20 °C to 55 °C (-4 °F to 131 °F).

Output current derating must be applied at ambient temperatures >40 °C (104 °F).

Cooling method: Forced convection

Maximum humidity: 95 % non-condensing at 40 °C (104 °F)

12.1.7 Storage

-40 °C (-40 °F) to +55 °C (131 °F) for long term storage, or to +70 °C (158 °F) for short term storage.

Storage time is 2 years.

Electrolytic capacitors in any electronic product have a storage period after which they require reforming or replacing.

The low voltage capacitors on the control supplies typically have a storage period of 2 years and are thus the limiting factor.

Low voltage capacitors cannot be reformed due to their location in the circuit and thus may require replacing if the drive is stored for a period of 2 years or greater without power being applied.

It is therefore recommended that drives are powered up for a minimum of 30 minutes after every 2 years of storage.

This process allows the drive to be stored for a further 2 years.

12.1.8 Altitude

Altitude range: 0 to 3,000 m (9,900 ft), subject to the following conditions:

1,000 m to 3,000 m (3,300 ft to 9,900 ft) above sea level: de-rate the maximum output current from the specified figure by 1% per 100 m (330 ft) above 1,000 m (3,300 ft)

For example at 3,000 m (9,900 ft) the output current of the drive would have to be de-rated by 20 %.

12.1.9 IP / UL Rating

The drive is rated to IP20 pollution degree 2 (dry, non-conductive contamination only) (NEMA 1). However, it is possible to configure the drive to achieve IP65 rating (sizes 3 to 8) or IP55 rating (size 9, 10 and 11) (NEMA 12) at the rear of the heatsink for through-panel mounting (some current derating is required).

In order to achieve the high IP rating at the rear of the heatsink with drive sizes 3, 4 and 5 it is necessary to seal a heatsink vent by installing the high IP insert.

The IP rating of a product is a measure of protection against ingress and contact to foreign bodies and water. It is stated as IP XX, where the two digits (XX) indicate the degree of protection provided as shown in Table 12-7 *Power losses from the front of the drive when through-panel mounted* on page 290.

Table 12-8 IP Rating degrees of protection

First digit	Second digit
Protection against foreign bodies and access to hazardous parts	Protection against ingress of water
0 Non-protected	0 Non-protected
1 Protected against solid foreign objects of 50 mm Ø and greater (back of a hand)	1 Protected against vertically falling water drops
2 Protected against solid foreign objects of 12.5mm Ø and greater (finger)	2 Protected against vertically falling water drops when enclosure tilted up to 15 °
3 Protected against solid foreign objects of 2.5 mm Ø and greater (tool)	3 Protected against spraying water
4 Protected against solid foreign objects of 1.0mm Ø and greater (wire)	4 Protected against splashing water
5 Dust-protected (wire)	5 Protected against water jets
6 Dust-tight (wire)	6 Protected against powerful water jets
7 -	7 Protected against the effects of temporary immersion in water
8 -	8 Protected against the effects of continuous immersion in water

Table 12-9 UL enclosure ratings

UL rating	Description
Type 1	Enclosures are intended for indoor use, primarily to provide a degree of protection against limited amounts of falling dirt.
Type 12	Enclosures are intended for indoor use, primarily to provide a degree of protection against dust, falling dirt and dripping non-corrosive liquids.

12.1.10 Corrosive gasses

Concentrations of corrosive gasses must not exceed the levels given in:

- Table A2 of EN 50178:1998
- Class 3C2 of IEC 60721-3-3

This corresponds to the levels typical of urban areas with industrial activities and/or heavy traffic, but not in the immediate neighborhood of industrial sources with chemical emissions.

12.1.11 RoHS compliance

The drive meets EU directive 2011/65/EU for RoHS compliance.

12.1.12 Vibration

Maximum recommended continuous vibration level 0.14 g r.m.s. broad-band 5 to 200 Hz.

NOTE

This is the limit for broad-band (random) vibration. Narrow-band vibration at this level which coincides with a structural resonance could result in premature failure.

Bump Test

Testing in each of three mutually perpendicular axes in turn.

Referenced standard: IEC 60068-2-29: Test Eb:

Severity: 18 g, 6 ms, half sine

No. of Bumps: 600 (100 in each direction of each axis)

Random Vibration Test

Testing in each of three mutually perpendicular axes in turn.

Referenced standard: IEC 60068-2-64: Test Fh:

Severity: 1.0 m²/s³ (0.01 g²/Hz) ASD from 5 to 20 Hz

-3 dB/octave from 20 to 200 Hz

Duration: 30 minutes in each of 3 mutually perpendicular axes.

Sinusoidal Vibration Test

Testing in each of three mutually perpendicular axes in turn.

Referenced standard: IEC 60068-2-6: Test Fc:

Frequency range: 5 to 500 Hz

Severity: 3.5 mm peak displacement from 5 to 9 Hz

10 m/s² peak acceleration from 9 to 200 Hz

15 m/s² peak acceleration from 200 to 500 Hz

Sweep rate: 1 octave/minute

Duration: 15 minutes in each of 3 mutually perpendicular axes.

EN 61800-5-1:2007, Section 5.2.6.4. referring to IEC 60068-2-6

Frequency range: 10 to 150 Hz

Amplitude: 10 to 57 Hz at 0.075 mm pk

57 to 150 Hz at 1g p

Sweep rate: 1 octave/minute

Duration: 10 sweep cycles per axis in each of 3 mutually perpendicular axes

12.1.13 Starts per hour

By electronic control: unlimited

By interrupting the AC supply: ≤20 (equally spaced)

12.1.14 Start up time

This is the time taken from the moment of applying power to the drive, to the drive being ready to run the motor:

Sizes 3 to 6 = 2.5 s

Sizes 7 to 11 = 5 s

12.1.15 Output frequency / speed range

In all operating modes (Open loop, RFC-A, RFC-S) the maximum output frequency is limited to 550 Hz.

12.1.16 Accuracy and resolution

Speed:

The absolute frequency and speed accuracy depends on the accuracy of the crystal used with the drive microprocessor. The accuracy of the crystal is 100 ppm, and so the absolute frequency/speed accuracy is 100 ppm (0.01 %) of the reference, when a preset speed is used. If an analog input is used the absolute accuracy is further limited by the absolute accuracy of the analog input.

The following data applies to the drive only; it does not include the performance of the source of the control signals.

Open loop resolution:

Preset frequency reference: 0.1 Hz

Precision frequency reference: 0.001 Hz

Closed loop resolution

Preset speed reference: 0.1 rpm

Precision speed reference: 0.001 rpm

Analog input 1: 11 bit plus sign

Analog input 2: 11 bit plus sign

Current:

The resolution of the current feedback is 10 bit plus sign.

Accuracy: typical 2 %

worst case 5 %

12.1.17 Acoustic noise

The heatsink fan generates the majority of the sound pressure level at 1 m produced by the drive. The heatsink fan on all drive sizes are a variable speed fan. The drive controls the speed at which the fan runs based on the temperature of the heatsink and the drive's thermal model system.

Table 12-10 gives the sound pressure level at 1 m produced by the drive for the heatsink fan running at the maximum and minimum speeds.

Table 12-10 Acoustic noise data

Size	Max speed dBA	Min speed dBA
3	62.8	42.9
4	62.6	45.8
5	61.1	41.9
6	65.3	48.2
7	66.8	49.6
8	67.9	49.8
9A/9E/10E	75	52.6
11E	82.5	58
12	73	51

12.1.18 Overall dimensions

- H Height including surface mounting brackets
- W Width
- D Projection forward of panel when surface mounted
- F Projection forward of panel when through-panel mounted
- R Projection rear of panel when through-panel mounted

Table 12-11 Overall drive dimensions

Size	Dimension				
	H	W	D	F	R
3	382 mm (15.04 in)	83 mm (3.27 in)	200 mm (7.87 in)	134 mm (5.28 in)	67 mm (2.64 in)
4	391 mm (15.39 in)	124 mm (4.88 in)			67 mm (2.64 in)
5	391 mm (15.39 in)	143 mm (5.63 in)	200 mm (7.87 in)	135 mm (5.32 in)	67 mm (2.64 in)
6	391 mm (15.39 in)	210 mm (8.27 in)	227 mm (8.94 in)	131 mm (5.16 in)	96 mm (3.78 in)
7	557 mm (21.93 in)	270 mm (10.63 in)	280 mm (11.02 in)	187 mm (7.36 in)	92 mm (3.62 in)
8	804 mm (31.65 in)	310 mm (12.21 in)	290 mm (11.42 in)	190 mm (7.48 in)	100 mm (3.94 in)
9A	1108 mm (43.61 in)	310 mm (12.21 in)	290 mm (11.42 in)	190 mm (7.48 in)	100 mm (3.94 in)
9E and 10E	1069 mm (42.09 in)	310 mm (12.21 in)	290 mm (11.42 in)	190 mm (7.48 in)	99 mm (3.90 in)
11E	1242 mm (48.9 in)	310 mm (12.21 in)	313 mm (12.32 in)	190 mm (7.48 in)	122 mm (4.8 in)
12	1750 (68.89)	295 (11.61)	526 (20.70)		

12.1.19 Weights

Table 12-12 Overall drive weights

Size	Type	Model	kg	lb
3	Std	03400104, 03400123	4.5	9.9
	Std	All other variants	4.0	8.8
	High IP	All Variants	7.5	16.5
4	Std	All variants	6.5	14.30
	High IP		9.3	20.5
5	Std		7.4	16.30
	High IP		10.0	22
6	Std		14	30.90
	High IP		16.9	37.3
7	Std		28	61.70
8	Std		52	114.64
9A	Std		66.5	146.6
9E/10E	Std		46	101.40
11E	Std		63	138.9
12	Std		130	287

12.1.20 Input current, fuse and cable size ratings

The input current is affected by the supply voltage and impedance.

Typical input current

The values of typical input current are given to aid calculations for power flow and power loss.

The values of typical input current are stated for a balanced supply.

Maximum continuous input current

The values of maximum continuous input current are given to aid the selection of cables and fuses. These values are stated for the worst case condition with the unusual combination of stiff supply with bad balance. The value stated for the maximum continuous input current would only be seen in one of the input phases. The current in the other two phases would be significantly lower.

The values of maximum input current are stated for a supply with a 2 % negative phase-sequence imbalance and rated at the maximum supply fault current given in Table 12-13.

Table 12-13 Supply fault current used to calculate maximum input currents

Model	Symmetrical fault level (kA)
All	100



Fuses

The AC supply to the drive must be installed with suitable protection against overload and short-circuits. Table 12-14 shows the recommended fuse ratings. Failure to observe this requirement will cause risk of fire.

Table 12-14 AC Input current and fuse ratings (200 V)

Model	Typical input current A	Maximum continuous input current A	Maximum overload input current A	Fuse rating					
				IEC			UL / USA		
				Nominal A	Maximum A	Class	Nominal A	Maximum A	Class
03200066	8.2	10.4	15.8	16	25	gG	20	25	CC, J or T*
03200080	9.9	12.6	20.9	20			25		
03200110	14	17	25	25			25		
03200127	16	20	34	25	25	gG	25	25	CC, J or T*
04200180	17	20	30	25			25		
04200250	23	28	41	32	32	gG	30	30	CC, J or T*
05200300	24	31	52	40	40		40		
06200500	42	48	64	63	63	gG	60	60	CC, J or T*
06200580	49	56	85				60		
07200750	58	67	109	80	80	gG	80	80	CC, J or T*
07200940	73	84	135	100	100		100		
07201170	91	105	149	125	125		125		
08201490	123	137	213	200	200	gR	200	200	HSJ
08201800	149	166	243				225		
09202160	172	205	270	250	250	gR	250	250	HSJ
09202660	228	260	319	315	315		300		
10203250	277	305	421	400	400	gR	400	400	HSJ
10203600	333	361	494	450	450		450		

Table 12-15 AC Input current and fuse ratings (400 V)

Model	Typical input current A	Maximum continuous input current A	Maximum overload input current A	Fuse rating					
				IEC			UL / USA		
				Nominal A	Maximum A	Class	Nominal A	Maximum A	Class
03400034	5	5	7	10	10	gG	10	10	CC, J or T*
03400045	6	7	9						
03400062	8	9	13						
03400077	11	13	21	20	20	gG	20	20	CC, J or T*
03400104	12	13	20						
03400123	14	16	25						
04400185	17	19	30	25	25	gG	25	25	CC, J or T*
04400240	22	24	35	32	32		30		
05400300	26	29	52	40	40	gG	35	35	CC, J or T*
06400380	32	36	67	63	63		gG		
06400480	41	46	80						
06400630	54	60	90						
07400790	67	74	124	100	100	gG	80	80	CC, J or T*
07400940	80	88	145						
07401120	96	105	188						
08401550	137	155	267	250	250	gR	225	225	HSJ
08401840	164	177	303						
09402210	211	232	306	315	315	gR	300	300	HSJ
09402660	245	267	359				350		
10403200	306	332	445	400	400	gR	400	400	HSJ
10403610	370	397	523	450	450		450		
11404370	424	449	579	500	500	gR	600	600	HSJ
11404870	455	492	613						
11405070	502	539	752	630	630	gR	600	600	HSJ

Table 12-16 AC Input current and fuse ratings (575 V)

Model	Typical input current A	Maximum continuous input current A	Maximum overload input current A	Fuse rating					
				IEC			UL / USA		
				Nominal A	Maximum A	Class	Nominal A	Maximum A	Class
05500039	4	4	7	10	20	gG	10	10	CC, J or T*
05500061	6	7	9						
05500100	9	11	15						
06500120	12	13	22	20	40	gG	20	30	CC, J or T*
06500170	17	19	33						
06500220	22	24	41						
06500270	26	29	50	50	63	gG	35	50	CC, J or T*
06500340	33	37	63						
06500430	41	47	76						
07500530	41	45	75	50	50	gG	50	50	CC, J or T*
07500730	57	62	94	80	80		80	80	
08500860	74	83	121	125	125	gR	100	100	HSJ
08501080	92	104	165	160	160		150	150	
09501250	145	166	190	150	150	gR	150	150	HSJ
09501500	145	166	221	200	200		175	175	
10502000	177	197	266	250	250	gR	250	250	HSJ
11502480	240	265	327	400	400	gR	400	400	HSJ
11502880	285	310	395						
11503150	313	338	473						

Table 12-17 AC Input current and fuse ratings (690 V)

Model	Typical input current A	Maximum continuous input current A	Maximum overload input current A	Fuse rating					
				IEC			UL / USA		
				Nominal A	Maximum A	Class	Nominal A	Maximum A	Class
07600230	18	20	32	25	50	gG	25	50	CC, J or T*
07600300	23	26	41	32					
07600360	28	31	49	40					
07600460	36	39	65	50	80	gG	50	80	CC, J or T*
07600520	40	44	75						
07600730	57	62	92	80	80	gG	80	80	CC, J or T*
08600860	74	83	121	125	125	gR	100	100	HSJ
08601080	92	104	165	160	160		150	150	
09601250	124	149	194	150	150	gR	150	150	HSJ
09601550	145	171	226	200	200		200	200	
10601720	180	202	268	225	225	gR	250	250	HSJ
10601970	202	225	313	250	250	gR	250	250	
11602250	225	256	379	400	400	gR	400	400	HSJ
11602750	217	302	425						
11603050	298	329	465						

* These fuses are fast acting.

NOTE

Ensure cables used suit local wiring regulations.



The following nominal cable sizes are only a guide. The mounting and grouping of cables affects their current-carrying capacity, in some cases smaller cables may be acceptable but in other cases a larger cable is required to avoid excessive temperature or voltage drop. Refer to local wiring regulations for the correct size of cables.

CAUTION

Table 12-18 Cable ratings (200V)

Model	Cable size (IEC) mm ²						Cable size (UL) AWG			
	Input			Output			Input		Output	
	Nominal	Maximum	Installation method	Nominal	Maximum	Installation method	Nominal	Maximum	Nominal	Maximum
03200066	1.5	4	B2	1.5	4	B2	14	10	14	10
03200080				4			12			
03200110				4			12			
03200127				4			12			
04200180	6	8	B2	6	8	B2	10	8	10	8
04200250	8			8			8			
05200300	10	10	B2	10	10	B2	8	8	8	8
06200500	16	25	B2	16	25	B2	4	3	4	3
06200580	25			25			3		3	
07200750	35	70	B2	35	70	B2	2	1/0	2	1/0
07200940				1			1			
07201170				1/0			1/0			
08201490	95	2 x 70	B2	95	2 x 70	B2	3/0	2 x 1	3/0	2 x 1
08201800	2 x 70			2 x 1			2 x 1			
09202160	2 x 70	2 x 185	B1	2 x 95	2 x 150	B2	2 x 2/0	2 x 500	2 x 2/0	2 x 350
09202660	2 x 95			2 x 120			2 x 4/0		2 x 4/0	
10203250	2 x 120	2 x 185	B1	2 x 120	2 x 150	C	2 x 250	2 x 500	2 x 250	2 x 350
10203600	2 x 150		C	2 x 120			2 x 300		2 x 300	

Table 12-19 Cable ratings (400 V)

Model	Cable size (IEC) mm ²						Cable size (UL) AWG			
	Input			Output			Input		Output	
	Nominal	Maximum	Installation method	Nominal	Maximum	Installation method	Nominal	Maximum	Nominal	Maximum
03400034	1.5	4	B2	1.5	4	B2	18	10	18	10
03400045				16			16			
03400062				14			14			
03400077				12			12			
03400104				12			12			
04400185	4	6	B2	4	6	B2	10	8	10	8
04400240	6			8			8			
05400300	6	6	B2	6	6	B2	8	8	8	8
06400380	10	25	B2	10	25	B2	6	3	6	3
06400480	16			4			4			
06400630	25			3			3			
07400790	35	70	B2	35	70	B2	1	1/0	1	1/0
07400940	50			2			2			
07401120	70			1/0			1/0			
08401550	2 x 50	2 x 70	B2	2 x 50	2 x 70	B2	2 x 1	2 x 1/0	2 x 1	2 x 1/0
08401840	2 x 70			2 x 1/0			2 x 1/0			
09402210	2 x 70	2 x 185	B1	2 x 95	2 x 150	B2	2 x 3/0	2 x 500	2 x 2/0	2 x 350
09402660	2 x 95			2 x 120			2 x 4/0		2 x 4/0	
10403200	2 x 120	2 x 185	C	2 x 120	2 x 150	C	2 x 300	2 x 500	2 x 250	2 x 350
10403610	2 x 150			2 x 150			2 x 350		2 x 300	
11404370	4 x 95	C	C	2 x 185	2 x 185	C	4 x 3/0	2 x 400	4 x 3/0	2 x 400
11404870				2 x 240	2 x 240		4 x 4/0			
11405070				2 x 240	2 x 240		4 x 4/0			

Table 12-20 Cable ratings (575 V)

Model	Cable size (IEC) mm ²						Cable size (UL) AWG			
	Input			Output			Input		Output	
	Nominal	Maximum	Installation method	Nominal	Maximum	Installation method	Nominal	Maximum	Nominal	Maximum
05500039	0.75	1.5	B2	0.75	1.5	B2	16	16	16	16
05500061	1			1			14		14	
05500100	1.5			1.5			14		14	
06500120	2.5	25	B2	2.5	25	B2	14	3	14	3
06500170	4			4			10		10	
06500220	6			6			10		10	
06500270	10			10			8		8	
06500340							6		6	
06500430							6		6	
07500530	16	25	B2	16	25	B2	4	3	4	3
07500730	25			25			3		3	
08500860	35	50	B2	35	50	B2	1	1	1	1
08501080	50			50			1		1	
09501250	2 x 70	2 x 185	B2	2 x 35	2 x 150	B2	2 x 1	2 x 500	2 x 3	2 x 350
09501500				2 x 50					2 x 1	
10502000	2 x 70	2 x 185	B2	2 x 70	2 x 150	B2	2 x 2/0	2 x 500	2 x 2/0	2 x 350
11502480	2 x 70		C	2 x 70		C	2 x 3/0			
11502880	2 x 95			2 x 95			2 x 4/0			
11503150	2 x 120			2 x 120			2 x 250			

Table 12-21 Cable ratings (690 V)

Model	Cable size (IEC) mm ²						Cable size (UL) AWG			
	Input			Output			Input		Output	
	Nominal	Maximum	Installation method	Nominal	Maximum	Installation method	Nominal	Maximum	Nominal	Maximum
07600230	10	25	B2	10	25	B2	8	3	8	3
07600300							6		6	
07600360							6		6	
07600460							4		4	
07600520							4		4	
07600730							3		3	
08600860	50	70	B2	50	70	B2	2	1/0	2	1/0
08601080	70			70			1/0		1/0	
09601250	2 x 50	2 x 185	B2	2 x 35	2 x 150	B2	2 x 1	2 x 500	2 x 3	2 x 350
09601550	2 x 70			2 x 50			2 x 1/0		2 x 1	
10601720	2 x 70	2 x 185	B2	2 x 70	2 x 150	B2	2 x 2/0	2 x 500	2 x 1/0	2 x 350
10601970	2 x 95						2 x 3/0		2 x 2/0	
11602250	2 x 70		C	2 x 70		C	2 x 3/0			
11602750	2 x 95			2 x 95			2 x 4/0			
11603050							2 x 250			

12.1.21 Protective ground cable ratings

Table 12-22 Protective ground cable ratings

Input phase conductor size	Minimum ground conductor size
$\leq 10 \text{ mm}^2$	Either 10 mm^2 or two conductors of the same cross-sectional area as the input phase conductor (an additional ground connection is provided on sizes 3, 4 and 5 for this purpose).
$> 10 \text{ mm}^2$ and $\leq 16 \text{ mm}^2$	The same cross-sectional area as the input phase conductor
$> 16 \text{ mm}^2$ and $\leq 35 \text{ mm}^2$	16 mm^2
$> 35 \text{ mm}^2$	Half of the cross-sectional area of the input phase conductor

12.1.22 Maximum motor cable lengths

Table 12-23 Maximum motor cable lengths (200 V drives)

200 V Nominal AC supply voltage							
Model	Maximum permissible motor cable length for each of the following switching frequencies						
	2 kHz	3 kHz	4 kHz	6 kHz	8 kHz	12 kHz	16 kHz
03200066	65 m (210 ft)						
03200080	100 m (330 ft)						
03200110	130 m (425 ft)			100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)
03200127	200 m (660 ft)	150 m (490 ft)					
04200180	200 m (660 ft)	150 m (490 ft)		100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)
04200250		150 m (490 ft)		100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)
05200300	200 m (660 ft)	150 m (490 ft)		100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)
06200500	200 m (660 ft)	150 m (490 ft)		100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)
06200580		150 m (490 ft)		100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)
07200750	250 m (820 ft)	187 m (614 ft)		125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)
07200940		187 m (614 ft)		125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)
07201170		187 m (614 ft)		125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)
08201490	250 m (820 ft)	187 m (614 ft)		125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)
08201800		187 m (614 ft)		125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)
09202160	250 m (820 ft)	187 m (614 ft)		125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)
09202660		187 m (614 ft)		125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)
10203250	250 m (820 ft)	187 m (614 ft)		125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)
10203600		187 m (614 ft)		125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)

Table 12-24 Maximum motor cable lengths (400 V drives)

400 V Nominal AC supply voltage							
Model	Maximum permissible motor cable length for each of the following switching frequencies						
	2 kHz	3 kHz	4 kHz	6 kHz	8 kHz	12 kHz	16 kHz
03400034	65 m (210 ft)						
03400045	100 m (330 ft)						
03400062	130 m (425 ft)						
03400077	200 m (660 ft)	150 m (490 ft)	100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)	
03400104							
03400123							
04400185	200 m (660 ft)	150 m (490 ft)	100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)	
04400240	200 m (660 ft)	150 m (490 ft)	100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)	
05400300	200 m (660 ft)	150 m (490 ft)	100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)	
06400380	200 m (660 ft)	150 m (490 ft)	100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)	
06400480							
06400630							
07400790	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
07400940							
07401120							
08401550	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
08401840							
09402210	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
09402660							
10403200	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
10403610							
11404370	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)			
11404870							
11405070							

Table 12-25 Maximum motor cable lengths (575 V drives)

575 V Nominal AC supply voltage							
Model	Maximum permissible motor cable length for each of the following switching frequencies						
	2 kHz	3 kHz	4 kHz	6 kHz	8 kHz	12 kHz	16 kHz
05500039	200 m (660 ft)	150 m (490 ft)	100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)	
05500061							
05500100							
06500120	200 m (660 ft)	150 m (490 ft)	100 m (330 ft)	75 m (245 ft)	50 m (165 ft)	37 m (120 ft)	
06500170							
06500220							
06500270							
06500340							
06500430							
07500530	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
07500730							
08500860	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
08501080							
09501250	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
09501500							
10502000	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
11502480	250 m (820 ft)	187 m (614 ft)					
11502880							
11503150							

Table 12-26 Maximum motor cable lengths (690 V drives)

690 V Nominal AC supply voltage							
Model	Maximum permissible motor cable length for each of the following switching frequencies						
	2 kHz	3 kHz	4 kHz	6 kHz	8 kHz	12 kHz	16 kHz
07600230	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
07600300							
07600360							
07600460							
07600520							
07600730							
08600860	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
08601080							
09601250	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
09601550							
10601720	250 m (820 ft)	187 m (614 ft)	125 m (410 ft)	93 m (305 ft)	62 m (203 ft)	46 m (151 ft)	
10601970							
11602250	250 m (820 ft)	187 m (614 ft)					
11602750							
11603050							

- Cable lengths in excess of the specified values may be used only when special techniques are adopted; refer to the supplier of the drive.
 - The default switching frequency is 3 kHz for Open-loop and RFC-A and 6 kHz for RFC-S mode.
- The maximum cable length is reduced from that shown in Table 12-25 and Table 12-26 if high capacitance or reduced diameter motor cables are used. For further information, refer to section 4.9.2 *High-capacitance / reduced diameter cables* on page 113.

12.1.23 Torque settings

Table 12-27 Drive control and relay terminal data

Model	Connection type	Torque setting
All	Plug-in terminal block	0.5 Nm (4.8 lb in)

Table 12-28 Drive power terminal data

H300 frame size	AC and motor terminals		DC terminals		Ground terminals	
	Recommended	Maximum	Recommended	Maximum	Recommended	Maximum
3 and 4	Plug-in terminal block		T20 Torx (M4)		T20 Torx (M4) / M4 Nut (7 mm AF)	
	0.7 Nm (6 lb in)	0.8 Nm (7.2 lb in)	2.0 Nm (16.8 lb in)	2.5 Nm (21.6 lb in)	2.0 Nm (16.8 lb in)	2.5 Nm (21.6 lb in)
5	Plug-in terminal block		T20 Torx (M4) / M4 Nut (7 mm AF)		M5 Nut (8 mm AF)	
	1.5 Nm (13.2 lb in)	1.8 Nm (15.6 lb in)	1.5 Nm (13.2 lb in)	2.5 Nm (21.6 lb in)	2.0 Nm (18 lb in)	5.0 Nm (44.4 lb in)
6			M6 Nut (10 mm AF)			
	6.0 Nm (52.8 lb in)	8.0 Nm (72 lb in)	6.0 Nm (52.8 lb in)	8.0 Nm (72 lb in)	6.0 Nm (52.8 lb in)	8.0 Nm (72 lb in)
7	M8 Nut (13 mm AF)		M8 Nut (13 mm AF)		M8 Nut (13 mm AF)	
	12 Nm (106.2 lb in)	14 Nm (124 lb in)	12 Nm (106.2 lb in)	14 Nm (124 lb in)	12 Nm (106.2 lb in)	14 Nm (124 lb in)
8 to 11	M10 Nut (17 mm AF)		M10 Nut (17 mm AF)		M10 Nut (17 mm AF)	
	15 Nm (133.2 lb in)	20 Nm (177.6 lb in)	15 Nm (133.2 lb in)	20 Nm (177.6 lb in)	15 Nm (133.2 lb in)	20 Nm (177.6 lb in)

*For Frame 12, please refer to the Frame 12 Power Module manual.

Table 12-29 Plug-in terminal block maximum cable sizes

Model size	Terminal block description	Max cable size
All	11 way control connectors	1.5 mm ² (16 AWG)
	2 way relay connector	2.5 mm ² (12 AWG)
3 4	6 way AC power connector	6 mm ² (10 AWG)
5	3 way AC power connector 3 way motor connector	8 mm ² (8 AWG)
6 7 8 9A/9E 10E/11E	2 way low voltage power 24 V supply connector	1.5 mm ² (16 AWG)

*For Frame 12, please refer to the Frame 12 Power Module manual.

12.1.24 Electromagnetic compatibility (EMC)

This is a summary of the EMC performance of the drive. For full details, refer to the *EMC Data Sheet* which can be obtained from the supplier of the drive.

Table 12-30 Immunity compliance

Standard	Type of immunity	Test specification	Application	Level
IEC61000-4-2 EN61000-4-2	Electrostatic discharge	6 kV contact discharge 8 kV air discharge	Module enclosure	Level 3 (industrial)
IEC61000-4-3 EN61000-4-3	Radio frequency radiated field	10 V/m prior to modulation 80 - 1000 MHz 80 % AM (1 kHz) modulation	Module enclosure	Level 3 (industrial)
IEC61000-4-4 EN61000-4-4	Fast transient burst	5/50 ns 2 kV transient at 5 kHz repetition frequency via coupling clamp	Control lines	Level 4 (industrial harsh)
		5/50 ns 2 kV transient at 5 kHz repetition frequency by direct injection	Power lines	Level 3 (industrial)
IEC61000-4-5 EN61000-4-5	Surges	Common mode 4 kV 1.2/50 μs waveshape	AC supply lines: line to ground	Level 4
		Differential mode 2 kV 1.2/50 μs waveshape	AC supply lines: line to line	Level 3
		Lines to ground	Signal ports to ground ¹	Level 2
IEC61000-4-6 EN61000-4-6	Conducted radio frequency	10V prior to modulation 0.15 - 80 MHz 80 % AM (1 kHz) modulation	Control and power lines	Level 3 (industrial)
IEC61000-4-11 EN61000-4-11	Voltage dips and interruptions	-30 % 10 ms +60 % 100 ms -60 % 1 s <-95 % 5 s	AC power ports	
IEC61000-6-1 EN61000-6-1:2007	Generic immunity standard for the residential, commercial and light - industrial environment			Complies
IEC61000-6-2 EN61000-6-2:2005	Generic immunity standard for the industrial environment			Complies
IEC61800-3 EN61800-3:2004	Product standard for adjustable speed power drive systems (immunity requirements)		Meets immunity requirements for first and second environments	

¹ See section 4.11.7 *Variations in the EMC wiring* on page 123 for control ports for possible requirements regarding grounding and external surge protection

Emission

The drive contains an in-built filter for basic emission control. An additional optional external filter provides further reduction of emission. The requirements of the following standards are met, depending on the motor cable length and switching frequency.

Table 12-31 Size 3 emission compliance (200 V drives)

Motor cable length (m)	Switching Frequency (kHz)						
	2	3	4	6	8	12	16
Using internal filter:							
0 – 2	C3			C4			
Using internal filter and ferrite ring (2 turns):							
0 – 10	C3			C4			
10-20	C3			C4			
Using external filter:							
0 – 20	C1	C1	C2	C2	C2	C2	C2
20 – 100	C2	C2	C3	C3	C3	C3	C3

Table 12-32 Size 3 emission compliance (400 V drives)

Motor cable length (m)	Switching Frequency (kHz)						
	2	3	4	6	8	12	16
Using internal filter:							
0 – 5	C3			C4			
Using internal filter and ferrite ring (2 turns):							
0 – 10	C3			C4			
Using external filter:							
0 – 20	C1	C1	C2	C2	C2	C2	C2
20 – 100	C2	C2	C3	C3	C3	C3	C3

Table 12-33 Size 4 emission compliance (200 V drives)

Motor cable length (m)	Switching Frequency (kHz)						
	2	3	4	6	8	12	16
Using internal filter:							
0 – 2	C3			C4			
Using internal filter and ferrite ring (2 turns):							
0 – 4	C3			C4			
Using external filter:							
0 – 20	C1	C1	C2	C2	C2	C2	C2
20 – 100	C2	C2	C3	C3	C3	C3	C3

Table 12-34 Size 4 emission compliance (400 V drives)

Motor cable length (m)	Switching Frequency (kHz)						
	2	3	4	6	8	12	16
Using internal filter:							
0 – 4	C3			C4			
Using internal filter and ferrite ring (2 turns):							
0 – 10	C3			C4			
Using external filter:							
0 – 20	C1	C1	C2	C2	C2	C2	C2
20 – 100	C2	C2	C3	C3	C3	C3	C3

Table 12-35 Size 5 emission compliance (200 V drives)

Motor cable length (m)	Switching Frequency (kHz)						
	2	3	4	6	8	12	16
Using internal filter:							
0 – 2	C3			C4			
Using internal filter and ferrite ring (1 turn – no advantage to 2 turns):							
0 – 2	C3			C4			
0 – 5	C3			C4			
0 – 7	C3			C4			
0 – 10	C3	C4					
Using external filter:							
0 – 20	C1	C1	C2	C2	C2	C2	C2
20 – 100	C2	C2	C3	C3	C3	C3	C3

Table 12-36 Size 5 emission compliance (400 V drives)

Motor cable length (m)	Switching Frequency (kHz)						
	2	3	4	6	8	12	16
Using internal filter:							
0 – 4	C3			C4			
0 – 10	C3	C4					
No advantage to using ferrite ring							
Using external filter:							
0 – 20	C1	C1	C2	C2	C2	C2	C2
20 – 100	C2	C2	C3	C3	C3	C3	C3

Table 12-37 Size 5 emission compliance (575 V drives)

Motor cable length (m)	Switching Frequency (kHz)						
	2	3	4	6	8	12	16
Using internal filter:							
-	C4						
Using internal filter and ferrite ring (2 turns):							
0 – 4	C3			C4			
0 – 2	C3						C4
Using external filter:							
0 – 20	C1	C1	C2	C2	C2	C2	C2
20 – 100	C2	C2	C3	C3	C3	C3	C3

Table 12-38 Size 6 emission compliance (200 V drives)

Motor cable length (m)	Switching Frequency (kHz)						
	2	3	4	6	8	12	16
Using internal filter:							
0 – 2	C3	C4					
Using internal filter and ferrite ring (1 turn – no advantage to 2 turns):							
0 – 2	C3			C4			
0 – 5	C3			C4			
0 – 7	C3		C4				
0 – 10	C3	C4					
Using external filter:							
0 – 20	C1	C1	C2	C2	C2	C2	C2
20 – 100	C2	C2	C3	C3	C3	C3	C3

Table 12-39 Size 6 emission compliance (400 V drives)

Motor cable length (m)	Switching Frequency (kHz)						
	2	3	4	6	8	12	16
Using internal filter:							
0 – 4	C3			C4			
0 – 10	C3	C4					
No advantage to using ferrite ring							
Using external filter:							
0 – 20	C1	C1	C2	C2	C2	C2	C2
20 – 100	C2	C2	C3	C3	C3	C3	C3

Table 12-40 Size 6 emission compliance (575 V drives)

Motor cable length (m)	Switching Frequency (kHz)						
	2	3	4	6	8	12	16
Using internal filter:							
-	C4						
Using internal filter and ferrite ring (2 turns):							
0 – 4	C3			C4			
0 – 2	C3						C4
Using external filter:							
0 – 20	C1	C1	C2	C2	C2	C2	C2
20 – 100	C2	C2	C3	C3	C3	C3	C3

Table 12-41 Size 7 emission compliance (200 V drives)

Motor cable length (m)	Switching Frequency (kHz)						
	2	3	4	6	8	12	16
Using internal filter:							
0 – 100	C4	C4	C4	C4	C4	C4	C4
Using external filter:							
0 – 20	C2	C2	C2	C2	C2	C2	C2
20 – 100	C2	C2	C3	C3	C3	C3	C3

Table 12-42 Size 7 emission compliance (400 V drives)

Motor cable length (m)	Switching Frequency (kHz)						
	2	3	4	6	8	12	16
Using internal filter:							
0 – 100	C4	C4	C4	C4	C4	C4	C4
Using external filter:							
0 – 20	C2	C2	C2	C2	C2	C2	C2
20 – 100	C2	C2	C3	C3	C3	C3	C3

Table 12-43 Size 7 emission compliance (575 and 690 V drives)

Motor cable length (m)	Switching Frequency (kHz)						
	2	3	4	6	8	12	16
Using internal filter:							
0 – 100	C4	C4	C4	C4	C4	C4	C4
Using external filter:							
0 – 20	C2	C2	C2	C2	C2	C2	C2
20 – 100	C2	C2	C3	C3	C3	C3	C3

Table 12-44 Size 8 emission compliance (200 V drives)

Motor cable length (m)	Switching Frequency (kHz)						
	2	3	4	6	8	12	16
Using internal filter:							
0 – 10	C3	C3	C3	C3	C3	C3	C3
Using external filter:							
0 – 20	C2	C2	C2	C2	C2	C2	C2
20 – 100	C2	C2	C3	C3	C3	C3	C3

Table 12-45 Size 8 emission compliance (400 V drives)

Motor cable length (m)	Switching Frequency (kHz)						
	2	3	4	6	8	12	16
Using internal filter:							
0 – 10	C3	C3	C3	C3	C3	C3	C3
Using external filter:							
0 – 20	C2	C2	C2	C2	C2	C2	C2
20 – 100	C2	C2	C3	C3	C3	C3	C3

Table 12-46 Size 8 emission compliance (575 V and 690 V drives)

Motor cable length (m)	Switching Frequency (kHz)						
	2	3	4	6	8	12	16
Using internal filter:							
0 – 100	C4	C4	C4	C4	C4	C4	C4
Using external filter:							
0 – 20	C2	C2	C2	C2	C2	C2	C2
20 – 100	C2	C2	C3	C3	C3	C3	C3

Table 12-47 Size 9E and 10E emission compliance (all voltages)

Motor cable length (m)	Switching Frequency (kHz)						
	2	3	4	6	8	12	16
Using internal filter:							
0 – 100	C3	C3	C3	C3	C3	C3	C3
Using external filter:							
0 – 20	C2	C2	C2	C2	C2	C2	C2
20 – 100	C2	C2	C3	C3	C3	C3	C3

Table 12-48 Size 11 emission compliance (all voltages)

Motor cable length (m)	Switching Frequency (kHz)				
	2	3	4	6	8
Using internal filter:					
0 – 50	C3	C3	C3	C3	C3
100	C3	C3	C3	C3	C4
Using external filter:					
20	C2	C2	C2	C2	C2
100	C2	C2	C3	C3	C3

Key (shown in decreasing order of permitted emission level):

- E2R EN 61800-3 second environment, restricted distribution (Additional measures may be required to prevent interference)
- E2U EN 61800-3 second environment, unrestricted distribution
- I Industrial generic standard EN 61000-6-4
EN 61800-3 first environment restricted distribution (The following caution is required by EN 61800-3)



This is a product of the restricted distribution class according to IEC 61800-3. In a residential environment this product may cause radio interference in which case the user may be required to take adequate measures.

- R Residential generic standard EN 61000-6-3
EN 61800-3 first environment unrestricted distribution

EN 61800-3 defines the following:

- The first environment is one that includes residential premises. It also includes establishments directly connected without intermediate transformers to a low-voltage power supply network which supplies buildings used for residential purposes.
- The second environment is one that includes all establishments other than those directly connected to a low-voltage power supply network which supplies buildings used for residential purposes.
- Restricted distribution is defined as a mode of sales distribution in which the manufacturer restricts the supply of equipment to

suppliers, customers or users who separately or jointly have technical competence in the EMC requirements of the application of drives.

EN 61800-3:2004+A1:2012

The 2004 revision of the standard uses different terminology to align the requirements of the standard better with the EC EMC Directive.

Power drive systems are categorized C1 to C4:

Category	Definition	Corresponding code used above
C1	Intended for use in the first or second environments	R
C2	Not a plug-in or movable device, and intended for use in the first environment only when installed by a professional, or in the second environment	I
C3	Intended for use in the second environment, not the first environment	E2U
C4	Intended for use in the second environment in a system rated at over 400 A, or in a complex system	E2R

Note that category 4 is more restrictive than E2R, since the rated current of the PDS must exceed 400 A or the supply voltage exceed 1000 V, for the complete PDS.

*For Frame 12, please refer to the Frame 12 Power Module manual.

12.2 Optional external EMC filters

Table 12-49 EMC filter cross reference

Model	CT part number
200 V	
03200066 to 03200127	4200-3230
04200180 to 04200250	4200-0272
05200300	4200-0312
06200500 to 06200580	4200-2300
07200750 to 07201170	4200-1132
08201490 to 08201800	4200-1972
09202160 to 09202660 (9A)	4200-3021
09202160 to 09202660 (9E)	4200-4460
10203250 to 10203600	4200-4460
400 V	
03400034 to 03400123	4200-3480
04400185 to 04400240	4200-0252
05400300	4200-0402
06400380 to 06400630	4200-4800
07400790 to 07401120	4200-1132
08401550 to 08401840	4200-1972
09402210 to 09402660 (9A)	4200-3021
09402210 to 09402660 (9E)	4200-4460
10403200 to 10403610	4200-4460
11404370 to 11405070	4200-0400
575 V	
05500039 to 05500100	4200-0122
06500120 to 06500430	4200-3690
07500530 to 07500730	4200-0672
08500860 to 08501080	4200-1662
09501250 to 09501500 (9A)	4200-1660
09501250 to 09501500 (9E)	4200-2210
10502000	4200-2210
11502480 to 11503150	4200-0690
690 V	
07600230 to 07600730	4200-0672
08600860 to 08601080	4200-1662
09601250 to 09601550 (9A)	4200-1660
09601250 to 09601550 (9E)	4200-2210
10601720 to 10601970	4200-2210
11602250 to 11603050	4200-0690

12.2.1 EMC filter ratings

Table 12-50 Optional external EMC filter details

CT part number	Maximum continuous current		Voltage rating		IP rating	Power dissipation at rated current		Ground leakage		Discharge resistors MΩ
	@ 40 °C (104 °F)	@ 50 °C (122 °F)	IEC	UL		@ 40 °C (104 °F)	@ 50 °C (122 °F)	Balanced supply phase-to-phase and phase-to-ground mA	Worst case mA	
	A	A	V	V		W	W			
4200-3230	20	18.5	250	300	20	20	17	2.4	60	1.68
4200-0272	27	24.8	250	300		33	28	6.8	137	
4200-0312	31	28.5	250	300		20	17	2.0	80	
4200-2300	55	51	250	300		41	35	4.2	69	
4200-3480	16	15	528	600		13	11	10.7	151	
4200-0252	25	23	528	600		28	24	11.1	182	
4200-0402	40	36.8	528	600		47	40	18.7	197	
4200-4800	63	58	528	600		54	46	11.2	183	
4200-0122	12	11	760	600						
4200-3690	42	39	760	600		45	39	12	234	

12.2.2 Overall EMC filter dimensions

Table 12-51 Optional external EMC filter dimensions

CT part number	Dimension (mm)						Weight	
	H		W		D		kg	lb
	mm	inch	mm	inch	mm	inch		
4200-3230	426	16.77	83	3.27	41	1.61	1.9	4.20
4200-0272	437	17.20	123	4.84	60	2.36	4.0	8.82
4200-0312	437	17.20	143	5.63	60	2.36	5.5	12.13
4200-2300	434	17.09	210	8.27	60	2.36	6.5	14.30
4200-3480	426	16.77	83	3.27	41	1.61	2.0	4.40
4200-0252	437	17.20	123	4.84	60	2.36	4.1	9.04
4200-0402	437	17.20	143	5.63	60	2.36	5.5	12.13
4200-4800	434	17.09	210	8.27	60	2.36	6.7	14.80
4200-0122	437	17.20	143	5.63	60	2.36	5.5	12.13
4200-3690	434	17.09	210	8.27	60	2.36	7.0	15.40
4200-1132	270	10.63	90	3.54	205	5.9	6.0	13.20
4200-0672	270	10.63	90	3.54	205	5.9	6.2	13.70
4200-1972	300	11.81	120	4.72	170	6.69	9.6	21.10
4200-1662	270	10.63	90	3.54	205	8.07	9.4	20.70
4200-3021	339	13.34	230	9.06	120	4.72	11	24.25
4200-4460	105	4.13	360	14.2	245	9.65	12	26.50
4200-0400	135	5.32	386	15.2	260	10.2	14.7	32.41
4200-1660	360	14.7	245	9.65	105	4.13	5.2	11.46
4200-2210	105	4.13	360	14.2	245	9.65	10.3	22.71
4200-0690	135	5.32	386	15.2	260	10.2	16.75	36.90

12.2.3 EMC filter torque settings

Table 12-52 Optional external EMC Filter terminal data

CT part number	Power connections			Ground connections		
	Bar hole diameter	Max cable size	Max torque	Ground stud size	Max torque	
4200-1132	N/A	50 mm ² (1/0 AWG)	8.0 Nm (72 lb in)	M10	18 Nm (159.6 lb in)	
4200-0672						
4200-1972		95 mm ² (3/0 AWG)	20 Nm (177.6 lb in)			
4200-1662						
4200-0122		16 mm ² (6 AWG)	2.3 Nm (20.4 lb in)	M6	4.8 Nm (33.6 lb in)	
4200-0252						
4200-0272		1.8 Nm (6.8 lb in)				
4200-0312						
4200-0402						
4200-3230		4 mm ² (12 AWG)	0.8 Nm (7.2 lb in)	M5	3.0 Nm (26.4 lb in)	
4200-3480		4 mm ² (12 AWG)	0.8 Nm (7.2 lb in)	M5		
4200-2300		16 mm ² (6 AWG)	2.3 Nm (20.4 lb in)	M6	4.8 Nm (33.6 lb in)	
4200-4800						
4200-3690						
4200-3021		10.8 mm	N/A	30 Nm (265.2 lb in)	M10	18 Nm (159.6 lb in)
4200-4460		11 mm				
4200-1660	10.8 mm					
4200-2210	11 mm					
4200-0400	10.5 mm	M12			25 Nm (220.8 lb in)	
4200-0690	10.5 mm					

13 Diagnostics

The keypad display on the drive gives various information about the status of the drive. The keypad display provides information on the following categories:

- Trip indications
- Alarm indications
- Status indications



Users must not attempt to repair a drive if it is faulty, nor carry out fault diagnosis other than through the use of the diagnostic features described in this chapter.

WARNING If a drive is faulty, it must be returned to an authorized Control Techniques distributor for repair.

13.1 Status modes (Keypad and LED status)

Figure 13-1 Keypad status modes

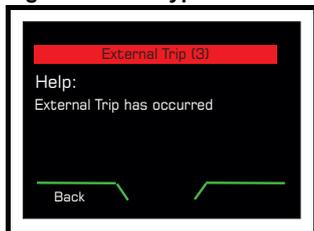
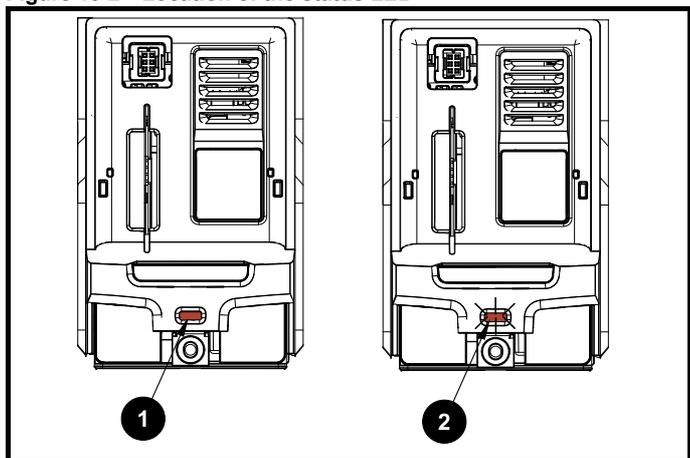


Figure 13-2 Location of the status LED



1. Non flashing: Normal status
2. Flashing: Trip status

13.2 Trip indications

The output of the drive is disabled under any trip condition so that the drive stops controlling the motor. If the motor is running when the trip occurs it will coast to a stop.

To read the latest fault data and history, the data is stored in Pr 10.020 through to Pr 10.029 with Pr 10.020 being the most recent.

To access fault data go to - Main Menu/Drive Menus/10: Status and Trips

Pr 10.020 Trip 0 - Most recent Trip data Pr 10.070 sub-trip data for Pr 10.020.

Pr 10.021 Trip 1 Pr 10.071 Sub-trip data for Pr 10.021

Through to:

Pr 10.029 Trip 9 Pr 10.029 Sub-trip Data for Pr 10.029

13.3 Identifying a trip / trip source

Some trips only contain a trip string whereas some other trips have a trip string along with a sub-trip number which provides the user with additional information about the trip.

A trip can be generated from a control system or from a power system. The sub-trip number associated with the trips listed in Table 13-1 is in the form xxyz and used to identify the source of the trip.

Table 13-1 Trips associated with xxyz sub-trip number

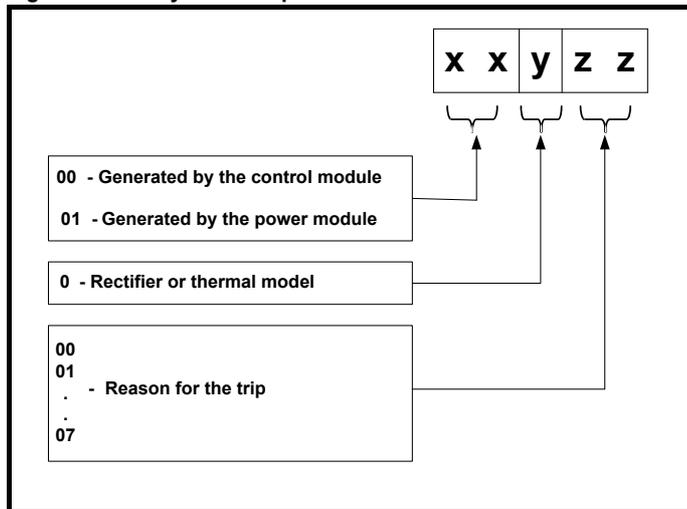
Over Volts	OHT dc bus
OI ac	Phase Loss
OI Brake	Power Comms
PSU	OI Snubber
OHT Inverter	Temp Feedback
OHT Power	Power Data
OHT Control	

The digits xx are 00 for a trip generated by the control system. For a single drive (not part of a multi-power module drive), if the trip is related to the power system then xx will have a value of 01, when displayed the leading zeros are suppressed.

The y digit is used to identify the location of a trip which is generated by a rectifier module connected to a power module (if xx is non zero). For a control system trip (xx is zero), the y digit, where relevant is defined for each trip. If not relevant, the y digit will have a value of zero.

The zz digits give the reason for the trip and are defined in each trip description.

Figure 13-3 Key to sub-trip number



For example, if the drive has tripped and the lower line of the display shows 'OHT Control.2', with the help Table 13-2 below the trip can be interpreted as; an over temperature has been detected; the trip was generated by fault in the control module, the control board thermistor 2 over temperature.

Table 13-2 Sub-trip identification

Source	xx	y	zz	Description
Control system	00	0	01	Control board thermistor 1 over temperature
Control system	00	0	02	Control board thermistor 2 over temperature
Control system	00	0	03	Control board thermistor 3 over temperature

13.4 Trips, Sub-trip numbers

Table 13-3 Trip indications

Trip	Diagnosis								
Active Rectifier	Active Rectifier								
95	Normally active input rectifier trips give similar trips to the output converter that controls the motor with a suitable sub-trip code to indicate that the trip has been initiated by the rectifier. However it is possible for a fault in the active input rectifier control board to cause other trips that are not intercepted by the main control board. These are indicated by this trip with a sub-trip code that indicates the reason for the trip. The sub-trip code value corresponds to the trips defined by <i>Trip 0 (10.020)</i> .								
An Input 1 Loss	Analog input 1 current loss								
28	<p><i>An Input 1 Loss</i> trip indicates that a current loss was detected in current mode on Analog input 1 (Terminal 5, 6). In 4-20 mA and 20-4 mA modes loss of input is detected if the current falls below 3 mA.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Check control wiring is correct • Check control wiring is undamaged • Check the <i>Analog Input 1 Mode (07.007)</i> • Current signal is present and greater than 3 mA 								
An Input 2 Loss	Analog input 2 current loss								
29	<p><i>An Input 2 Loss</i> indicates that a current loss was detected in current mode on Analog input 2 (Terminal 7). In 4-20 mA and 20-4 mA modes loss of input is detected if the current falls below 3 mA.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Check control wiring is correct • Check control wiring is undamaged • Check the <i>Analog Input 2 Mode (07.011)</i> • Current signal is present and greater than 3 mA 								
An Output Calib	Analog output calibration failed								
219	<p>The zero offset calibration of one or both of the analogue outputs has failed. This indicates that the drive hardware has failed or a voltage is applied to the output via a low impedance, possibly due to a wiring error. The failed output can be identified by the sub-trip number.</p> <table border="1"> <thead> <tr> <th>Sub-trip</th> <th>Reason</th> </tr> </thead> <tbody> <tr> <td>1</td> <td>Output 1 failed (Terminal 9)</td> </tr> <tr> <td>2</td> <td>Output 2 failed (Terminal 10)</td> </tr> </tbody> </table> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Check the wiring associated with analog outputs • Remove all the wiring that is connected to analog outputs and perform a re-calibration by power cycling the drive. • If trip persists replace the drive 	Sub-trip	Reason	1	Output 1 failed (Terminal 9)	2	Output 2 failed (Terminal 10)		
Sub-trip	Reason								
1	Output 1 failed (Terminal 9)								
2	Output 2 failed (Terminal 10)								
App Menu Changed	Customization table for an application module has changed								
217	<p>The <i>App Menu Changed</i> trip indicates that the customization table for an application menu has changed. The menu that has been changed can be identified by the sub-trip number.</p> <table border="1"> <thead> <tr> <th>Sub-trip</th> <th>Reason</th> </tr> </thead> <tbody> <tr> <td>1</td> <td>Menu 18</td> </tr> <tr> <td>2</td> <td>Menu 19</td> </tr> <tr> <td>3</td> <td>Menu 20</td> </tr> </tbody> </table> <p>If more than one menu has changed the lowest menu has priority. Drive user parameters must be saved to prevent this trip on the next power-up.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Reset the trip and perform a parameter save to accept the new settings 	Sub-trip	Reason	1	Menu 18	2	Menu 19	3	Menu 20
Sub-trip	Reason								
1	Menu 18								
2	Menu 19								
3	Menu 20								
Autotune 1	Position feedback did not change or required speed could not be reached								
11	<p>The drive has tripped during an autotune. The cause of the trip can be identified from the sub-trip number.</p> <table border="1"> <thead> <tr> <th>Sub-trip</th> <th>Reason</th> </tr> </thead> <tbody> <tr> <td>1</td> <td>The position feedback did not change when position feedback is being used during rotating autotune.</td> </tr> <tr> <td>2</td> <td>The motor did not reach the required speed during rotating autotune or mechanical load measurement.</td> </tr> </tbody> </table> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Ensure the motor is free to turn i.e. mechanical brake was released • Ensure Pr 03.026 is set correctly (or appropriate 2nd motor map parameter) • Check feedback device wiring is correct • Check encoder mechanical coupling to the motor 	Sub-trip	Reason	1	The position feedback did not change when position feedback is being used during rotating autotune.	2	The motor did not reach the required speed during rotating autotune or mechanical load measurement.		
Sub-trip	Reason								
1	The position feedback did not change when position feedback is being used during rotating autotune.								
2	The motor did not reach the required speed during rotating autotune or mechanical load measurement.								

Trip	Diagnosis								
Autotune 2	Position feedback direction incorrect								
12	The drive has tripped during a rotating autotune. The cause of the trip can be identified from the associated sub-trip number.								
	<table border="1"> <thead> <tr> <th>Sub-trip</th> <th>Reason</th> </tr> </thead> <tbody> <tr> <td>1</td> <td>The position feedback direction is incorrect when position feedback is being used during a rotating autotune</td> </tr> <tr> <td>2</td> <td>A SINCOS encoder with comms is being used for position feedback and the comms position is rotating in the opposite direction to the sine wave based position.</td> </tr> </tbody> </table>	Sub-trip	Reason	1	The position feedback direction is incorrect when position feedback is being used during a rotating autotune	2	A SINCOS encoder with comms is being used for position feedback and the comms position is rotating in the opposite direction to the sine wave based position.		
	Sub-trip	Reason							
1	The position feedback direction is incorrect when position feedback is being used during a rotating autotune								
2	A SINCOS encoder with comms is being used for position feedback and the comms position is rotating in the opposite direction to the sine wave based position.								
<p>Recommended actions:</p> <ul style="list-style-type: none"> • Check motor cable wiring is correct • Check feedback device wiring is correct • Swap any two motor phases 									
Autotune 3	Measured inertia has exceeded the parameter range or commutation signals changed in wrong direction								
13	The drive has tripped during a rotating autotune or mechanical load measurement test. The cause of the trip can be identified from the associated sub-trip number.								
	<table border="1"> <thead> <tr> <th>Sub-trip</th> <th>Reason</th> </tr> </thead> <tbody> <tr> <td>1</td> <td>Measured inertia has exceeded the parameter range during a mechanical load measurement</td> </tr> <tr> <td>2</td> <td>The commutation signals changed in the wrong direction during a rotating autotune</td> </tr> <tr> <td>3</td> <td>The mechanical load test has been unable to identify the motor inertia</td> </tr> </tbody> </table>	Sub-trip	Reason	1	Measured inertia has exceeded the parameter range during a mechanical load measurement	2	The commutation signals changed in the wrong direction during a rotating autotune	3	The mechanical load test has been unable to identify the motor inertia
	Sub-trip	Reason							
	1	Measured inertia has exceeded the parameter range during a mechanical load measurement							
2	The commutation signals changed in the wrong direction during a rotating autotune								
3	The mechanical load test has been unable to identify the motor inertia								
<p>Recommended actions for sub-trip 2:</p> <ul style="list-style-type: none"> • Check motor cable wiring is correct • Check feedback device U,V and W commutation signal wiring is correct 									
<p>Recommended actions for sub-trip 3:</p> <ul style="list-style-type: none"> • Increase the test level. • If the test was carried out at standstill repeat the test with the motor rotating within the recommended speed range. 									
Autotune 4	Autotune 4								
14	A position feedback device with commutation signals is being used (i.e. AB Servo, FD Servo, FR Servo, SC Servo or Commutation Only encoder) and the U commutation signal did not change during a rotating auto-tune.								
	<p>Recommended actions:</p> <ul style="list-style-type: none"> • Check feedback device U commutation signal wiring is correct (Encoder terminals 7 and 8). 								
Autotune 5	Autotune 5								
15	A position feedback device with commutation signals is being used (i.e. AB Servo, FD Servo, FR Servo, SC Servo or Commutation Only encoder) and the V commutation signal did not change during a rotating auto-tune.								
	<p>Recommended actions:</p> <ul style="list-style-type: none"> • Check feedback device V commutation signal wiring is correct (Encoder terminals 9 and 10). 								
Autotune 6	Autotune 6								
16	A position feedback device with commutation signals is being used (i.e. AB Servo, FD Servo, FR Servo, SC Servo or Commutation Only encoder) and the W commutation signal did not change during a rotating auto-tune.								
	<p>Recommended actions:</p> <ul style="list-style-type: none"> • Check feedback device W commutation signal wiring is correct (Encoder terminals 11 and 12). 								
Autotune 7	Motor number of poles / position feedback resolution set incorrectly								
17	An <i>Autotune 7</i> trip is initiated during a rotating autotune, if the motor poles or the position feedback resolution have been set up incorrectly where position feedback is being used.								
	<p>Recommended actions:</p> <ul style="list-style-type: none"> • Check line per revolution for feedback device • Check the number of poles in Pr 05.011 								
Autotune Stopped	Autotune test stopped before completion								
18	The drive was prevented from completing an autotune test, because either the drive enable or the drive run were removed.								
	<p>Recommended actions:</p> <ul style="list-style-type: none"> • Check the drive enable signal (Terminal 29) was active during the autotune • Check the run command was active in Pr 08.005 during autotune 								

Trip	Diagnosis														
Brake R Too Hot	Braking resistor overload timed out (I²t)														
19	<p>The <i>Brake R Too Hot</i> indicates that braking resistor overload has timed out. The value in <i>Braking Resistor Thermal Accumulator</i> (10.039) is calculated using <i>Braking Resistor Rated Power</i> (10.030), <i>Braking Resistor Thermal Time Constant</i> (10.031) and <i>Braking Resistor Resistance</i> (10.061). The <i>Brake R Too Hot</i> trip is initiated when <i>Braking Resistor Thermal Accumulator</i> (10.039) reaches 100 %.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> Ensure the values entered in Pr 10.030, Pr 10.031 and Pr 10.061 are correct If an external thermal protection device is being used and the braking resistor software overload protection is not required, set Pr 10.030, Pr 10.031 or Pr 10.061 to 0 to disable the trip. 														
CAM	Advanced motion controller cam failure														
99	<p>Advanced motion controller cam failure.</p> <table border="1"> <thead> <tr> <th>Sub-trip</th> <th>Reason</th> </tr> </thead> <tbody> <tr> <td>1</td> <td>Measured inertia has exceeded the parameter range during a mechanical load measurement</td> </tr> <tr> <td>2</td> <td>The commutation signals changed in the wrong direction during a rotating autotune</td> </tr> <tr> <td>3</td> <td>The mechanical load test has been unable to identify the motor inertia</td> </tr> </tbody> </table> <p>Recommended actions:</p> <ul style="list-style-type: none"> Check the cam setup parameters in menu 35 and cam table parameters in menu 36. 	Sub-trip	Reason	1	Measured inertia has exceeded the parameter range during a mechanical load measurement	2	The commutation signals changed in the wrong direction during a rotating autotune	3	The mechanical load test has been unable to identify the motor inertia						
Sub-trip	Reason														
1	Measured inertia has exceeded the parameter range during a mechanical load measurement														
2	The commutation signals changed in the wrong direction during a rotating autotune														
3	The mechanical load test has been unable to identify the motor inertia														
Cloning	Failure of the cloning function														
102	<p>If an attempt is made to use the cloning system to back-up the drive and option modules (parameter mm.000 values from 40001 to 40999) or restore the drive and option modules (parameter mm.000 values from 60001 to 60999) and the action fails then a "Cloning" trip is initiated. The sub-trip value indicates the reason for the trip.</p> <table border="1"> <thead> <tr> <th>Sub-trip</th> <th>Reason</th> </tr> </thead> <tbody> <tr> <td>1</td> <td>The option module in Slot 1 has indicated that it will either back-up or restore its data to/from an SD card, but has failed to respond correctly and the system has timed out.</td> </tr> <tr> <td>2</td> <td>As 1, but for Option Slot 2.</td> </tr> <tr> <td>3</td> <td>As 1, but for Option Slot 3.</td> </tr> <tr> <td>4</td> <td>As 1, but for Option Slot 4.</td> </tr> <tr> <td>5</td> <td>Back-up folders exist or cannot be created when a back-up is initiated.</td> </tr> <tr> <td>6</td> <td>The required back-up folders do not exist when a restore is initiated.</td> </tr> </tbody> </table>	Sub-trip	Reason	1	The option module in Slot 1 has indicated that it will either back-up or restore its data to/from an SD card, but has failed to respond correctly and the system has timed out.	2	As 1, but for Option Slot 2.	3	As 1, but for Option Slot 3.	4	As 1, but for Option Slot 4.	5	Back-up folders exist or cannot be created when a back-up is initiated.	6	The required back-up folders do not exist when a restore is initiated.
Sub-trip	Reason														
1	The option module in Slot 1 has indicated that it will either back-up or restore its data to/from an SD card, but has failed to respond correctly and the system has timed out.														
2	As 1, but for Option Slot 2.														
3	As 1, but for Option Slot 3.														
4	As 1, but for Option Slot 4.														
5	Back-up folders exist or cannot be created when a back-up is initiated.														
6	The required back-up folders do not exist when a restore is initiated.														
Configuration	The number of power modules installed is different from the modules expected														
111	<p>The <i>Configuration</i> trip indicates that the <i>Number Of Power Modules Detected</i> (11.071) does not match the previous value stored. The sub-trip value indicates the number of power modules expected.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> Ensure that all the power modules are correctly connected Ensure all the power modules have powered up correctly Ensure that the value in Pr 11.071 is set to the number of power modules connected Set Pr 11.035 to 0 to disable the trip if it is not required <p>This trip is also initiated if the number of external rectifiers connected to each power module is less than the number defined by <i>Number Of Rectifiers Expected</i> (11.096). If this is the reason for the trip the sub-trip is 10x where x is the number of external rectifiers that should be connected.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> Ensure that all the external rectifiers are connected correctly. Ensure that the value in <i>Number Of Rectifiers Expected</i> (11.096) is correct. 														
Control Word	Trip initiated from the Control Word (06.042)														
35	<p>The <i>Control Word</i> trip is initiated by setting bit 12 on the control word in Pr 06.042 when the control word is enabled (Pr 06.043 = On).</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> Check the value of Pr 06.042. Disable the control word in <i>Control Word Enable</i> (Pr 06.043) <p>Bit 12 of the control word set to a one causes the drive to trip on Control Word</p> <p>When the control word is enabled, the trip can only be cleared by setting bit 12 to zero</p>														
Current Offset	Current feedback offset error														

Trip	Diagnosis								
225	<p>The current feedback offset is too large to be trimmed correctly. The sub-trip relates to the output phase for which the offset error has been detected.</p> <table border="1" style="margin-left: 20px;"> <thead> <tr> <th style="text-align: center;">Sub-trip</th> <th style="text-align: center;">Phase</th> </tr> </thead> <tbody> <tr> <td style="text-align: center;">1</td> <td style="text-align: center;">U</td> </tr> <tr> <td style="text-align: center;">2</td> <td style="text-align: center;">V</td> </tr> <tr> <td style="text-align: center;">3</td> <td style="text-align: center;">W</td> </tr> </tbody> </table> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Ensure that there is no possibility of current flowing in the output phases of the drive when the drive is not enabled • Hardware fault – Contact the supplier of the drive 	Sub-trip	Phase	1	U	2	V	3	W
Sub-trip	Phase								
1	U								
2	V								
3	W								
Data Changing	Drive parameters are being changed								
97	<p>A user action or a file system write is active that is changing the drive parameters and the drive has been commanded to enable, i.e. <i>Drive Active (10.002)</i> = 1. The user actions that change drive parameters are loading defaults, changing drive mode, or transferring data from an NV memory card or a position feedback device to the drive. The file system actions that will cause this trip to be initiated if the drive is enabled during the transfer are writing a parameter or macro file to the drive, or transferring a derivative or user program to the drive. It should be noted that none of these actions can be started if the drive is active, and so the trip only occurs if the action is started and then the drive is enabled.</p> <p>Recommended actions:</p> <p>Ensure the drive is not enabled when one of the following is being carried out:</p> <ul style="list-style-type: none"> • Loading defaults • Changing drive mode • Transferring data from NV Media Card or position feedback device • Transferring user programs 								
Derivative ID	There is a problem with the identifier associated with derivative image which customizes the drive.								
247	<p>There is a problem with the identifier associated with derivative image which customizes the drive. The reason for the trip is given by the sub-trip as follows:</p> <table border="1" style="margin-left: 20px;"> <thead> <tr> <th style="text-align: center;">Sub-trip</th> <th style="text-align: center;">Reason</th> </tr> </thead> <tbody> <tr> <td style="text-align: center;">1</td> <td>There should be a derivative image in the product but this has been erased.</td> </tr> <tr> <td style="text-align: center;">2</td> <td>The identifier is out of range.</td> </tr> <tr> <td style="text-align: center;">3</td> <td>The derivative image has been changed.</td> </tr> </tbody> </table>	Sub-trip	Reason	1	There should be a derivative image in the product but this has been erased.	2	The identifier is out of range.	3	The derivative image has been changed.
Sub-trip	Reason								
1	There should be a derivative image in the product but this has been erased.								
2	The identifier is out of range.								
3	The derivative image has been changed.								

Trip	Diagnosis		
Derivative Image	Derivative Image error		
248	The <i>Derivative Image</i> trip indicates that an error has been detected in the derivative image. The sub-trip number indicates the reason for the trip.		
	Sub-trip	Reason	Comments
	1 to 52	An error has been detected in the derivative image, contact the supplier of the drive.	
	61	The option module fitted in slot 1 is not allowed with the derivative image	Occurs when the drive powers-up or the image is programmed. The image tasks will not run.
	62	The option module fitted in slot 2 is not allowed with the derivative image	
	63	The option module fitted in slot 3 is not allowed with the derivative image	
	64	The option module fitted in slot 4 is not allowed with the derivative image	
	70	An option module that is required by the derivative image is not fitted in any slot	Occurs when the drive powers-up or the image is programmed. The image tasks will not run.
	71	An option module specifically required to be fitted in slot 1 not present	
	72	An option module specifically required to be fitted in slot 2 not present	
	73	An option module specifically required to be fitted in slot 3 not present	
	74	An option module specifically required to be fitted in slot 4 not present	
	80 to 81	An error has been detected in the derivative image, contact the supplier of the drive.	
Recommended action: Contact the supplier of the drive			
Destination	Two or more parameters are writing to the same destination parameter		
199	The <i>Destination</i> trip indicates that destination output parameters of two or more logic functions (Menus 5, 7, 8, 9, 12 or 14) within the drive are writing to the same parameter. Recommended actions: <ul style="list-style-type: none"> Set Pr mm.000 to 'Destinations' or 12001 and check all visible parameters in all menus for parameter write conflicts 		
Drive Size	Power stage recognition: Unrecognized drive size		
224	The <i>Drive Size</i> trip indicates that the control PCB has not recognized the drive size of the power circuit to which it is connected. Recommended action: <ul style="list-style-type: none"> Ensure the drive is programmed to the latest firmware version Hardware fault - return drive to supplier 		

Trip	Diagnosis																				
EEPROM Fail	Default parameters have been loaded																				
31	<p>The <i>EEPROM Fail</i> trip indicates that default parameters have been loaded. The exact cause/reason of the trip can be identified from the sub-trip number.</p> <table border="1"> <thead> <tr> <th>Sub-trip</th> <th>Reason</th> </tr> </thead> <tbody> <tr> <td>1</td> <td>The most significant digit of the internal parameter database version number has changed</td> </tr> <tr> <td>2</td> <td>The CRC's applied to the parameter data stored in internal non-volatile memory indicate that a valid set of parameters cannot be loaded</td> </tr> <tr> <td>3</td> <td>The drive mode restored from internal non-volatile memory is outside the allowed range for the product or the derivative image does not allow the previous drive mode</td> </tr> <tr> <td>4</td> <td>The drive derivative image has changed</td> </tr> <tr> <td>5</td> <td>The power stage hardware has changed</td> </tr> <tr> <td>6</td> <td>The internal I/O hardware has changed</td> </tr> <tr> <td>7</td> <td>The position feedback interface hardware has changed</td> </tr> <tr> <td>8</td> <td>The control board hardware has changed</td> </tr> <tr> <td>9</td> <td>The checksum on the non-parameter area of the EEPROM has failed</td> </tr> </tbody> </table> <p>The drive holds two banks of user save parameters and two banks of power down save parameters in non-volatile memory. If the last bank of either set of parameters that was saved is corrupted a User Save or Power Down Save trip is produced. If one of these trips occurs the parameters values that were last saved successfully are used. It can take some time to save parameters when requested by the user and if the power is removed from the drive during this process it is possible to corrupt the data in the non-volatile memory.</p> <p>If both banks of user save parameters or both banks of power down save parameters are corrupted or one of the other conditions given in the table above occurs EEPROM Fail.xxx trip is produced. If this trip occurs it is not possible to use the data that has been saved previously, and so the drive will be in lowest allowed drive mode with default parameters. The trip can only be reset if Pr mm.000 (mm.000) is set to 10, 11, 1233 or 1244 or if <i>Load Defaults</i> (11.043) is set to a non-zero value.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Default the drive and perform a reset • Allow sufficient time to perform a save before the supply to the drive is removed • If the trip persists - return drive to supplier 	Sub-trip	Reason	1	The most significant digit of the internal parameter database version number has changed	2	The CRC's applied to the parameter data stored in internal non-volatile memory indicate that a valid set of parameters cannot be loaded	3	The drive mode restored from internal non-volatile memory is outside the allowed range for the product or the derivative image does not allow the previous drive mode	4	The drive derivative image has changed	5	The power stage hardware has changed	6	The internal I/O hardware has changed	7	The position feedback interface hardware has changed	8	The control board hardware has changed	9	The checksum on the non-parameter area of the EEPROM has failed
	Sub-trip	Reason																			
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	7	The position feedback interface hardware has changed																			
	8	The control board hardware has changed																			
9	The checksum on the non-parameter area of the EEPROM has failed																				
External Trip	An External trip is initiated																				
6	<p>An <i>External Trip</i> has occurred. The cause of the trip can be identified from the sub trip number displayed after the trip string. See table below. An external trip can also be initiated by writing a value of 6 in Pr 10.038.</p> <table border="1"> <thead> <tr> <th>Sub-trip</th> <th>Reason</th> </tr> </thead> <tbody> <tr> <td>1</td> <td><i>External Trip Mode</i> (08.010) = 1 or 3 and Safe Torque Off input 1 is low</td> </tr> <tr> <td>2</td> <td><i>External Trip Mode</i> (08.010) = 2 or 3 and Safe Torque Off input 2 is low</td> </tr> <tr> <td>3</td> <td><i>External Trip</i> (10.032) = 1</td> </tr> </tbody> </table> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Check the Safe Torque Off signal voltage on terminal 29 equals to 24 V • Check the value of Pr 08.009 which indicates the digital state of terminal 29, equates to 'on'. • If external trip detection of the Safe Torque Off input is not required, set Pr 08.010 to Off (0). • Check the value of Pr 10.032. • Select 'Destinations' (or enter 12001) in Pr mm.000 and check for a parameter controlling Pr 10.032. • Ensure Pr 10.032 or Pr 10.038 (= 6) is not being controlled by serial comms 	Sub-trip	Reason	1	<i>External Trip Mode</i> (08.010) = 1 or 3 and Safe Torque Off input 1 is low	2	<i>External Trip Mode</i> (08.010) = 2 or 3 and Safe Torque Off input 2 is low	3	<i>External Trip</i> (10.032) = 1												
	Sub-trip	Reason																			
	1	<i>External Trip Mode</i> (08.010) = 1 or 3 and Safe Torque Off input 1 is low																			
	2	<i>External Trip Mode</i> (08.010) = 2 or 3 and Safe Torque Off input 2 is low																			
3	<i>External Trip</i> (10.032) = 1																				
HF01	Data processing error: CPU address error																				
	<p>The <i>HF01</i> trip indicates that a CPU address error has occurred. This trip indicates that the control PCB on the drive has failed.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Hardware fault – Contact the supplier of the drive 																				

Trip	Diagnosis
HF02	Data processing error: DMAC address error
	The <i>HF02</i> trip indicates that a DMAC address error has occurred. This trip indicates that the control PCB on the drive has failed. Recommended actions: <ul style="list-style-type: none"> Hardware fault – Contact the supplier of the drive
HF03	Data processing error: Illegal instruction
	The <i>HF03</i> trip indicates that an illegal instruction has occurred. This trip indicates that the control PCB on the drive has failed. Recommended actions: <ul style="list-style-type: none"> Hardware fault – Contact the supplier of the drive
HF04	Data processing error: Illegal slot instruction
	The <i>HF04</i> trip indicates that an illegal slot instruction has occurred. This trip indicates that the control PCB on the drive has failed. Recommended actions: <ul style="list-style-type: none"> Hardware fault – Contact the supplier of the drive
HF05	Data processing error: Undefined exception
	The <i>HF05</i> trip indicates that an undefined exception error has occurred. This trip indicates that the control PCB on the drive has failed. Recommended actions: <ul style="list-style-type: none"> Hardware fault – Contact the supplier of the drive
HF06	Data processing error: Reserved exception
	The <i>HF06</i> trip indicates that a reserved exception error has occurred. This trip indicates that the control PCB on the drive has failed. Recommended actions: <ul style="list-style-type: none"> Hardware fault – Contact the supplier of the drive
HF07	Data processing error: Watchdog failure
	The <i>HF07</i> trip indicates that a watchdog failure has occurred. This trip indicates that the control PCB on the drive has failed. Recommended actions: <ul style="list-style-type: none"> Hardware fault – Contact the supplier of the drive
HF08	Data processing error: CPU interrupt crash
	The <i>HF08</i> trip indicates that a CPU interrupt crash has occurred. This trip indicates that the control PCB on the drive has failed. Recommended actions: <ul style="list-style-type: none"> Hardware fault – Contact the supplier of the drive
HF09	Data processing error: Free store overflow
	The <i>HF09</i> trip indicates that a free store overflow has occurred. This trip indicates that the control PCB on the drive has failed. Recommended actions: <ul style="list-style-type: none"> Hardware fault – Contact the supplier of the drive
HF10	Data processing error: Parameter routing system error
	The <i>HF10</i> trip indicates that a Parameter routing system error has occurred. This trip indicates that the control PCB on the drive has failed. Recommended actions: <ul style="list-style-type: none"> Hardware fault – Contact the supplier of the drive
HF11	Data processing error: Access to EEPROM failed
	The <i>HF11</i> trip indicates that access to the drive EEPROM has failed. This trip indicates that the control PCB on the drive has failed. Recommended actions: <ul style="list-style-type: none"> Hardware fault – Contact the supplier of the drive

Trip	Diagnosis																				
HF12	<p>Data processing error: Main program stack overflow</p> <p>The <i>HF12</i> trip indicates that the main program stack over flow has occurred. The stack can be identified by the sub-trip number. This trip indicates that the control PCB on the drive has failed.</p> <table border="1"> <thead> <tr> <th>Sub-trip</th> <th>Stack</th> </tr> </thead> <tbody> <tr> <td>1</td> <td>Background tasks</td> </tr> <tr> <td>2</td> <td>Timed tasks</td> </tr> <tr> <td>3</td> <td>Main system interrupts</td> </tr> </tbody> </table> <p>Recommended actions:</p> <ul style="list-style-type: none"> Hardware fault – Contact the supplier of the drive 	Sub-trip	Stack	1	Background tasks	2	Timed tasks	3	Main system interrupts												
Sub-trip	Stack																				
1	Background tasks																				
2	Timed tasks																				
3	Main system interrupts																				
HF13	<p>Data processing error: Firmware incompatible with hardware</p> <p>The <i>HF13</i> trip indicates that the drive firmware is not compatible with the hardware. This trip indicates that the control PCB on the drive has failed. The sub-trip number gives the actual ID code of the control board hardware.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> Re-program the drive with the latest version of the drive firmware Hardware fault – Contact the supplier of the drive 																				
HF14	<p>Data processing error: CPU register bank error</p> <p>The <i>HF14</i> trip indicates that a CPU register bank error has occurred. This trip indicates that the control PCB on the drive has failed.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> Hardware fault – Contact the supplier of the drive 																				
HF15	<p>Data processing error: CPU divide error</p> <p>The <i>HF15</i> trip indicates that a CPU divide error has occurred. This trip indicates that the control PCB on the drive has failed.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> Hardware fault – Contact the supplier of the drive 																				
HF16	<p>Data processing error: RTOS error</p> <p>The <i>HF16</i> trip indicates that a RTOS error has occurred. This trip indicates that the control PCB on the drive has failed.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> Hardware fault – Contact the supplier of the drive 																				
HF17	<p>Data processing error: Clock supplied to the control board is out of specification</p> <p>The <i>HF17</i> trip indicates that the clock supplied to the control board logic is out of specification. This trip indicates that the control PCB on the drive has failed.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> Hardware fault – Contact the supplier of the drive 																				
HF18	<p>Data processing error: Internal flash memory has failed</p> <p>The <i>HF18</i> trip indicates that the internal flash memory has failed when writing option module parameter data. The reason for the trip can be identified by the sub-trip number.</p> <table border="1"> <thead> <tr> <th>Sub-trip</th> <th>Reason</th> </tr> </thead> <tbody> <tr> <td>1</td> <td>Option module initialization timed out</td> </tr> <tr> <td>2</td> <td>Programming error while writing menu in flash</td> </tr> <tr> <td>3</td> <td>Erase flash block containing setup menus failed</td> </tr> <tr> <td>4</td> <td>Erase flash block containing application menus failed</td> </tr> <tr> <td>5</td> <td>Incorrect setup menu CRC contained in flash</td> </tr> <tr> <td>6</td> <td>Incorrect application menu CRC contained in flash</td> </tr> <tr> <td>7</td> <td>Incorrect common application menu 18 CRC contained in flash</td> </tr> <tr> <td>8</td> <td>Incorrect common application menu 19 CRC contained in flash</td> </tr> <tr> <td>9</td> <td>Incorrect common application menu 20 CRC contained in flash</td> </tr> </tbody> </table> <p>Recommended actions:</p> <ul style="list-style-type: none"> Hardware fault - Contact the supplier of the drive. 	Sub-trip	Reason	1	Option module initialization timed out	2	Programming error while writing menu in flash	3	Erase flash block containing setup menus failed	4	Erase flash block containing application menus failed	5	Incorrect setup menu CRC contained in flash	6	Incorrect application menu CRC contained in flash	7	Incorrect common application menu 18 CRC contained in flash	8	Incorrect common application menu 19 CRC contained in flash	9	Incorrect common application menu 20 CRC contained in flash
Sub-trip	Reason																				
1	Option module initialization timed out																				
2	Programming error while writing menu in flash																				
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7	Incorrect common application menu 18 CRC contained in flash																				
8	Incorrect common application menu 19 CRC contained in flash																				
9	Incorrect common application menu 20 CRC contained in flash																				
HF19	<p>Data processing error: CRC check on the firmware has failed</p> <p>The <i>HF19</i> trip indicates that the CRC check on the drive firmware has failed.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> Re-program the drive Hardware fault - Contact the supplier of the drive 																				

Trip	Diagnosis																				
HF20	Data processing error: ASIC is not compatible with the hardware																				
	The <i>HF20</i> trip indicates that the ASIC version is not compatible with the drive firmware. The ASIC version can be identified from the sub-trip number. Recommended actions: <ul style="list-style-type: none"> Hardware fault - Contact the supplier of the drive 																				
HF23 to HF28	Hardware fault																				
	Recommended actions: <ul style="list-style-type: none"> Hardware fault - Contact the supplier of the drive 																				
I/O Overload	Digital output overload																				
26	The <i>I/O Overload</i> trip indicates that the total current drawn from 24 V user supply or from the digital output has exceeded the limit. A trip is initiated if one or more of the following conditions: <ul style="list-style-type: none"> Maximum output current from one digital output is 100 mA. The combined maximum output current from outputs 1 and 2 is 100 mA The combined maximum output current from output 3 and +24 V output is 100 mA Recommended actions: <ul style="list-style-type: none"> Check total loads on digital outputs Check control wiring is correct Check output wiring is undamaged 																				
Inductance	This trip occurs in RFC-S mode when the drive has detected that the motor inductances are not suitable.																				
8	This trip occurs in RFC-S mode when the drive has detected that the motor inductances are not suitable for the operation being attempted. The trip is either caused because the ratio or difference between Ld and Lq is too small or because the saturation characteristic of the motor cannot be measured. If the inductance ratio or difference is too small this is because one of the following conditions is true: $(\text{No-load } L_q \text{ (05.072)} - L_d \text{ (05.024)}) / L_d \text{ (05.024)} < 0.1$ $(\text{No-load } L_q \text{ (05.072)} - L_d \text{ (05.024)}) < (K / \text{Full Scale Current } K_c \text{ (11.061)})H$ where: <table border="1" style="margin-left: 20px;"> <thead> <tr> <th>Drive Rated voltage (11.033)</th> <th>K</th> </tr> </thead> <tbody> <tr> <td>200 V</td> <td>0.0073</td> </tr> <tr> <td>400 V</td> <td>0.0146</td> </tr> <tr> <td>575 V</td> <td>0.0174</td> </tr> <tr> <td>690 V</td> <td>0.0209</td> </tr> </tbody> </table> If the saturation characteristic of the motor cannot be measured this is because when the flux in the motor is changed the measured value of Ld does change sufficiently due to saturation to be measured. When half of <i>Rated Current</i> (05.007) is applied in the d axis of the motor in each direction the inductance must fall change at least $(K / (2 \times \text{Full Scale Current } K_c \text{ (11.061)))) H$. The specific reasons for each of the sub-trips and recommended actions are given in the table below. <table border="1" style="margin-left: 20px;"> <thead> <tr> <th>Sub-trip</th> <th>Reason</th> </tr> </thead> <tbody> <tr> <td>1</td> <td>The inductance ratio or difference is too small when the drive has been started in sensorless mode.</td> </tr> <tr> <td>2</td> <td>The saturation characteristic of the motor cannot be measured when the drive has been started in sensorless mode.</td> </tr> <tr> <td>3</td> <td>The inductance ratio or difference is too small when an attempt is made to determine the location of the motor flux during a stationary auto-tune in RFC-S mode. This trip is also produced when the inductance ratio or inductance difference is too small when carrying out a phasing test on starting in RFC-S mode. If position feedback is being used the measured value for <i>Position Feedback Phase Angle</i> (03.025) may not be reliable. Also the measured values of <i>Ld</i> (05.024) and <i>No-load Lq</i> (05.072) may not correspond to the d and q axis respectively.</td> </tr> <tr> <td>4</td> <td>The direction of the flux in the motor is detected by the change of inductance with different currents. This trip is initiated if the change cannot be detected when an attempt is made to perform a stationary auto-tune when position feedback is being used, or to perform a phasing test on starting in RFC-S mode.</td> </tr> </tbody> </table> Recommended actions for sub-trip 1: <ul style="list-style-type: none"> Ensure that RFC Low Speed Mode (05.064) is set to Non-salient (1), Current (2) or Current No test (3). Recommended Actions For Sub-trip 2: <ul style="list-style-type: none"> Ensure that RFC Low Speed Mode (05.064) is set to Non-salient (1), Current (2) or Current No test (3). Recommended actions for sub-trip 3: <ul style="list-style-type: none"> None. The trip acts as a warning. Recommended actions for sub-trip 4: <ul style="list-style-type: none"> Stationary autotune is not possible. Perform a minimal movement or rotating autotune. Phasing test on starting is not possible. Use a position feedback device with commutation signals or absolute position. 	Drive Rated voltage (11.033)	K	200 V	0.0073	400 V	0.0146	575 V	0.0174	690 V	0.0209	Sub-trip	Reason	1	The inductance ratio or difference is too small when the drive has been started in sensorless mode.	2	The saturation characteristic of the motor cannot be measured when the drive has been started in sensorless mode.	3	The inductance ratio or difference is too small when an attempt is made to determine the location of the motor flux during a stationary auto-tune in RFC-S mode. This trip is also produced when the inductance ratio or inductance difference is too small when carrying out a phasing test on starting in RFC-S mode. If position feedback is being used the measured value for <i>Position Feedback Phase Angle</i> (03.025) may not be reliable. Also the measured values of <i>Ld</i> (05.024) and <i>No-load Lq</i> (05.072) may not correspond to the d and q axis respectively.	4	The direction of the flux in the motor is detected by the change of inductance with different currents. This trip is initiated if the change cannot be detected when an attempt is made to perform a stationary auto-tune when position feedback is being used, or to perform a phasing test on starting in RFC-S mode.
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Trip	Diagnosis										
Inductor Too Hot	Regen inductor thermal protection overload timed out										
93	Regen inductor overload. See Inductor Thermal Time Constant.										
Inter-connect	Multi-power module drive interconnection cable error										
103	The sub-trip "xx.0.00" indicates which power module has detected the fault where xx is the power module number. It should be noted that this trip is also initiated if the communication fails either when a rectifier signals a fault or a trip is reset. In this case, the sub-trip is the number of modules that are still communicating correctly.										
Island	Island supply condition detected in regen mode										
160	<p>This trip indicates that a regen system is connected to an island supply. The sub-trips indicate the reason for the trip.</p> <table border="1"> <thead> <tr> <th>Sub-trip</th> <th>Reason</th> </tr> </thead> <tbody> <tr> <td>1</td> <td>Island detection system has been enabled and detected an island condition</td> </tr> <tr> <td>2</td> <td>The supply loss is active at the end of the auto-synchronisation ride-through period</td> </tr> </tbody> </table> <p>Recommended actions: Check the supply and supply connections to the regen drive.</p>	Sub-trip	Reason	1	Island detection system has been enabled and detected an island condition	2	The supply loss is active at the end of the auto-synchronisation ride-through period				
Sub-trip	Reason										
1	Island detection system has been enabled and detected an island condition										
2	The supply loss is active at the end of the auto-synchronisation ride-through period										
Keypad Mode	Keypad has been removed when the drive is receiving the speed reference from the keypad										
34	<p>The <i>Keypad Mode</i> trip indicates that the drive is in keypad mode [<i>Reference Selector (01.014)</i> = 4 or 6 or M2 reference selector (<i>21.003</i> = 4 or 6 if motor map 2 is selected)] and the keypad has been removed or disconnected from the drive.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Re-install keypad and reset • Change <i>Reference Selector (01.014)</i> to select the reference from another source 										
Line Sync	The load on the drive has fallen below the Low Load Detection Level										
39	This trip is initiated if the low load detector is set up to produce a trip on low load detection and this condition occurs. See <i>Enable Trip On Low Load (04.029)</i> .										
Motor Too Hot	Output current overload timed out (I^2t)										
20	<p>The <i>Motor Too Hot</i> trip indicates a motor thermal overload based on the rated current (Pr <i>05.007</i>) and motor thermal time constant (Pr <i>04.015</i>). Pr <i>04.019</i> displays the motor temperature as a percentage of the maximum value. The drive will trip on <i>Motor Too Hot</i> when Pr <i>04.019</i> gets to 100 %.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Ensure the load is not jammed / sticking • Check the load on the motor has not changed • If seen during an auto-tune test in RFC-S mode, ensure the motor rated current in Pr <i>05.007</i> is \leq Heavy duty current rating of the drive • Tune the rated speed parameter (RFC-A mode only) • Check feedback signal for noise • Ensure the motor rated current is not zero 										
Name Plate	Electronic nameplate transfer has failed										
176	<p>The <i>Name Plate</i> trip is initiated if an electronic name plate transfer between the drive and the motor has failed. The exact reason for the trip can be identified from the sub-trip number.</p> <table border="1"> <thead> <tr> <th>Sub-trip</th> <th>Description</th> </tr> </thead> <tbody> <tr> <td>1</td> <td>Not enough memory space to complete the transfer</td> </tr> <tr> <td>2</td> <td>Communication with encoder failed</td> </tr> <tr> <td>3</td> <td>The transfer has failed</td> </tr> <tr> <td>4</td> <td>The checksum of the stored object has failed</td> </tr> </tbody> </table> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Ensure that the device encoder memory has at least 128 bytes to store the nameplate data • When writing the motor object (xx.000 = 11000), ensure that the device encoder memory has at least 256 bytes to store all the nameplate data. • When transferring between option module and encoder, ensure that the option slot has a feedback option module installed. • Check if the encoder has been initialized, <i>Position Feedback Initialized (03.076)</i>. • Verify the encoder wiring. 	Sub-trip	Description	1	Not enough memory space to complete the transfer	2	Communication with encoder failed	3	The transfer has failed	4	The checksum of the stored object has failed
Sub-trip	Description										
1	Not enough memory space to complete the transfer										
2	Communication with encoder failed										
3	The transfer has failed										
4	The checksum of the stored object has failed										

Trip	Diagnosis																				
No Encoder Found	An encoder could not be identified during auto-discovery																				
167	<p>An encoder supported by the auto-discovery process has not been found (see Discovery in <i>P1 Device Type (03.038)</i> for more information on this process). Please ensure that a supported device is connected to the drive <i>P1 interface</i> and the required <i>P1 Supply Voltage (03.036)</i> is set for the device. The sub-trip will always be 1 as only the P1 interface supports auto-discovery.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> Ensure the position feedback device is correctly connected to the drive. Ensure that <i>P1 Supply Voltage (03.036)</i> is set correctly. Set <i>P1 Device Type (03.038)</i> to the type of the connected position feedback device. 																				
Oht Brake	Braking IGBT over-temperature																				
101	<p>The <i>Oht Brake over-temperature</i> trip indicates that braking IGBT over-temperature has been detected based on software thermal model.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> Check braking resistor value is greater than or equal to the minimum resistance value 																				
Oht Control	Control stage over temperature																				
23	<p>This <i>Oht Control</i> trip indicates that a control stage over-temperature has been detected. From the sub-trip 'xyzz', the Thermistor location is identified by 'zz'.</p> <table border="1"> <thead> <tr> <th>Source</th> <th>xx</th> <th>y</th> <th>zz</th> <th>Description</th> </tr> </thead> <tbody> <tr> <td>Control system</td> <td>00</td> <td>0</td> <td>01</td> <td>Control board thermistor 1 over temperature</td> </tr> <tr> <td>Control system</td> <td>00</td> <td>0</td> <td>02</td> <td>Control board thermistor 2 over temperature</td> </tr> <tr> <td>Control system</td> <td>00</td> <td>0</td> <td>03</td> <td>I/O board thermistor over temperature</td> </tr> </tbody> </table> <p>Recommended actions:</p> <ul style="list-style-type: none"> Check enclosure / drive fans are still functioning correctly Check enclosure ventilation paths Check enclosure door filters Increase ventilation Reduce the drive switching frequency Check ambient temperature 	Source	xx	y	zz	Description	Control system	00	0	01	Control board thermistor 1 over temperature	Control system	00	0	02	Control board thermistor 2 over temperature	Control system	00	0	03	I/O board thermistor over temperature
Source	xx	y	zz	Description																	
Control system	00	0	01	Control board thermistor 1 over temperature																	
Control system	00	0	02	Control board thermistor 2 over temperature																	
Control system	00	0	03	I/O board thermistor over temperature																	

Trip	Diagnosis																				
Oht dc bus	DC bus over temperature																				
27	<p>The <i>Oht dc bus</i> trip indicates a DC bus component over temperature based on a software thermal model. The drive includes a thermal protection system to protect the DC bus components within the drive. This includes the effects of the output current and DC bus ripple. The estimated temperature is displayed as a percentage of the trip level in Pr 07.035. If this parameter reaches 100 % then an <i>Oht dc bus</i> trip is initiated. The drive will attempt to stop the motor before tripping. If the motor does not stop in 10 seconds the drive trips immediately.</p> <table border="1"> <thead> <tr> <th>Source</th> <th>xx</th> <th>y</th> <th>zz</th> <th>Description</th> </tr> </thead> <tbody> <tr> <td>Control system</td> <td>00</td> <td>2</td> <td>00</td> <td>DC bus thermal model gives trip with sub-trip 0</td> </tr> </tbody> </table> <p>It is also possible in a multi-power module system for DC bus over-temperature to be detected from within the power stage. From this source the estimated temperature as a percentage of trip is not available and the trip is indicated as follows:</p> <table border="1"> <thead> <tr> <th>Source</th> <th>xx</th> <th>y</th> <th>zz</th> <th>Description</th> </tr> </thead> <tbody> <tr> <td>Control system</td> <td>01</td> <td>0</td> <td>00</td> <td>Power stage gives trip with sub-trip 0</td> </tr> </tbody> </table> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Check the AC supply voltage balance and levels • Check DC bus ripple level • Reduce duty cycle • Reduce motor load • Check the output current stability. If unstable; <ul style="list-style-type: none"> • Check the motor map settings with motor nameplate (Pr 05.006, Pr 05.007, Pr 05.008, Pr 05.009, Pr 05.010, Pr 05.011) – (All Modes) • Disable slip compensation (Pr 05.027 = 0) – (Open loop) • Disable dynamic V to F operation (Pr 05.013 = 0) - (Open loop) • Select fixed boost (Pr 05.014 = Fixed) – (Open loop) • Select high stability space vector modulation (Pr 05.020 = 1) – (Open loop) • Disconnect the load and complete a rotating autotune (Pr 05.012) – (RFC-A, RFC-S) • Reduce speed loop gains (Pr 03.010, Pr 03.011, Pr 03.012) – (RFC-A, RFC-S) • Add a speed feedback filter value (Pr 03.042) – (RFC-A, RFC-S) • Add a current demand filter (Pr 04.012) – (RFC-A, RFC-S) • Check encoder signals for noise with an oscilloscope (RFC-A, RFC-S) • Check encoder mechanical coupling - (RFC-A, RFC-S) 	Source	xx	y	zz	Description	Control system	00	2	00	DC bus thermal model gives trip with sub-trip 0	Source	xx	y	zz	Description	Control system	01	0	00	Power stage gives trip with sub-trip 0
	Source	xx	y	zz	Description																
	Control system	00	2	00	DC bus thermal model gives trip with sub-trip 0																
	Source	xx	y	zz	Description																
Control system	01	0	00	Power stage gives trip with sub-trip 0																	
Oht Inverter	Inverter over temperature based on thermal model																				
21	<p>This trip indicates that an IGBT junction over-temperature has been detected based on a firmware thermal model. The sub-trip indicates which model has initiated the trip in the form xxyzz as given below:</p> <table border="1"> <thead> <tr> <th>Source</th> <th>xx</th> <th>y</th> <th>zz</th> <th>Description</th> </tr> </thead> <tbody> <tr> <td>Control system</td> <td>00</td> <td>1</td> <td>00</td> <td>Inverter thermal model</td> </tr> <tr> <td>Control system</td> <td>00</td> <td>3</td> <td>00</td> <td>Braking IGBT thermal model</td> </tr> </tbody> </table> <p>Recommended actions with sub-trip 100:</p> <ul style="list-style-type: none"> • Reduce the selected drive switching frequency • Ensure <i>Auto-switching Frequency Change Disable</i> (05.035) is set to Off • Reduce duty cycle • Increase acceleration / deceleration rates • Reduce motor load • Check DC bus ripple • Ensure all three input phases are present and balanced <p>Recommended actions with sub-trip 300:</p> <ul style="list-style-type: none"> • Reduce the braking load. 	Source	xx	y	zz	Description	Control system	00	1	00	Inverter thermal model	Control system	00	3	00	Braking IGBT thermal model					
	Source	xx	y	zz	Description																
	Control system	00	1	00	Inverter thermal model																
	Control system	00	3	00	Braking IGBT thermal model																

Trip	Diagnosis																																																		
Oht Power	Power stage over temperature																																																		
22	<p>This trip indicates that a power stage over-temperature has been detected. The sub-trip "xxyz" indicates which thermistor is indicating the over-temperature. The thermistor numbering is different for a single module type drive (i.e. no parallel board fitted) and a multi-module type drive (i.e. parallel board fitted with one or more power modules) as shown below:</p> <p>Single module type drive:</p> <table border="1"> <thead> <tr> <th>Source</th> <th>xx</th> <th>y</th> <th>zz</th> <th>Description</th> </tr> </thead> <tbody> <tr> <td>Power system</td> <td>01</td> <td>0</td> <td>zz</td> <td>Thermistor location defined by zz in the power board</td> </tr> <tr> <td>Power system</td> <td>01</td> <td>Rectifier number</td> <td>zz</td> <td>Thermistor location defined by zz in the rectifier</td> </tr> </tbody> </table> <p>Multi-module type system:</p> <table border="1"> <thead> <tr> <th>Source</th> <th>xx</th> <th>y</th> <th>zz</th> <th>Description</th> </tr> </thead> <tbody> <tr> <td>Power system</td> <td>power module number</td> <td>0</td> <td>01</td> <td>U phase power device</td> </tr> <tr> <td>Power system</td> <td>power module number</td> <td>0</td> <td>02</td> <td>V phase power device</td> </tr> <tr> <td>Power system</td> <td>power module number</td> <td>0</td> <td>03</td> <td>W phase power device</td> </tr> <tr> <td>Power system</td> <td>power module number</td> <td>0</td> <td>04</td> <td>Rectifier</td> </tr> <tr> <td>Power system</td> <td>power module number</td> <td>0</td> <td>05</td> <td>General power system</td> </tr> <tr> <td>Power system</td> <td>power module number</td> <td>0</td> <td>00</td> <td>Braking IGBT</td> </tr> </tbody> </table> <p>Note that the power module that has caused the trip cannot be identified except for the braking IGBT temperature measurement</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Check enclosure / drive fans are still functioning correctly • Force the heatsink fans to run at maximum speed • Check enclosure ventilation paths • Check enclosure door filters • Increase ventilation • Reduce the drive switching frequency • Reduce duty cycle • Decrease acceleration / deceleration rates • Reduce motor load • Check the derating tables and confirm the drive is correctly sized for the application. • Use a drive with larger current / power rating 	Source	xx	y	zz	Description	Power system	01	0	zz	Thermistor location defined by zz in the power board	Power system	01	Rectifier number	zz	Thermistor location defined by zz in the rectifier	Source	xx	y	zz	Description	Power system	power module number	0	01	U phase power device	Power system	power module number	0	02	V phase power device	Power system	power module number	0	03	W phase power device	Power system	power module number	0	04	Rectifier	Power system	power module number	0	05	General power system	Power system	power module number	0	00	Braking IGBT
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Power system	power module number	0	00	Braking IGBT																																															
OI ac	Instantaneous output over current detected																																																		
3	<p>The instantaneous drive output current has exceeded VM_DRIVE_CURRENT_MAX. This trip cannot be reset until 10 s after the trip was initiated.</p> <table border="1"> <thead> <tr> <th>Source</th> <th>xx</th> <th>y</th> <th>zz</th> <th>Description</th> </tr> </thead> <tbody> <tr> <td>Control system</td> <td>00</td> <td>0</td> <td rowspan="2">00</td> <td rowspan="2">Instantaneous over-current trip when the measured a.c. current exceeds VM_DRIVE_CURRENT[MAX].</td> </tr> <tr> <td>Power system</td> <td>Power module number</td> <td>0</td> </tr> </tbody> </table> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Acceleration/deceleration rate is too short • If seen during auto-tune reduce the voltage boost • Check for short circuit on the output cabling • Check integrity of the motor insulation using an insulation tester • Check feedback device wiring • Check feedback device mechanical coupling • Check feedback signals are free from noise • Is motor cable length within limits for the frame size • Reduce the values in the speed loop gain parameters - (Pr 03.010, 03.011, 03.012) or (Pr 03.013, 03.014, 03.015) • Has the phase angle autotune been completed? (RFC-S mode only) • Reduce the values in current loop gain parameters (RFC-A, RFC-S modes only) 	Source	xx	y	zz	Description	Control system	00	0	00	Instantaneous over-current trip when the measured a.c. current exceeds VM_DRIVE_CURRENT[MAX].	Power system	Power module number	0																																					
	Source	xx	y	zz	Description																																														
Control system	00	0	00	Instantaneous over-current trip when the measured a.c. current exceeds VM_DRIVE_CURRENT[MAX].																																															
Power system	Power module number	0																																																	

Trip	Diagnosis												
OI Brake	Braking IGBT over current detected: short circuit protection for the braking IGBT activated												
4	The <i>OI Brake</i> trip indicates that over current has been detected in braking IGBT or braking IGBT protection has been activated. This trip cannot be reset until 10 s after the trip was initiated.												
	<table border="1"> <thead> <tr> <th>Source</th> <th>xx</th> <th>y</th> <th>zz</th> <th>Description</th> </tr> </thead> <tbody> <tr> <td>Power system</td> <td>Power module number</td> <td>0</td> <td>00</td> <td>Braking IGBT instantaneous over-current trip</td> </tr> </tbody> </table>	Source	xx	y	zz	Description	Power system	Power module number	0	00	Braking IGBT instantaneous over-current trip		
	Source	xx	y	zz	Description								
Power system	Power module number	0	00	Braking IGBT instantaneous over-current trip									
<p>Recommended actions:</p> <ul style="list-style-type: none"> • Check brake resistor wiring • Check braking resistor value is greater than or equal to the minimum resistance value • Check braking resistor insulation 													
OI dc	Power module over current detected from IGBT on state voltage monitoring												
109	The <i>OI dc</i> trip indicates that the short circuit protection for the drive output stage has been activated. The table below shows where the trip has been detected..This trip cannot be reset until 10 s after the trip was initiated.												
	<table border="1"> <thead> <tr> <th>Source</th> <th>xx</th> <th>y</th> <th>zz</th> </tr> </thead> <tbody> <tr> <td>Control system</td> <td>00</td> <td>0</td> <td>00</td> </tr> <tr> <td>Power system</td> <td>Power module number</td> <td>0</td> <td>00</td> </tr> </tbody> </table>	Source	xx	y	zz	Control system	00	0	00	Power system	Power module number	0	00
	Source	xx	y	zz									
Control system	00	0	00										
Power system	Power module number	0	00										
<p>Recommended actions:</p> <ul style="list-style-type: none"> • Disconnect the motor cable at the drive end and check the motor and cable insulation with an insulation tester • Replace the drive 													
OI Snubber	Snubber over-current detected												
92	The <i>OI Snubber</i> trip indicates that an over-current condition has been detected in the rectifier snubber circuit. The reason for the trip can be identified by the sub-trip number.												
	<table border="1"> <thead> <tr> <th>Source</th> <th>xx</th> <th>y</th> <th>zz</th> <th>Description</th> </tr> </thead> <tbody> <tr> <td>Power system</td> <td>01</td> <td>Rectifier number*</td> <td>00</td> <td>Rectifier snubber over-current trip detected.</td> </tr> </tbody> </table>	Source	xx	y	zz	Description	Power system	01	Rectifier number*	00	Rectifier snubber over-current trip detected.		
	Source	xx	y	zz	Description								
Power system	01	Rectifier number*	00	Rectifier snubber over-current trip detected.									
<p>* For a parallel power-module system the rectifier number will be one as it is not possible to determine which rectifier has detected the fault.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Ensure the internal EMC Filter is installed • Ensure the motor cable length does not exceed the maximum for selected switching frequency • Check for supply voltage imbalance • Check for supply disturbance such as notching from a DC drive • Check the motor and motor cable insulation with an insulation tester • Fit an output line reactor or sinusoidal filter • Adjust brake turn on threshold to control the DC bus at a lower level when the drive is regenerating, by reducing the value in <i>Braking IGBT Upper Threshold</i> (Pr 06.074). 													
Option Disable	Option module does not acknowledge during drive mode changeover												
215	<p>During drive mode changeover option modules must acknowledge that they have stopped accessing the communications system between the option slots and the drive. If an option module does not do this in the allowed time then this trip is produced.</p> <p>Recommended trip:</p> <ul style="list-style-type: none"> • Reset the trip • If the trip persists replace the option module 												

Trip	Diagnosis																											
Out Phase Loss	Output phase loss detected																											
98	<p>The <i>Out Phase Loss</i> trip indicates that a phase loss has been detected at the drive output.</p> <p>Note that if <i>Reverse Output Phase Sequence (05.042)</i> = 1 the physical output phases are reversed, and so sub-trip 3 refers to physical output phase V and sub-trip 2 refers to physical output phase W.</p> <table border="1"> <thead> <tr> <th>Sub-trip</th> <th>Reason</th> </tr> </thead> <tbody> <tr> <td>1</td> <td>U phase detected as disconnected when drive enabled to run</td> </tr> <tr> <td>2</td> <td>V phase detected as disconnected when drive enabled to run</td> </tr> <tr> <td>3</td> <td>W phase detected as disconnected when drive enabled to run</td> </tr> <tr> <td>4</td> <td>Output phase loss detected when the drive is running</td> </tr> </tbody> </table> <p>Recommended action:</p> <ul style="list-style-type: none"> • Check motor and drive connections • To disable the trip set <i>Output Phase Loss Detection Enable (06.059)</i> = 0 	Sub-trip	Reason	1	U phase detected as disconnected when drive enabled to run	2	V phase detected as disconnected when drive enabled to run	3	W phase detected as disconnected when drive enabled to run	4	Output phase loss detected when the drive is running																	
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	2	V phase detected as disconnected when drive enabled to run																										
	3	W phase detected as disconnected when drive enabled to run																										
4	Output phase loss detected when the drive is running																											
Over Speed	Motor speed has exceeded the over speed threshold																											
7	<p>In open loop mode, if the <i>Output Frequency (05.001)</i> exceeds the threshold set in <i>Over Speed Threshold (03.008)</i> in either direction an Over Speed trip is produced. In RFC-A and RFC-S mode, if the <i>Speed Feedback (03.002)</i> exceeds the <i>Over Speed Threshold</i> in Pr 03.008 in either direction an Over Speed trip is produced. If Pr 03.008 is set to 0.0 the threshold is then equal to 1.2 x the value set in Pr 01.006.</p> <p>In RFC-A and RFC-S modes if an SSI encoder is being used and <i>P1 SSI Incremental Mode (03.047)</i> is set to Off, an Over Speed trip will be produced when the encoder passes through the boundary between its maximum position and zero.</p> <p>The above description relates to a standard over speed trip, however in RFC-S mode it is possible to produce an Overspeed trip with sub-trip 1. This is caused if the speed is allowed to exceed the safe level in RFC-S mode with flux weakening. See <i>Enable High Speed Mode (05.022)</i> for details.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Check the motor is not being driven by another part of the system • Reduce the <i>Speed Controller Proportional Gain (03.010)</i> to reduce the speed overshoot (RFC-A, RFC-S modes only) • If an SSI encoder is being used set Pr 03.047 to 1 <p>The above description relates to a standard Over Speed trip, however in RFC-S mode it is possible to produce an <i>Over Speed.1</i> trip. This is caused if the speed is allowed to exceed the safe level in RFC-S mode with flux weakening when <i>Enable High Speed Mode (05.022)</i> is set to -1.</p>																											
	Over Volts	DC bus voltage has exceeded the peak level or maximum continuous level for 15 seconds																										
2	<p>The <i>Over Volts</i> trip indicates that the DC bus voltage has exceeded the VM_DC_VOLTAGE[MAX] or VM_DC_VOLTAGE_SET[MAX] for 15 s. The trip threshold varies depending on voltage rating of the drive as shown below.</p> <table border="1"> <thead> <tr> <th>Voltage rating</th> <th>VM_DC_VOLTAGE[MAX]</th> <th>VM_DC_VOLTAGE_SET[MAX]</th> </tr> </thead> <tbody> <tr> <td>200</td> <td>415</td> <td>410</td> </tr> <tr> <td>400</td> <td>830</td> <td>815</td> </tr> <tr> <td>575</td> <td>990</td> <td>970</td> </tr> <tr> <td>690</td> <td>1190</td> <td>1175</td> </tr> </tbody> </table> <p>Sub-trip Identification</p> <table border="1"> <thead> <tr> <th>Source</th> <th>xx</th> <th>y</th> <th>zz</th> </tr> </thead> <tbody> <tr> <td>Control system</td> <td>00</td> <td>0</td> <td>01: Instantaneous trip when the DC bus voltage exceeds VM_DC_VOLTAGE[MAX].</td> </tr> <tr> <td>Control system</td> <td>00</td> <td>0</td> <td>02: Time delayed trip indicating that the DC bus voltage is above VM_DC_VOLTAGE_SET[MAX].</td> </tr> </tbody> </table> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Increase deceleration ramp (Pr 00.004) • Decrease the braking resistor value (staying above the minimum value) • Check nominal AC supply level • Check for supply disturbances which could cause the DC bus to rise • Check motor insulation using an insulation tester 	Voltage rating	VM_DC_VOLTAGE[MAX]	VM_DC_VOLTAGE_SET[MAX]	200	415	410	400	830	815	575	990	970	690	1190	1175	Source	xx	y	zz	Control system	00	0	01: Instantaneous trip when the DC bus voltage exceeds VM_DC_VOLTAGE[MAX].	Control system	00	0	02: Time delayed trip indicating that the DC bus voltage is above VM_DC_VOLTAGE_SET[MAX].
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Control system	00	0	02: Time delayed trip indicating that the DC bus voltage is above VM_DC_VOLTAGE_SET[MAX].																									
Phase Imbalance	Phase imbalance has been detected (Regen mode only)																											
104	<p>The level of supply phase imbalance has cause the negative phase sequence components to exceed the threshold defined by Phase Imbalance Threshold.</p>																											

Trip	Diagnosis												
Phase Loss	Supply phase loss												
32	<p>This trip indicates that the drive has detected an input phase loss or large supply imbalance. Phase loss can be detected directly from the supply where the drive has a thyristor base charge system (Frame size 7 and above). If phase loss is detected using this method the drive trips immediately and the xx part of the sub-trip is set to 01. In all sizes of drive phase loss is also detected by monitoring the ripple in the DC bus voltage in which case the drive attempts to stop the drive before tripping unless bit 2 of <i>Action On Trip Detection (10.037)</i> is set to one. When phase loss is detected by monitoring the ripple in the DC bus voltage the xx part of the sub-trip is zero.</p> <table border="1" style="width: 100%; border-collapse: collapse;"> <thead> <tr> <th style="text-align: center;">Source</th> <th style="text-align: center;">xx</th> <th style="text-align: center;">y</th> <th style="text-align: center;">zz</th> </tr> </thead> <tbody> <tr> <td style="text-align: center;">Control system</td> <td style="text-align: center;">00</td> <td style="text-align: center;">0</td> <td>00: Phase loss detected from DC bus ripple</td> </tr> <tr> <td style="text-align: center;">Power system (1)</td> <td style="text-align: center;">Power module number</td> <td style="text-align: center;">Rectifier number (2)</td> <td>00: Phase loss detected directly from the supply</td> </tr> </tbody> </table> <p>(1) Input phase loss detection can be disabled when the drive required to operate from the DC supply or from a single phase supply in <i>Input Phase Loss Detection Mode (06.047)</i>.</p> <p>(2) For a parallel power-module system the rectifier number will be one as it is not possible to determine which rectifier has detected the fault.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Check the AC supply voltage balance and level at full load • Check the DC bus ripple level with an isolated oscilloscope • Check the output current stability • Reduce the duty cycle • Reduce the motor load • Disable the phase loss detection, set Pr 06.047 to 2. • Check for mechanical resonance with the load 	Source	xx	y	zz	Control system	00	0	00: Phase loss detected from DC bus ripple	Power system (1)	Power module number	Rectifier number (2)	00: Phase loss detected directly from the supply
Source	xx	y	zz										
Control system	00	0	00: Phase loss detected from DC bus ripple										
Power system (1)	Power module number	Rectifier number (2)	00: Phase loss detected directly from the supply										
Phasing error	This indicates that the phase offset angle is incorrect												
198	<p>This indicates that the phase offset angle in <i>Position Feedback Phase Angle (03.025)</i> (or <i>M2 Position Feedback Phase Angle (21.020)</i> if the second motor map is being used) is incorrect if position feedback is being used and the drive is unable to control the motor correctly.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Check the encoder wiring. • Check the encoder signals for noise with an oscilloscope. • Check encoder mechanical coupling. • Perform an auto-tune to measure the encoder phase angle or manually enter the correct phase angle into <i>Position Feedback Phase Angle (03.025)</i>. • Spurious Phasing Error trips can sometimes be seen in very dynamic applications. This trip can be disabled by setting <i>Over Speed Threshold (03.008)</i> to a value greater than zero. <p>If sensorless control is being used this indicates that significant instability has occurred and the motor has accelerated without control.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Ensure that the motor parameters are set-up correctly. • Reduce the speed controller gains. 												
Power Comms	A Power Comms trip indicates a communications problem within the power system of the drive												
90	<p>A Power Comms trip indicates a communications problem within the power system of the drive. The reason for the trip can be identified by the sub-trip number.</p> <table border="1" style="width: 100%; border-collapse: collapse;"> <thead> <tr> <th style="text-align: center;">Type of drive</th> <th style="text-align: center;">xx</th> <th style="text-align: center;">y</th> <th style="text-align: center;">zz</th> </tr> </thead> <tbody> <tr> <td style="text-align: center;">Control system</td> <td style="text-align: center;">Power module number</td> <td style="text-align: center;">Rectifier number*</td> <td>00: Excessive communications errors detected by the rectifier module</td> </tr> </tbody> </table> <p>* For a parallel power-module system the rectifier number will be one as it is not possible to determine which rectifier has detected the fault.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Hardware fault – Contact the supplier of the drive 	Type of drive	xx	y	zz	Control system	Power module number	Rectifier number*	00: Excessive communications errors detected by the rectifier module				
Type of drive	xx	y	zz										
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Trip	Diagnosis																																													
Power Data	Power system configuration data error																																													
220	The <i>Power Data</i> trip indicates that there is an error in the configuration data stored in the power system.																																													
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Power Down Save	Power down save error																																													
37	The <i>Power Down Save</i> trip indicates that an error has been detected in the power down save parameters saved in non-volatile memory.																																													
Recommended actions:																																														
<ul style="list-style-type: none"> Perform a 1001 save in Pr mm.000 to ensure that the trip doesn't occur the next time the drive is powered up. 																																														
PSU	Internal power supply fault																																													
5	The <i>PSU</i> trip indicates that one or more internal power supply rails are outside limits or overloaded.																																													
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<ul style="list-style-type: none"> Remove any option modules and perform a reset Remove encoder connection and perform a reset Hardware fault within the drive – return the drive to the supplier 																																														
PSU 24V	24V internal power supply overload																																													
9	The total user load of the drive and option modules has exceeded the internal 24 V power supply limit. The user load consists of the drive digital outputs and main encoder supply.																																													
Recommended actions:																																														
<ul style="list-style-type: none"> Reduce the load and reset Provide an external 24 V power supply on control terminal 2 Remove all option modules 																																														

Trip	Diagnosis								
Rating Mismatch	Power stage recognition: Multi module voltage or current rating mismatch								
223	<p>The <i>Rating Mismatch</i> trip indicates that there is a voltage rating or current rating mismatch in a multi-module drive system. This trip is only applicable to modular drives that are connected in parallel. A mixture of power modules with different voltage or current ratings within the same multi-module drive system is not allowed and will cause a Rating Mismatch trip.</p> <p>Recommended action:</p> <ul style="list-style-type: none"> • Ensure that all modules in a multi-modular drive system are of the same frame size and rating (voltage and current) • Hardware fault – Contact the supplier of the drive 								
Rectifier Set-up	A rectifier has not been set-up correctly in a multi-power module system.								
94	<p>A rectifier has not been set-up correctly in a multi-power module system.</p> <p>Recommended action:</p> <ul style="list-style-type: none"> • Check the inter-power module wiring 								
Reserved	Reserved trips								
01 95 104 - 108 161-168 170-173 222 228-246	<p>These trip numbers are reserved trip numbers for future use. These trips should not be used by the user application programs.</p>								
Resistance	Measured resistance has exceeded the parameter range								
33	<p>This trip indicates that either the value being used for motor stator resistance is too high or that an attempt to do a test involving measuring motor stator resistance has failed. The maximum for the stator resistance parameters is generally higher than the maximum value that can be used in the control algorithms. If the value exceeds $(VFS / \sqrt{2}) / Full\ Scale\ Current\ Kc$ (11.061), where VFS is the full scale DC bus voltage then this trip is initiated. If the value is the result of a measurement made by the drive then sub-trip 1 is applied, or if it is because the parameter has been changed by the user then sub-trip 3 is applied. During the stator resistance section of auto-tuning an additional test is performed to measured the drive inverter characteristics to provide the compensation necessary for dead-times. If the inverter characteristic measurement fails then sub-trip 2 is applied.</p> <table border="1"> <thead> <tr> <th>Sub-trip</th> <th>Reason</th> </tr> </thead> <tbody> <tr> <td>1</td> <td>Measured stator resistance exceeded the allowed range</td> </tr> <tr> <td>2</td> <td>It was not possible to measure the inverter characteristic</td> </tr> <tr> <td>3</td> <td>The stator resistance associated with the presently selected motor map exceeds the allowed range</td> </tr> </tbody> </table> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Check that the value that has been entered in the stator resistance does not exceed the allowed range (for the presently selected motor map) • Check the motor cable / connections • Check the integrity of the motor stator winding using an insulation tester • Check the motor phase to phase resistance at the drive terminals • Check the motor phase to phase resistance at the motor terminals • Ensure the stator resistance of the motor falls within the range of the drive model • Select fixed boost mode (Pr 05.014 = Fixed) and verify the output current waveforms with an oscilloscope • Replace the motor 	Sub-trip	Reason	1	Measured stator resistance exceeded the allowed range	2	It was not possible to measure the inverter characteristic	3	The stator resistance associated with the presently selected motor map exceeds the allowed range
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1	Measured stator resistance exceeded the allowed range								
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Slot App Menu	Application menu Customization conflict error								
216	<p>The Slot App Menu trip indicates that more than one option slot has requested to customize the application menus 18, 19 and 20. The sub-trip number indicates which option slot has been allowed to customize the menus.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> • Ensure that only one of the Application modules is configured to customize the application menus 18, 19 and 20 								

Trip	Diagnosis																						
SlotX Different	Option module in option slot X has changed																						
204 209 214 254	The <i>SlotX Different</i> trip indicates that the option module in option slot X on the drive is a different type to that installed when parameters were last saved on the drive. The reason for the trip can be identified by the sub-trip number.																						
	<table border="1"> <thead> <tr> <th>Sub-trip</th> <th>Reason</th> </tr> </thead> <tbody> <tr> <td>1</td> <td>No module was installed previously</td> </tr> <tr> <td>2</td> <td>A module with the same identifier is installed, but the set-up menu for this option slot has been changed, and so default parameters have been loaded for this menu.</td> </tr> <tr> <td>3</td> <td>A module with the same identifier is installed, but the applications menu for this option slot has been changed, and so default parameters have been loaded for this menu.</td> </tr> <tr> <td>4</td> <td>A module with the same identifier is installed, but the set-up and applications menu for this option slot have been changed, and so default parameters have been loaded for these menus.</td> </tr> <tr> <td>>99</td> <td>Shows the identifier of the module previously installed.</td> </tr> </tbody> </table>	Sub-trip	Reason	1	No module was installed previously	2	A module with the same identifier is installed, but the set-up menu for this option slot has been changed, and so default parameters have been loaded for this menu.	3	A module with the same identifier is installed, but the applications menu for this option slot has been changed, and so default parameters have been loaded for this menu.	4	A module with the same identifier is installed, but the set-up and applications menu for this option slot have been changed, and so default parameters have been loaded for these menus.	>99	Shows the identifier of the module previously installed.										
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Recommended actions:																							
<ul style="list-style-type: none"> Turn off the power, ensure the correct option modules are installed in the correct option slots and re-apply the power. Confirm that the currently installed option module is correct, ensure option module parameters are set correctly and perform a user save in Pr mm.000. 																							
SlotX Error	Option module in option slot X has detected a fault																						
202 207 212 252	The <i>SlotX Error</i> trip indicates that the option module in option slot X on the drive has detected an error. The reason for the error can be identified by the sub-trip number.																						
Recommended actions:																							
<ul style="list-style-type: none"> See relevant <i>Option Module User Guide</i> for details of the trip 																							
SlotX HF	Option module X hardware fault																						
200 205 210 250	The <i>SlotX HF</i> trip indicates that the option module in option slot X on the drive has indicated a hardware fault. The possible causes of the trip can be identified by the sub-trip number.																						
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Recommended actions:																							
<ul style="list-style-type: none"> Ensure the option module is installed correctly Replace the option module Replace the drive 																							
SlotX Not Fitted	Option module in option slot X has been removed																						
203 208 213 253	The <i>SlotX Not Fitted</i> trip indicates that the option module in option slot X on the drive has been removed since the last power up.																						
Recommended actions:																							
<ul style="list-style-type: none"> Ensure the option module is installed correctly. Re-install the option module. To confirm that the removed option module is no longer required perform a save function in Pr mm.000. 																							
SlotX Watchdog	Option module watchdog function service error																						
201 206 211 251	The <i>SlotX Watchdog</i> trip indicates that the option module installed in Slot X has started the option watchdog function and then failed to service the watchdog correctly.																						
Recommended actions:																							
<ul style="list-style-type: none"> Replace the option module 																							

Trip	Diagnosis																																															
Soft Start	Soft start relay failed to close, soft start monitor failed																																															
226	<p>The <i>Soft Start</i> trip indicates that the soft start relay in the drive failed to close or the soft start monitoring circuit has failed.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> Hardware fault – Contact the supplier of the drive 																																															
Stored HF	Hardware trip has occurred during last power down																																															
221	<p>The <i>Stored HF</i> trip indicates that a hardware trip (HF01 –HF19) has occurred and the drive has been power cycled. The sub-trip number identifies the HF trip i.e. stored HF.17.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> Enter 1299 in Pr mm.000 and press reset to clear the trip 																																															
Sub-array RAM	RAM allocation error																																															
227	<p>The <i>Sub-array RAM</i> trip indicates that an option module, derivative image or user program image has requested more parameter RAM than is allowed. The RAM allocation is checked in order of resulting sub-trip numbers, and so the failure with the highest sub-trip number is given. The sub-trip is calculated as (parameter size) + (parameter type) + sub-array number.</p> <table border="1" style="display: inline-table; margin-right: 20px;"> <thead> <tr> <th>Parameter size</th> <th>Value</th> </tr> </thead> <tbody> <tr> <td>1 bit</td> <td>1000</td> </tr> <tr> <td>8 bit</td> <td>2000</td> </tr> <tr> <td>16 bit</td> <td>3000</td> </tr> <tr> <td>32 bit</td> <td>4000</td> </tr> <tr> <td>64 bit</td> <td>5000</td> </tr> </tbody> </table> <table border="1" style="display: inline-table;"> <thead> <tr> <th>Parameter type</th> <th>Value</th> </tr> </thead> <tbody> <tr> <td>Volatile</td> <td>0</td> </tr> <tr> <td>User save</td> <td>100</td> </tr> <tr> <td>Power-down save</td> <td>200</td> </tr> </tbody> </table> <table border="1"> <thead> <tr> <th>Sub-array</th> <th>Menus</th> <th>Value</th> </tr> </thead> <tbody> <tr> <td>Applications menu</td> <td>18-20</td> <td>1</td> </tr> <tr> <td>Derivative image</td> <td>29</td> <td>2</td> </tr> <tr> <td>Option slot 1 set-up</td> <td>15</td> <td>4</td> </tr> <tr> <td>Option slot 1 applications</td> <td>25</td> <td>5</td> </tr> <tr> <td>Option slot 2 set-up</td> <td>16</td> <td>6</td> </tr> <tr> <td>Option slot 2 applications</td> <td>26</td> <td>7</td> </tr> <tr> <td>Option slot 3 set-up</td> <td>17</td> <td>8</td> </tr> <tr> <td>Option slot 3 applications</td> <td>27</td> <td>9</td> </tr> </tbody> </table>	Parameter size	Value	1 bit	1000	8 bit	2000	16 bit	3000	32 bit	4000	64 bit	5000	Parameter type	Value	Volatile	0	User save	100	Power-down save	200	Sub-array	Menus	Value	Applications menu	18-20	1	Derivative image	29	2	Option slot 1 set-up	15	4	Option slot 1 applications	25	5	Option slot 2 set-up	16	6	Option slot 2 applications	26	7	Option slot 3 set-up	17	8	Option slot 3 applications	27	9
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Temp Feedback	Internal thermistor has failed																																															
218	<p>The <i>Temp Feedback</i> trip indicates that an internal thermistor has failed. The thermistor location can be identified by the sub-trip number.</p> <table border="1"> <thead> <tr> <th>Source</th> <th>xx</th> <th>y</th> <th>zz</th> </tr> </thead> <tbody> <tr> <td>Control board</td> <td>00</td> <td>00</td> <td>01: Control board thermistor 1 02: Control board thermistor 2 03: I/O board thermistor</td> </tr> <tr> <td>Power system</td> <td>Power module number</td> <td>0</td> <td>Zero for temperature feedback provided via power system comms.21, 22 and 23 for direct ELV temperature feedback.</td> </tr> <tr> <td>Power system</td> <td>Power module number</td> <td>Rectifier number*</td> <td>Always zero</td> </tr> </tbody> </table> <p>* For a parallel power-module system the rectifier number will be one as it is not possible to determine which rectifier has detected the fault.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> Hardware fault – Contact the supplier of the drive 	Source	xx	y	zz	Control board	00	00	01: Control board thermistor 1 02: Control board thermistor 2 03: I/O board thermistor	Power system	Power module number	0	Zero for temperature feedback provided via power system comms.21, 22 and 23 for direct ELV temperature feedback.	Power system	Power module number	Rectifier number*	Always zero																															
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Th Brake Res	Brake resistor over temperature																																															
10	<p>The <i>Th Brake Res</i> is initiated, If hardware based braking resistor thermal monitoring is connected and the resistor overheats. If the braking resistor is not used then this trip must be disabled with bit 3 of Action <i>On Trip Detection</i> (10.037) to prevent this trip.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> Check brake resistor wiring Check braking resistor value is greater than or equal to the minimum resistance value Check braking resistor insulation 																																															

Trip	Diagnosis						
Th Short Circuit	Motor thermistor short circuit						
25	This trip indicates that a temperature sensor connected to an analogue input or terminal 15 on the position feedback interface has a low impedance (i.e. < 50 Ω). The cause of the trip can be identified by the sub-trip number.						
	<table border="1"> <thead> <tr> <th>Sub-trip</th> <th>Reason</th> </tr> </thead> <tbody> <tr> <td>3</td> <td><i>Analog Input 3 Mode (07.015) = 7</i> and the resistance of the thermistor connected to analog input 3 is less than 50 Ω.</td> </tr> <tr> <td>4</td> <td><i>P1 Thermistor Short Circuit Detect (03.123) = 1</i> and the resistance of the thermistor connected to the drive P1 position feedback interface is less than 50 Ω.</td> </tr> </tbody> </table>	Sub-trip	Reason	3	<i>Analog Input 3 Mode (07.015) = 7</i> and the resistance of the thermistor connected to analog input 3 is less than 50 Ω.	4	<i>P1 Thermistor Short Circuit Detect (03.123) = 1</i> and the resistance of the thermistor connected to the drive P1 position feedback interface is less than 50 Ω.
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4	<i>P1 Thermistor Short Circuit Detect (03.123) = 1</i> and the resistance of the thermistor connected to the drive P1 position feedback interface is less than 50 Ω.						
<p>Recommended actions:</p> <ul style="list-style-type: none"> • Check thermistor continuity • Replace motor / motor thermistor 							
Thermistor	Motor thermistor over-temperature						
24	The <i>Thermistor</i> trip indicates that the motor thermistor connected to terminal 8 (analog input 3) on the control connections or terminal 15 on the encoder terminal (15 way D-type connector) has indicated a motor over temperature. The cause of the trip can be identified by the sub-trip number						
	<table border="1"> <thead> <tr> <th>Sub-trip</th> <th>Reason</th> </tr> </thead> <tbody> <tr> <td>3</td> <td>Trip initiated from analog input 3</td> </tr> <tr> <td>4</td> <td>Trip initiated from P1 position feedback interface</td> </tr> </tbody> </table>	Sub-trip	Reason	3	Trip initiated from analog input 3	4	Trip initiated from P1 position feedback interface
	Sub-trip	Reason					
3	Trip initiated from analog input 3						
4	Trip initiated from P1 position feedback interface						
<p>Recommended actions:</p> <ul style="list-style-type: none"> • Check motor temperature • Check threshold level (07.048) • Check thermistor continuity 							
Undefined	Drive has tripped and the cause of the trip is Undefined						
110	The <i>Undefined</i> trip indicates that the power system has generated but did not identify the trip the power system. The cause of the trip is unknown.						
	<p>Recommended actions:</p> <ul style="list-style-type: none"> • Hardware fault – return the drive to the supplier 						
User 24V	User 24 V supply is not present on control terminals (1,2)						
91	A <i>User 24 V</i> trip is initiated, if <i>User Supply Select (Pr 06.072)</i> is set to 1 or <i>Low Under Voltage Threshold Select (06.067) = 1</i> and no user 24 V supply is present on control terminals 1 and 2.						
	<p>Recommended actions:</p> <ul style="list-style-type: none"> • Ensure the user 24 V supply is present on control terminals 1 (0V) and 2 (24 V) 						

Trip	Diagnosis																																																																																	
User Program	On board user program error (On Board User Program not supported on H300)																																																																																	
	The <i>User Program</i> trip indicates that an error has been detected in the onboard user program image. The reason for the trip can be identified by the sub-trip number.																																																																																	
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Defaults are loaded for the derivative menu and the trip will keep occurring until drive parameters are saved.</td> </tr> <tr> <td>61</td> <td>The option module installed in slot 1 is not allowed with the derivative image</td> <td>As 30</td> </tr> <tr> <td>62</td> <td>The option module installed in slot 2 is not allowed with the derivative image</td> <td>As 30</td> </tr> <tr> <td>63</td> <td>The option module installed in slot 3 is not allowed with the derivative image</td> <td>As 30</td> </tr> <tr> <td>64</td> <td>The option module installed in slot 4 is not allowed with the derivative image</td> <td>As 30</td> </tr> <tr> <td>70</td> <td>An option module that is required by the derivative image is not installed in any slot.</td> <td>As 30</td> </tr> <tr> <td>71</td> <td>An option module specifically required to be installed in slot 1 not present</td> <td>As 30</td> </tr> <tr> <td>72</td> <td>An option module specifically required to be installed in slot 2 not present</td> <td>As 30</td> </tr> <tr> <td>73</td> <td>An option module specifically required to be installed in slot 3 not present</td> <td>As 30</td> </tr> <tr> <td>74</td> <td>An option module specifically required to be installed in slot 4 not present</td> <td>As 30</td> </tr> <tr> <td>80</td> <td>Image is not compatible with the control board</td> <td>Initiated from within the image code</td> </tr> <tr> <td>81</td> <td>Image is not compatible with the control board serial number</td> <td>As 80</td> </tr> </tbody> </table>	Sub-trip	Reason	Comments	1	Divide by zero		2	Undefined trip		3	Attempted fast parameter access set-up with non-existent parameter		4	Attempted access to non-existent parameter		5	Attempted write to read-only parameter		6	Attempted and over-range write		7	Attempted read from write-only parameter		30	The image has failed because either its CRC is incorrect, or there are less than 6 bytes in	Occurs when the drive powers-up or the image is programmed. 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User Prog Trip	Trip generated by an onboard user program (On Board User Program not supported on H300)																																																																																	
	This trip can be initiated from within an onboard user program using a function call which defines the sub-trip number.																																																																																	
96	<p>Recommended actions:</p> <ul style="list-style-type: none"> • Check the user program 																																																																																	

Trip	Diagnosis						
User Save	User Save error / not completed						
36	<p>The <i>User Save</i> trip indicates that an error has been detected in the user save parameters saved in non-volatile memory. For example, following a user save command, If the power to the drive was removed when the user parameters were being saved.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> Perform a user save in Pr mm.000 to ensure that the trip doesn't occur the next time the drive is powered up. Ensure that the drive has enough time to complete the save before removing the power to the drive. 						
User Trip	User generated trip						
40 -89 112 -159	<p>These trips are not generated by the drive and are to be used by the user to trip the drive through an application program.</p> <p>Recommended actions:</p> <ul style="list-style-type: none"> Check the user program 						
Voltage Range	Supply voltage is outside of the defined range in Regen mode						
169	<p>This trip is initiated if the Maximum Supply Voltage is set to a non-zero value and the supply voltage is outside the range defined by Minimum Supply Voltage and Maximum Supply Voltage for more than 100 ms.</p> <table border="1"> <thead> <tr> <th>Sub-trip</th> <th>Reason</th> </tr> </thead> <tbody> <tr> <td>1</td> <td>Supply voltage is below Minimum Supply Voltage</td> </tr> <tr> <td>2</td> <td>Supply voltage is above Maximum Supply Voltage</td> </tr> </tbody> </table> <p>Recommended actions:</p> <ul style="list-style-type: none"> Ensure the supply voltage is operating within the drive specification. Ensure Minimum Supply Voltage and Maximum Supply Voltage are set correctly. Check the supply voltage waveform using an oscilloscope. Reduce the level of supply disturbance. Set Maximum Supply Voltage to zero to disable this trip. 	Sub-trip	Reason	1	Supply voltage is below Minimum Supply Voltage	2	Supply voltage is above Maximum Supply Voltage
Sub-trip	Reason						
1	Supply voltage is below Minimum Supply Voltage						
2	Supply voltage is above Maximum Supply Voltage						
Watchdog	Control word watchdog has timed out						
30	<p>The <i>Watchdog</i> trip indicates that the control word has been enabled and has timed out</p> <p>Recommended actions:</p> <p>Once Pr 06.042 bit 14 has been changed from 0 to 1 to enable the watchdog, this must be repeated every 1s or a Watchdog trip will be initiated. The watchdog is disabled when the trip occurs and must be re-enabled if required when the trip is reset.</p>						

Table 13-4 Serial communications look up table

No	Trip	No	Trip	No	Trip
1	Reserved 001	94	Rectifier Set-Up	218	Temp Feedback
2	Over Volts	95	Reserved 95	219	An Output Calib
3	OI ac	96	User Prog Trip	220	Power Data
4	OI Brake	97	Data Changing	221	Stored HF
5	PSU	98	Out Phase Loss	222	Reserved 222
6	External Trip	99	CAM	223	Rating Mismatch
7	Over Speed	100	Reset	224	Drive Size
8	Inductance	101	OHT Brake	225	Current Offset
9	PSU 24	102	Cloning	226	Soft Start
10	Th Brake Res	103	Inter-connect	227	Sub-array RAM
11	Autotune 1	104	Phase Imbalance	228 - 246	Reserved 228 - 246
12	Autotune 2	105 - 108	Reserved 105 - 108	247	Derivative ID
13	Autotune 3	109	OI dc	248	Derivative Image
14	Autotune 4	110	Undefined	249	User Program
15	Autotune 5	111	Configuration	250	Slot4 HF
16	Autotune 6	112 - 159	User Trip 112 - 159	251	Slot4 Watchdog
17	Autotune 7	160	Island	252	Slot4 Error
18	Autotune Stopped	161 - 166	Reserved 161 - 166	253	Slot4 Not installed
19	Brake R Too Hot	167	No Encoder Found	254	Slot4 Different
20	Motor Too Hot	168	Reserved 168	255	Reset Logs
21	OHT Inverter	169	Voltage Range		
22	OHT Power	170 - 173	Reserved 170 - 173		
23	OHT Control	176	Name Plate		
24	Thermistor	198	Phasing Error		
25	Th Short Circuit	199	Destination		
26	I/O Overload	200	Slot1 HF		
27	OHT dc bus	201	Slot1 Watchdog		
28	An Input Loss 1	202	Slot1 Error		
29	An Input Loss 2	203	Slot1 Not installed		
30	Watchdog	204	Slot1 Different		
31	EEPROM Fail	205	Slot2 HF		
32	Phase Loss	206	Slot2 Watchdog		
33	Resistance	207	Slot2 Error		
34	Keypad Mode	208	Slot2 Not installed		
35	Control Word	209	Slot2 Different		
36	User Save	210	Slot3 HF		
37	Power Down Save	211	Slot3 Watchdog		
38	Low Load	212	Slot3 Error		
39	Line Sync	205	Slot2 HF		
40 -89	User Trip 40 - 89	213	Slot3 Not installed		
90	Power Comms	214	Slot3 Different		
91	User 24V	215	Option Disable		
92	OI Snubber	216	Slot App Menu		
93	Inductor Too Hot	217	App Menu Changed		

The trips can be grouped into the following categories. It should be noted that a trip can only occur when the drive is not tripped or is already tripped but with a trip with a lower priority number.

Table 13-5 Trip categories

Priority	Category	Trips	Comments
1	Internal faults	HF01 to HF28	These indicate internal problems and cannot be reset. All drive features are inactive after any of these trips occur. If a KI-Keypad is installed it will show the trip, but the keypad will not function.
1	Stored HF trip	{Stored HF}	This trip cannot be cleared unless 1299 is entered into <i>Parameter (mm.000)</i> and a reset is initiated.
2	Non-resettable trips	Trip numbers 218 to 247, {Slot1 HF}, {Slot2 HF}, {Slot3 HF} or {Slot4 HF}	These trips cannot be reset.
3	Volatile memory failure	{EEPROM Fail}	This can only be reset if Parameter mm.000 is set to 1233 or 1244, or if <i>Load Defaults (11.043)</i> is set to a non-zero value.
3	Internal 24 V power supply	{PSU 24}	
4	NV Media Card trips	Trip numbers 174, 175 and 177 to 188	These trips are priority 5 during power-up.
5	Trips with extended reset times	{OI ac}, {OI Brake} and {OI dc}	These trips cannot be reset until 10 s after the trip was initiated.
5	Phase loss and d.c. link power circuit protection	{Phase Loss} and {Oht dc bus}	The drive will attempt to stop the motor before tripping if a {Phase Loss}.000 trip occurs unless this feature has been disabled (see <i>Action On Trip Detection (10.037)</i>). The drive will always attempt to stop the motor before tripping if an {Oht dc bus} occurs.
5	Standard trips	All other trips	

13.5 Internal / Hardware trips

Trips {HF01} to {HF20} are internal faults that do not have trip numbers. If one of these trips occurs, the main drive processor has detected an irrecoverable error. All drive functions are stopped and the trip message will be displayed on the drive keypad. If a non permanent trip occurs this may be reset by power cycling the drive. On power up after it has been power cycled the drive will trip on Stored HF. Enter 1299 in **mm.000** to clear the Stored HF trip.

13.6 Alarm indications

In any mode, an alarm is an indication given on the display by alternating the alarm string with the drive status string on the first row and showing the alarm symbol in the last character in the first row. If an action is not taken to eliminate any alarm except "Auto Tune and Limit Switch" the drive may eventually trip. Alarms are not displayed when a parameter is being edited, but the user will still see the alarm character on the upper row.

Table 13-6 Alarm indications

Alarm string	Description
Motor Overload	Motor Protection Accumulator (04.019) in the drive has reached 75.0 % of the value at which the drive will trip and the load on the drive is >100 %.
Drive Overload	Drive over temperature. Percentage Of Drive Thermal Trip Level (07.036) in the drive is greater than 90 %.
Auto Tune	The autotune procedure has been initialized and an autotune in progress.

13.7 Status indications

Table 13-7 Status indications

Upper row string	Description	Drive output stage
Inhibit	The drive is inhibited and cannot be run. The Safe Torque Off signal is not applied to Safe Torque Off terminals or Pr 06.015 is set to 0	Disabled
Off	The drive is stopped	Disabled
Hand	The drive is active and running. The motor speed/frequency is determined by the value in the Keypad Control Mode Reference Pr 01.017	Enabled
Auto	The drive is active and running. The reference for the motor speed/frequency is defined by Reference Selector Pr 01.014	Enabled
Supply Loss	Supply loss condition has been detected	Enabled
Deceleration	The motor is being decelerated to zero speed / frequency because the final drive run has been deactivated.	Enabled
dc injection	The drive is applying dc injection braking	Enabled
Trip	The drive has tripped and no longer controlling the motor. The trip code appears in the lower display	Disabled
Under Voltage	The drive is in the under voltage state either in low voltage or high voltage mode	Disabled
Heat	The motor pre-heat functions inactive	Enabled
Phasing	The drive is performing a 'phasing test on enable'.	Enabled

Table 13-8 Option module and NV Media Card and other status indications at power-up

First row string	Second row string	Status
Booting	Parameters	Parameters are being loaded
Drive parameters are being loaded from a NV Media Card		
Booting	Option Program	User program being loaded
User program is being loaded from a NV Media Card to the option module in slot X		
Writing To	NV Card	Data being written to NV Media Card
Data is being written to a NV Media Card to ensure that its copy of the drive parameters is correct because the drive is in Auto or Boot mode		
Waiting For	Power System	Waiting for power stage
The drive is waiting for the processor in the power stage to respond after power-up		
Waiting For	Options	Waiting for an option module
The drive is waiting for the Options Modules to respond after power-up		
Uploading From	Options	Loading parameter database
At power-up it may be necessary to update the parameter database held by the drive because an option module has changed or because an applications module has requested changes to the parameter structure. This may involve data transfer between the drive and option modules. During this period 'Uploading From Options' is displayed		

13.8 Programming error indications

Following are the error message displayed on the drive keypad when an error occurs during programming of drive firmware.

Table 13-9 Programming error indications

Error String	Reason	Solution
Error 1	There is not enough drive memory requested by all the option modules.	Power down drive and remove some of the option modules until the message disappears.
Error 2	At least one option module did not acknowledge the reset request.	Power cycle drive
Error 3	The boot loader failed to erase the processor flash	Power cycle drive and try again. If problem persists, return drive
Error 4	The boot loader failed to program the processor flash	Power cycle drive and try again. If problem persists, return drive
Error 5	One option module did not initialize correctly. Option module did not set Ready to Run flag.	Remove faulty option module.

13.9 Displaying the trip history

The drive retains a log of the last ten trips that have occurred. *Trip 0* (10.020) to *Trip 9* (10.029) store the most recent 10 trips that have occurred where *Trip 0* (10.020) is the most recent and *Trip 9* (10.029) is the oldest. When a new trip occurs it is written to *Trip 0* (10.020) and all the other trips move down the log, with oldest being lost. The date and time when each trip occurs are also stored in the date and time log, i.e. *Trip 0 Date* (10.041) to *Trip 9 Time* (10.060). The date and time are taken from *Date* (06.016) and *Time* (06.017). The date / time source can be selected with *Date / Time Selector* (06.019). Some trips have sub-trip numbers which give more detail about the reason for the trip. If a trip has a sub-trip number its value is stored in the sub-trip log, i.e. *Trip 0 Sub-trip Number* (10.070) to *Trip 9 Sub-trip Number* (10.079). If the trip does not have a sub-trip number then zero is stored in the sub-trip log.

If any parameter between Pr 10.020 and Pr 10.029 inclusive is read by serial communication, then the trip number in Table 13-3 is the value transmitted.

NOTE

The trip logs can be reset by writing a value of 255 in Pr 10.038.

13.10 Behaviour of the drive when tripped

If the drive trips, the output of the drive is disabled so the load coasts to a stop. If any trip occurs the following read only parameters are frozen until the trip is cleared. This is to help in diagnose the cause of the trip.

Parameter	Description
01.001	Frequency / speed reference
01.002	Pre-skip filter reference
01.003	Pre-ramp reference
02.001	Post-ramp reference
03.001	Final speed ref
03.002	Speed feedback
03.003	Speed error
03.004	Speed controller output
04.001	Current magnitude
04.002	Active current
04.017	Reactive current
05.001	Output frequency
05.002	Output voltage
05.003	Power
05.005	DC bus voltage
07.001	Analog input 1
07.002	Analog input 2

If the parameters are not required to be frozen then this can be disabled by setting bit 4 of Pr 10.037.

14 UL listing information

14.1 UL file reference

All products covered by this Guide are UL Listed to both Canadian and US requirements. The UL file reference is: NMMS/7.E171230. Products that incorporate the Safe Torque Off function have been investigated by UL. The UL file reference is: FSFC.E171230.

14.2 Option modules, kits and accessories

All Option Modules, Control Pods and Installation Kits supplied by Nidec Industrial Automation for use with these drives are UL Listed.

14.3 Enclosure ratings

Drives are UL Open Type as supplied.

Drives fitted with a conduit box are UL Type 1.

Drives that are capable of through-hole mounting are UL Type 12 when installed with the high-IP insert (where provided), and the Type 12 sealing kit to prevent ingress of dust and water.

Remote Keypads are UL Type 12.

14.4 Mounting

Drives can be mounted directly onto a vertical surface. This is known as 'surface' or 'standard' mounting. Refer to section 3.5.1 *Surface mounting* on page 42 for further information.

Drives can be installed side by side with recommended spacing between them. This is known as 'bookcase' mounting. Refer to section 3.6 *Enclosure for standard drives* on page 59 for further information.

Drives fitted with a conduit box can be mounted directly onto a wall or other vertical surface without additional protection. Suitable conduit boxes are available from Nidec Industrial Automation.

Some drives may be through-hole mounted. Mounting brackets and sealing kits are available from Nidec Industrial Automation. Refer to section 3.5.2 *Through-panel mounting* on page 49 for further information.

Remote Keypads can be mounted on the outside of a UL Type 12 enclosure. A sealing and mounting kit is provided with the keypad.

14.5 Environment

Drives must be installed in a Pollution Degree 2 environment or better (dry, non-conductive pollution only). All drives are capable of delivering full rated output current at surrounding air temperatures up to 40 °C.

Drives may be operated in surrounding air temperatures up to 50 °C or 55 °C at de-rated current, depending on the model number. Refer to section 12.1.1 *Power and current ratings (Derating for switching frequency and temperature)* on page 279.

14.6 Electrical Installation

TERMINAL TORQUE

Terminals must be tightened to the rated torque as specified in the Installation Instructions. Refer to section 3.12.2 *Terminal sizes and torque settings* on page 77 for further information.

WIRING TERMINALS

Drives must be installed using cables rated for 75 °C operation, copper wire only.

UL Listed closed-loop connectors sized according to the field wiring shall be used for all field wiring connections. Refer to section 3.12.2 *Terminal sizes and torque settings* on page 77 for further information.

BRANCH CIRCUIT PROTECTION

The fuses and circuit breakers required for branch circuit protection are contained in the Installation Instructions. Refer to section 12.1.20 *Input current, fuse and cable size ratings* on page 292

OPENING OF BRANCH CIRCUIT

Opening of the branch-circuit protective device may be an indication that a fault has been interrupted. To reduce the risk of fire or electric shock, the equipment should be examined and replaced if damaged. If burnout of the current element of an overload relay occurs, the complete overload relay must be replaced.

Integral solid state short circuit protection does not provide branch circuit protection. Branch circuit protection must be provided in accordance with the National Electrical Code and any additional local "codes".

14.7 Motor overload protection and thermal memory retention

All drives incorporate internal overload protection for the motor load that does not require the use of an external or remote overload protection device.

The protection level is adjustable and the method of adjustment is provided in section 8.2 *Motor thermal protection* on page 186. Maximum current overload is dependent on the values entered into the current limit parameters (motoring current limit, regenerative current limit and symmetrical current limit entered as percentage) and the motor rated current parameter (entered in amperes).

The duration of the overload is dependent on motor thermal time constant. The time constant is programmable. The default overload protection is set such that the product is capable of 150 % of the current value entered into the motor rated current parameter for 60 seconds.

The drives are provided with user terminals that can be connected to a motor thermistor to protect the motor from high temperature, in the event of a motor cooling fan failure.

The method of adjustment of the overload protection is provided in the Installation Instructions shipped with the product.

All models are provided with thermal memory retention.

14.8 Electrical supply

The drives are suitable for use on a circuit capable of delivering not more than 100,000 RMS Symmetrical Amperes, at rated voltage when protected by fuses as specified in the Installation Instructions.

Some smaller drives are suitable for use on a circuit capable of delivering not more than 10,000 RMS Symmetrical Amperes, at rated voltage when protected by circuit breakers as specified in the Installation Instructions.

14.9 External Class 2 supply

The external power supply used to power the 24 V control circuit shall be marked: "UL Class 2". The power supply voltage shall not exceed 24 Vdc.

14.10 Requirement for Transient Surge Suppression

This requirement applies to drives with rated input voltage = 575 V, Frame Size 7 only.

TRANSIENT SURGE SUPPRESSION SHALL BE INSTALLED ON THE LINE SIDE OF THIS EQUIPMENT AND SHALL BE RATED 575 Vac (PHASE TO GROUND), 575 Vac (PHASE TO PHASE), SUITABLE FOR OVERVOLTAGE CATEGORY III, AND SHALL PROVIDE PROTECTION FOR A RATED IMPULSE VOLTAGE TO WITHSTAND VOLTAGE PEAK OF 6 kV AND A CLAMPING VOLTAGE OF MAXIMUM 2400 V.

14.11 Group Installation and Modular Drive Systems

Drives with DC+ and DC- supply connections, with 230 V or 480 V supply voltage rating, are UL approved for use in modular drive systems as inverters when supplied by the converter sections: Mentor MP25A, 45A, 75A, 105A, 155A or 210A range manufactured by Nidec Industrial Automation.

Alternatively, the inverters may be supplied by converters from the *HVAC Drive-H300* range manufactured by Nidec Industrial Automation.

In these applications the inverters are required to be additionally protected by supplemental fuses.

Drives have not been evaluated for other Group Installation applications, for example where a single inverter is wired directly to two or more motors. In these applications, additional thermal overload protection is needed. Contact Nidec Industrial Automation for further details.

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