

SY200 series Servo Driver User Manual



SHANGHAI SANYU INDUSTRY CO., LTD.

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Note: The main manual is for DB15 version, For DB9 servo wiring diagram please refer to appendices.

Chapter 1 Specification and Size

1.1 The nameplate of servo unit

1.1.1 The nameplate of servo unit

Model: SY200 - 40A - 2 (□□)
 ① ② ③ ④

- ① Servo driver series: SY200: SY200 series
- ② Servo driver power: 40A: 400W; 75A: 750W; 100A: 1kW; 150A: 1.5kW; 200A: 2kW; 300A:3kW; 450A: 4.5kW; 550A:5.5kW; 750A: 7.5kW; 11kA: 11kW; 15kA: 15kW; 18kA:18.5kW
- ③ Voltage: 2: 1PH/3PH AC220V; 4: 3PH AC380V
- ④ Software model: 00: General purpose;

1.1.2 The nameplate of servo motor

Model: SY - 60 KP 40A 30 D A Y Y B
 ① ② ③ ④ ⑤ ⑥ ⑦ ⑧ ⑨ ⑩

- ① Motor series: SY series
- ② Flange: 60: 60 flange ; 80: 80 flange ; 130: 130 flange , 180: 180 flange
- ③ Inertia: KP: Low inertia; SP: Medium inertia; HP: High inertia
- ④ Motor power: 40A: 400W; 75A: 750W; 100A: 1kW; 150A: 1.5kW; 200A: 2kW; 300A:3kW; 450A: 4.5kW; 550A:5.5kW; 750A: 7.5kW; 11kA: 11kW; 15kA: 15kW; 18kA:18.5kW
- ⑤ Motor rotation: 10: 1000rpm; 15:1500rpm; 20: 2000rpm; 25: 2500rpm; 30: 3000rpm
- ⑥ Encoder model: S: 2500 line(wire-saving); T: 2500 line; D: 17 bit absolute; P: 23 bit absolute
- ⑦ Electromagnetic braking: A: Without brake B: With brake
- ⑧ Keyway: Y: Yes
- ⑨ Oil seal: Y: Yes
- ⑩ Voltage: B: 220V; D:380V

1.2 The general specifications of servo unit

Basic Specification	Control Mode		1. Position Control 2. Speed Control 3.Torque Control	
	Feedback Type		1. Square wave incremental Encoder 2. Absolute Encoder	
	Use Conditions	Using/Storage temperature	0~+55℃/-20~+85℃	
		Using/Storage humidity	90% RH or less (non-condensing)	
Resistance to vibration/impact resistance		4.9m/s ² ,19.6m/s ²		
Speed Control Mode	Performance	Speed control range	1:5000 (The lower limit of the speed control range is the condition of not stopping in rated torque load)	
		Speed changing rate	load changing rate	When the load is 0~100%: less than ±0.01% (in the rated speed)
			Voltage changing rate	Rated voltage ±10%: 0% (in the rated speed)
			temperature	25±25℃: less than ±0.1% (in the rated

		changing rate	speed)	
		frequency characteristics	1.25kHz (when JL = JM)	
		torque control precision (reproducibility)	±2%	
		Soft start time setting	0~65s (can respectively set acceleration and deceleration time)	
	Input Signal	Speed instruction input	Instruction Voltage	DC±10V(DC 0V~±10V: Variable setting range)/rated rotating speed input voltage:±12V (motor forward when the instruction is positive)
			Input impedance	About 10KΩ
			the circuit time parameter	About 47μs
		Torque instruction input	Instruction voltage	DC±10V(DC 0V~±10V: Variable setting range)/rated rotating speed input voltage:±12V (motor forward when the instruction is positive)
			Input impedance	About 10KΩ
			the circuit time parameter	About 47μs
		Torque speed instruction	Selection of the rotating direction	Input using DI signal
	Position Control Mode	Performance	Feed forward compensation	0~100% (Setting resolution 1%)
			Position complete width setting	1~65535 command unit (Setting resolution 1 Command unit)
Encoder		Incremental	2500 lines, 5000 lines, wire-saving model	
		Absolute Value	17bits, 20bits, 23bits	
Input Signal		Command pulse	Input pulse types	1. Symbol+pulse sequence 2. CCW+CW pulse sequence 3. 90° Phase difference 2-phase pulse (A phase+B phase)
			Input pulse state	Differential drive (+5V level)
				Open collector (+5V, +12V, +24V level)
		Input pulse frequency	Differential drive: maximum 4Mpps	
			Open collector drive: maximum 500kpps	
Control signal		Clear signal (input pulse shape and is the same as command pulse)		
Input Output	Position output	Output state	A phase, B phase, Z phase, Differential driver output	
		Divide ratio	Arbitrarily divide	

	Input signal digital	Function can be defined	9 DI; Serve ON, P action (or control mode switching, motor's forward/reverse switch carried by internal speed, zero phase, prohibit command pulse), prohibits forward drive (P-OT), prohibiting reverse drive (N-OT), alarm reset, the forward current limiting, reverse side current limit (or internal speed selection)	
	Output signal sequentially	Function can be defined	8 DO; Include the positioning complete (consistent speed), the rotating motor, servo ready, current limit, the speed limit, the release of the brake ,warning, Near signal	
Built-in Function	Dynamic brake (DB) function		The main power OFF, servo alarm, servo OFF, over-travel action	
	Over-travel(OT) prevention function		P-OT, N-OT action when DB stops, deceleration stop or coasting stop	
	Electronic gear		$0.001 \leq B/A \leq 4000$	
	Protection function		Overcurrent, overvoltage, undervoltage, overload, abnormal regeneration, the main circuit error, heat sink overheat, loss phase of power supply, overflow, overspeed, encoder error, precaution runaway, CPU error, abnormal parameters, position offset, ect	
	LED display function		Main power CHARGER, 5 LED display	
	Communication function	Connected devices		CAN(Optional); MODBUS
		Axis address setting		Set according to user parameter
1:N communication		RS-485 port, maximum slave station is depend on the quantity supported by master station		
function		Status display, the user parameter settings, monitor display, alarm trace display, JOG operation and auto-tuning operation, speed, torque command signal, such as mapping functions		
	Others		Zero point search; motor auto-tuning; incremental auto adjust; low-frequency vibration suppression; Operating mode switch; Motor resonance suppression, plenty DIDO function, Full close loop control; Interrupt the length function	

1.3 Installation of the servo unit

SY200 servo unit is the base type (applicable to shelving) servo driver. If you install in the wrong way, the fault will occur. Please install properly according to the following instruction.

1. 3. 1 The environment

When in the unpowered state to keep the servo unit, for safekeeping in the temperature range $-20 \sim +85\text{ }^{\circ}\text{C}$, and no condensation at 90% RH or less.

- Overvoltage category: III
- Defacement degree: 2
- the degree of protection: 1X
- Altitude: 1000m or less

According to the following standard

- UL508C • CSA C22.2 No.14 • EN50178 • EN55011 group 1 class A • EN61000-6-2

1. 3. 2 Installation place

◆ Installed in the control cabinet, designing the control cabinet size, the configuration of the servo unit and cooling method so that the peripheral portion of the servo unit is at a temperature below $55\text{ }^{\circ}\text{C}$.

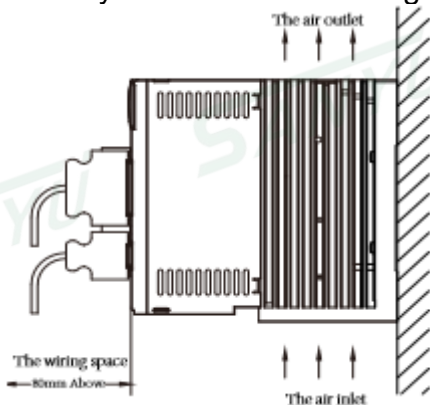
◆ When installed near the heating element, the temperature of the servo unit should be maintained below around $55\text{ }^{\circ}\text{C}$, please control the heating due to heat radiation or convection caused by the heating element

◆ When installed near the vibration source, Please install vibration isolator on the surface of servo unit to prevent vibration transmission to the servo unit

◆ When installed in corrosive gases place, try to prevent the intrusion of corrosive gases. Although no immediate impact, but will lead to fault of electronic components and the fault of related components of contactors.

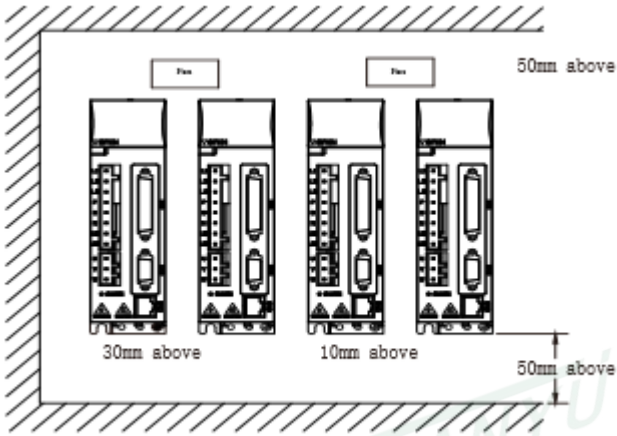
1.3.3 Mounting direction

As shown below, the direction perpendicular to the direction of installing wall. Use self-cooling or fan-cooling servo unit. Be sure to observe the direction of the installation requirements. Please Using 2 ~ 4 (installed holes varies due to the capacity) mounting holes of the servo unit is securely fixed to the mounting surface.



1.3.4 The installation standard

Be sure to comply with the installation standard in the control cabinet as shown in the figure, the standard adapted to multiple servo units mounted side by side in the control cabinet occasions (refer to "side by side installation")



◆ The servo unit's direction

When installing, make positive servo unit (actual mounting surface of the panel operator) for the operator, and make it perpendicular to wall.

◆ Cooling

To ensure it can be cooled by natural convection fan, please refer to the figure, leave enough space around the servo unit.

◆ When installed side by side

In the lateral sides, leaving over 10mm, leaving over 50mm in longitudinal sides. In addition,, install a cooling fan in the upper part of the servo unit. In order not to make the ambient temperature of the servo unit appear partial overheating phenomenon, the temperature in the control cabinet required to maintain.

◆ Environmental conditions in the control cabinet

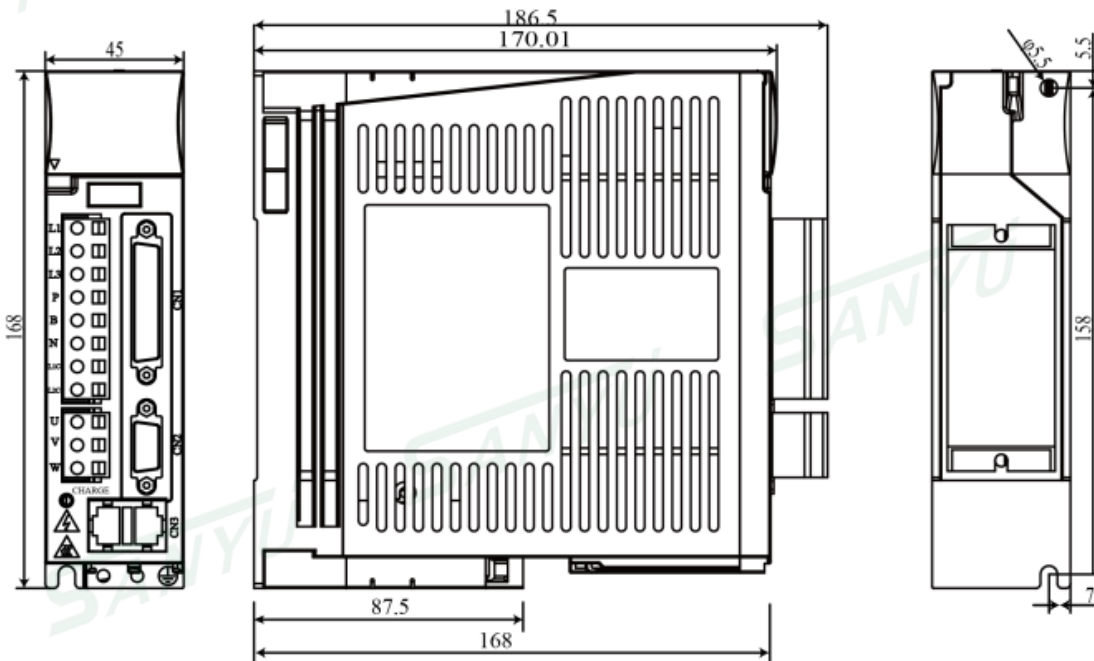
Servo unit's ambient temperature : 0 ~ 55 °C; Humidity: 90% RH (relative humidity) below; Vibration:4.9m/s²; Pay attention to avoid the occurrence of frozen condensation phenomena, in order to ensure long-term reliability, it is recommended to use at temperatures below 55 °C ambient temperature conditions.

1.4 Servo driver's dimension

1.4.1 Dimension A

Model: 750W and below

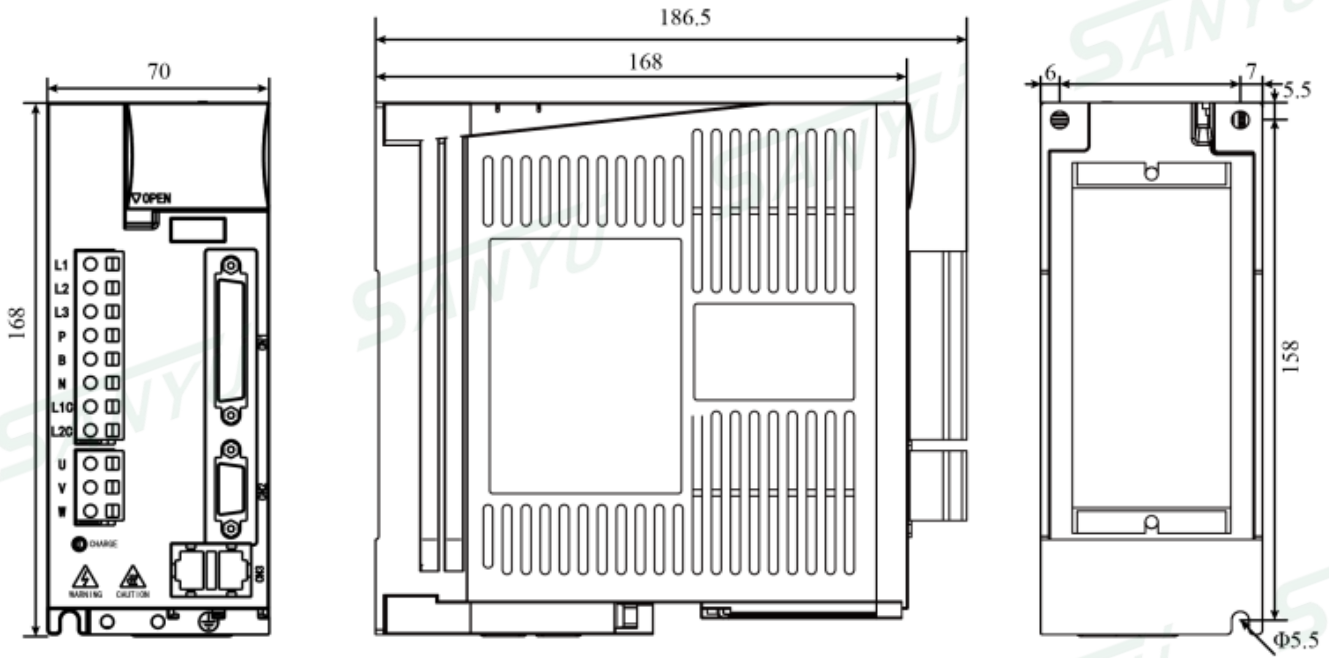
H x L x W = 168 x 168 x 45mm



1.4.2 Dimension B

Model: 220V: 1kW-2kW ; 380V: 2kW-3kW

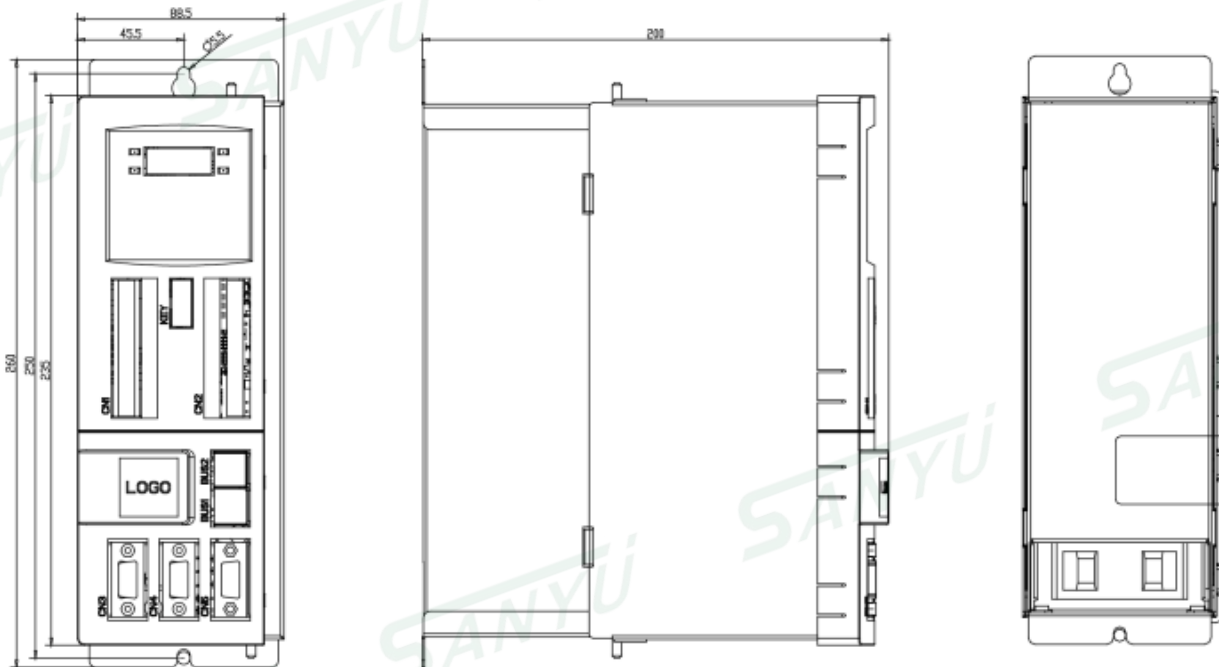
H x L x W = 168 x 168 x 70mm



1.4.3 Dimension C

Model: 380V: 4.5kW-5.5kW

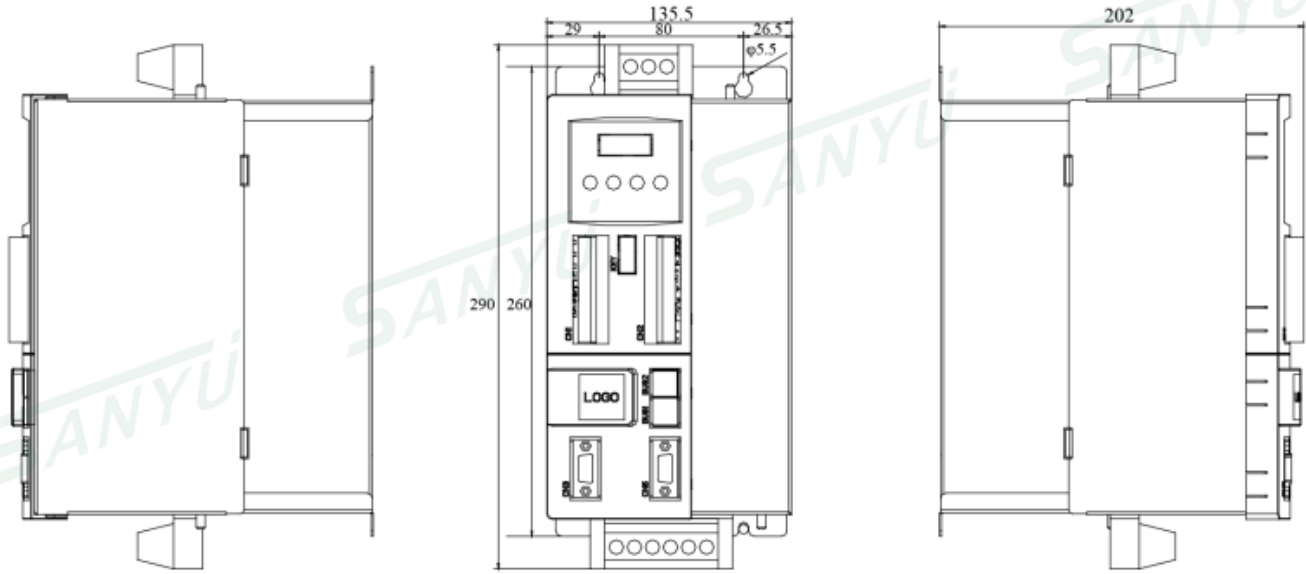
H x L x W = 260 x 200x 88.5mm



1.4.4 Dimension D

Model: 380V: 7.5kW-11kW

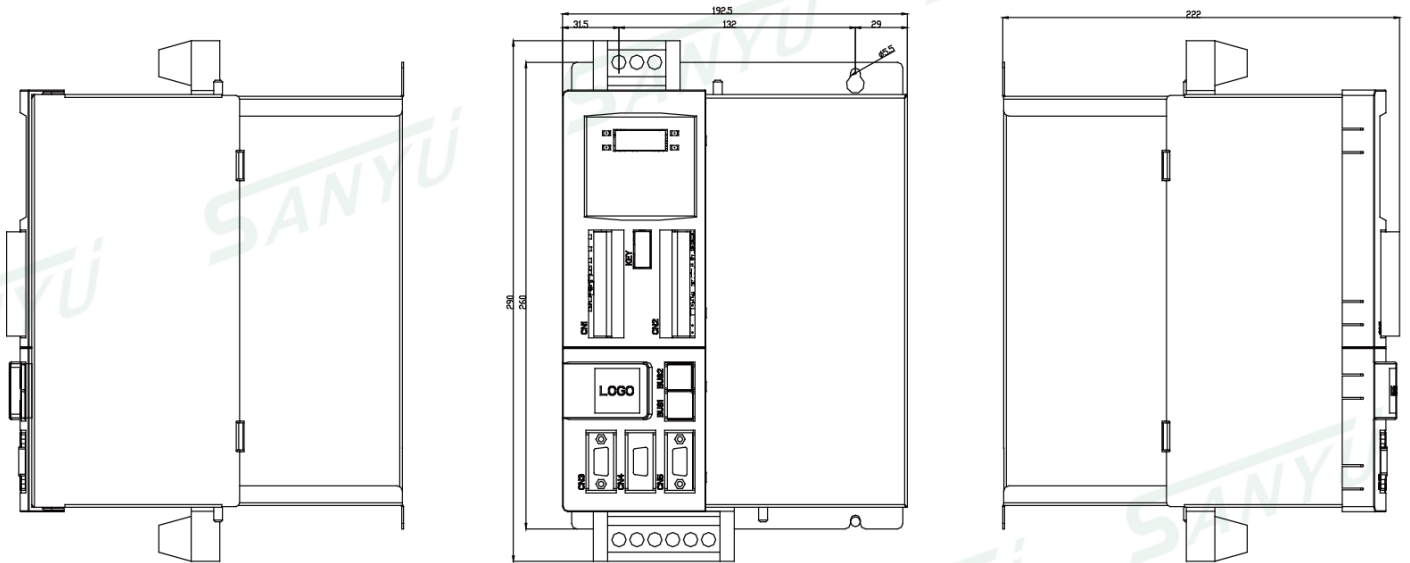
H x L x W = 290 x 202x 135.5mm



1.4.5 Dimension E

Model: 380V: 15kW-18.5kW

H x L x W = 290 x 222x 192.5mm



Chapter 2 Electrical wiring

2.1 Main Circuit Wiring

- Do not pass power lines and signal lines through the same pipeline through, and do not banding together. When wiring, power lines and signal lines should leave more than 30cm. Otherwise, it may result in malfunction.
- Signal line, encoder (PG) feedback lines use stranded wire and multi-core shield wire. For the wiring length, the command input line up to 3m, encoder feedback line up to 20m.
- Even if the power is turned off, the servo unit may remain high voltage. Within five minutes ,do not touch the power terminals. Please confirm CHARGE lamp goes out before further inspection operations.
- Do not frequently switch the power supply. When you need to repeatedly continuously switch power supply, control one minute one time or less. Since servo unit's power with a capacitance, so when the power is on ,there will be large charging current flowing through (charging time 0.2 seconds). Therefore, if frequently switch the power supply, it will reduce the performance of the main circuit element inside the servo unit.

2.1.1 The main circuit power connector (spring type) wiring method.

The servo unit below 3.0kW capacity with the main circuit power supply terminal and the control power supply terminal with removable connector. Follow the steps below for the power connector wiring.

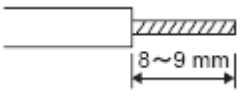
(1) Wire Size

Wire sizes that can be used as below. Stripe the wire jacket to use.

- A. single wire..... $\Phi 0.5 \sim \Phi 1.6$ mm
- B. Stranded wire.....AWG28 \sim AWG12

(2) Connection methods

1. Strip the skin of cable

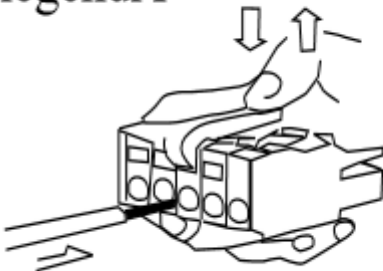


2. Use the tool opening portion in the power connector wire insertion. – Openings include two methods(A and B)

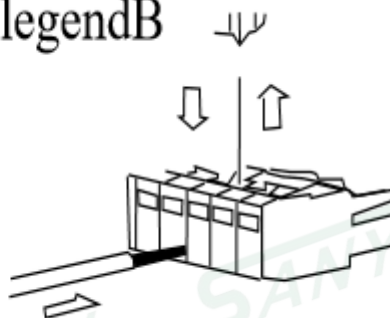
In the case of A, hang incidental rod of servo unit to open portion.

In the case of B, use a slotted screw driver (Blade width of 3.0~3.5mm).

legendaA



legendaB



3. The core wire partially inserted in the opening, after insertion, releases the lever or a slotted screwdriver.

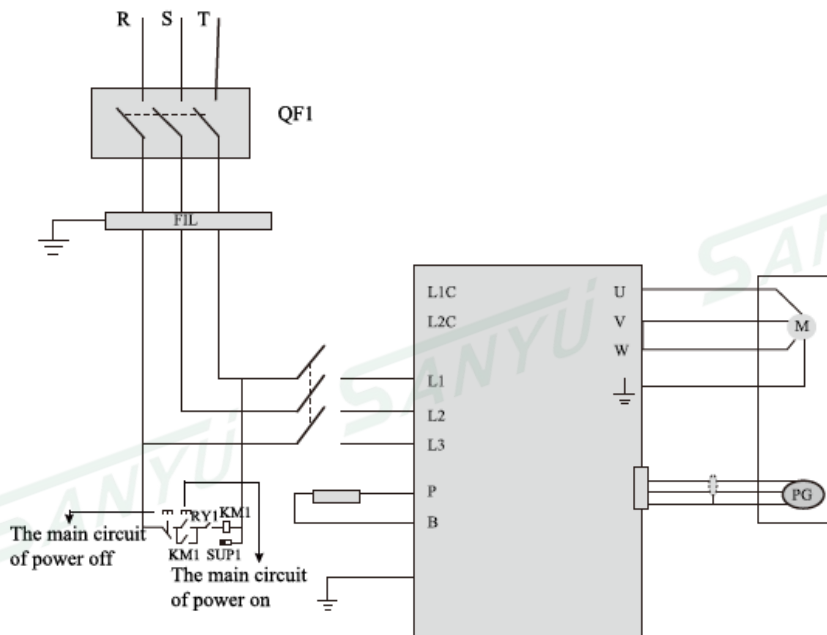
When wiring, remove the power supply connector from the body of the servo unit.

A port of electric power supply connector is inserted only one wire.

When insert wires, Please do not make the core wire and the adjacent electrical short circuit.

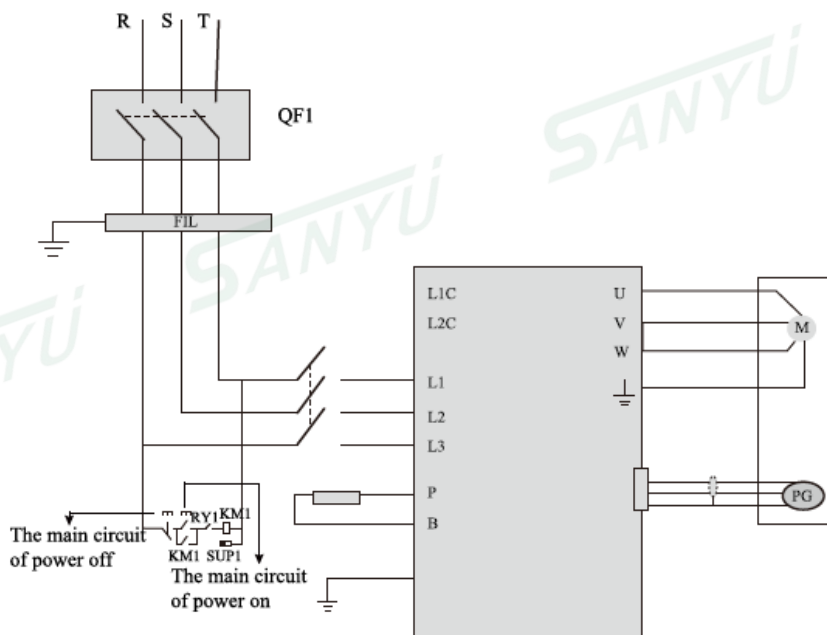
2.1.2 Wire diagram

(1) 3PH 220V wiring :



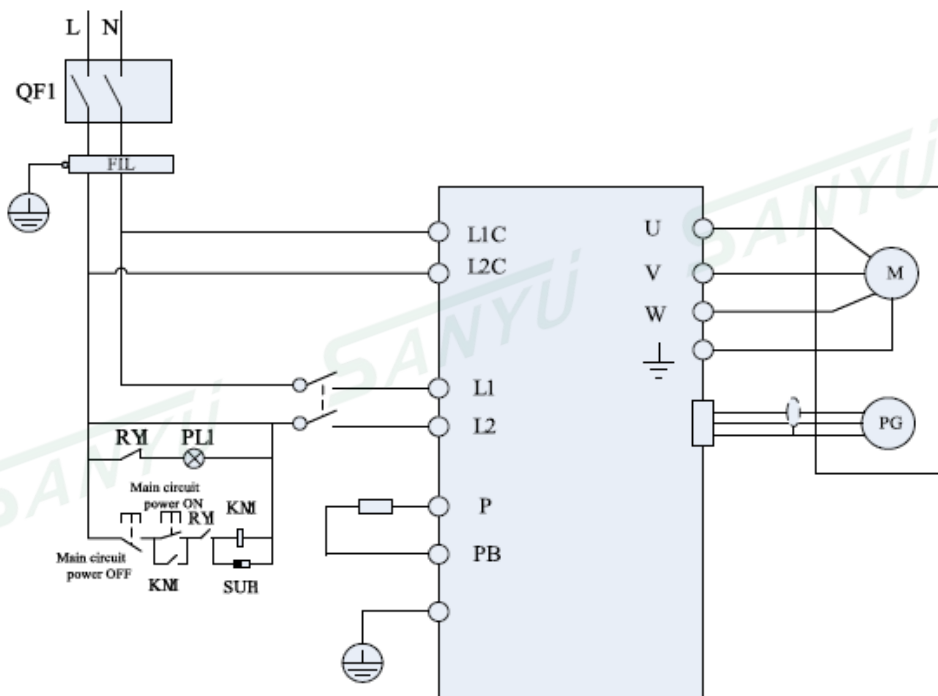
QF1: Breaker; RY1: Relay; FIL: Filter; PL1: Display lamp; SUP1: Suppressor; KM1: Magnetic contactor

(2) 3PH 380V wiring: 380V 2KW-3KW



QF1: Breaker; RY1: Relay; FIL: Filter; PL1: Display lamp; SUP1: Suppressor; KM1: Magnetic contactor

(3) 1PH 220V wiring: (Connect L1, L2, otherwise it will display nrd)



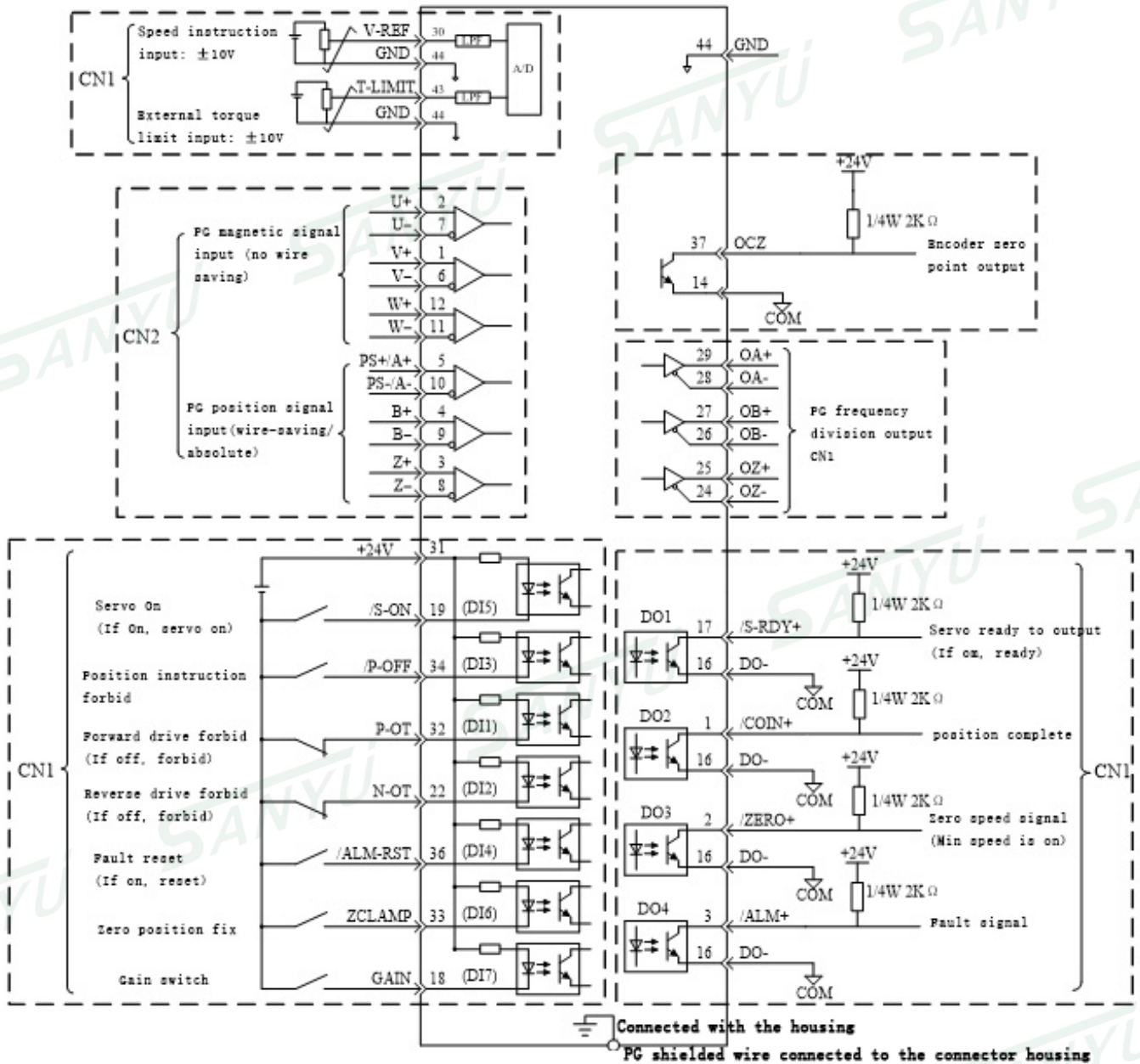
QF1: Breaker; RY1: Relay; FIL: Filter; PL1: Display lamp; SUP1: Suppressor; KM1: Magnetic contactor

Important Note:

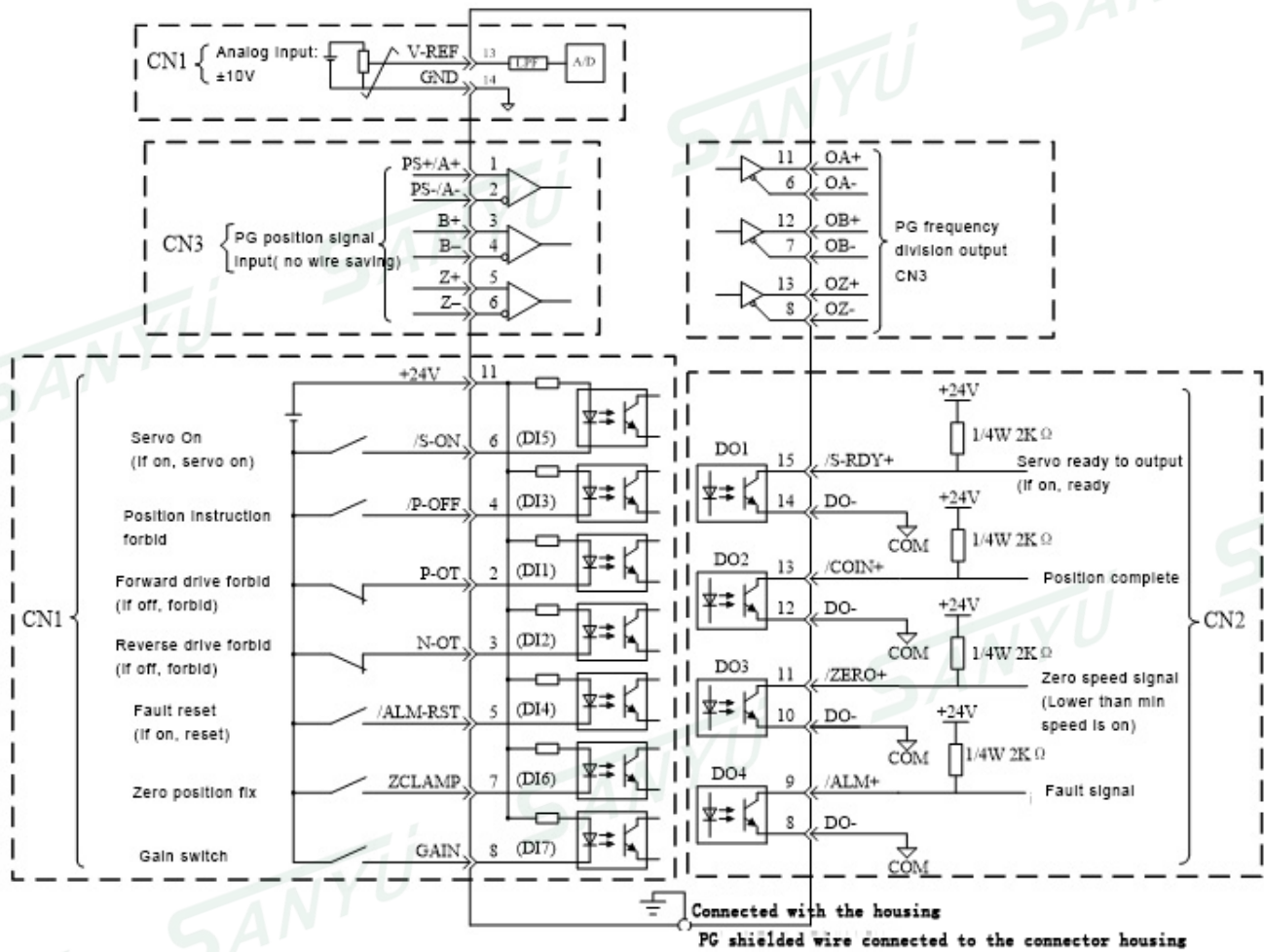
The shafts of motor and encoder are coupled, please don't strike it when install belt wheel or connecting shaft at motor shaft. Otherwise, the encoder will be damaged.

2.2 Standard wiring for different control mode

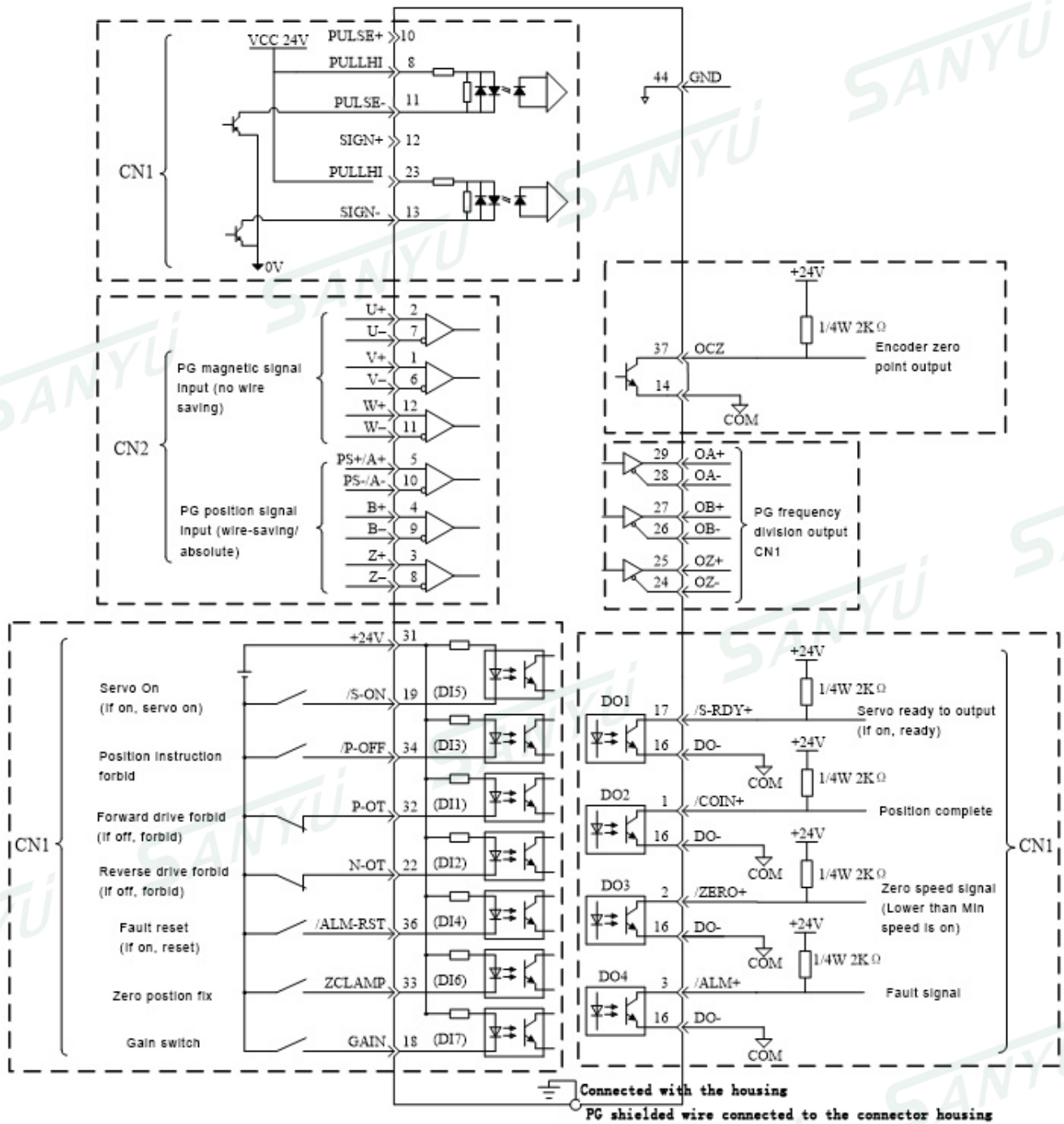
2.2.1 Speed Control Mode (200W-3kW)



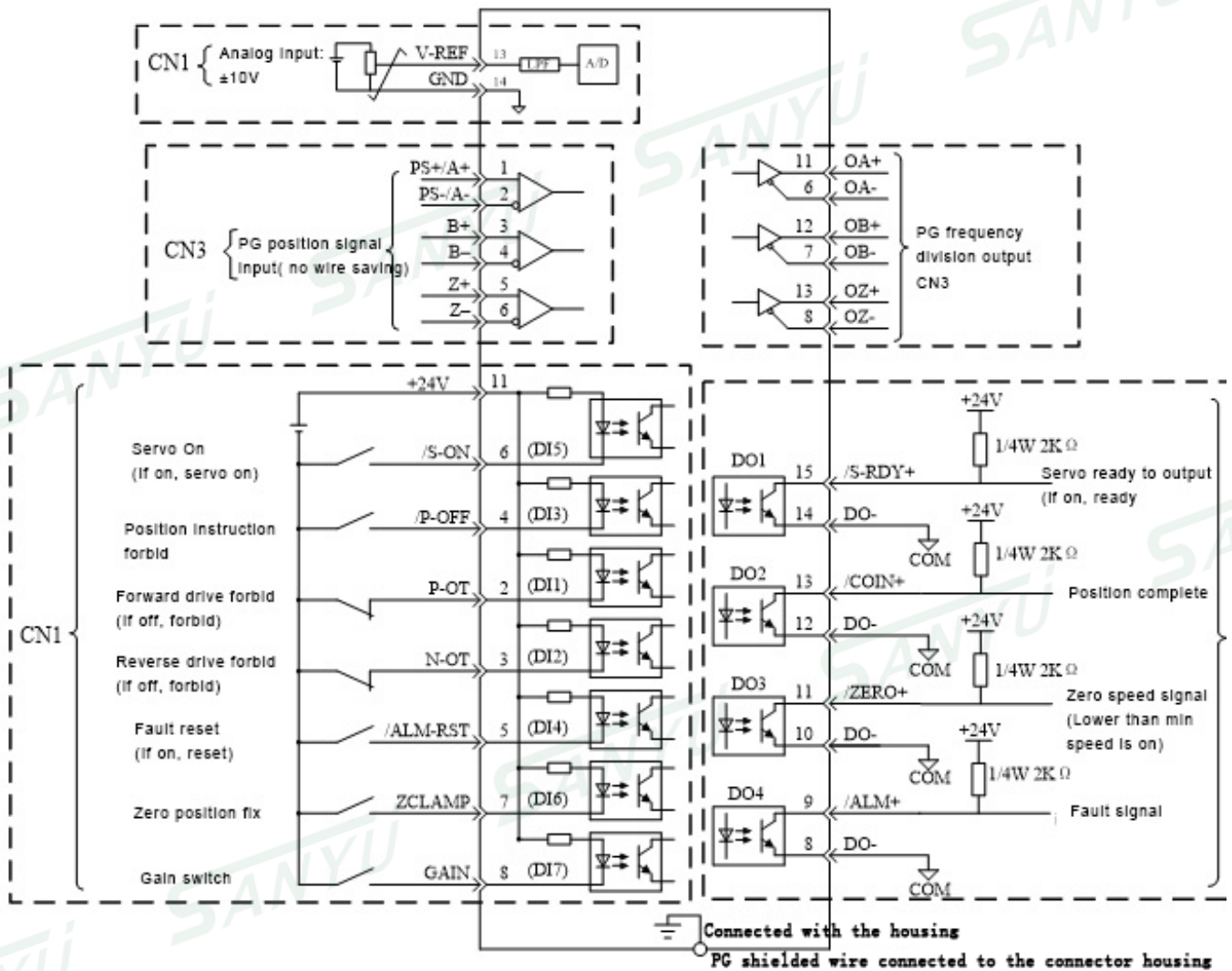
2.2.2 Speed Control Mode (4.5kW-18.5kW)



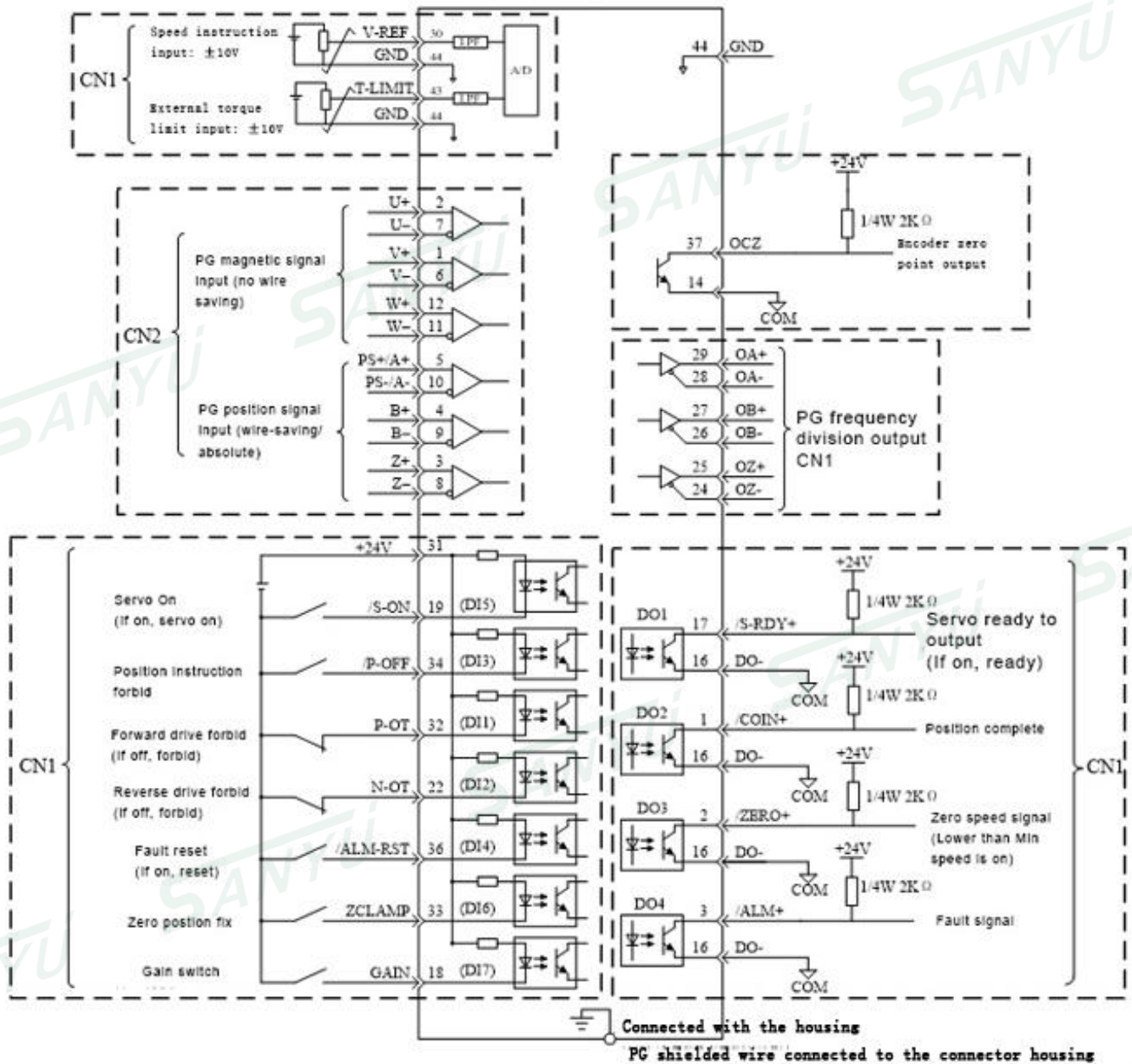
2.2.3 Position Control Mode(200W-3kW)



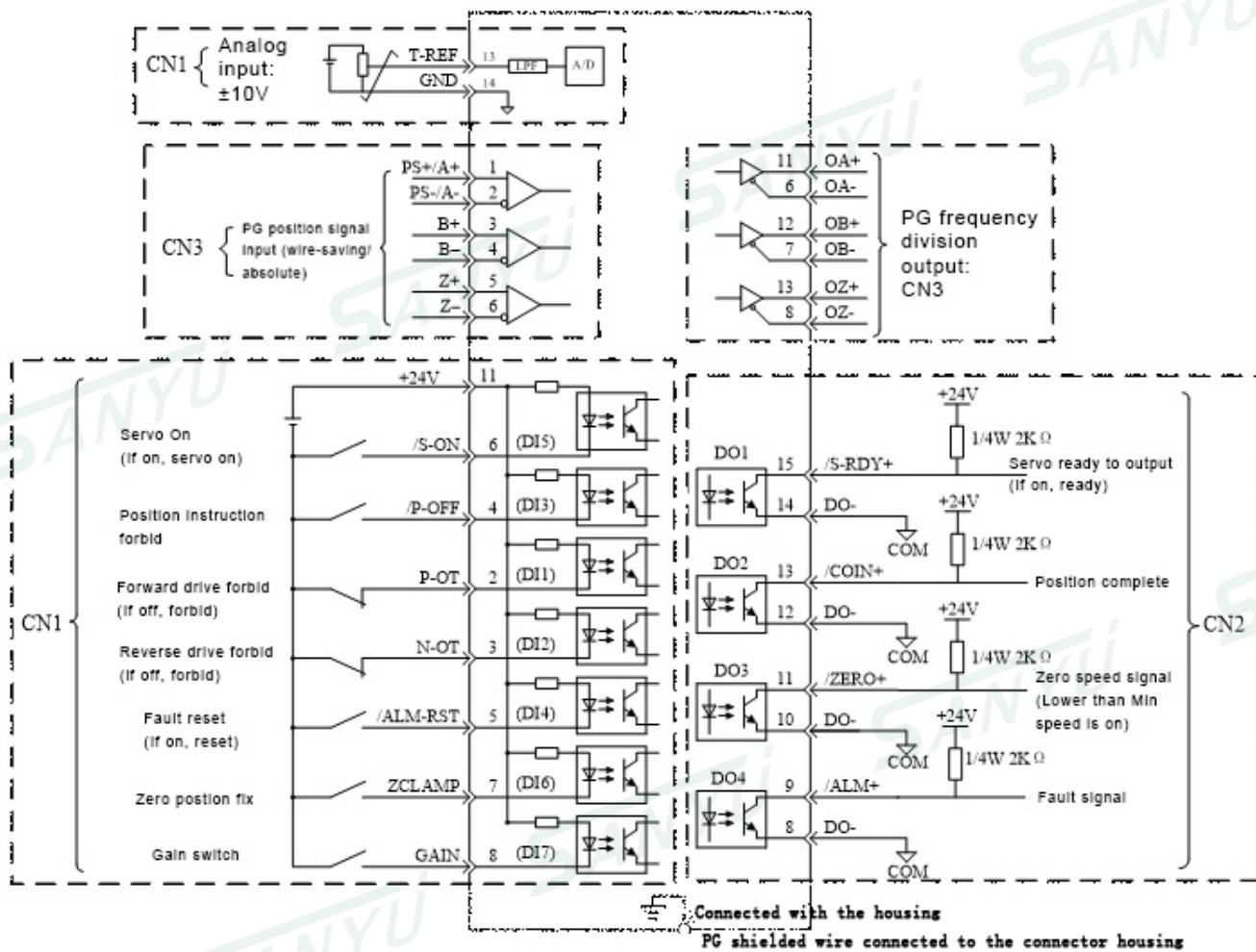
2.2.4 Position Control Mode(4.5kW-18.5kW)



2.2.5 Torque control mode (200W-3kW)



2.2.6 Torque control mode (4.5kW-18.5kW)



2.3 Wiring port definition (200W-3kW)

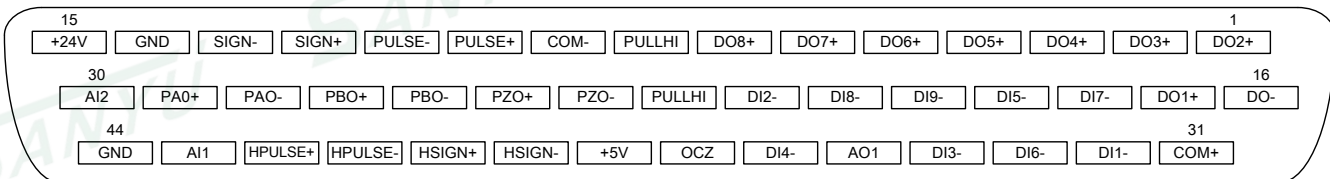
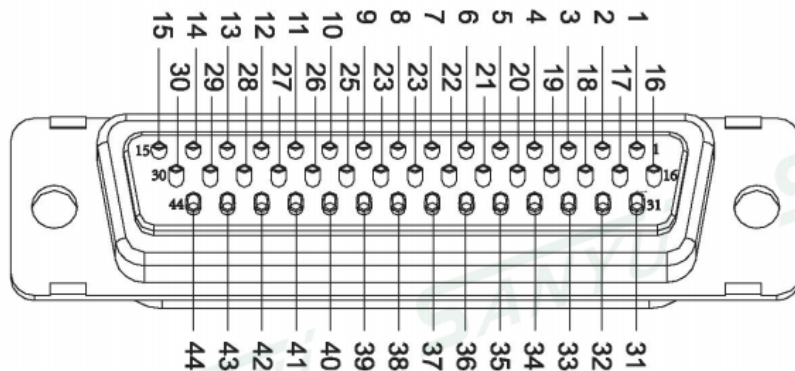
2.3.1 Strong power terminals instructions

Terminal	Signal Name	Function
L1	The main circuit power input single phase or three phase interface terminal	187V - 242V(-15%~10%) 50/60Hz The maximum inrush current is 20A.
L2		
L3		
U	Servo motor connection terminal	Connect Correspondingly to servo motor's U、V、W
V		
W		
L1C	Control circuit power input terminal	Single phase AC200V ~ 230V (-15 ~ +10%) 50Hz/60Hz
L2C		
B	External regenerate resistor connection terminal	Servo built-in regenerative resistor under factory setting, B-P is disconnected. If regenerative power is insufficient connect an external braking resistor between B-P.
P		

2.3.2 Input and output signal connector (CN1) terminal definition

Pin number of interface terminal	Signal name	Function Description	Pin number of interface terminal	Signal name	Function Description
1	DO2+	Digital signal 2 output +	2	DO3+	Digital signal 3 output +
3	DO4+	Digital signal 4 output +	4	DO5+	Digital signal 5 output +
5	DO6+	Digital signal 6 output +	6	DO7+	Digital signal 7 output +
7	DO8+	Digital signal 8 output +	8	PULLHI	Instruction pulse outside source's input interface
9	COM-	Interior 24V power gnd	10	Pulse +	Instruction pulse input +
11	Pulse -	Instruction pulse input -	12	Sign +	Instruction symbol input +
13	Sign -	Instruction symbol input -	14	GND	Command ground
15	+24V	Interior 24V power positive	16	DO-	Digital signal output -
17	DO1+	Digital signal 1 output +	18	DI7-	Digital signal 7 input -
19	DI5-	Digital signal 5 input -	20	DI9 -	Digital signal 9 input -
21	DI8 -	Digital signal 8 input -	22	DI2 -	Digital signal 2 input -
23	PULLHI	External power input for instruction pulse	24	PZO-	PG frequency division output Z signal-
25	PZO+	PG frequency division output Z signal +	26	PBO-	PG frequency division output B signal -
27	PBO+	PG frequency division output B signal +	28	PAO-	PG frequency division output A signal -
29	PAO+	PG frequency division output A signal+	30	AI2	Analog 2 input
31	COM +	External 24V power	32	DI1 -	Digital signal 1 input -
33	DI6 -	Digital signal 6 input -	34	DI3 -	Digital signal 3 input -
35	AO1	Analog output 1	36	DI4 -	Digital signal 4 input -
37	OCZ	Encoder zero point output	38	+5V	5V power +
39	HSIGH -	High speed pulse instruction symbol input -	40	HSIGH +	High speed pulse instruction symbol input +
41	HPULSE-	High speed pulse instruction input-	42	HPULSE+	High speed pulse instruction input+
43	AI1	Analog 1 input	44	GND	Common ground

(Note)Please make input and output signals connect to the connector with cable shielding, servo unit side connects to the FG(frame ground).

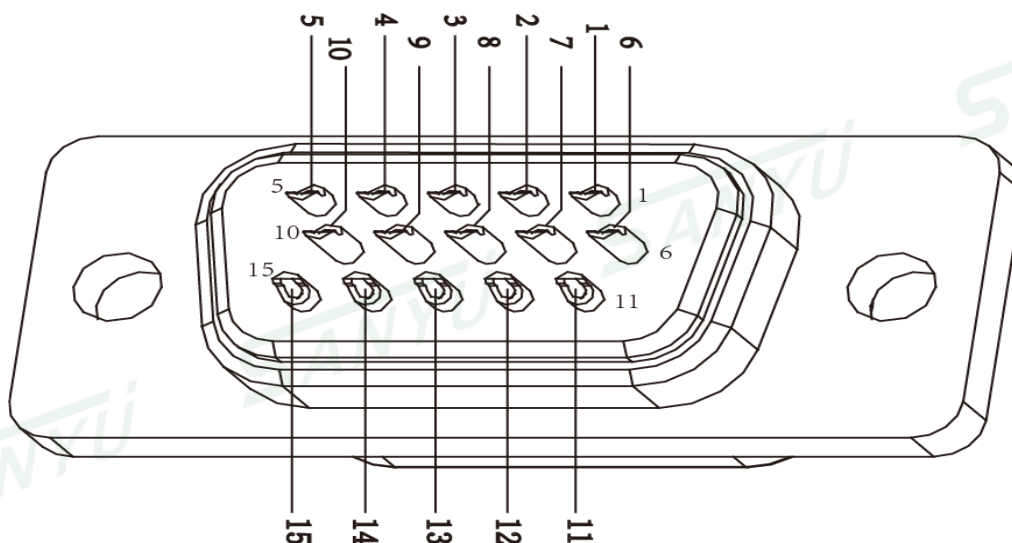


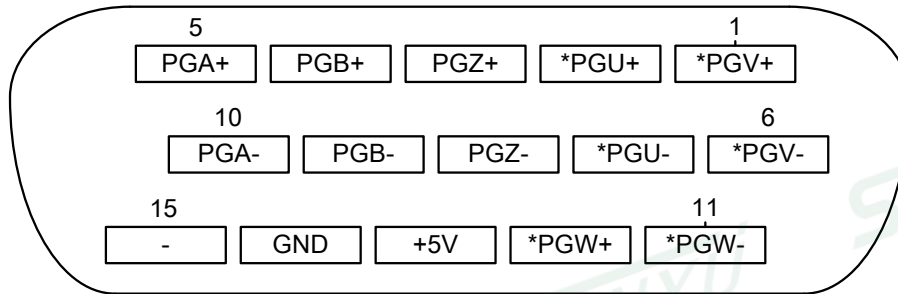
2.3.3 Encoder signal connection (CN2) terminal definition.

2.3.3.1 Incremental encoder interface definition:

Pin number of interface terminal	Signal name	Function description	Pin number of interface terminal	Signal name	Function description
1	*PGV+	Magnetic signal V signal +	2	*PGU+	Magnetic signal U signal +
3	PGZ+	Differential signal Z signal +	4	PGB +	Differential signal B signal +
5	PGA+	Differential signal A signal +	6	*PGV-	Magnetic signal V signal -
7	*PGU-	Magnetic signal U signal-	8	PGZ -	Differential signal Z signal -
9	PGB-	Differential signal B signal -	10	PGA -	Differential signal A signal -
11	*PGW-	Magnetic signal W signal -	12	*PGW+	Magnetic signal W signal+
13	+5V	5V power +	14	GND	Common ground
15					

Note: Please connect the shielded wire to the DB15 metal shell, The magnetic pole signal is floating when connected to the wire-saving encoder

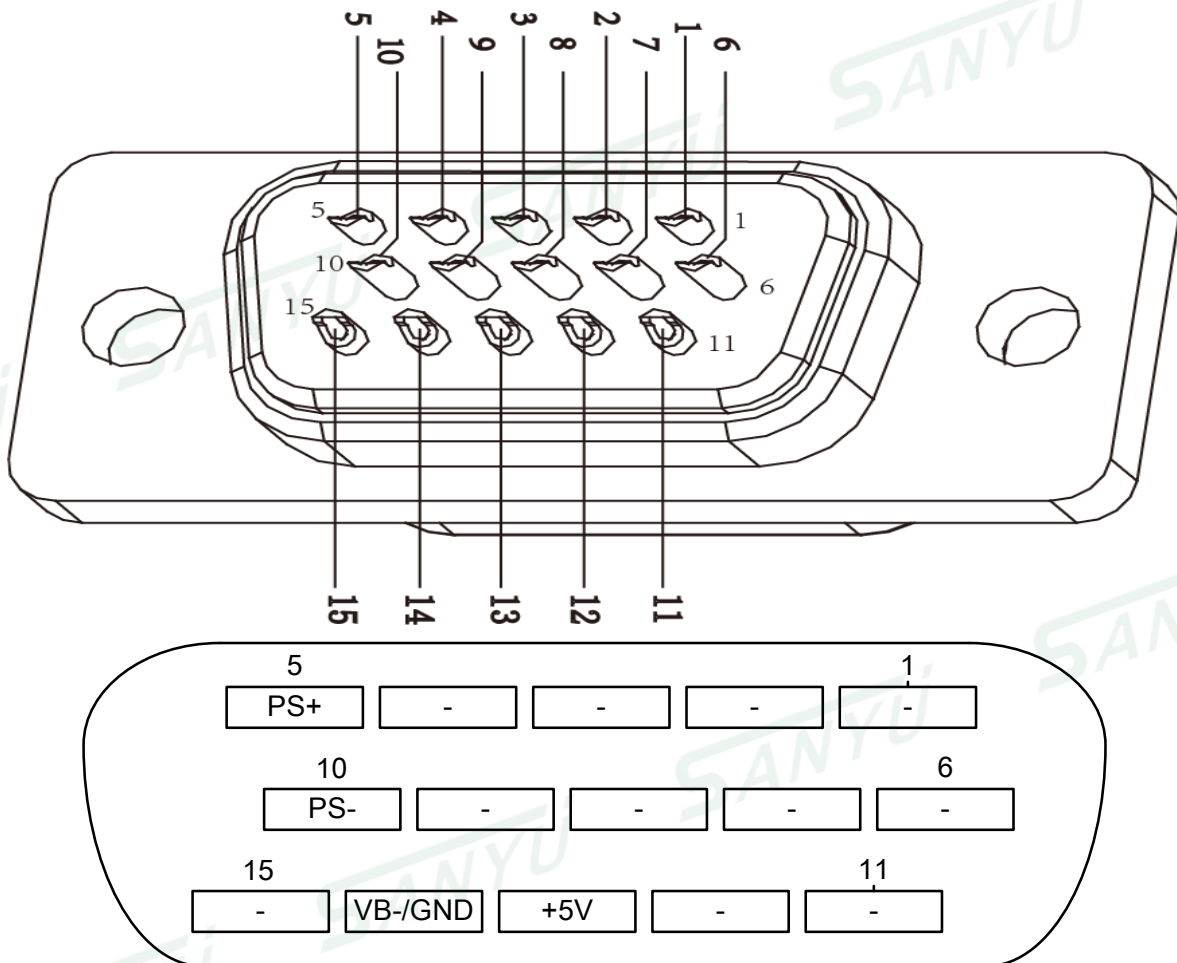




2.3.3.2 Bus-type encoder interface definition:

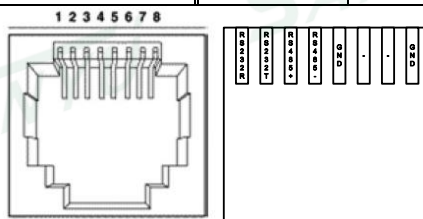
Pin number of interface terminal	Signal name	Function description	Pin number of interface terminal	Signal name	Function description
1			2		
3			4		
5	PS +	Bus differential signal input +	6		
7			8		
9	VB+	Battery +	10	PS-	Bus differential signal input-
11			12		
13	+ 5V	5V power	14	GND/VB-	Common ground/Battery-
15					

Note: Please connect the shielded wire to the DB15 metal shell



2.3.4 Communication signal connector (CN3) terminal definitions

Pin number of interface terminal	Signal name	Function Description	Pin number of interface terminal	Signal name	Function Description
1	RS232R	RS232 receiving line	2	RS232T	RS232 output line
3	RS485+	RS485+ insert	4	RS485-	RS485- insert
5	GND	Ground	6	NC	-
7	NC	-	8	GND	Ground



2.4 Connector interface (4.5kW-18.5kW)

2.4.1 Strong power terminals instructions.

Terminal symbol	Signal Name	Function
R	The main circuit power input single-phase or three-phase interface terminal	323-418V (-15%~10%) 50/60Hz The maximum inrush current is 20A
S		
T		
U	Servo motor connection terminals	Connect correspondingly to servo motor's U,V,W
V		
W		
-	Bus voltage -	
PB	External regenerative resistor connection terminals	Connect an external regenerative resistor;
+		

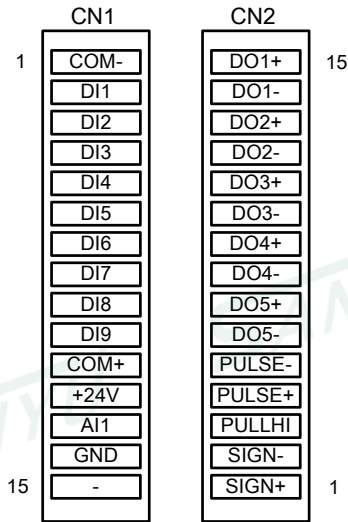
2.4.2 Input and output signal connection (CN1,CN2,CN5) terminal definition

1)CN1

Pin number of interface terminal	Signal name	Function description	Pin number of interface terminal	Signal name	Function description
1	COM-	Interior 24V power GND	2	DI1	Digital signal 1 input
3	DI2	Digital signal 2 input	4	DI3	Digital signal 3 input
5	DI4	Digital signal 4 input	6	DI5	Digital signal 5 input
7	DI6	Digital signal 6 input	8	DI7	Digital signal 7 input
9	DI8	Digital signal 8 input	10	DI9	Digital signal 9 input
11	COM+	Outside 24V power	12	24V+	Interior 24V power positive
13	AI1	Analog 1 input	14	GND	GND
15					

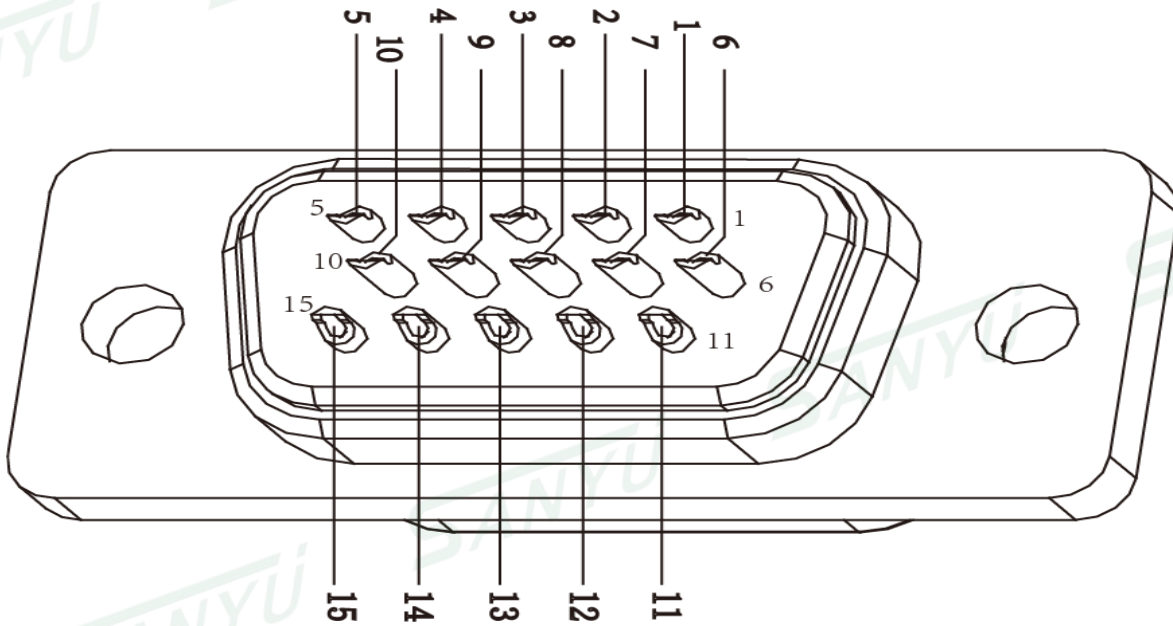
2) CN2

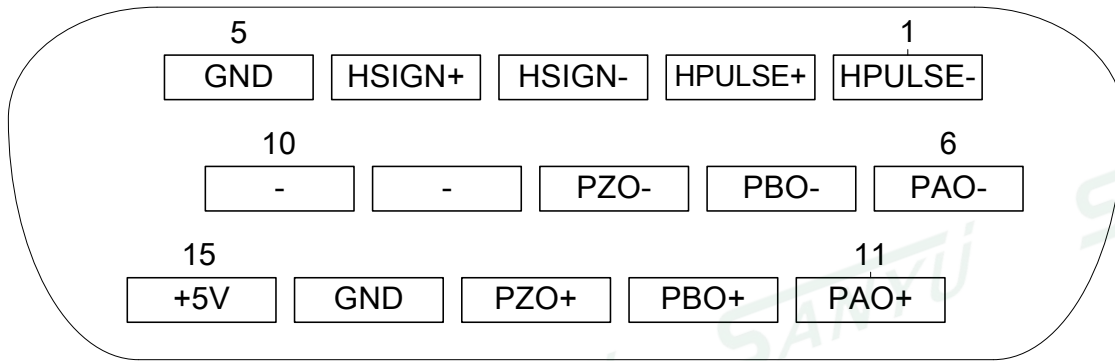
Pin number of interface terminal	Signal name	Function description	Pin number of interface terminal	Signal name	Function description
1	SIGN+	Instruction symbol input+	2	SIGN-	Instruction symbol input-
3	PULLHI	Instruction pulse outside source's input interface	4	PULSE+	Instruction pulse input+
5	PULSE-	Instruction pulse input-	6	DO5-	Digital signal 5 output-
7	DO5+	Digital signal 5 output+	8	DO4-	Digital signal 4 output-
9	DO4+	Digital signal 4 output+	10	DO3-	Digital signal 3 output-
11	DO3+	Digital signal 3 output+	12	DO2-	Digital signal 2 output-
13	DO2+	Digital signal 2 output+	14	DO1-	Digital signal 1 output-
15	DO1+	Digital signal 1 output+			



3) CN5

Pin number of interface terminal	Signal name	Function description	Pin number of interface terminal	Signal name	Function description
1	HPULSE-	High speed pulse instruction input -	2	HPULSE+	High speed pulse instruction input +
3	HSIGN-	High speed pulse instruction symbol input-	4	HSIGN+	High speed pulse instruction symbol input+
5	GND	GND	6	PAO-	PG frequency division output A signal-
7	PBO-	PG frequency division output B signal-	8	PZO-	PG frequency division output Z signal-
9	NC	Not connected	10	NC	Not connected
11	PAO+	PG frequency division output A signal+	12	PBO+	PG frequency division output B signal-
13	PZO+	PG frequency division output Z signal +	14	GND	GND
15	+5V	5V power +			

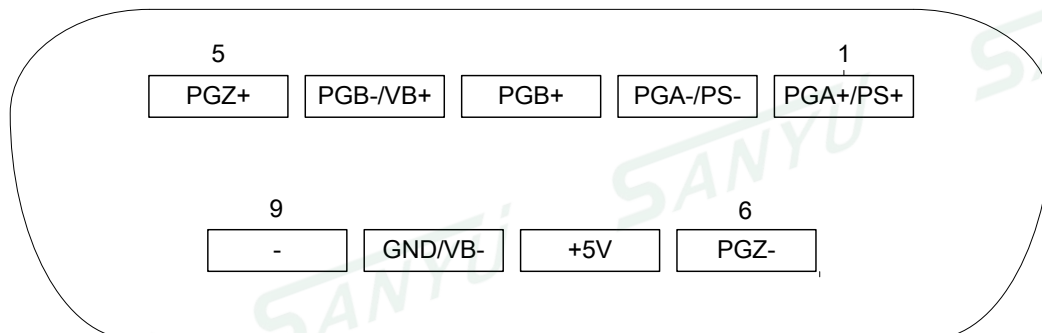
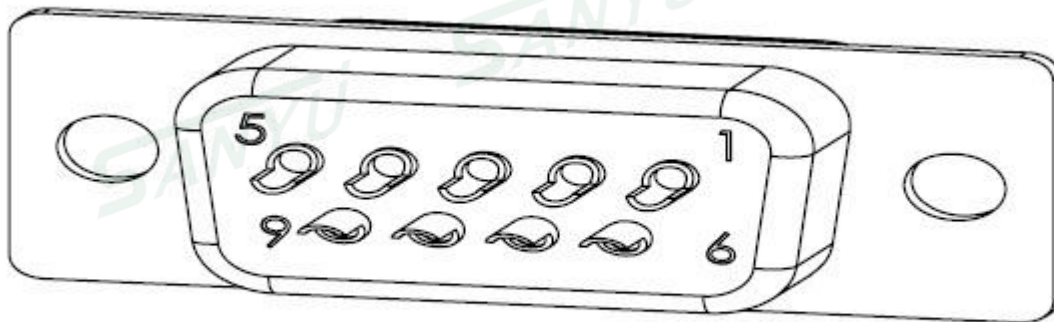




2.4.3 Encoder signal connection (CN3) terminal definition

Pin number of interface terminal	Signal name	Function description	Pin number of interface terminal	Signal name	Function description
1	PGA+/PS+	Differential signal A signal +/Bus differential signal input +	2	PGA-/PS-	Differential signal A signal -/Bus differential signal input -
3	PGB+	Differential signal B signal +	4	PGB-	Differential signal B signal -
5	PGZ+	Differential signal Z signal +	6	PGZ-	Differential signal Z signal -
7	+5V	5V power+	8	GND	GND
9	PE	Shield wire ground			

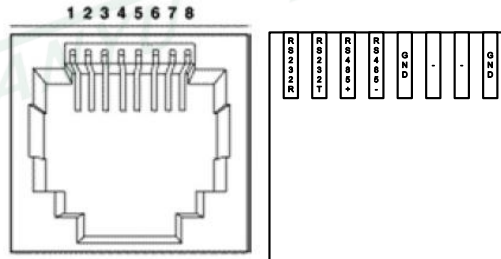
Note: Please connect the shielded wire to the DB9 metal shell



2.4.4 Communication signal connection (CN6, CN7) terminal definitions

Pin number of interface terminal	Signal name	Function description	Pin number of interface terminal	Signal name	Function description
1	RS232R	RS232 receiving line	2	RS232T	RS232 output line
3	RS485+	RS485+ insert	4	RS485-	RS485- insert
5	GND	Ground	6	CANH	CAN+ insert
7	CANL	CAN- insert	8	GND	Ground

Remark: the CN6 and CN7 are the same.



2.5 Connector port circuit

Servo unit's input output signal and the instruction controller's connection example is as follows.

2.5.1 Wiring diagram (200w-3kW)

(1) Instruction input circuit's port.

1. Analog input circuit

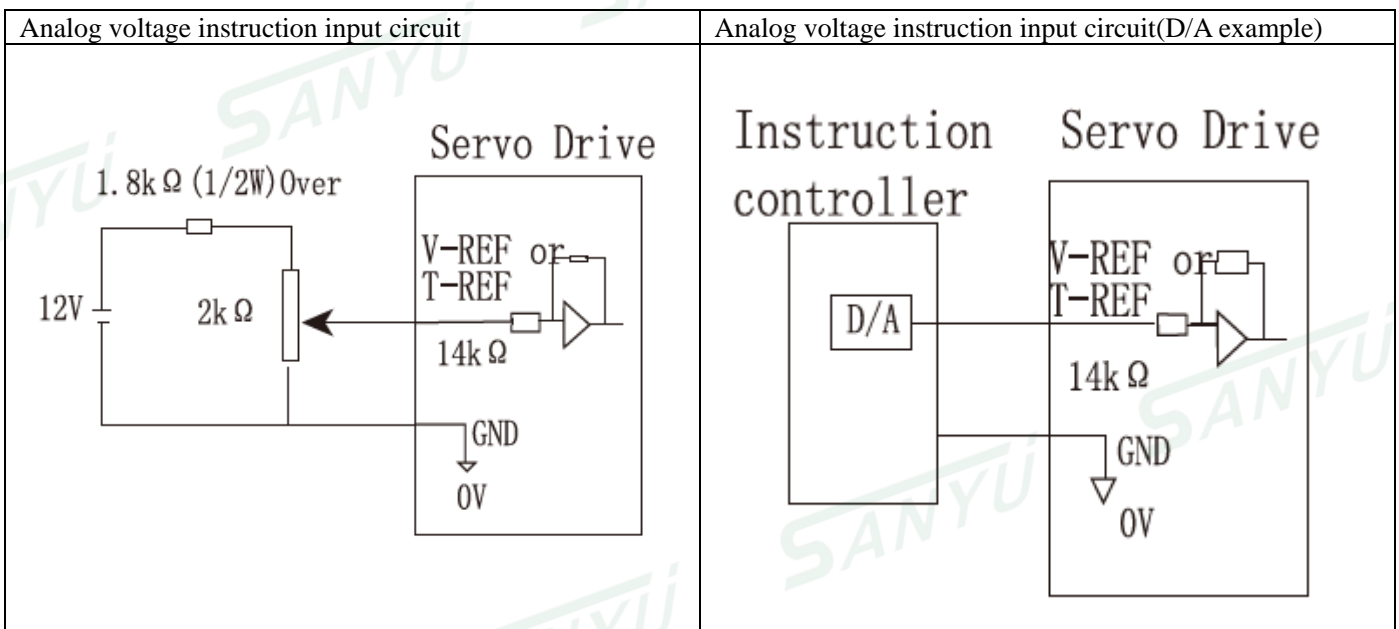
CN1 connector's 30-44 (the speed instruction input) 、 43-14 (the torque instruction input) terminal

Analog signal is the speed instruction or the torque instruction signal, the input impedance is as follows.

The speed instruction input: about 14kΩ

The torque instruction input: about 14kΩ

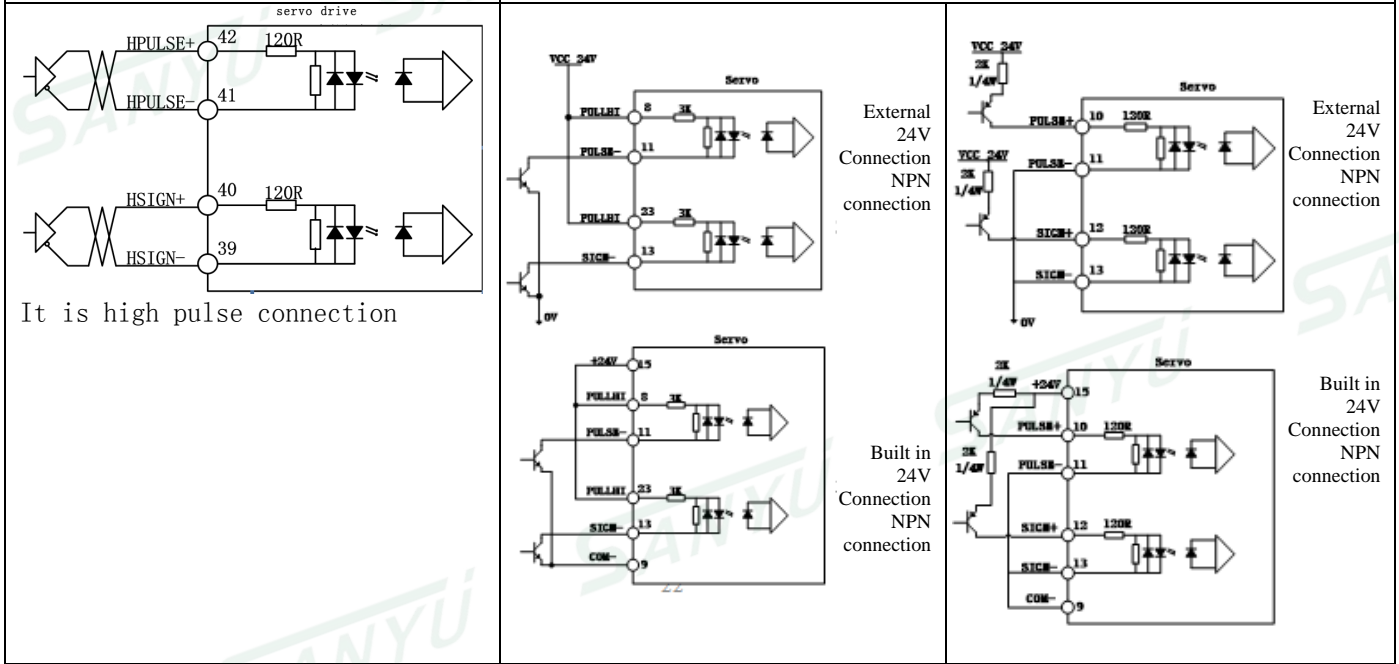
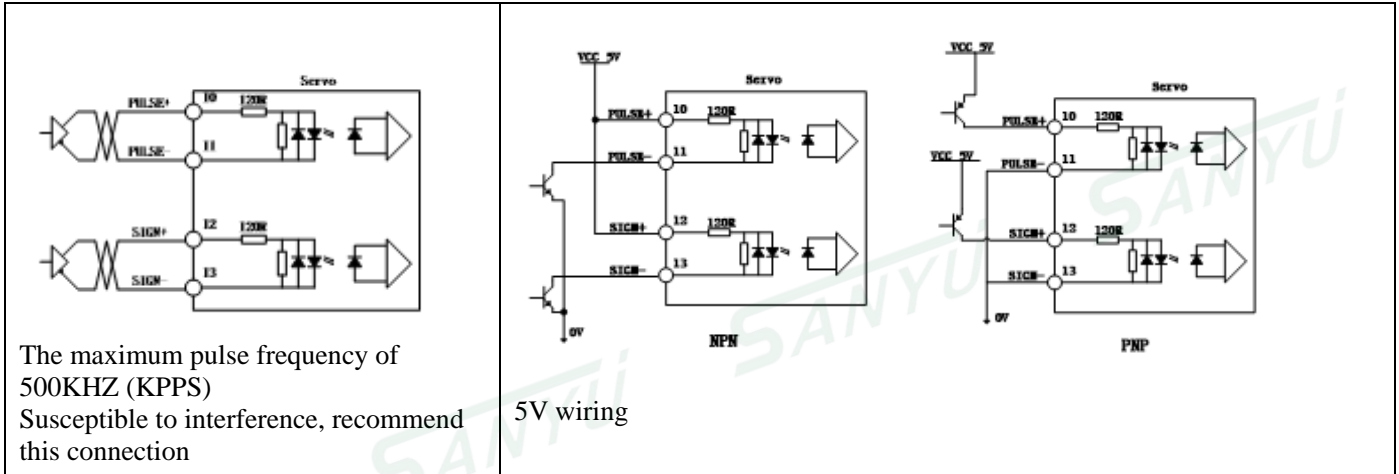
The input signal's maximum allowable voltage is 12V



2. Position instruction input circuit

Command controller side's command pulse, offset pulse cleared signal's output circuit, can output from the bus driver, open collector output (2 types). Classification is expressed as follows.

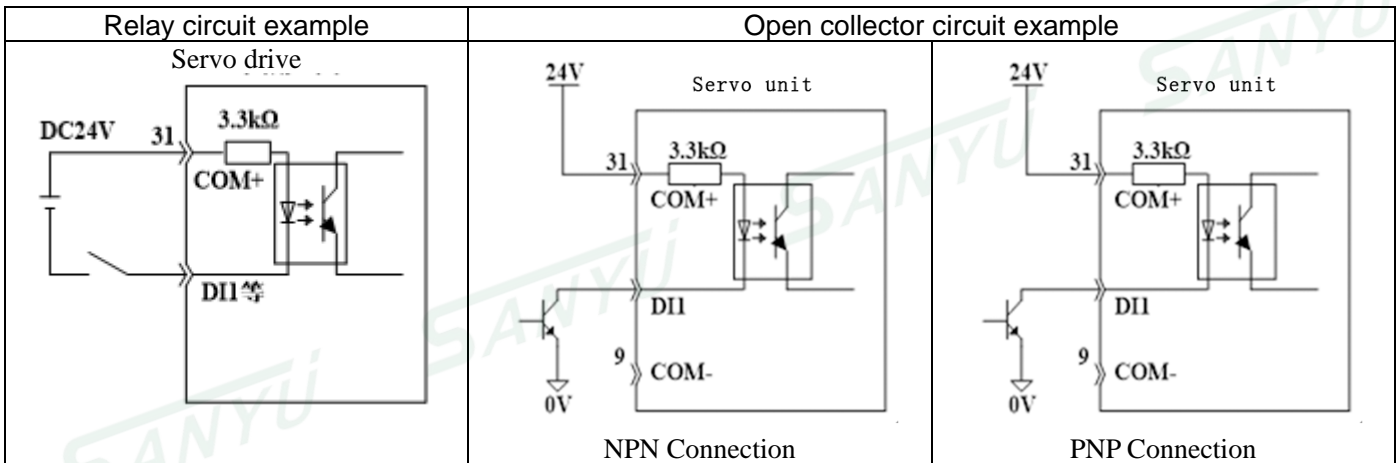
Position control differential drive	Position control single-end drive
-------------------------------------	-----------------------------------



(2)The control input circuit's port

Explain CN1 connector's 32、22、34、36、19、33、18 terminal.

Connected by a relay or open collector transistor circuit. The use of relay connection, select the micro current relay, if don't use the micro current reply, it will lead to poor contact.



(3)Output circuit's connection port

Servo unit's signal output circuit has the following 3 kinds.

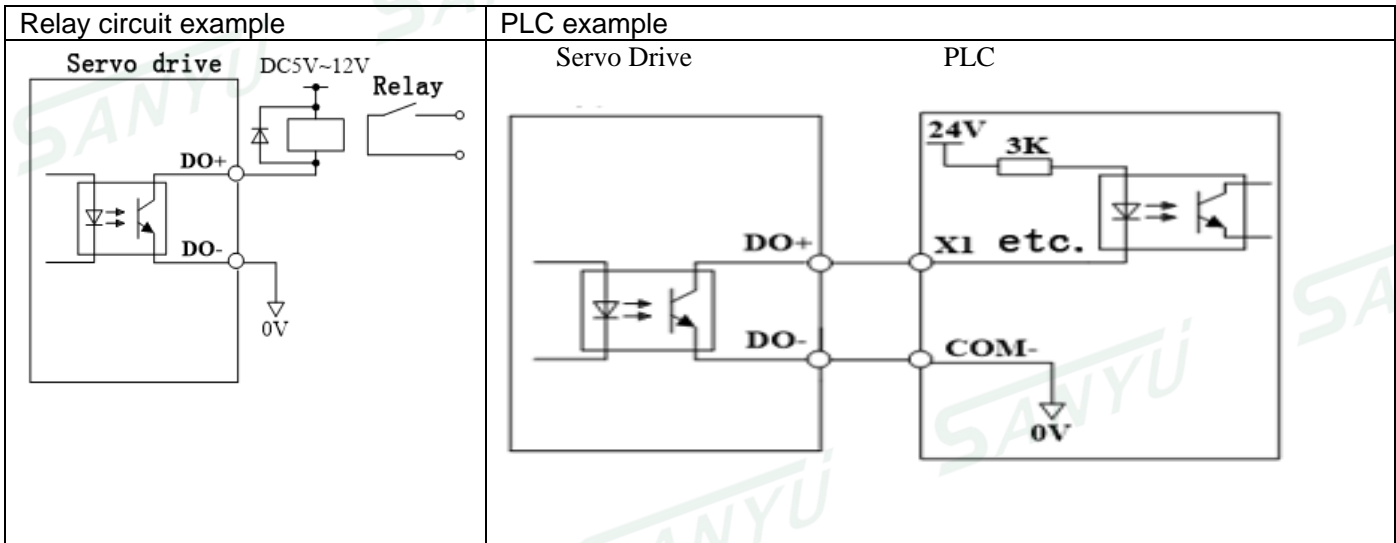
1. Differential driver output circuit

Following, to explain the CN1 connector's 29-28 (A phase signal)、27-26 (B phase signal) 、25-24 (Z phase signal)、25-24 (Z phase signal) signals.

Conduct 2 phase (A phase、B phase)transform output signal (OA+, OA-, OB+, OB-) for the encoder's serial data and the origin of the pulse signal(OZ+, OZ-)is output by the bus driver circuit. in general, use when the servo unit by speed control, constituting position control at the side of command controller. when at the side of command controller, please receive using the bus receiver circuit.

2. Photoelectric encoder's output circuit

Servo alarm(ALM)、 servo ready(/S-RDY)and other output signals related with the output circuit signal, and is connected by the relay or the PLC receiver.

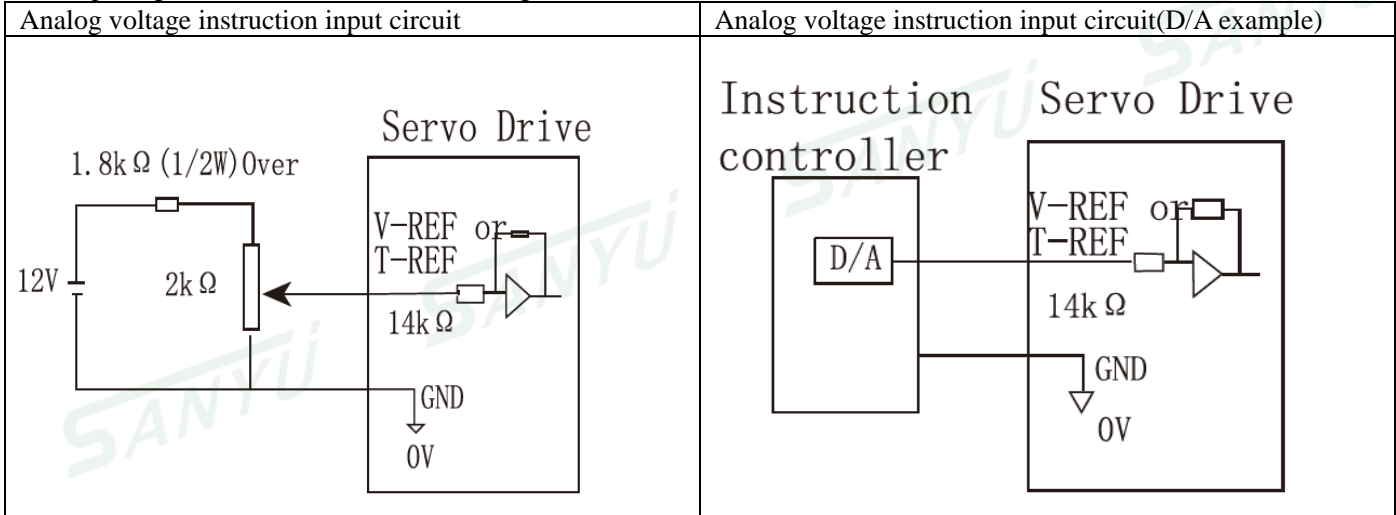


(NOTE) Photoelectric encoder's maximum allowable voltage current capacity is as follows.
 Maximum voltage: DC30V Maximum current: DC50mA

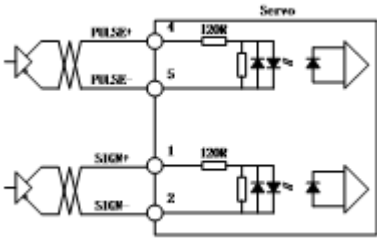
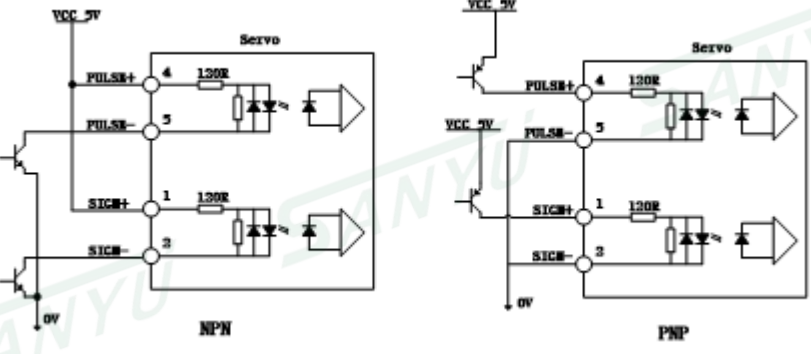
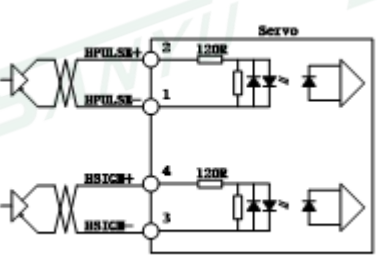
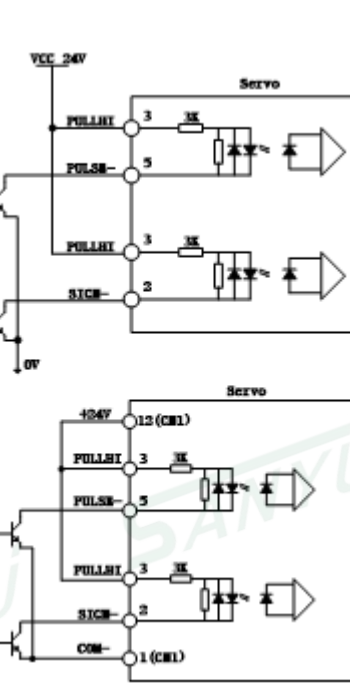
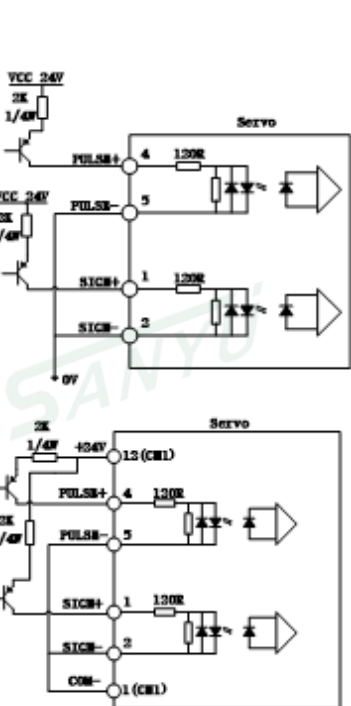
2.5.2 Wiring diagram(4.5kW-18.5kW)

1. Analog input circuit

CN1 connector's 13-14 (the speed instruction input) 、 15-14 (the torque instruction input) terminal
 Analog signal is the speed instruction or the torque instruction signal, the input impedance is as follows.
 The speed instruction input: about 14kΩ
 The torque instruction input: about 14kΩ
 The input signal's maximum allowable voltage is 12V



2.Position instruction input circuit

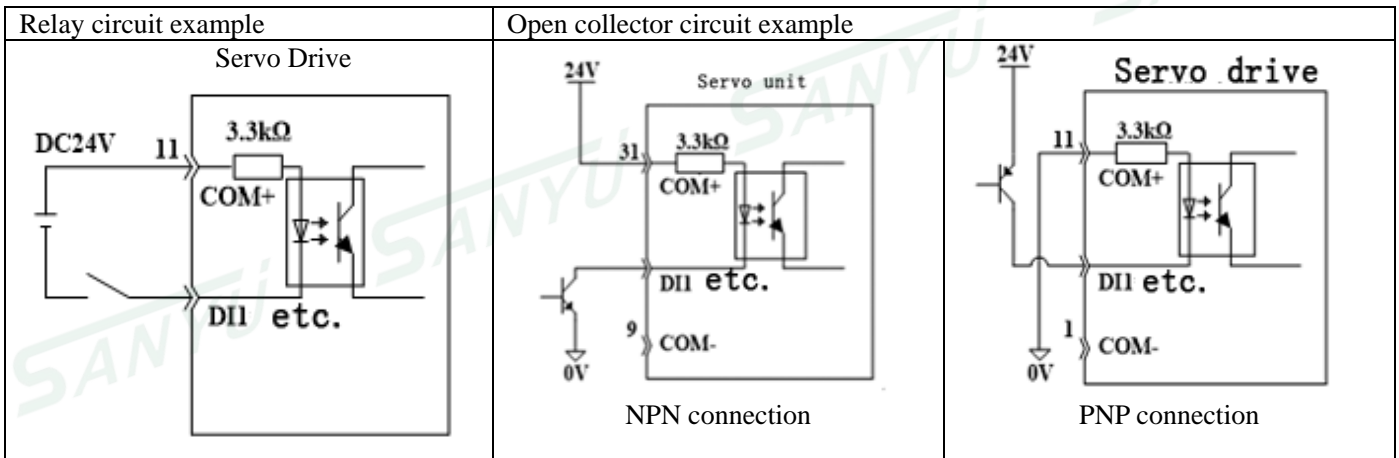
Position control differential drive	Position control single-end drive	
 <p>The maximum pulse frequency of 500KHZ (KPPS) Susceptible to interference, recommend this connection</p>	 <p>5V wiring</p>	
 <p>It is high speed pulse connection The connector is on CN5</p>	 <p>External 24V nnection NPN nnection</p> <p>Built in 24V nnection NPN nnection</p>	 <p>External 24V Connection NPN connection</p> <p>Built in 24V Connection NPN connection</p>

Command controller side's command pulse, offset pulse cleared signal's output circuit, can output from the bus driver, open collector output (2 types). Classification is expressed as follows.

(2) Control input circuit connector

Explain CN1 connector's 2、3、4、5、6、7、9、10 terminal.

Connected by a relay or open collector transistor circuit. The use of relay connection, select the micro current relay, if don't use the micro current reply, it will lead to poor contact.



(3) Output circuit connector

There are 3 types of output signal circuit:

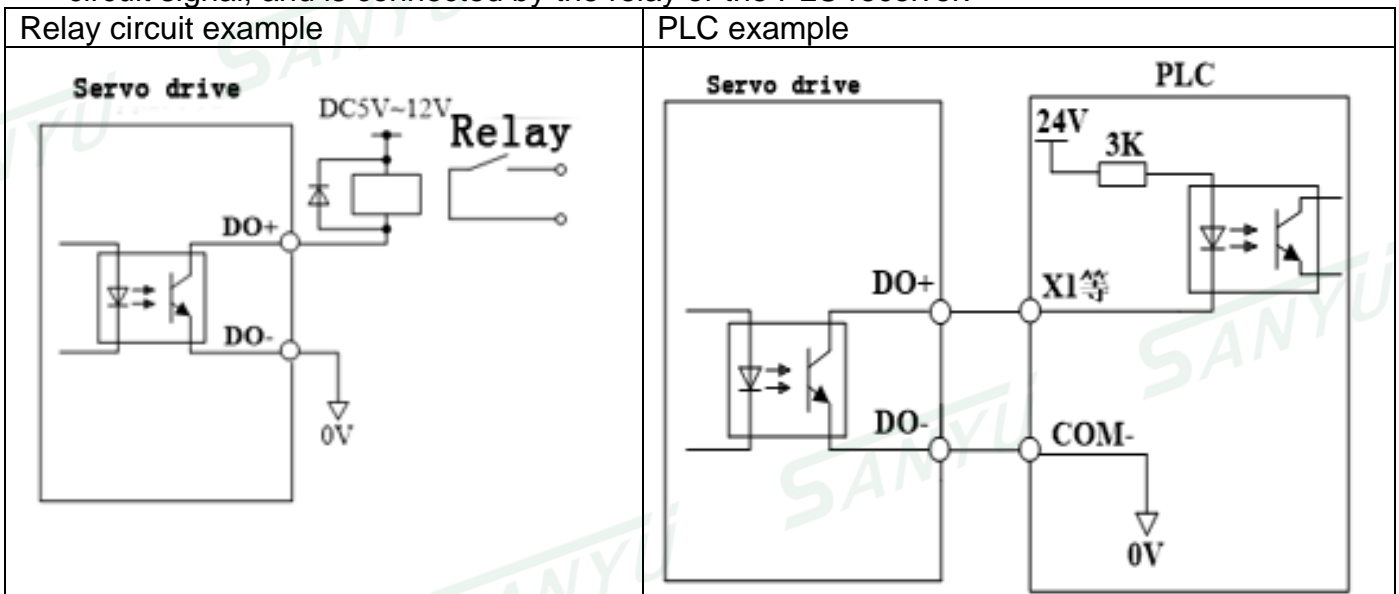
1. Differential driver output circuit

Following, to explain the CN1 connector's 11-6 (A phase signal)、12-7 (B phase signal)、13-8 (Z phase signal) signals.

Conduct 2 phase (A phase、B phase) transform output signal (OA+、OA-、OB+、OB-) for the encoder's serial data and the origin of the pulse signal (OZ+、OZ-) is output by the bus driver circuit. in general, use when the servo unit by speed control, constituting position control at the side of command controller. when at the side of command controller, please receive using the bus receiver circuit.

2. Photoelectric encoder's output circuit

Servo alarm (ALM)、servo ready (/S-RDY) and other output signals related with the output circuit signal, and is connected by the relay or the PLC receiver.



(NOTE) Photoelectric encoder's maximum allowable voltage、current capacity is as follows.

Maximum voltage: DC30V Maximum current: DC50mA

2.6 Introduction of external brake resistor

Model	Input current, voltage	Output current, voltage	Brake I _{max}	Built-in	External min	Resistance / power
SY200-40A-2	1PH 5.5A 220VAC	3PH 2.8A 0~200VAC	20A	90Ω/50W		
SY200-75A-2	1PH 10.9A 220VAC	3PH 5.5A 0~200VAC	20A	90Ω/50W		
SY200-100A-2	3PH 8.7A 220VAC	3PH 7.6A 0~200VAC	40A	30Ω/120W		
	1PH 15.1A 220VAC					
SY200-150A-2	3PH 11A 220VAC	3PH 9.6A 0~200VAC	40A	30Ω/120W		
	1PH 19.1A 220VAC					
SY200-200A-2	3PH 13.3A 220VAC	3PH 11.6A 0~200VAC	40A	30Ω/120W		
	1PH 23.1A 220VAC					
SY200-300A-2	3PH 17.2A 220VAC	3PH 15A 0~200VAC	25A		>25Ω	30Ω/300W
	1PH 28.2A 220VAC					
SY200-200A-4	3PH 6.9A 380VAC	3PH 6.0A 0~360VAC	15A		>50Ω	100Ω/300W
SY200-300A-4	3PH 10.3A 380VAC	3PH 9.0A 0~360VAC	15A		>50Ω	100Ω/300W
SY200-450A-4	3PH 14.8A 380VAC	3PH 12.9A 0~360VAC	25A		>30Ω	50Ω/500W
SY200-550A-4	3PH 18.9A 380VAC	3PH 16.5A 0~360VAC	25A		>30Ω	40Ω/600W
SY200-750A-4	3PH 29.5A 380VAC	3PH 25.7A 0~360VAC	50A		>15Ω	25Ω/1000W
SY200-11kA-4	3PH 37.8A 380VAC	3PH 33.0A 0~360VAC	50A		>15Ω	25Ω/1000W
SY200-15kA-4	3PH 51.7A 380VAC	3PH 45A 0~360VAC	100A		>10Ω	20Ω/1200W
SY200-18kA-4	3PH 57.5A 380VAC	3PH 50A 0~360VAC	100A		>10Ω	20Ω/1200W







Chapter 3 Panel Operator

3.1 Panel operator's functions

Panel operation can be used for various kinds of user parameters' setting, JOG running command's execution and status display.

3.1.1 Key's name and function

The following summarizes the names and the functions of each key.

Built-in panel operator	Functions
 MODE/SET (MODE/SET)	<ol style="list-style-type: none"> Used to switch the basic mode (status display mode, the auxiliary function mode, parameter setting mode, monitor mode). Used as digital setting key
 DATA/◀ (MODE/SHIFT)	For displaying each user parameter's setting and setting value
 ▲ (UP)	<ol style="list-style-type: none"> Pressing the UP key can increase the set value In JOG operation, used as a Forward start key
 ▲ (UP)	<ol style="list-style-type: none"> Pressing the DOWN key can decrease the set value In JOG operation, used as Reverse start key.
 DATA/◀ (MODE/SHIFT)	Press this button can move the selected bit(blinking) to the left a bit.
 MODE/SET (MODE/SET)	In JOG operation carried out by the operator, used for Servo ON/ Servo OFF.

3.2 Operation in the auxiliary function mode

3.2.1 Auxiliary function mode list

This part is using to explain the digital operator's operation of motor running and adjustment. The following shows the auxiliary function mode of the user parameter list and their functions.

Parameter group	Functions
Group P00	Servo driver parameters
Group P01	Servo basic control parameters
Group P02	Input terminal parameters
Group P03	Output terminal parameters
P04 group	Positioning control parameters
P05 group	Speed control parameters
P0group 6	Torque control parameters
Group P07	Gain setting parameters
Group P08	System parameters self-learning
Group P09	Default and protection parameters
Group P0A	MODBUS communication parameters
Group P0B	System state display
Group P0D	Servo auxiliary control parameters
Group P0E	Full closed loop control parameters
Group P10	Multistage position control parameters
Group P11	Multistage speed control parameters

3.2 Operation under user parameter setting mode

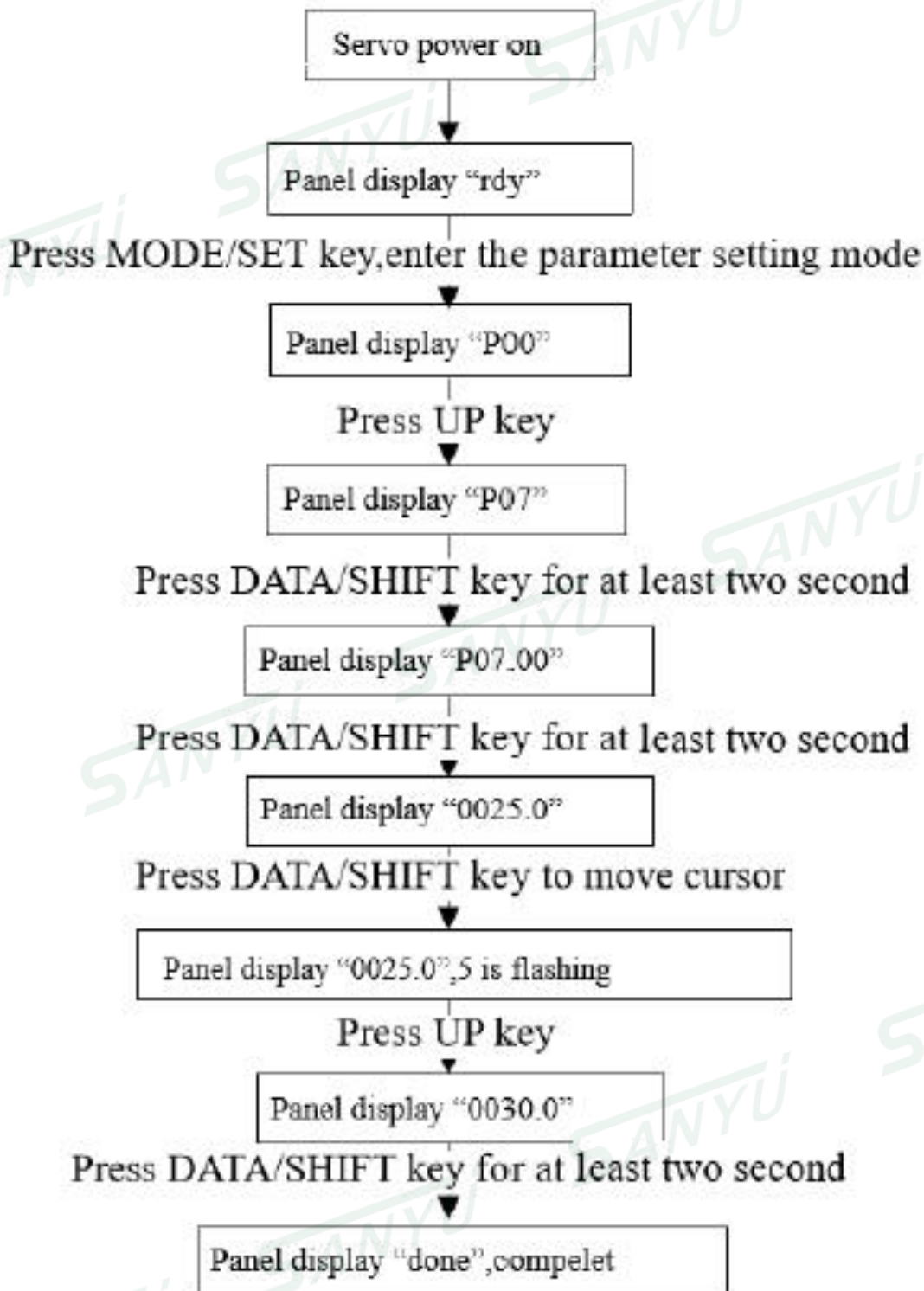
"Setting the user parameter can select or adjust functions, it include "parameters Setting" and "function

selection". User parameters setting is the function to adjust the parameters data within a certain range to change. Function selection is to choose the function of every digit that already assigned to the panel operator.

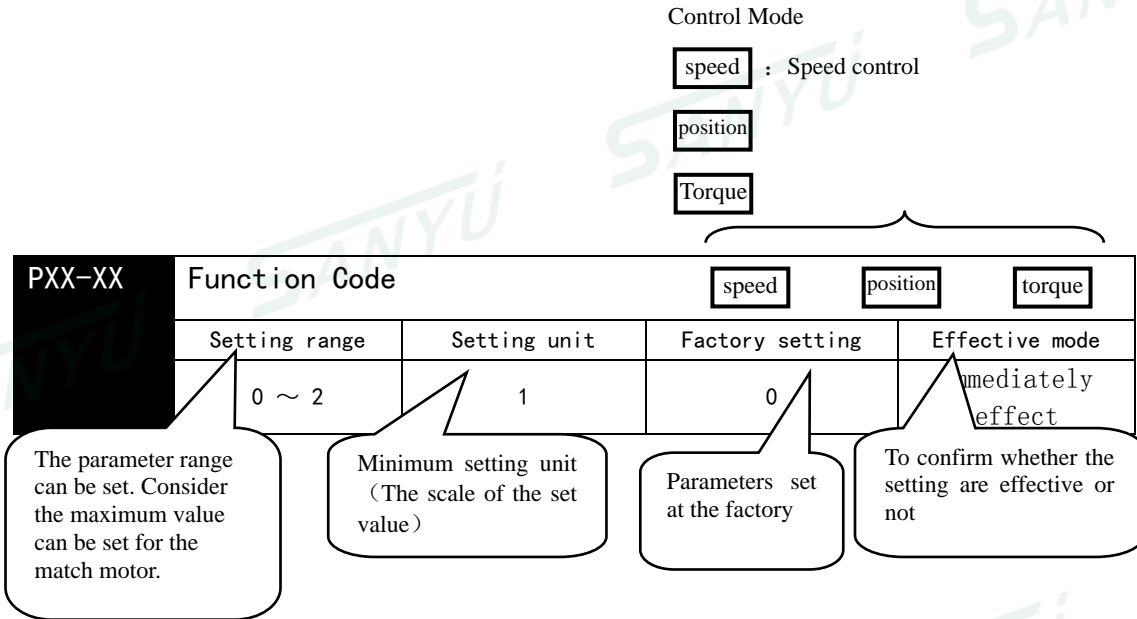
3.3 User parameter setting

(1) Parameter setting

(A) The following shows the operating steps of the user parameter P07-00's contents (speed loop gain) from "25.0" change to "30.0"



(B) This manual's user parameters representation
 This manual describes the user parameters by the following format.



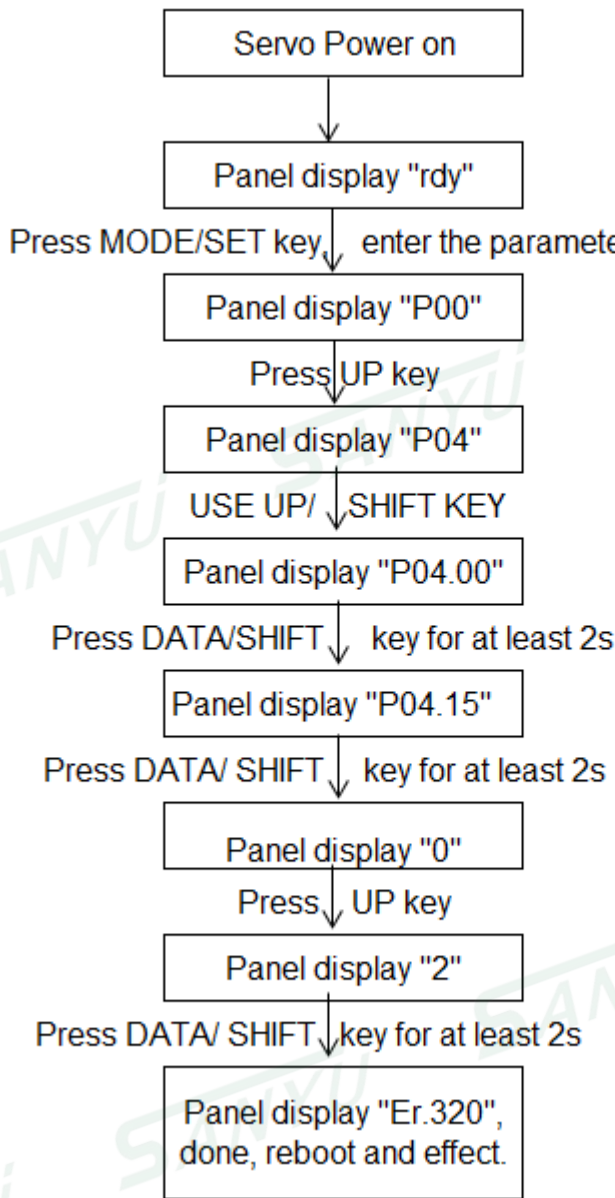
(2) Effective mode

(a) Effective mode description

Type	Control power restart
Power on next time	Yes
Immediately effect	No

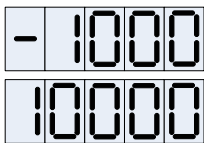
(b) Effective mode-Power on next time change step example

The following shows the pulse instruction form (P04-15) changes from 0-pulse + direction to 2-AB.



(c) User display mode of this manual

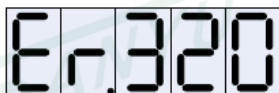
① 5 digits' tube single page display, under 4 digits' signed number and under 5 digits' unsigned number. The example shows the following:



② 5 Digits' tube single page can't display, above 4 digits' signed number and above 5 digits' unsigned number. The example shows the following:



③ Fault display

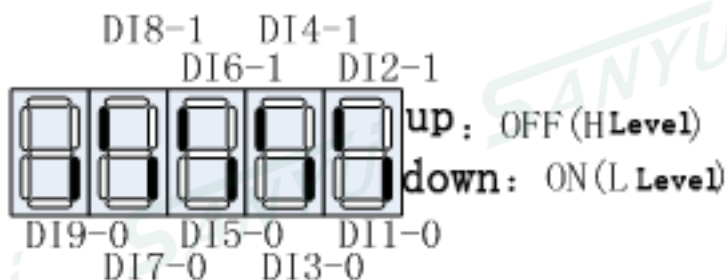


3.4 Operation in the monitoring mode

3.4.1 Monitoring mode display

((1)Display in the monitoring mode with input/output signal the example as follows

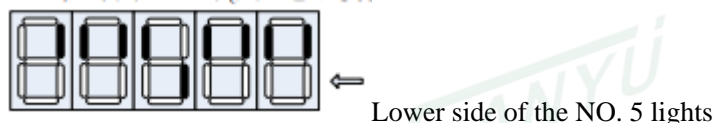
(a)The monitor display of input signal state Display the input status of input terminal's signal assigned. When the input is OFF (open state), the upper display segment (LED) lights. When the input is ON (short-circuit) state, the lower display segment (LED) lights



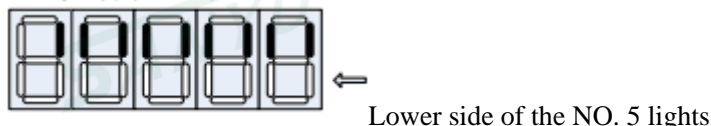
Please confirm the relationship between the input terminal and input signal.

Display LED number	Input terminal's name	The factory setting
1	CN1-32	P-OT
2	CN1-22	N-OT
3	CN1-34	/INHIBIT
4	CN1-36	/ALM-RST
5	CN1-19	/S-ON

./S-ON signal is ON(make servo on with L level)

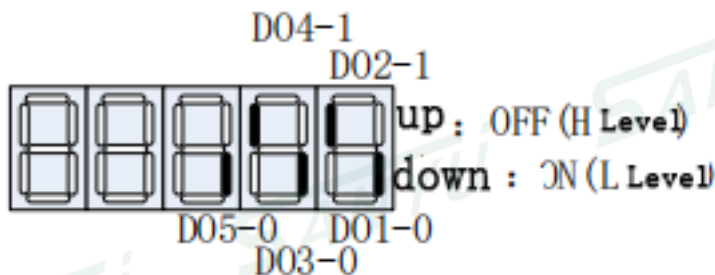


./S-ON signal is OFF



(b)Monitor display of the output signal state

Display the output status of input terminal's signal assigned. When the input is OFF (open state), the upper display segment (LED) lights. When the output is ON (short-circuit) state, the lower display segment (LED) lights.



Display LED number	Input terminal's name	The factory setting
1	CN1-17、16	/S-RDY
2	CN1-1、16	/COIN
3	CN1-2、16	/ZERO

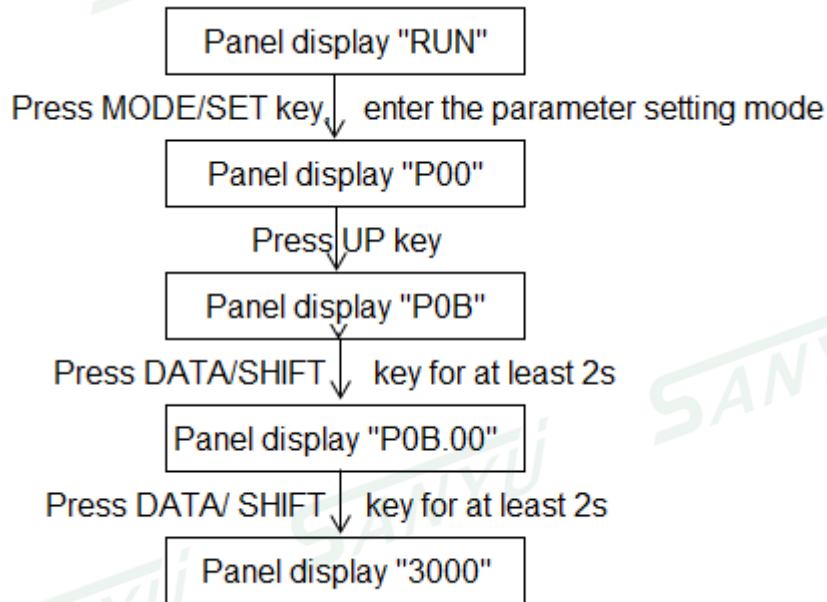
The monitoring display of the output signal is the same as the monitoring display of the input signal, as described above, are allocated on the panel display. Output signal ON / OFF to ON (L-level) on the lower side, OFF (H-level) on the side of the display section lights for display.

S-RDY signal action (alarm performed by the H-level)



Lower side of the NO. 1 lights

(2) Using methods in the monitoring mode The following shows display step of monitoring number P0B-00 data (Servo motor rotates at the speed of 3000min^{-1})



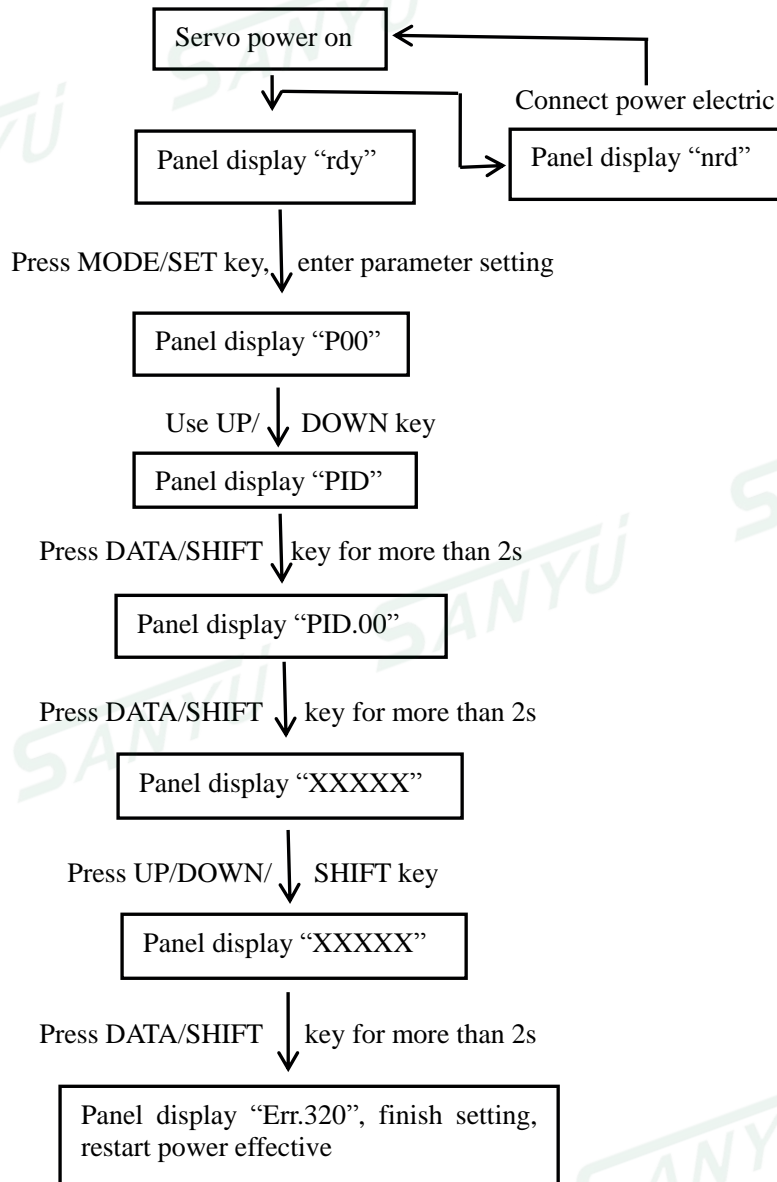
Chapter 4 Motor Self-learning

Tip: Before debug servo, we must ensure it don't keep running, if motor parameters are wrong, the motor will be burnout, after trial operation OK, then do other operation.

4.1 Motor angle self-learning

On display rdy state,first check motor type(P1D.00),see if it's right.If it's wrong,please set the correct motor type.After setting correct motor type,it will hint power loss restart fault(Er320),after restart, driver will set correct motor parameters by motor type.

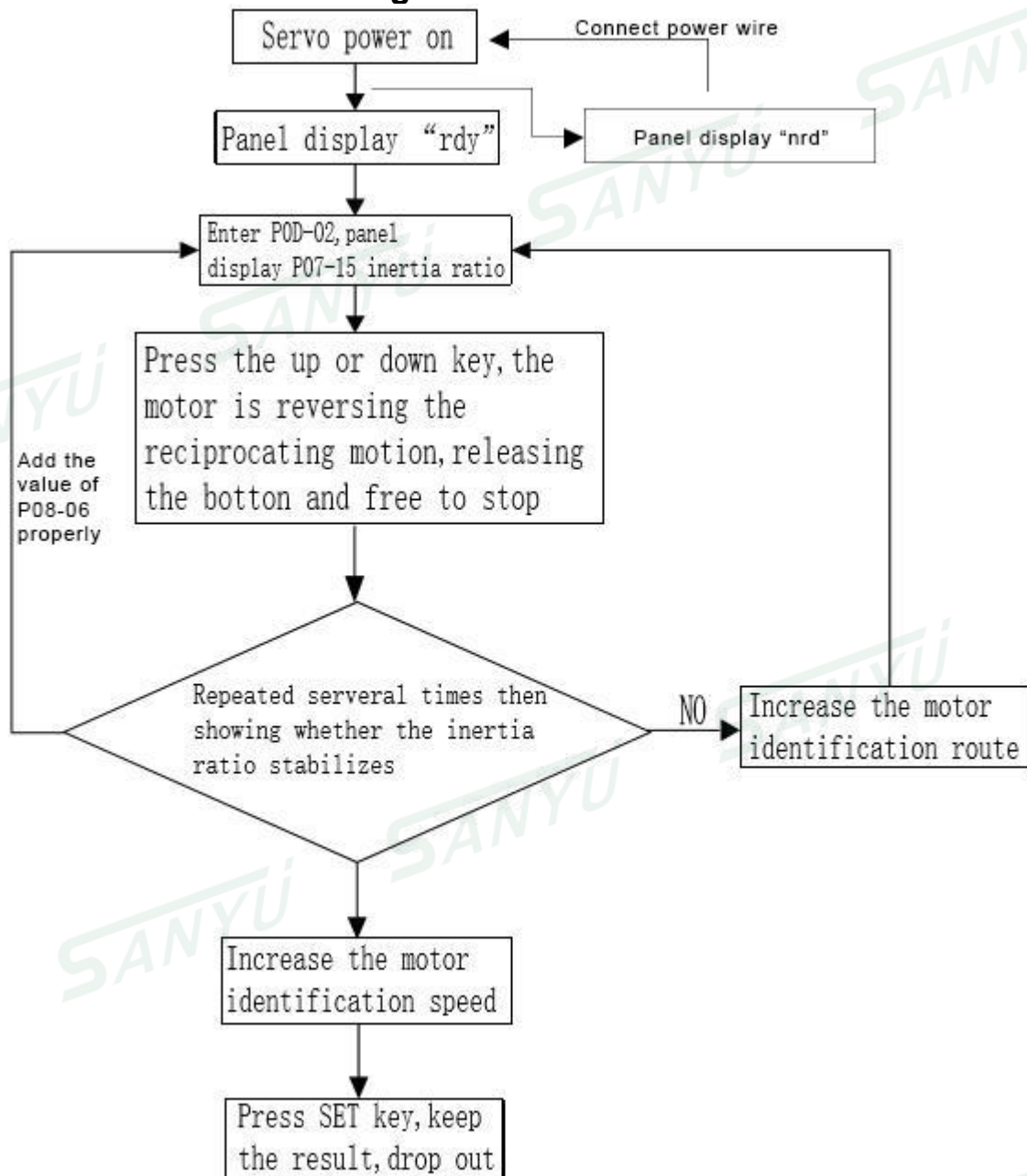
(1) Set motor parameters correctly



(2) Trial operation

Power on, trial operation, enter parameter P0D.11, set JOG trial operation speed, hold pressing DATE/SHIFT key, display -JOG, press UP/ DOWN key, if motor is running with setting speed, it's regular, then it can equip on the device. If it is unusual working, then solve the problem, while trial operate regular, then connect to the equipment.

4.2 Load inertia self-learning



Instruction:

*If on the default condition that P07-15=1, as inertia ratio is too small that cause the actual speed can't match the command, identify failure. This moment, we shall set a reasonable value to P07-15, preset value shall start at 5 times, gradually increasing to a appropriate value which can make identify successfully.

*Off-line inertia identify model, generally suggest to use triangle wave mode, if appear some occasion that identification is not good, then we can use step rectangular wave mode.

*When P08-05=1, we shall notice mechanical travel, prevent the accident may be caused by over range during Off-line inertia identification.

Chapter 5 Operation

5.1 Trail operation

5.1.1 Servo motor's trail operation

Make sure the power and the motor's main circuit cable, encoder cable is properly connected. Servo motor in the trial operation state can not smoothly rotate, many reasons are due to wiring errors. So please confirm again. After confirming the wiring is correct, make a trial operation for the servo motor in the order shown below.

Disconnect the servo motor and the mechanical connection part, only the servo motor is in a fixed state. To avoid unexpected accidents, in the present description, making the servo motor in the no-load state (state like coupling with the belt from the servo motor), conduct the servo motor's trial operation.

Joy (JOG) Mode operation (P0d-11):

Step	The display after operation	Built-in panel operator	Explanation
1			Press the MODE/SET key, to enter the auxiliary function mode
2			Press the UP or DOWN key. *Bits that can operate blink
3			Press the DATA /SHIFT button for 2 second or more, the display appears as shown on the left, enter the JOG running speed setting.
4			Press the DATA / SHIFT key to enter the servo ON (servo motor with power) state, enter JOG mode.
5			Press UP key (forward rotation) or DOWN key (reverse rotation). During the time of pressing the key, the servo motor rotates.
6			Press the MODE / SET key to exit JOG mode.

The direction of the servo motor's rotation depends on the "Selection of rotation direction" of the user parameters P01-09'. The factory setting of P01-09 is shown in the example above.

P05-04	Jog(JOG) speed			
	Setting range	Setting unit	Default	Power restart
	0~3000	1min-1	100	Don't need

The motor rotational speed instruction value of setting accessibility "jog (JOG) mode (POD-11)"

In the case of instruction controller that does not issue commands, servo motor can also be run with a digital operation. To perform jog(JOG)mode, you must meet the following conditions.

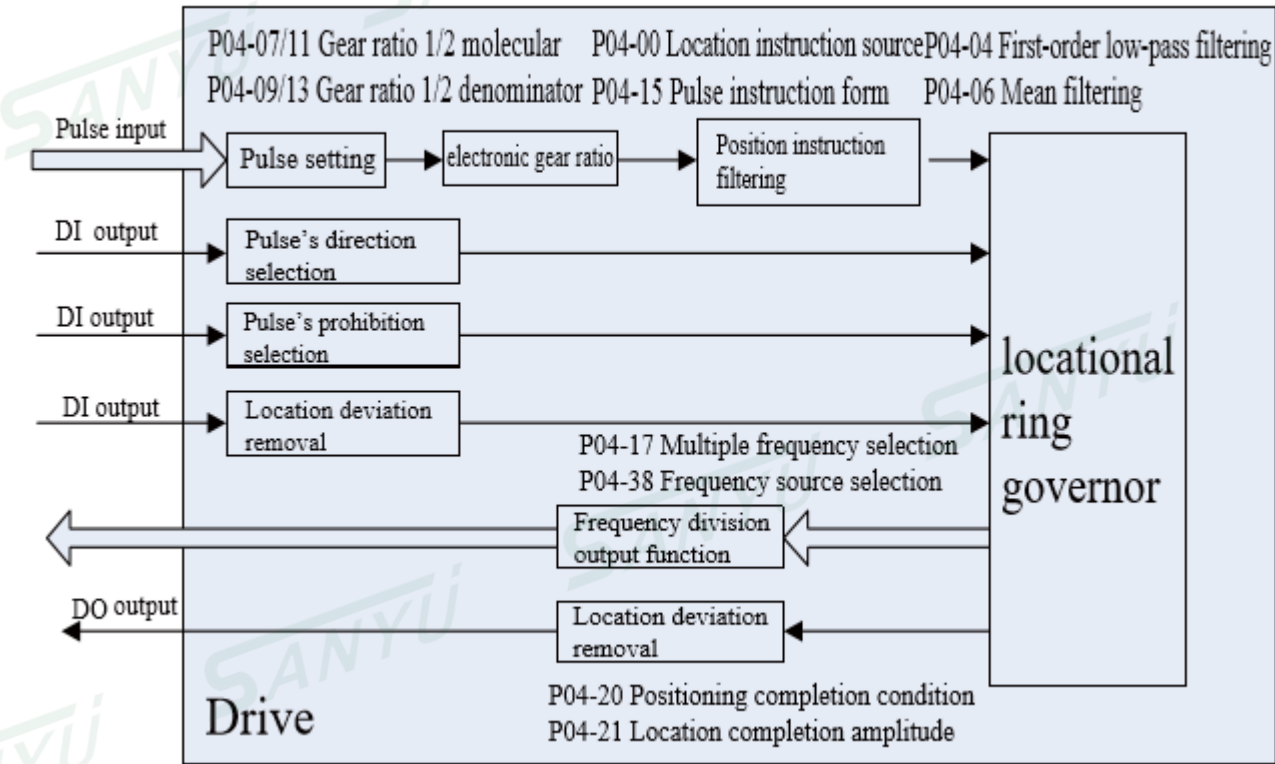
1. Servo ON (/ S-ON), input signal is OFF (H-level) state.
2. By assigning an external input signal setting, not conduct" effective internal servo ON" setting. In addition,

please pay more attention, in jog(JOG) mode operation, the forward rotation drive prohibited(P-OT) and reverse rotation drive prohibited (N-OT) signal is invalid.

5.2 Position control mode selection

Position control mode usually uses number of pulses to ensure displacement of movement,extra input pulse frequency to ensure the magnitude of rotational speed. As position mode can strictly control speed and position, so it usually used for positioning device,it is the control mode which servo apply most,main applications such as mechanical arm, chip mounter, engraving and milling cutting, CNC machine and so on.

5.2.1 Position control mode instructions



Position mode using steps as follow:

1. Connect servo driver's main circuit line,control circuit line,motor power line,encoder line,brake line(if motor has brake function) properly,after power up,driver's panel display "rdy",it indicates that the connections are correct.
2. Using JOG mode,make sure the motor is running regularly.
3. Connect the line which needed by pulse command, pulse direction and DI/DO of CN1 terminal,setting related function code.
4. After servo enable, make sure the connection and motor rotate direction is correct by send low speed pulse command.

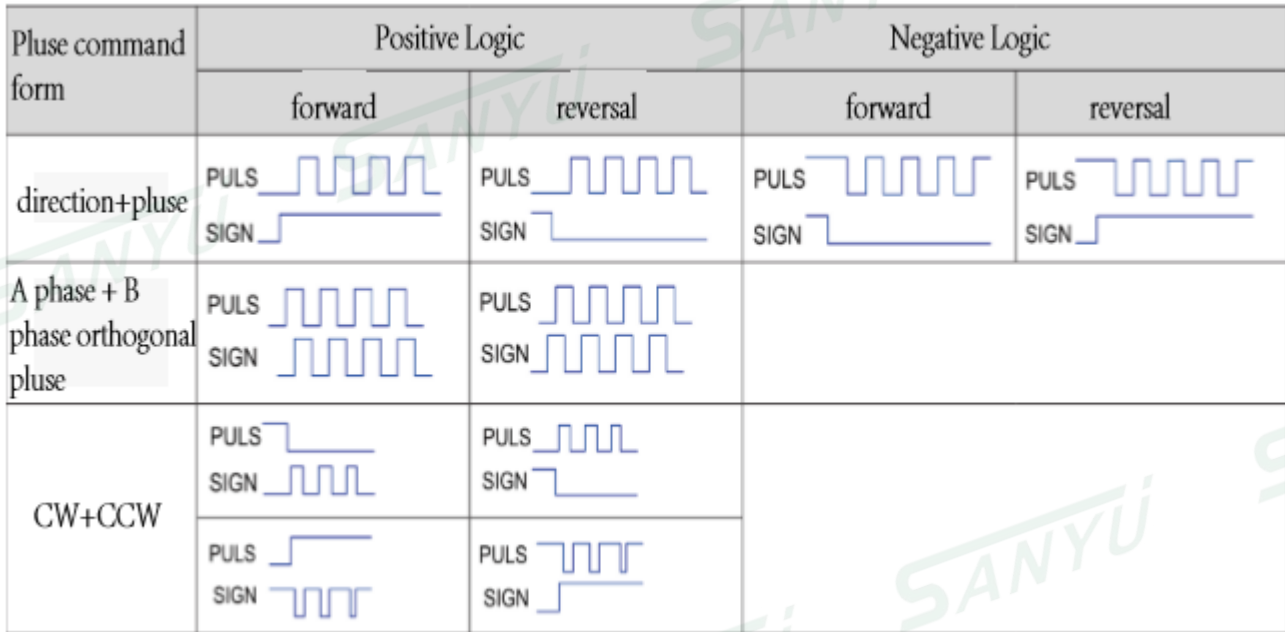
5.2.2 User parameter setting

P04-00	Position command source			
	Setting range	Setting unit	Default	Power restart
	0~2	1	0	Don't need
0—Pulse command 1— step value given 2—Multiple position command given				

P04-15	Pulse command form			
	Setting range	Setting unit	Default	Power restart
	0~3	1	0	Need

0—Direction + pulse, positive logic
1—Direction + pulse, negative logic
2—A phase + B phase orthogonal pulse, 4 times frequency
3—CW + CCW

Pulse command form's specific form as following picture:



P04-07	Numerator of the electronic gear ratio 1			
	Setting range	Setting unit	Default	Power restart
	1~1073741824	1	8388608	Don't need
P04-09	Denominator of the electronic gear ratio 1			
	Setting range	Setting unit	Default	Power restart
	1~1073741824	1	10000	Don't need
P04-11	Numerator of the electronic gear ratio 2			
	Setting range	Setting unit	Default	Power restart
	1~1073741824	1	8388608	Don't need
P04-13	Denominator of the electronic gear ratio 2			
	Setting range	Setting unit	Default	Power restart
	1~1073741824	1	10000	Don't need

Electronic gear ratio's main function is make position command pulse zoom in or zoom out, send processed value as position reference command to position loop for calculation. If connect motor and load by using reduction gear, assume reduction ratio of motor shaft and load machinery side is n/m (motor shaft rotate m circles, load shaft rotate n circles), electronic gear ratio's calculation formula as follow:

$$\text{Electronic gear ratio} = \frac{P04-07}{P04-09} = \frac{\text{Encoder resolution}}{\text{The resolution of the rotation of the load axis}} * \frac{m}{n}$$

At present, driver support two way electronic gear ratio, switch over by DI terminal input.

Driver support two mode electronic gear ratio at present, switch over by DI terminal input.

P04-04	Filter time of first-order lowpass			
	Setting range	Setting unit	Default	Power restart
	0.0ms~6553.5ms	0.1ms	0.0ms	Do not need
P04-06	Filter time of positioning command moving average value			
	Setting range	Setting unit	Default	Power restart
	0.0ms~128.0ms	0.1ms	0.0ms	Don't need

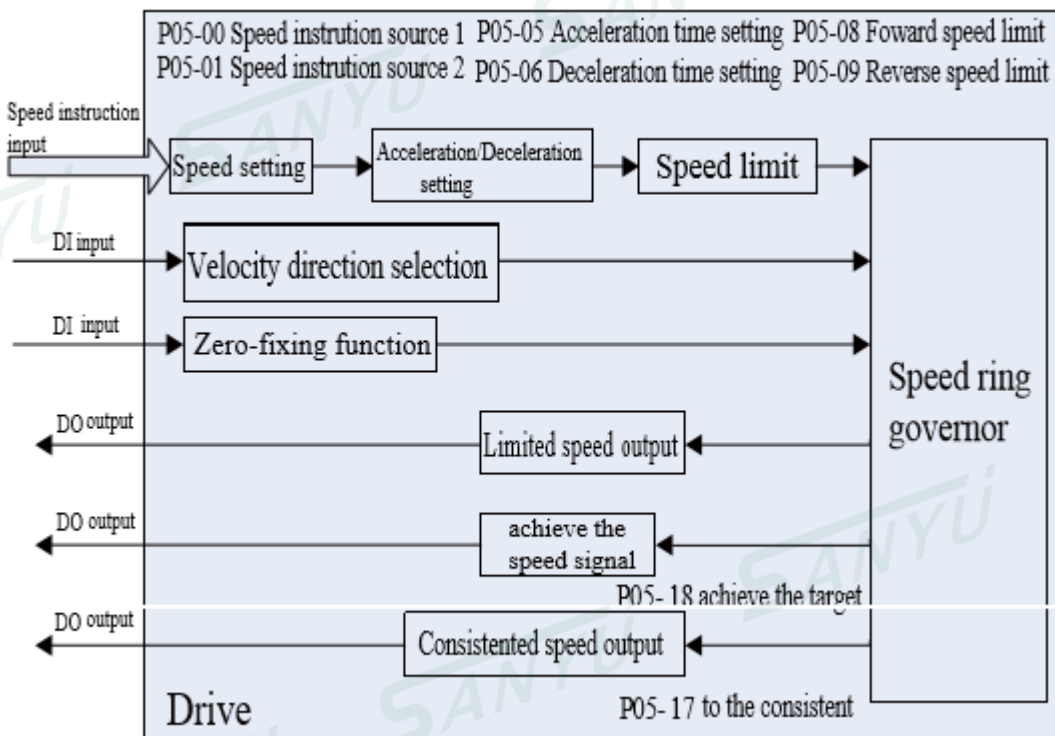
Position command filter function is filtering input position command, make servo motor rotate more smoothly, reduce impact to load. At present, we support two modes to position command filter: first-order lowpass filter and average filter, this function has a obvious effect on the following occasions:

- <1>Upper device output pulse command has no accelerate/decelerate operation and accelerate/decelerate speed is high;
 - <2>Command pulse frequency is too low;
 - <3>Electronic gear ratio over 10 times;
- Introduction: After filter, there is no effect on amount of pulse position command;

5.3 Speed control mode running

Speed control mode control rotational speed by analog input, function code digital value given or communication given, mainly used for some constant speed occasions, usually used by servo, typical applied occasion such as: analog carves-milling machine, upper computer adopt position control, servo driver adopt speed control mode.

5.3.1 Speed control mode instructions



Speed mode using steps as follow:

1. Connect servo driver's main circuit line, control circuit line, motor power line, encoder line, brake line (if motor has brake function) properly, after power up, driver's panel display "rdy", it indicates that the connections are correct.
2. Using JOG mode, make sure the motor is running regularly.
3. Connect the line which needed by speed command, speed direction and DI/DO of CN1 terminal, setting related

function code.

4.After servo enable, make sure the connection and motor rotate direction is correct by input low-speed speed command.

5.3.2 User parameters setting

P05-00	Main speed command A source			
	Setting range	Setting unit	Default	Power restart
	0~5	1	0	Don't need
0-digital given (P0503) 1-AI1 2-AI2 3-AI3(reserved) 4-JOG speed command 5-Multiple speed command				
P05-01	Auxiliary speed command B source			
	Setting range	Setting unit	Default	Power restart
	0~5	1	1	Don't need
0-digital given (P0503) 1-AI1 2-AI2 3-AI3(reserved) 4-JOG speed command 5- Multiple speed command				
P05-03	Speed command panel setting value			
	Setting range	Setting unit	Factory setting	Power restart
	-9000rpm~9000rpm	1rpm	200rpm	Don't need
P05-04	JOG speed setting value			
	Setting range	Setting unit	Factory setting	Power restart
	0rpm~3000rpm	1rpm	100rpm	Do not need

The driver offers two speed command sources, it can also assign the switchover between two speed sources. If use analog quantity as speed command source, we need to set correlative parameters of AI in group P02.

P05-05	Accelerate time			
	Setting range	Setting unit	Factory setting	Power restart
	0ms~65535ms	1ms	0ms	Don't need
P05-06	Decelerate time			
	Setting range	Setting unit	Default	Power restart
	0ms~65535ms	1ms	0ms	Don't need

The function of accelerate decelerate time is change the speed command which has a great change to the smooth speed command of constant acceleration and deceleration, in other words, it's aim is to control acceleration and deceleration by setting accelerate/decelerate time. With speed control mode,if the given speed command has a great change,it will cause the motor arise pulsatile and vibratory phenomenon,if increase the accelerate/decelerate time of soft boot,then it can realize the smooth start of motor,avoid the above situation,damage the mechanical parts.

P05-07	Maximum speed limit value			
	Setting range	Setting unit	Default	Power restart
	0rpm~9000rpm	1rpm	9000rpm	Don't need
P05-08	Forward speed limit value			
	Setting range	Setting unit	Default	Power restart
	0rpm~9000rpm	1rpm	9000rpm	Don't need
P05-09	Reverse speed limit value			
	Setting range	Setting unit	Default	Power restart
	0rpm~9000rpm	1rpm	9000rpm	Don't need

Effective forward speed limit values are P05-07,P05-08,the minimum of motor's maximum speed;Effective reverse speed limit values are P0507,P05-09,the minimum of motor's maximum speed;

5.3.3 Introduction of analog used as speed command input

Issued to the servo unit in the form of analog voltage instruction, places the input voltage proportional to the speed of the

servo motor to conduct the speed control.

Kind	Signal name	Connector pin' s number	Name
Input	V-REF	CN1-30/43	Speed instruction input
	GND	CN1-44	Speed instruction input signal ground

Use during the speed control (analog voltage instruction). (P05-00=1,2) Use P02-80 to set the speed instruction input gain.

■ Input specifications

- Input range: DC±0V ~ ±10V/rated speed
- The maximum allowable input voltage: DC±12V

• The setting example
P02-80=3000:the rated speed when the voltage is ± 10V
Specific examples are shown below.

Speed command input	Direction of rotation	Rotate speed	Mode type
+6V	Forward	1800min ⁻¹	3000min ⁻¹
+1V	Forward	300min ⁻¹	3000min ⁻¹
-3V	Reverse	-900min ⁻¹	3000min ⁻¹

■ Examples of input circuit

- In order to be able to take effective measures to prevent interference, be sure to use the multi-stranded wires when wiring.
- Examples of variable resistor

When using the programmable controllers in the instruction controller to conduct the position control, the controller is connected to the instruction controller's speed instruction output terminals.

Instruction controller

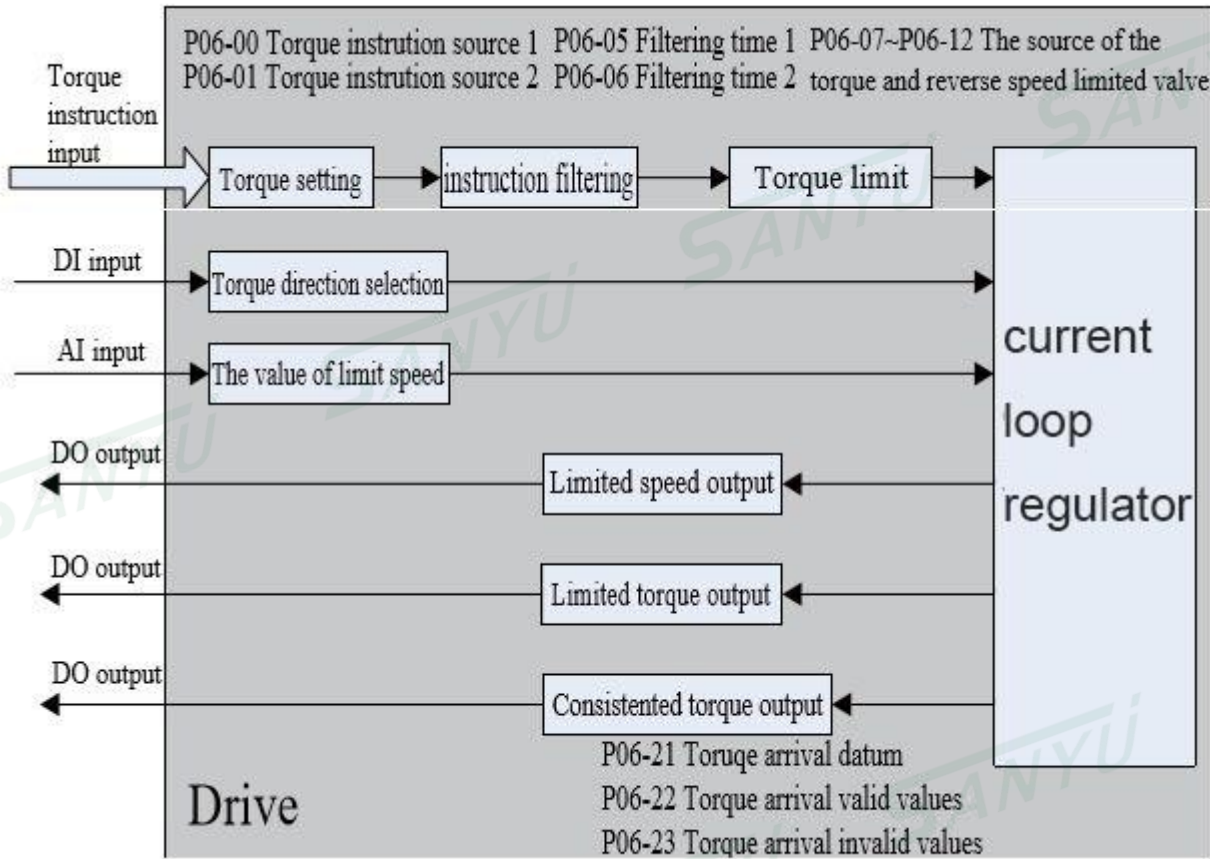
Instruction controller terminal	servo unit terminal
Speed command output terminal	V-REF → 30
	GND → 44
Feedback pulse input terminal	OA+ → 29
	OA- → 28
	OB+ → 27
	OB- → 26

Legend: Stranded wire

5.4 Torque control mode running

Torque control mode change the torque size by change analog quantity's setting instantaneously or change function code's value with communication, mainly apply to the devices which have strict requirements on the force of material such as winding and unreeling, typical application's occasion like winding device or pull fiber equipment which controlled by tension. The setting of torque need changing with winding radius. Make sure the force of material not changing with winding radius.

5.4.1 Torque control mode instructions



Torque mode using steps as follow:

1. Connect servo driver's main circuit line, control circuit line, motor power line, encoder line, brake line (if motor has brake function) properly, after power up, driver's panel display "rdy", it indicates that the connections are correct.
2. Using JOG mode, make sure the motor is running regularly.
3. Connect the line which needed by torque command, torque direction and DIDO of CN1 terminal, setting related function code.
4. After servo enable, set a lower speed limit value, exert a forward or reverse torque command on servo. make sure the motor rotate direction and rotate speed's limitation is correct. If it's normal then we can use it.

5.4.2 Torque command input

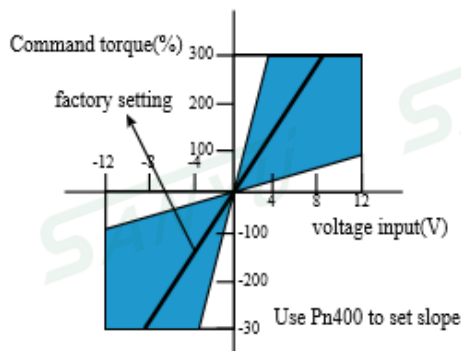
Issued to the servo unit in the form of analog voltage instruction, places the input voltage proportional to the torque of the servo motor to conduct the torque control.

Kind	Signal name	Connector pin number	name
Input	T-REF	CN1-43	Torque command input
	GND	CN1-44	Torque command input signal ground cable

■ Use during in the process of torque control (analog voltage instruction). Use P02-81 to set torque instruction input gain.

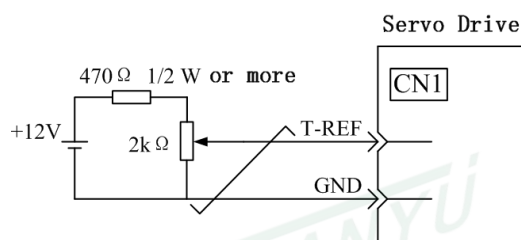
Input specifications:

Input range: DC±0V~±10V/ the rate torque
 The maximum allowable input voltage: DC±12V
 (The factory setting):
 P02-81=1.00: Rated torque when the voltage is ±10V
 +3V input: 30% rated torque when it is in the positive direction
 +9V input: 90% rated torque when it is in the positive direction
 -1V input: 10% rated torque when it is in the reverse direction to change the voltage input corresponding rated torque times by the user parameter P02-81.



■ Examples of input circuit

To be able to take effective measures to prevent interference, be sure to use the multi-stranded wires when wiring.

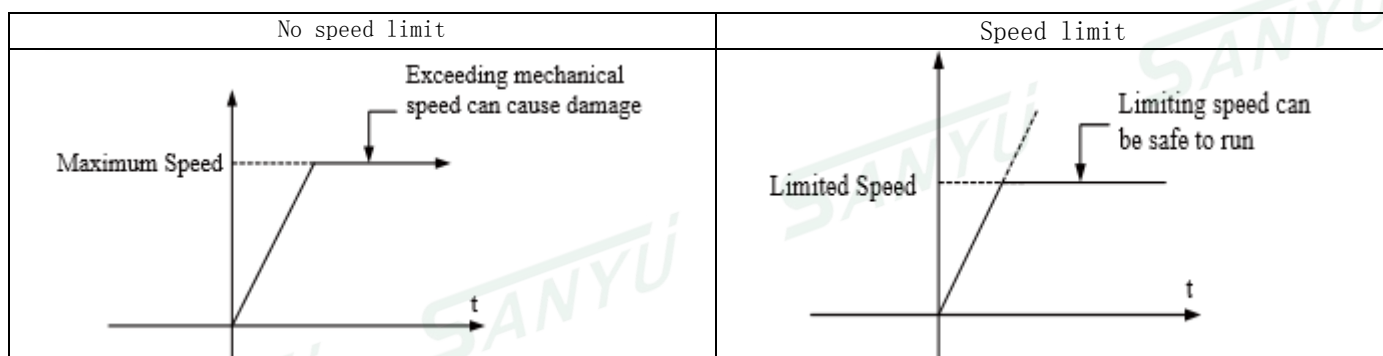


■ The confirmation of internal torque reference

1. Confirmed by internal torque reference panel operator. Can confirm that the internal torque reference in monitor mode (P0B-02).
2. Confirmed by monitoring internal analog torque instruction. can monitor by analog, monitoring internal instruction torque by analog voltage instruction .

5.4.3 The speed limit when it is torque control.

Since when it is torque control, need to control the servo motor to input the issued instruction's torque. so the motor speed's management is not performed. If the mechanical side's load torque setting is too high, will exceed the mechanical's torque, Causing the motor speed greatly improved. As the mechanical side's protective measure, with function to limit the servo motor speed control when it is servo motor's torque control.



(1)The selection of the speed control mode (torque limiting options)

The user parameter	Contents
P06-17	0-Internal speed limit, set P06-19、P06-20 as forward/reverse speed limit
	1-Analog speed limit, according to P06-18 set AI1, AI2 as speed limit
	2-DI Switch speed limit, through DI input set P06-19 or P06-20 as speed limit

(2)Internal speed limit function

P06-19	The speed limit when it is torque control			
	Setting range	Setting unit	Default	Power restart
	0~9000rpm	1rpm	3000rpm	Don't need

The motor rotate speed limit when set the torque limit.
Even more than the value of the maximum speed of the servo motor set in P0619, the actual value is still limited to the maximum rotate speed of the servo motor.

P06-20	Speed limit at torque control			
	Setting range	Setting unit	Default	Power restart
	0~9000rpm	1rpm	3000rpm	Don't need

Set motor rotate speed limit at torque limit
Even if the value exceeding the maximum of servo motor speed set in P06-20, the actual value is still limited to the maximum speed of the servo motor used.

(3) Output speed limit function

Kind	Signal name	Connector pin number	Name
Input	V-REF	CN1-30/43	Output speed limit input
	GND	CN1-44	Signal ground

P02-80	Speed command input gain			
	Setting range	Setting unit	Default	Power restart
	0~9000rpm	1rpm	3000rpm	Don't need

■ The theory of speed limit:

Over the range of speed limit, places the speed difference of speed limit proportional to the torque of the servo motor to conduct the negative feedback, then we can back to the range of speed limit. So, actual motor rotate speed limit will change with loading condition.

(4) Output signal of motor rotate speed limit

Kind	Signal name	Connector pin number	Setting	Significance
output	/V-LT	Need to assign CN1-□□	ON=L electric level	Are limiting the motor speed
			OFF=H electric level	Not the motor rotating speed limit state

When conduct the torque limit, if the motor speed reaches the set value P06-19, P06-20 or the speed limit basing on the analog voltage instruction, will output / V-LT signal. must conduct the output terminals assigned by the user parameters P03

5.4.4 Absolute encoder

This section applies to servo driver with absolute encoder and it's invalid for servo driver with incremental encoder.

Multi-turn type absolute encoder can not only detect the position of motor at rotate a circle but also count the circle numbers of motor, single circle resolution is decided by the motor type's encoder(17 bits ~ 23 bits), it can memorize 16 bits' multi-turn data. The absolute system constituted by using absolute encoder can be divided into absolute position linear mode and absolute position rotate mode, can be used on position, speed and torque control mode, when the driver is power down, encoder can back-up data by battery equipment, after power on, driver can calculate the absolute position of machinery by the absolute position of encoder, it don't need perform the mechanical origin reset operation repeatedly. When SY200 servo driver match the absolute encoder, we need set corresponding motor type (P1D00), choose corresponding motor type (P1D-00). When connect to the battery firstly, it will occur Er.220 (Encoder battery warning), we need set POD-20=1 to reset encoder fault, then perform the origin reset operation.

This servo driver support Tamawaga 17/23bits absolute single-circle and multi-circle encoder. Multi-circle's data is +32767 ~ -32768. When higher than the upper limit of forward direction (+32767), Multi-circle's data change to -32768. When lower than the lower limit of reserved direction (32767), Multi-circle's data change to +32768. When standard equipped our company's motor, you only need choose corresponding motor code.

Chapter 6 Parameter list

6.1 User parameters

6.1.1 Main parameters

(NOTE) The detail of property is instead by the following pictures:

☆ : Don't need power restart/With immediate effect;

★ : Need power restart/Power on next time;

● : Read only;

Function Code	Name	Setting range	Unit	Default	Property
P01-00	Control mode selection	0. Speed mode 1. Position mode 2. Torque mode 3. Speed mode↔Torque mode 4. Position mode↔Speed mode 5. Position mode↔Torque mode 6. Position mode↔Speed↔Torque mixed mode 7. Absolute position mode	1	1	☆
P01-01	System parameter initialization	0.No function 1.Restore factory settings(expect group P00/P1D) 2.Clear error log	1	0	☆
P01-02	Panel warning display selection	0. Display warning information 1. No display warning information	1	0	☆
P01-03	Selection of servo off stop mode	0. Coast to stop , keep free running state 1. Zero-speed stop , keep free running state	1	0	☆
P01-04	Stop mode of over range	0.Coast to stop,keep free running state 1.Scram torque stop,position locking state 2.Scram torque stop,keep free running state	1	1	☆
P01-05	Selection of fault which can reset stop mode	0. Coast to stop, keep free running state 1. zero-speed stop, keep free running state	1	0	☆

P01-09	Selection of rotate direction	0.Use CCW direction as forward direction(A lead B) 1.Use CW direction as forward direction(A lag B)	1	0	★
P01-10	Selection of divisible frequency output pulse direction	0.Use CCW direction as forward direction(A lead B) 1.Use CW direction as forward direction(reserve mode, A lag B)	1	0	★
P01-11	Minimum speed set	0.2~14.0rpm	0.1rpm	4.0rpm	★
P01-12	Delay time of brake open when servo ON	20ms~500ms	1	250ms	☆
P01-13	Delay time of brake output when zero speed servo OFF	1ms~500ms	1ms	150ms	☆
P01-14	Output speed limit of brake command	0rpm~3000rpm	1rpm	30rpm	☆
P01-15	Delay time of brake output when free stop	1ms~1000ms	1ms	500ms	☆
P01-18	Filter time of servo ON signal	0~64	1ms	0	☆
P01-20	Brake resistor minimum allowed by driver	-	-	40	-
P01-21	Power of built-in brake resistor	-	-	40	-
P01-22	Value of built-in brake resistor	-	-	50	-
P01-23	Heat release coefficient of resistor	10~100	1	30	Immediately effective
P01-24	Brake resistor set	0.Use built-in power resistor 1.Use external power resistor and natural cooling 2.Use external power resistor and air cooling 3.Don't use power resistor,absorbed by capacitor	1	0	☆

P01-25	External brake resistor power	1W~65535W	1W	-	☆
P01-26	External brake resistor value	1Ω ~1000Ω User can set by yourself	1	-	Ω

P02-00	DI function default state 1 (HEX)	0~0xFFFF Bit0-correspond to FunIN.1 Bit0-correspond to FunIN.2 Bit0-correspond to FunIN.16	1	0	★
P02-01	DI function default state 2 (HEX)	0~0xFFFF Bit0-correspond to FunIN.17 Bit0-correspond to FunIN.18 Bit0-correspond to FunIN.32	1	0	★
P02-02	DI function default state 3 (HEX)	0~0xFFFF Bit0-correspond to FunIN.33 Bit0-correspond to FunIN.34 Bit0-correspond to FunIN.48	1	0	★
P02-03	DI function default state 4 (HEX)	0~0xFFFF Bit0-correspond to FunIN.49 Bit0-correspond to FunIN.50 Bit0-correspond to FunIN.64	1	0	★
P02-04	Selection of DI1 terminal's functions	0~36	1	14	☆
P02-05	Selection of DI1 terminal's logic	0.Low level valid 1.High level valid 2.Rising edge valid 3.Falling edge valid 4.Both rising edge and falling edge valid	1	0	☆
P02-06	Selection of DI2 terminal's functions	Same as DI1	1	15	☆
P02-07	Selection of DI2 terminal's logic	Same as DI1	1	0	☆
P02-08	Selection of DI3 terminal's functions	Same as DI1	1	13	☆
P02-09	Selection of DI3 terminal's logic	Same as DI1	1	0	☆
P02-10	Selection of DI4 terminal's functions	Same as DI1	1	2	☆
P02-11	Selection of DI4 terminal's logic	Same as DI1	1	0	☆
P02-12	Selection of DI5 terminal's functions	Same as DI1	1	1	☆
P02-13	Selection of DI5 terminal's logic	Same as DI1	1	0	☆
P02-14	Selection of DI6 terminal's functions	Same as DI1	1	12	☆
P02-15	Selection of DI6	Same as DI1	1	0	☆

	terminal's logic				
P02-16	Selection of DI7 terminal's functions	Same as DI1	1	3	☆
P02-17	Selection of DI7 terminal's logic	Same as DI1	1	0	☆
P02-18	Selection of DI8 terminal's functions	Same as DI1	1	31	☆
P02-19	Selection of DI8 terminal's logic	Same as DI1	1	0	☆
P02-20	Selection of DI9 terminal's functions	Same as DI1	1	0	★
P02-21	Selection of DI9 terminal's logic	Same as DI1	1	0	★
P02-50	AI1 bias	-5000~5000mV	1mV	0	☆
P02-51	AI1 input filter time	0~655.35ms	0.01ms	200	☆
P02-52	AI1 input median filter enable	0.Forbid 1.Enable	1	1	☆
P02-53	AI1 dead zone	0~1000.0mV	0.1mV	100	☆
P02-54	AI1 zero drift	-500.0~500.0mV	0.1mV	0	☆
P02-55	AI2 bias	-5000~5000mV	1mV	0	☆
P02-56	AI2 input filter time	0~655.35ms	0.01ms	200	☆
P02-57	AI2 input median filter enable	0-prohibit 1-enable	1	1	☆
P02-58	AI2 dead zone	0~1000.0mV	0.1mV	100	☆
P02-59	AI2 zero drift	-500.0~500.0mV	0.1mV	0	☆
P02-80	Analog quantity 100% correspond to speed value	0rpm~9000rpm	1rpm	3000rpm	☆
P02-81	Analog quantity 100% correspond to torque value	1.00~8.00 times rated torque	1.00	1.00 times rated torque	☆

Instruction : DI terminal's function

Function code setting value	Function	Description																																									
0	No function	No function																																									
1	S-ON: Servo on enable	When the signal is on, servo circuit connection, servo motor coil passing current																																									
2	ALM-RST: fault and warning reset, detail refer to 8.1.1	When the signal is on, servo fault and warning reset, refer to 8.1.1 for detail																																									
3	GAIN-SEL: gain switch	When P07-09=1, this signal is off, use the first gain; when this signal is on, use the second gain.																																									
4	CMD-SEL: main and auxiliary command switch	When P05-02=3 or P06-02=3, the signal is off, use the source A; the signal is on, use the source B.																																									
5	DIR-SEL: Multi-speed command direction selection	When use multi-speed position ode, the signal is on, motor rotating direction will change.																																									
6	CMD1: Multi-running command switch 1	<table border="1"> <thead> <tr> <th>CMD1</th> <th>CMD2</th> <th>CMD3</th> <th>CMD4</th> <th>Parameter used</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>P10-12~P10-16</td> </tr> <tr> <td>7</td> <td>CMD2: Multi-running command switch 2</td> <td> <table border="1"> <thead> <tr> <th>CMD1</th> <th>CMD2</th> <th>CMD3</th> <th>CMD4</th> <th>Parameter used</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>0</td> <td>0</td> <td>1</td> <td>P10-17~P10-21</td> </tr> <tr> <td>8</td> <td>CMD3: Multi-running command</td> <td> <table border="1"> <thead> <tr> <th>CMD1</th> <th>CMD2</th> <th>CMD3</th> <th>CMD4</th> <th>Parameter used</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>0</td> <td>1</td> <td>0</td> <td>P10-22~P10-26</td> </tr> <tr> <td></td> <td>0</td> <td>0</td> <td>1</td> <td>P10-27~P10-31</td> </tr> </tbody> </table> </td> </tr> </tbody> </table> </td> </tr> </tbody> </table>	CMD1	CMD2	CMD3	CMD4	Parameter used	0	0	0	0	P10-12~P10-16	7	CMD2: Multi-running command switch 2	<table border="1"> <thead> <tr> <th>CMD1</th> <th>CMD2</th> <th>CMD3</th> <th>CMD4</th> <th>Parameter used</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>0</td> <td>0</td> <td>1</td> <td>P10-17~P10-21</td> </tr> <tr> <td>8</td> <td>CMD3: Multi-running command</td> <td> <table border="1"> <thead> <tr> <th>CMD1</th> <th>CMD2</th> <th>CMD3</th> <th>CMD4</th> <th>Parameter used</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>0</td> <td>1</td> <td>0</td> <td>P10-22~P10-26</td> </tr> <tr> <td></td> <td>0</td> <td>0</td> <td>1</td> <td>P10-27~P10-31</td> </tr> </tbody> </table> </td> </tr> </tbody> </table>	CMD1	CMD2	CMD3	CMD4	Parameter used	0	0	0	1	P10-17~P10-21	8	CMD3: Multi-running command	<table border="1"> <thead> <tr> <th>CMD1</th> <th>CMD2</th> <th>CMD3</th> <th>CMD4</th> <th>Parameter used</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>0</td> <td>1</td> <td>0</td> <td>P10-22~P10-26</td> </tr> <tr> <td></td> <td>0</td> <td>0</td> <td>1</td> <td>P10-27~P10-31</td> </tr> </tbody> </table>	CMD1	CMD2	CMD3	CMD4	Parameter used	0	0	1	0	P10-22~P10-26		0	0	1	P10-27~P10-31
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0	0	0	1	P10-17~P10-21																																							
8	CMD3: Multi-running command	<table border="1"> <thead> <tr> <th>CMD1</th> <th>CMD2</th> <th>CMD3</th> <th>CMD4</th> <th>Parameter used</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>0</td> <td>1</td> <td>0</td> <td>P10-22~P10-26</td> </tr> <tr> <td></td> <td>0</td> <td>0</td> <td>1</td> <td>P10-27~P10-31</td> </tr> </tbody> </table>	CMD1	CMD2	CMD3	CMD4	Parameter used	0	0	1	0	P10-22~P10-26		0	0	1	P10-27~P10-31																										
CMD1	CMD2	CMD3	CMD4	Parameter used																																							
0	0	1	0	P10-22~P10-26																																							
	0	0	1	P10-27~P10-31																																							

	switch 3	0	1	0	0	P10-32~P10-36												
9	CMD4: Multi-running command switch 4	0	1	0	1	P10-37~P10-41												
		0	1	1	0	P10-42~P10-46												
		0	1	1	1	P10-47~P10-51												
		1	0	0	0	P10-52~P10-56												
		1	0	0	1	P10-57~P10-61												
		1	0	1	0	P10-62~P10-66												
		1	0	1	1	P10-67~P10-71												
		1	1	0	0	P10-72~P10-76												
		1	1	0	1	P10-77~P10-81												
		1	1	1	0	P10-82~P10-86												
				1	1	1	1	P10-87~P10-91										
When use multi-stage, you can use this four DI to switch multi-stage.																		
10	M1-SEL: mode switch 1	<table border="1"> <thead> <tr> <th>M1-SEL</th> <th>M2-SEL</th> <th>Mode using</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>0</td> <td>Mode 1</td> </tr> <tr> <td>0</td> <td>1</td> <td>Mode 2</td> </tr> <tr> <td>1</td> <td>0</td> <td>Mode 3</td> </tr> </tbody> </table>					M1-SEL	M2-SEL	Mode using	0	0	Mode 1	0	1	Mode 2	1	0	Mode 3
M1-SEL	M2-SEL						Mode using											
0	0						Mode 1											
0	1						Mode 2											
1	0	Mode 3																
11	M2-SEL: mode switch 2																	
When use mix mode, you can use this two DI to switch mode																		
12	ZCLAMP : zero position fix enable	When servo on, the signal is on, servo motor will lock on zero speed																
13	INHIBIT : position command prohibit	When the signal is on, servo will no operate position command																
14	P-OT: forward over travel switch	When this signal is on, servo motor stop forward, servo display Er.322																
15	N-OT: reverse over travel switch	When the signal is on, servo motor stop reverse, servo display Er.323																
16	P-CL: Positive external torque limit	P06-07=1:																
17	N-CL: negative external torque limit	PCL	NCL	Forward torque limit	Reverse torque limit													
		0	0	P06-09	P06-10													
		1	0	P06-11	P06-10													
		0	1	P06-09	P06-12													
		1	1	P06-11	P06-12													
		P06-07=4:																
		PCL	NCL	Forward torque limit	Reverse torque limit													
		0	0	P06-08														
		1	0	P06-11	P06-08													
		0	1	P06-08	P06-12													
1	1	P06-11	P06-12															
18	JOGCMD+: forward JOG	The signal is on, servo motor will forward																
19	JOGCMD-: reverse JOG	The signal is on, servo motor will reverse																
20	PosStep: step size enable	Use step size mode, the signal is on, motor will run in step size mode																
21	HX1: handwheel multiply signal 1	-																
22	HX2: handwheel multiply signal 2	-																
23	HX_EN: handwheel-on signal	-																
24	GEAR_SEL: electric gear ratio selection	When P04-39=1, this signal is on, use electric; this signal is off, use electronic gear ratio 1, this signal is off, use electronic gear ratio 2.																
25	ToqDirSel : torque command direction setting	Under the torque mode, the signal is on, motor rotate direction will change																
26	SpdDirSel : speed command	Under the speed mode, the signal is on, motor rotate direction																

	direction setting	will change
27	PosDirSel : position command direction setting	Under position mode, the signal is on, motor rotate direction will change
28	PosInSen: Multi-position enable	Under multi-stage position mode, the signal is on, motor will run on multi-stage position mode.
29	XintFree: interrupt fixed length status release	When the signal is on, stop interrupt fixed length action, continue operate position command
30	No function	No function
31	HomeSwitch: zero point switch	Motor performs zero point reset, the signal is on, motor will complete the return-to-origin movement with the current position as the origin
32	HomingStart : zero point reset enable	When P04-30=1 or 2, the signal is on, motor will perform zero point reset.
33	XintInhibit : interrupt length prohibit	The signal is on, forbid interrupt fixed length function
34	EmergencyStop: Emergency stop	The signal is on, servo motor will stop
35	ClrPosErr : clear position deviation	When P04-16=3, the signal effective, it will clear the value of P0B-15 (Position deviation counter)
36	V_LmtSel: internal speed limit source	When P06-17=2, the signal is off, use P06-19(First speed limit) as speed limit, when the signal is on, use P06-20(Second speed limit) as speed limit.

Group 03:Output parameters					
P03-00	Selection of DO1 terminal's functions	0~19	1	1	☆
P03-01	Selection of DO1 terminal's logic level	0-Output low level when effective (optocoupler breakover) 1-Output high level when effective (optocoupler turn off)	1	0	☆
P03-02	Selection of DO2 terminal's functions	Same as DO1	1	5	☆
P03-03	Selection of DO2 terminal's logic level	Same as DO1	1	0	☆
P03-04	Selection of DO3 terminal's functions	Same as DO1	1	3	☆
P03-05	Selection of DO3 terminal's logic level	Same as DO1	1	0	☆
P03-06	Selection of DO4 terminal's functions	Same as DO1	1	11	☆
P03-07	Selection of DO4 terminal's logic level	Same as DO1	1	0	☆
P03-08	Selection of DO5 terminal's functions	Same as DO1	1	16	☆
P03-09	Selection of DO5 terminal's logic level	Same as DO1	1	0	☆
P03-22	Selection of DO source	Bit0-DO1 source Bit4-DO5 source	—	0	☆

		Bit6~Bit15 reserved Bitx=0:DO given by driver Bitx=1:DO given by communication			
*P03-50	Selection of AO1 signal	00-Motor rotate speed(1V/1000rpm) 01-Speed command 02-Torque command (1V/100%) 03-Positional deviation (0.05V/1 command unit) 04-Position amplifier deviation (after electronic gear) (0.05V/1 encoder pulse unit) 05-Position command speed(1V/1000rpm) 06-Positioning complete command (complete:5V not complete :0V) 07-Speed feed forward (1V/1000rpm)	1	0	☆
*P03-51	AO1 offset voltage	0-10000mV	1mV	5000mV	☆
*P03-52	AO1 rate	-99.99~99.99	0.01 times	1.00	☆
*P03-53	Selection of AO2 signal	Same as AO1	1	0	☆
*P03-54	AO2 offset voltage	0-10000mV	1mV	5000mV	☆
*P03-55	AO2 rate	-99.99~99.99	0.01 times	1.00	☆

Instruction : DO terminal's function

Function code setting value	Function description	Description
0	No function	No function
1	S-RDY: servo get ready	When servo is on "rdy" state, output the signal
2	TGON: motor rotation	When motor rotate speed \geq P05-16, output the signal
3	ZERO: zero speed signal	When motor rotate speed \leq P05-19, output the signal
4	V-CMP: speed accordance	When motor rotate speed \leq P05-17, output the signal
5	COIN: position complete	When servo is in position mode and complete position command, output the signal, refer to P04-20, P04-21 for detail
6	NEAR: position approach	When motor is on zero point reset, number of phase difference pulses \leq P04-22, output the signal
7	C-LT: torque limit	Output when motor torque limit, refer to P06-07~P06-12 for detail
8	V-LT: speed limit	Output when motor speed limit, refer to P06-17~P06-20 for detail
9	BK: brake	Refer to P01-12~P01-15
10	WARN: warning	Output when servo warning

11	ALM: fault	Output when servo fault
12	No function	No function
13	No function	No function
14	No function	No function
15	Xintcoin : interrupt fixed length complete	Output when servo interrupt fixed length finished, refer to P04-24 for detail
16	HomeAttain: original point return to zero complete	Output when motor finish zero point return to zero
17	ElecHomeAttain: electric return to zero complete	Output when motor finish electric return to zero
18	ToqReach: torque reach	Output when motor torque reach P06-22, reduce to P06-23, withdraw
19	V-Arr: speed reach	When motor rotate speed \geq P05-18, output the signal

Group 04:Position control parameters					
P04-00	Source of position command	0-Pulse command 1-Punch advance given 2-Multistage position given	1	0	☆
P04-01	Selection of high/low speed pulse position command	0-Low speed pulse position command 1-High speed pulse position command	1	0	☆
P04-02	Command pulse number of motor rotate a circle	0~8388608	1 command unit	0	☆
P04-04	First order low pass filtering time of position command	0.0ms~6553.5ms	0.1ms	0.0ms	☆
P04-05	Punch advance	-9999~9999	1	50	☆
P04-06	Average time of position command move	0.0ms~128.0ms	0.1ms	0.0ms	☆
P04-07	Electronic tooth ratio 1(Numerator)	1~1073741824	1	8388608	☆
P04-09	Electronic tooth ratio 1(Denominator)	1~1073741824	1	10000	☆
P04-11	Electronic tooth ratio 2(Numerator)	1~1073741824	1	8388608	☆
P04-13	Electronic tooth ratio 2(Denominator)	1~1073741824	1	10000	☆
P04-15	Pulse command form	0-Dirction+pulse positive logic 1-Dirction+pulse negative logic 2-A phase+B phase orthogonal pulse,4 times frequency 3-CW+CCW	1	0	★
P04-16	Selection of positional deviation clear	0-Servo OFF and clear positional deviation pulse	1	0	☆

	action	when faults occurred 1-Clear positional deviation pulse when faults occurred 2-DI input clear positional deviation pulse when servo off			
P04-17	Frequency division pulse number of encoder	35~32767	1	2500	★
P04-19	Selection of speed feedforward control	0-No speed feedforward 1-interior speed feedforward 2-use AI1 as speed feedforward input 3-use AI2 as speed feedforward input	1	1	☆
P04-20	Output condition of positioning complete signal (COIN)	0-Output when positional deviation absolute value less than positioning complete range 1-Output when positional deviation absolute value less than positioning complete range and position command is 0 after filtering 2-Output when positional deviation absolute value less than positioning complete range and position command is 0	1	0	☆
P04-21	Positioning complete range	1~65535 command unit	1 command unit	6000 command unit	☆
P04-22	Positioning complete approach signal range	1~65535 command unit	1 command unit	65535 command unit	☆
P04-23	Interrupt fixed length enable	0-Forbid 1-Enable	-	0	★
P04-24	Interrupt fixed length displacement	0~1073741824(command unit)	1 command unit	10000 command unit	☆
P04-26	Interrupt fixed length constantly running speed	1rpm~9000rpm	1rpm	200	☆
P04-27	Interrupt fixed length acceleration/	0~1000	1ms	10ms	☆

	deceleration time				
P04-29	Fixed length locking relieve signal enable	0: no 1: yes	1	1	☆
P04-30	Original point reset enable control	0-Close origin reset function 1-Input ORGSET signal through DI to enable origin reset function 2-Input ORGSET signal through DI to enable electrical reset function 3-Immediately start origin reset after power on 4-Immediately process origin reset 5-Start electrical reset command 6-Using current position as origin	1	0	☆
P04-31	Original point reset mode	0-Forward return to zero,deceleration point,original point is original point switch 1-Reverse return to zero,deceleration point,original point is original point switch 2-Forward return to zero,deceleration point,original point is motor Z signal 3-Reverse return to zero,deceleration point,original point is motor Z signal 4-Forward return to zero,deceleration point is original point switch ,original point is motor Z signal 5-Reserve return to zero,deceleration	1	0	☆

		point is original point switch ,original point is motor Z signal 6-Forward return to zero,deceleration point,original point is forward over-range switch 7-Reverse return to zero,deceleration point,original point is reverse over-range switch 8-Forward return to zero,deceleration point is forward over-range switch,original point is motor Z signal 9-Reverse return to zero,deceleration point is reverse over-range switch,original point is motor Z signal			
P04-32	Speed of high speed search original point switch signal	0~3000	1rpm	100rpm	☆
P04-33	Speed of low speed search original point switch signal	0~1000	1rpm	10rpm	☆
P04-34	Acceleration/ deceleration time of limit search original point	0~1000	1ms	1000	☆
P04-35	Time of limit seek original point	0~65535	1ms	10000	☆
P04-36	Mechanical origin offset	-1073741824~1073741824	1 command unit	0	☆
P04-38	Selection of servo pulse output source	0-Encoder frequency division output 1-Pulse command synchronization output	1	0	★
P04-39	Electronic gear ratio DI switch enable	0-Switch after position pulse command is 0 continue 10ms 1- Allow DI switch	1	0	☆
P04-40	Original point reset mode	0-P04.36 is coordinate after	1	0	★

		original point reset ,meet limit,reverse find original point after restart original point reset enable 1-P04.36 is relative offset after original point reset ,meet limit,reverse find original point after restart original point reset enable 2-P04.36 is coordinate after original point reset,meet limit,reverse find zero-point automatically 3-P04.36 is relative offset after original point reset,meet limit,reverse find zero-point automatically			
P04-41	Selection of Z pulse output polarity	0~1	1	1	★
P04-46	Absolute position bias(low 32 bit)	-2147483648~2147483648	1 encoder unit	0	☆
P04-48	Absolute position bias(high 32 bit)	-2147483648~2147483648	1 encoder unit	0	☆

P05-00	Source of main speed command A	0-digital given (P0503) 1-AI1 2-AI2 3-reserved 4-reserved 5-multi-speed command	1	0	☆
P05-01	Source of auxiliary speed command B	0-digital given (P0503) 1-AI1 2-AI2 3-reserved 4-reserved 5-multistage speed command	1	1	☆
P05-02	Selection of speed command	0-Source of main speed command A 1-Source of auxiliary speed command B 2-A+B 3-A/B switch 4-Communication given	1	0	☆

P05-03	Speed command keyboard setting value	-9000rpm~9000rpm	1rpm	200rpm	☆
P05-04	JOG speed setting value	0rpm~3000rpm	1rpm	100rpm	☆
P05-05	Acceleration slope time of speed command	0ms~65535ms	1ms	0ms	☆
P05-06	Deceleration slope time of speed command	0ms~65535ms	1ms	0ms	☆
P05-07	Maximum rotate speed limit value	0rpm~9000rpm	1rpm	9000rpm	☆
P05-08	Speed forward limit	0rpm~9000rpm	1rpm	9000rpm	☆
P05-09	Speed reverse limit	0rpm~9000rpm	1rpm	9000rpm	☆
P05-11	Selection of torque feedforward	0-no torque feedforward 1-interior torque feedforward	1	1	☆
P05-15	Zero-position fixed rotate speed threshold value	0rpm~6000rpm	1rpm	10rpm	☆
P05-16	Motor rotate signal speed threshold value	0rpm~1000rpm	1rpm	20rpm	☆
P05-17	Width of speed accordance signal	0rpm~100rpm	1rpm	10rpm	☆
P05-18	Speed reach signal threshold value	10rpm~6000rpm	1rpm	1000rpm	☆
P05-19	Zero-speed output signal threshold value	1rpm~6000rpm	1rpm	10rpm	☆

P06-00	Source of main torque command A	0-digital given (P0603) 1-AI1 2-AI2	1	0	☆
P06-01	Source of auxiliary torque command B	0-digital given (P0603) 1-AI1 2-AI2	1	1	☆
P06-02	Selection of torque command	0-Source of main torque command A 1-Source of auxiliary torque command B 2-A+B source 3-A/B switch 4-Communication given	1	0	☆
P06-03	Torque command keyboard setting value	-300.0%~300.0%	0.1%	0	☆
P06-05	Torque command filter time 1	0.00ms~30.00ms	0.01ms	0.80ms	☆
P06-06	Torque command filter time 2	0.00ms~30.00ms	0.01ms	0.80ms	☆
P06-07	Source of	0-Forward/reverse	1	0	☆

	torque limit	interior torque limit 1-Forward/reverse external torque limit(using P-CL, N-CL to select) 2-Use T-LMT as external torque limit input 3-Use forward/reverse external torque and external T-LMT's minimum as torque limit(using P-CL, N-CL to select) 4-Use DI to process the switchover of first and second torque			
P06-08	Selection of T-LMT	1-Use AI1 as external torque limit 2-Use AI2 as external torque limit	1	2	☆
P06-09	Forward interior torque limit	0.0%~300.0% (100% correspond to one times rated torque)	0.1%	300.0%	☆
P06-10	Reverse interior torque limit	0.0%~300.0% (100% correspond to one times rated torque)	0.1%	300.0%	☆
P06-11	Forward external torque limit	0.0%~300.0% (100% correspond to one times rated torque)	0.1%	300.0%	☆
P06-12	Reverse external torque limit	0.0%~300.0% (100% correspond to one times rated torque)	0.1%	300.0%	☆
P06-17	Selection of speed limit source	0-Interior speed limit (P06-19/P06-20) 1-Use V-LMT as external speed limit input 2-Use DI's function 36 to select first or second speed limit input	1	0	☆
P06-18	Selection of V-LMT	1-Use AI1 as external speed limit 2-Use AI2 as external speed limit	1	2	☆
P06-19	Forward speed limit/first speed limit when torque	0~9000rpm	1rpm	3000rpm	☆

	control				
P06-20	Reverse speed limit/second speed limit when torque control	0~9000rpm	1rpm	3000rpm	☆
P06-21	Torque reach base value	0.0%~300.0% (100% corresponds to one times rated torque)	0.1%	0	☆
P06-22	Torque reach effective value	0.0%~300.0% (100% corresponds to one times rated torque)	0.1%	20.0%	☆
P06-23	Torque reach invalid value	0.0%~300.0% (100% corresponds to one times rated torque)	0.1%	10.0%	☆
P06-40	Speed over range window	0.5~30.0ms	0.1ms	1.0ms	☆

P07-00	Speed loop gain 1	1.0Hz~2000.0Hz	0.1Hz	25.0Hz	☆
P07-01	Speed loop integral time constant 1	0.15ms~512.00ms	0.01ms	31.83ms	☆
P07-02	Position loop gain 1	0.0Hz~2000.0Hz	0.1Hz	40.0Hz	☆
P07-03	Speed loop gain 2	1.0Hz~2000.0Hz	0.1Hz	40.0Hz	☆
P07-04	Speed loop intergral time constant 2	0.15ms~512.00ms	0.01ms	20.00ms	☆
P07-05	Position loop gain 2	0.0Hz~2000.0Hz	0.1Hz	64.0Hz	☆
P07-08	Setting of second gain mode	0-Use first gain regularly 1-Allow to switch first/second gain,switching condition is P07-09	1	1	☆
P07-09	Selection of gain's switching condition	0-Use first gain regularly 1-Use external DI switch first/second gain 2-Torque command great 3-Speed command great 4-Speed command's changing rate great 5-Speed command high/low speed threshold 6-Position deviation 7-Position command 8-Positioning complete 9-Actual speed great 10-Position command + actual speed	1	0	☆

P07-10	Delay time of gain's switchover	0~1000.0ms	0.1ms	5.0	☆
P07-11	Class of gain's switchover	0~20000	1	50	☆
P07-12	Time lag of gain's switchover	0~20000	1	30	☆
P07-13	Switch time of position gain	0.0~1000.0	0.1	3.0	☆
P07-15	Inertia ratio of load rotate	0.00~120.00	0.01	1	☆
P07-18	Filter time parameter of speed feedforward	0.00ms~64.00ms	0.01ms	0.50ms	☆
P07-19	Speed feedforward gain	0.0%~100.0%	0.1%	0.0%	☆
P07-20	Filter time parameter of torque feedforward	0.00ms~64.00ms	0.01ms	0.50ms	☆
P07-21	Torque feedforward gain	0.0%~200.0%	0.1%	0.0%	☆
P07-23	Filter cut off frequency of speed feedback	100Hz~4000Hz	1Hz	4000Hz	☆
P07-24	PDFF control coefficient	0.0%~100.0%	0.1%	100.0%	☆

P08-00	Selection of gain self adjusting mode	0-Manual adjust gain 1-Parameter self adjusting mode 1,use rigidity class adjust gain parameter 2-Parameter self-adjusting mode 2,enhance speed ability	1	0	☆
P08-01	Setting of rigidity class	0~31	1	12	☆
P08-02	Selection of adaptive wave trap mode	0~4	1	0	☆
P08-03	Online inertia recognize mode	0-close 1-open, change slowly 2-open, change generally 3-open, change quickly	1	0	☆
P08-04	Selection of low frequency	0-manual setup vibrational frequency	1	0	☆

	resonance suppression mode	1-automatic setup vibrational frequency			
P08-05	Selection of offline inertia recognize mode	0-Forward/reverse triangular wave mode 1-JOG mode	1	0	☆
P08-06	Maximum speed of inertia recognize	100rpm~1000rpm	1rpm	500rpm	☆
P08-07	Acceleration/deceleration time of inertia recognize	20ms~800ms	1ms	250ms	☆
P08-08	Waiting time of single inertia recognize complete	50ms~10000ms	1ms	800ms	☆
P08-09	First group wave trap frequency	-	0.01 circle	-	☆
P08-12	First group wave trap frequency	50Hz~4000Hz	1	4000	☆
P08-13	First group wave trap bandwidth class	0~20	1	2	☆
P08-14	First group wave trap depth class	0~99	1	0	☆
P08-15	Second group notch frequency	50Hz~4000Hz	1	4000	☆
P08-16	Second group wave trap bandwidth class	0~20	1	2	☆
P08-17	Second group wave trap depth class	0~99	1	0	☆
P08-18	Third group wave trap frequency	50Hz~4000Hz	1	4000	☆
P08-19	Third group wave trap bandwidth class	0~20	1	2	☆
P08-20	Third group wave trap depth class	0~99	1	0	☆
P08-21	Fourth group wave trap frequency	50Hz~4000Hz	1	4000	☆
P08-22	Fourth group wave trap	0~20	1	2	☆

	bandwidth class				
P08-23	Fourth group wave trap depth class	0~99	1	0	☆
P08-24	Result of resonant frequency recognize	-	-	-	☆
P08-30	Disturbance torque compensation gain	0.0%~100.0%	0.1	0.0	☆
P08-31	Filter time of disturbance observer	0.00ms~25.00ms	0.01	0.5	☆
P08-38	Low frequency resonance frequency	1.0~100.0	0.1	100.0	☆
P08-39	Low frequency resonance suppression range	0~10	1	2	☆

P09-00	Input phase loss protection selection	0-Enable fault,forbid warning 1-Enable fault and warning 2-Forbid fault and warning	1	0	☆
P09-03	If execute saving function when power down	0-no 1-yes	1	0	☆
P09-04	Motor overload protection gain	50%~300%	1%	100%	☆
P09-08	Threshold of over-speed judgement	0~10000	1	0	☆
P09-09	Maximum position pulse frequency	100kHz~4000kHz	1kHz	4000kHz	☆
P09-10	Fault value of too large position deviation	1~1073741824	1	25165824	☆
P09-12	Run away protection enable	0-without run away protection 1-open run away protection	1	1	☆
P09-16	Judgement threshold of low frequency resonance position deviation	1~1000	1	5	☆
P09-25	Speed feedback display filter time	0~5000ms	1	50ms	☆
P09-26	Motor overload shield enable	0-Don't shield 1-Shield warning	1	0	☆

		and fault of motor overload			
P09-27	Filter time constant of speed DO	0~5000	1	50ms	☆
P09-32	Locked-rotor overheat protection time window	10~65535	1	200ms	★
P09-33	Locked-rotor overheat protection enable	0~1	1	1	★

P0A-00	Servo axis address	1~247, 0 is broadcast address	1	1	☆
P0A-02	Setting of serial port baud rate	0-2400 1-4800 2-9600 3-19200 4-38400 5-57600	1	5	☆
P0A-03	Modbus data format	0-no check, 2 stop bit 1-even parity check, 1 stop bit 2-odd parity check, 1 stop bit 3-no check, 1 stop bit	1	0	☆
P0A-08	Selection of CAN communication rate	0-1M 1-800K 2-500K 3-250K 4-125K 5-100K 6-50K 7-20K	1	2	★
P0A-13	If communication write in function code update to EEPROM	0-don't update EEPROM 1-update EEPROM	1	1	☆
P0A-14	Modbus error code	0x0001 illegality function(command code) 0x0002 illegality data address 0x0003 illegality data 0x0004 slave station equipment fault	—	—	—
P0A-25	MODBUS response delay	0~5000ms	1	1	☆
P0A-26	MODBUS 32 bits function code's byte order	0-High 16 bits at front, low 16 bits at back 1-Low 16 bits at front, high 16 bits at back	1	0	☆

P0B-00	Actual motor rotate speed	—	1rpm	—	—
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P0B-01	Target speed	—	1rpm	—	—
P0B-02	Interior torque command (relative to rated torque)	—	0.1%	—	—
P0B-03	Input signal monitor DI	—	—	—	—
P0B-05	Output signal monitor DI	—	—	—	—
P0B-07	Absolute position counter (32 bits)	—	1 command unit	—	—
P0B-09	Mechanical angle (pulse start from origin)	—	1p	—	—
P0B-10	Rotate angle (electrical angle)	—	0.1degree	—	—
P0B-11	Input position command corresponding to given speed	—	1rpm	—	—
P0B-12	Average load rate	—	0.10%	—	—
P0B-13	Position command pulse counter (32bits)	—	1 command unit	—	—
P0B-15	Position deviation counter	—	1p	—	—
P0B-17	Feedback pulse counter (32bits)	—	1p	—	—
P0B-19	Power on times (32bits)	—	0.1s	—	—
P0B-21	AI1 sampling voltage value	—	1mV	—	—
P0B-22	AI2 sampling voltage value	—	1mV	—	—
P0B-24	Effective value of phase current	—	0.01A	—	—
P0B-26	Bus voltage	—	0.1V	—	—
P0B-27	Module temperature	—	1℃	—	—
P0B-33	Fault display record	0-current fault 1-latest 1 fault 2-latest 2 faults 9-latest 9 faults	1	0	☆
P0B-34	Fault code	—	—	—	—
P0B-35	Fault time	—	0.1s	—	—
P0B-37	Motor rotate speed during fault	—	1rpm	—	—
P0B-38	U phase current during fault	—	0.01A	—	—
P0B-39	V phase current during fault	—	0.01A	—	—
P0B-40	Bus voltage during fault	—	0.1V	—	—
P0B-41	DI state during fault	—	—	—	—

P0B-42	DO status during fault	—	—	—	—
P0B-60	Motor absolute position during power on (low 32bits)	—	1	—	—
P0B-62	Motor absolute position during power on (high 32bits)	—	1	—	—

P0D-01	Fault reset	0-no operation 1-fault reset	1	0	☆
P0D-02	Rotational inertia identification	1-enable	—	—	—
P0D-03	Encoder initial angle identification	0-no operation 1-Identification enable	1	0	☆
P0D-05	Emergency stop	0-No operation 1-Emergency stop	1	0	☆
P0D-10	Analog channel zero drift automatic adjustment	0-No operation 1-AI1 adjust 2-AI2 adjust	1	0	☆
P0D-11	JOG function	0-No operation 1-JOG enable	—	—	—
P0D-20	Absolute encoder reset enable	0-No operation 1-Fault reset	1	0	☆

P0E-00	Encoder feedback mode	0-interior encoder feedback 1-external encoder feedback 2-process interior/ external position close loop switch during electronic gear switch	1	0	Power on next time
P0E-01	External encoder usage mode	0-Same as current running direction 1-Different as current running direction	1	0	Power on next time
P0E-02	External encoder pulse when motor rotate a lap	0 ~ 1073741824	1 pulse unit	10000	Power on next time
P0E-04	Setting of full closed loop position deviation is too large	0 ~ 1073741824	1 pulse unit	10000	Effective immediately
P0E-06	Full closed loop control deviation clear setting	0 ~ 100	turn	0	Effective immediately
P0E-07	Filter time of position deviation	0~6553.5	0.1ms	0	Effective immediately
P0E-16	Full closed loop position deviation counter	-1073741824~1073741824	1 pulse unit	0	—

P0E-18	Interior encoder pulse feedback	-1073741824~1073741824	1 pulse unit	0	—
P0E-20	External encoder pulse feedback	-1073741824~1073741824	1 pulse unit	0	—

P10-00	Multistage position running mode	0-Stop after single run end(P1001 switch segment) 1-Cycle run(P1001 switch segment) 2-DI switch run(DI switch) 3-Order to run(P1001 switch segment,P1005 switch initial segment)	1	1	
P10-01	Selection of segment	1~16	1	1	
P10-02	Running mode of residual segment	0-Continue running residual segment 1-Start running from first segment	1	0	
P10-03	Waiting time unit	0-ms 1-s	1	0	
P10-04	Selection of displacement command type	0-Relative displacement command 1-Absolute displacement command	1	0	
P10-05	Initial segment selection when cycle running in order	0~16	1	0	☆
P10-12	First displacement	-1073741824 ~ 1073741824(command unit)	1 command unit	10000 command unit	
P10-14	First maximum running speed	1rpm~9000rpm	rpm	200	
P10-15	First acceleration/deceleration time	0~65535	1ms(1s)	10	
P10-16	Waiting time after first segment complete	0~10000	1ms(1s)	10	
P10-17	Second displacement	-1073741824 ~ 1073741824(command unit)	1 command unit	10000 command unit	
P10-19	Second maximum running speed	1rpm~9000rpm	rpm	200	
P10-20	Second acceleration/deceleration time	0~65535	1ms(1s)	10	
P10-21	Waiting time after second segment complete	0~10000	1ms(1s)	10	
P10-22	Third displacement	-1073741824 ~	1 command	10000 command	

		1073741824(command unit)	unit	unit
P10-24	Third maximum running speed	1rpm~9000rpm	rpm	200
P10-25	Third acceleration/deceleration time	0~65535	1ms(1s)	10
P10-26	Waiting time after third segment complete	0~10000	1ms(1s)	10
P10-27	4th displacement	-1073741824 ~ 1073741824(command unit)	1 command unit	10000 command unit
P10-29	4th maximum running speed	1rpm~9000rpm	rpm	200
P10-30	4th acceleration/deceleration time	0~65535	1ms(1s)	10
P10-31	Waiting time after 4th segment complete	0~10000	1ms(1s)	10
P10-32	5th displacement	-1073741824 ~ 1073741824(command unit)	1 command unit	10000 command unit
P10-34	5th maximum running speed	1rpm~9000rpm	rpm	200
P10-35	5th acceleration/deceleration time	0~65535	1ms(1s)	10
P10-36	Waiting time after 5th segment complete	0~10000	1ms(1s)	10
P10-37	6th displacement	-1073741824 ~ 1073741824(command unit)	1 command unit	10000 command unit
P10-39	6th maximum running speed	1rpm~9000rpm	rpm	200
P10-40	6th acceleration/deceleration time	0~65535	1ms(1s)	10
P10-41	Waiting time after 6th segment complete	0~10000	1ms(1s)	10
P10-42	7th displacement	-1073741824 ~ 1073741824(command unit)	1 command unit	10000 command unit
P10-44	7th maximum running speed	1rpm~9000rpm	rpm	200
P10-45	7th acceleration/deceleration time	0~65535	1ms(1s)	10
P10-46	Waiting time after 7th segment complete	0~10000	1ms(1s)	10
P10-47	8th displacement	-1073741824 ~ 1073741824(command unit)	1 command unit	10000 command unit
P10-49	8th maximum running speed	1rpm~9000rpm	rpm	200
P10-50	8th	0~65535	1ms(1s)	10

	acceleration/deceleration time			
P10-51	Waiting time after 8th segment complete	0~10000	1ms(1s)	10
P10-52	9th displacement	-1073741824 ~ 1073741824(command unit)	1 command unit	10000 command unit
P10-54	9th maximum running speed	1rpm~9000rpm	rpm	200
P10-55	9th acceleration/deceleration time	0~65535	1ms(1s)	10
P10-56	Waiting time after 9th segment complete	0~10000	1ms(1s)	10
P10-57	10th displacement	-1073741824 ~ 1073741824(command unit)	1 command unit	10000 command unit
P10-59	10th maximum running speed	1rpm~9000rpm	rpm	200
P10-60	10th acceleration/deceleration time	0~65535	1ms(1s)	10
P10-61	Waiting time after 10th segment complete	0~10000	1ms(1s)	10
P10-62	11th displacement	-1073741824 ~ 1073741824(command unit)	1 command unit	10000 command unit
P10-64	11th maximum running speed	1rpm~9000rpm	rpm	200
P10-65	11th acceleration/deceleration time	0~65535	1ms(1s)	10
P10-66	Waiting time after 11th segment complete	0~10000	1ms(1s)	10
P10-67	12th displacement	-1073741824 ~ 1073741824(command unit)	1 command unit	10000 command unit
P10-69	12th maximum running speed	1rpm~9000rpm	rpm	200
P10-70	12th acceleration/deceleration time	0~65535	1ms(1s)	10
P10-71	Waiting time after 12th segment complete	0~10000	1ms(1s)	10
P10-72	13th displacement	-1073741824 ~ 1073741824(command unit)	1 command unit	10000 command unit
P10-74	13th maximum running speed	1rpm~9000rpm	rpm	200
P10-75	13th acceleration/deceleration time	0~65535	1ms(1s)	10
P10-76	Waiting time after 13th segment	0~10000	1ms(1s)	10

	complete			
P10-77	14th displacement	-1073741824 1073741824(command unit) ~	1 command unit	10000 command unit
P10-79	14th maximum running speed	1rpm~9000rpm	rpm	200
P10-80	14th acceleration/decele ration time	0~65535	1ms(1s)	10
P10-81	Waiting time after 14th segment complete	0~10000	1ms(1s)	10
P10-82	15th displacement	-1073741824 1073741824(command unit) ~	1 command unit	10000 command unit
P10-84	15th maximum running speed	1rpm~9000rpm	rpm	200
P10-85	15th acceleration/decele ration time	0~65535	1ms(1s)	10
P10-86	Waiting time after 15th segment complete	0~10000	1ms(1s)	10
P10-87	16th displacement	-1073741824 1073741824(command unit) ~	1 command unit	10000 command unit
P10-89	16th maximum running speed	1rpm~9000rpm	rpm	200
P10-90	16th acceleration/decele ration time	0~65535	1ms(1s)	10
P10-91	Waiting time after 16th segment complete	0~10000	1ms(1s)	10

Group 11:Multistage speed control parameters				
P11-00	Multistage speed command running mode	0-Stop after single run end(P1101 switch segment) 1-Cycle run(P1101 switch segment) 2-Use external DI switch	1	1
P11-01	Selection of speed command segment	1~16	1	16
P11-02	Selection of running time unit	0-sec 1-min	1	0
P11-03	Acceleration time 1	0ms~65535ms	1ms	10ms
P11-04	Deceleration time 1	0ms~65535ms	1ms	10ms
P11-05	Acceleration time2	0ms~65535ms	1ms	50ms
P11-06	Deceleration time 2	0ms~65535ms	1ms	50ms
P11-07	Acceleration time 3	0ms~65535ms	1ms	100ms
P11-08	Deceleration time 3	0ms~65535ms	1ms	100ms
P11-09	Acceleration time 4	0ms~65535ms	1ms	150ms
P11-10	Deceleration time 4	0ms~65535ms	1ms	150ms
P11-20	First running speed	-9000~+9000rpm	1rpm	0rpm

☆

P11-21	First running time	0~6553.5	0.1s(m)	5.0s(m)
P11-22	First acceleration/deceleration time	0-zero acceleration/deceleration time 1- acceleration/deceleration time 1 2- acceleration/deceleration time 2 3- acceleration/deceleration time 3 4- acceleration/deceleration time 4	1	0
P11-23	Second running speed	-9000~+9000rpm	1rpm	100rpm
P11-24	Second running time	0~6553.5	0.1s(m)	5.0s(m)
P11-25	Second acceleration/deceleration time	Same as P11-22	1	0
P11-26	Third running speed	-9000~+9000rpm	1rpm	300rpm
P11-27	Third running time	0~6553.5	0.1s(m)	5.0s(m)
P11-28	Third acceleration/deceleration time	Same as P11-22	1	0
P11-29	4th running speed	-9000~+9000rpm	1rpm	500rpm
P11-30	Second running time	0~6553.5	0.1s(m)	5.0s(m)
P11-31	4th acceleration/deceleration time	Same as P11-22	1	0
P11-32	5th running speed	-9000~+9000rpm	1rpm	700rpm
P11-33	5th running time	0~6553.5	0.1s(m)	5.0s(m)
P11-34	5th acceleration/deceleration time	Same as P11-22	1	0
P11-35	6th running speed	-9000~+9000rpm	1rpm	900rpm
P11-36	6th running time	0~6553.5	0.1s(m)	5.0s(m)
P11-37	6th acceleration/deceleration time	Same as P11-22	1	0
P11-38	7th running speed	-9000~+9000rpm	1rpm	600rpm
P11-39	7th running time	0~6553.5	0.1s(m)	5.0s(m)
P11-40	7th acceleration/deceleration time	Same as P11-22	1	0
P11-41	8th running speed	-9000~+9000rpm	1rpm	300rpm
P11-42	8th running time	0~6553.5	0.1s(m)	5.0s(m)
P11-43	8th acceleration/deceleration time	Same as P11-22	1	0
P11-44	9th running speed	-9000~+9000rpm	1rpm	100rpm
P11-45	9th running time	0~6553.5	0.1s(m)	5.0s(m)
P11-46	9th acceleration/deceleration time	Same as P11-22	1	0
P11-47	10th running speed	-9000~+9000rpm	1rpm	-100rpm
P11-48	10th running time	0~6553.5	0.1s(m)	5.0s(m)
P11-49	10th acceleration/deceleration time	Same as P11-22	1	0

P11-50	11th running speed	-9000~+9000rpm	1rpm	-300rpm	
P11-51	11th running time	0~6553.5	0.1s(m)	5.0s(m)	
P11-52	11th acceleration/deceleration time	Same as P11-22	1	0	
P11-53	12th running speed	-9000~+9000rpm	1rpm	-500rpm	
P11-54	12th running time	0~6553.5	0.1s(m)	5.0s(m)	
P11-55	12th acceleration/deceleration time	Same as P11-22	1	0	
P11-56	13th running speed	-9000~+9000rpm	1rpm	-700rpm	
P11-57	13th running time	0~6553.5	0.1s(m)	5.0s(m)	
P11-58	13th acceleration/deceleration time	Same as P11-22	1	0	
P11-59	14th running speed	-9000~+9000rpm	1rpm	-900rpm	
P11-60	14th running time	0~6553.5	0.1s(m)	5.0s(m)	
P11-61	14th acceleration/deceleration time	Same as P11-22	1	0	
P11-62	15th running speed	-9000~+9000rpm	1rpm	-600rpm	
P11-63	15th running time	0~6553.5	0.1s(m)	5.0s(m)	
P11-64	15th acceleration/deceleration time	Same as P11-22	1	0	
P11-65	16th running speed	-9000~+9000rpm	1rpm	-300rpm	
P11-66	16th running time	0~6553.5	0.1s(m)	5.0s(m)	
P11-67	16th acceleration/deceleration time	Same as P11-22	1	0	
P1D-00	Motor code	0~65535	-	-	★

Chapter 7 Communication Protocol

7.1 Selection of MODBUS parameters

MODBUS communication mainly set slave station address, communication rate and data format, respectively relative to function code parameters:P0A-00,P0A-02,P0A-03,see chapter 6.1 for details.

7.2 MODBUS protocol

All ID is 1 as below all example:

A. Read P04-00 parameter, p04-00=0

Request		Example		Return value	
Slave station	ID	Slave station address	01	Slave station address	01
Function	03	Function	03	Function	03
Register high level address	ADDR(H)	Register high level address	04	Byte	01
Register low level address	ADDR(L)	Register low level address	00	Register Hi (1025)	00
Byte	0x 01~0x 2E	Byte	00 01	Register Lo (1025)	00
Check code	CRC(L)+CRC(H)	Check code	CRC(L)+CRC(H)	Check code	CRC(L)+CRC(H)

B. Write P04-00(16 bits) parameter, write value as 2

Request		Example		Return value	
Slave station	ID	Slave station address	01	Slave station address	01
Function	06	Function	06	Function	06
Register high level address	ADDR(H)	Register high level address	04	Register high level address	04
Register low level address	ADDR(L)	Register low level address	00	Register low level address	00
Register value Hi	DATA(H)	Register value Hi	00	Register value Hi	00
Register value Lo	DATA(L)	Register value Lo	02	Register value Lo	02
Check code	CRC(L)+CRC(H)	Check code	CRC(L)+CRC(H)	Check code	CRC(L)+CRC(H)

C. Write p04-07(32 bits) parameter, write value as 5000

Request		Example		Return value	
Slave station	ID	Slave station address	01	Slave station address	01
Function	10	Function	10	Function	10
Register high level address	ADDR(H)	Register high level address	04	Register high level address	04
Register low level address	ADDR(L)	Register low level address	07	Register low level address	07
Byte	0x02	Byte	02	Byte	02
Register value Hi	DATA(H)	Register value Hi	13	Check code	CRC(L)+CRC(H)
Register value Lo	DATA(L)	Register value Lo	88		
Register value Hi	DATA(H)	Register value Hi	00		
Register value Lo	DATA(L)	Register value Lo	00		
Check code	CRC(L)+CRC(H)	Check code	CRC(L)+CRC(H)		

Note:32 bits default decoding order is1234

D. Command fault return data:

ID+ (Command + 0x80) + fault code + CRC(L) + CRC(H)

Error code	
1	Invalid command code
2	Invalid function code address
3	Invalid data
4	Slave station fault

example: upper computer send: 0x01+0x03+0xff+0xff+0x00+0x01+0x84+0x2E

servo return value: 0x01+0x83+0x02+0xC0+0xF1

express data function code address sent by upper computer is invalid

Chapter 8 Maintenance and Inspection

8.1 Abnormality diagnosis and treatment measures

8.1.1 Alarm display list

The relationship between the alarm display and the alarm code output ON / OFF is shown in Table 7.1. When alarm occurs, the motor's stopping methods includes the following two.

- DB Stop: Emergency stop method using dynamic brake to stop the motor
- Coast to stop: not have to brake, the natural stopping method due to the motor rotation's frictional resistance.

Table 8.1 alarm display and output list

Alarm display	Alarm name	Alarm content	Alarm reset	Servo alarm (ALM) output
Er.001	parameter error	Servo unit EEPROM data error	NO	H
Er.004	FPGA running error	FPGA's clock, interrupt, calculation error	NO	H
Er.005	Parameter setting error	Exceed the setting range of the user parameter value	NO	H
Er.010	Matching error	Encoder, servo motor or the capacity of servo unit do not match	NO	H
Er.011	Function code parameter save error	Write/read operation of EEPROM error	NO	H
Er.012	Function code over range	Function code parameters of factory unreasonable setting	NO	H
Er.020	Software over current	Drive's output current is too large	NO	H
Er.021	Hardware over current	IGBT's output current is too large	NO	H
Er.022	Driver's output short-circuit to ground	Driver's output wire or motor power wire short-circuit to ground	NO	H
Er.023	UVW phase sequence error	UVW three-phase wiring error, change any two phase	NO	H
Er.024	Speed loss fault	Motor occur galloping, speed is out of control	NO	H
Er.030	Control voltage error	Control power bus under voltage	NO	H
Er.040	Encoder fault	Encoder signal Z, absolute encoder communication error	NO	H
Er.050	AI input voltage is too large	AI input voltage is too large and over 11.5V	NO	H
Er.061	Encoder break line error	Encoder not match or communication line is break	NO	H
Er.062	Incremental encoder signal Z loss	Signal Z is not captured	NO	H
Er.100	DI function repeat distribution	Group P2 function code unreasonable setting	YES	H
Er.101	DO function assignment repeated	Group P3 function code unreasonable setting	YES	H
Er.111	Bus overvoltage	The main circuit DC voltage is abnormally high	YES	H
Er.112	Bus undervoltage	The main circuit DC voltage is abnormally low	YES	H

Er. 113	Overspeed	The number of revolutions of the servo motor is abnormally high	YES	H
Er. 116	Angle self-learning fault	Initial angle identify failure	YES	H
Er. 200	Servo running enable fault	Angle self-learning, off-line inertia identification can't running	YES	H
Er. 201	STO enable	STO signal is valid	YES	H
Er. 210	Input phase loss fault	One phase of three phase main circuit's power is not connected	YES	H
Er. 211	Driver overload	Use torque which over rated value to run continuously	YES	H
Er. 212	Frequency dividing output over-speed	Frequency division output speed is too large	YES	H
Er. 213	Motor overload fault	Use current which over rated value to run continuously	YES	H
Er. 214	Motor locked-rotor	Motor shaft is stuck or load is too large can't rotate	YES	H
Er. 215	Cooling fin overheat	Cooling fin of servo unit overheat	YES	H
Er. 220	Encoder battery fault	Absolute encoder battery fault	YES	H
Er. 221	Encoder count error	Absolute encoder count error	YES	H
Er. 222	Encoder multi-circle count overflow	Absolute encoder multi-circle count overflow	YES	H
Er. 230	Electric gear ratio set error	Parameters of electronic gear ratio unreasonable setting, 0.001~4000	YES	H
Er. 250	Position deviation is too large	Offset pulse exceed the setting value of user parameter	YES	H
Er. 251	Position pulse input is too large	Pulse frequency exceed maximum value set by user	YES	H
Er. 252	Full closed loop position deviation is too large	Offset pulse exceed the setting value of user parameter	YES	H
Er. 300	Frequency dividing output setting fault	Pulse dividing setting exceed motor encoder line number	YES	H
Er. 301	Origin point back to zero overtime fault	No valid limit switch signal or searching time is too long	YES	H
Er. 302	AI zero offset too large fault	AI wiring error or zero drift exceed 50mV because of interference	YES	H
Er. 303	Emergency shut down warning	Detected DI emergency shut signal valid	YES	H
Er. 310	Regeneration overload warning	Brake resistance bad contact rotate speed is too high or load is too large cause brake resistance overload	YES	H
Er. 312	External brake resistance is too small	External brake resistance less than value asked by driver	YES	H
Er. 313	Motor power line break	Motor power line don't connect good or it has broken	YES	H
Er. 315	Motor overload warning	Load is too large or frequent acceleration/deceleration cause motor overload	YES	H
Er. 320	Power restart	Modify the function code parameter which need power restart	YES	H
Er. 322	Motor forward over range	Detected forward over-range DI signal vaild	YES	H
Er. 323	Motor reverse over-range	Detected reverse over-range DI signal vaild	YES	H
Er. 324	Input phase loss warning	One phase of three phase main circuit's power is not connected	YES	H

8.1.2 The causes and treatment measures for the alarm display

If the servo drive has bad situation, then there will be an alarm on the operator panel display Er.XXX. Alarm display and treatment measures are as follows. After processing, if you still do not solve the bad situation, please contact our service department. Table 8.2 is a list of alarm display.

Table 8.2 Causes and treatment measures to the alarm display

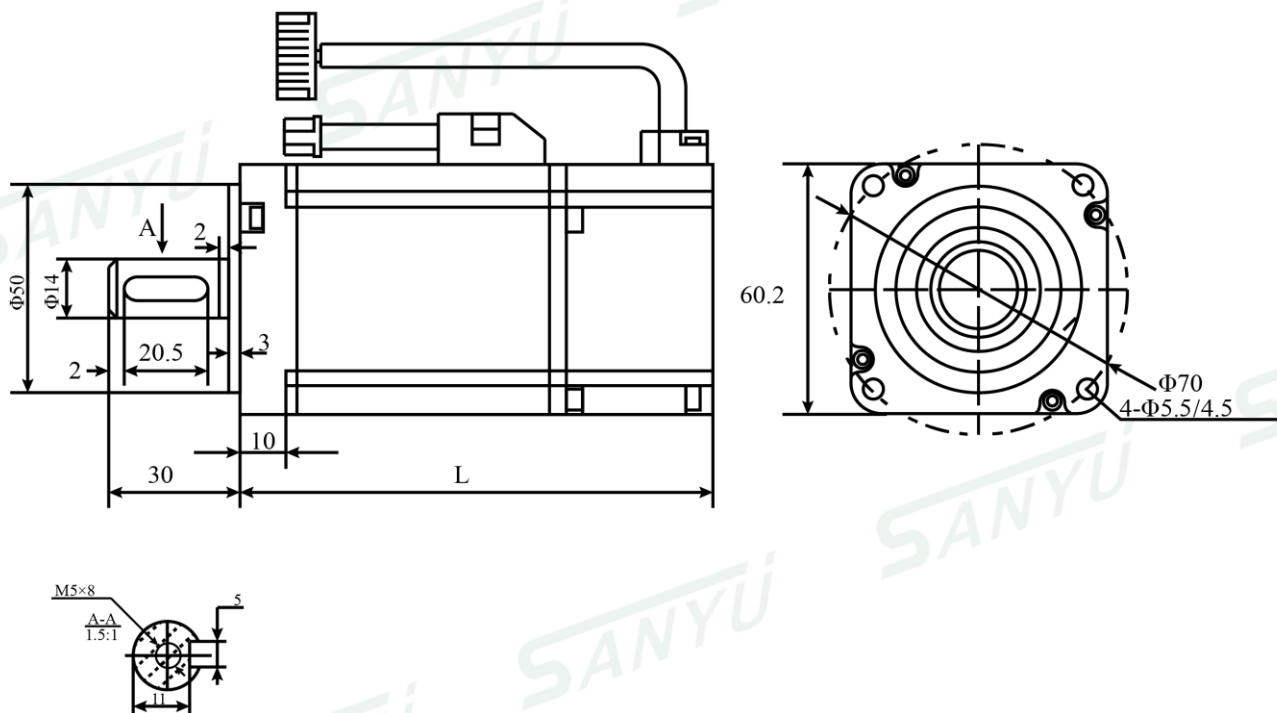
Alarm	Alarm contents	Causes and treatment measures
Er.001	Parameter error	Set P01-31=1, restore factory setting
Er.004	FPGA running error	FPGA internal error, if restart can't solve, please contact manufacturer
Er.005	Parameter setting error	Set P01-31=1, restore factory setting
Er.010	Matching error	Inspect if motor, driver type is correct, contact manufacturer;
Er.011	Function code parameter save error	EEPROM error, contact manufacturer.
Er.012	Function code over range	Function code parameters of factory unreasonable setting.
Er.020	Software over current	Drive's output current greater than flow point set
Er.021	Hardware over current	Brake resistance is too small, pulse command is too fast, output short circuit and so on.
Er.022	Drive's output short-circuit to ground	UVW wiring short-circuit to ground, wiring again or change cable; Motor short-circuit to ground, please change motor.
Er.023	UVW phase sequence error	UVW three phase wiring error, change any two phase
Er.024	Speed loss fault	Load drag, UVW phase error, encoder cable loose and so on.
Er.030	Control voltage error	Control power unstable or bad contact
Er.040	Encoder fault	Encoder signal interference, absolute encoder bad contact or wiring error
Er.050	AI input voltage is too large	AI input voltage is too high or interference is serious.
Er.061	Encoder break line error	Encoder don't match driver or communication wire is break
Er.062	Incremental encoder signal Z loss	Encoder wire bad contact, wiring error or encoder is damaged
Er.100	DI function repeat distribution	Set DI function parameters in group P2 correctly, restore factory settings
Er.101	DO function repeat distribution	Set DO function parameters in group P3 correctly, restore factory settings
Er.111	BUS over voltage	Input voltage is too high; Brake resistance is too small or loss efficacy; Motor decelerate time is too little; Sampling circuit fault
Er.112	BUS under voltage	Input voltage is too low or instantaneous power down
Er.113	Over speed	UVW phase error, P09-08 parameter unreasonable setting; input command too fast;
Er.116	Angle self-learning fault	Initial angle identification failure
Er.200	Servo running enable	Set DI servo enable signal invalid

	fault	
Er. 201	STO enable	STO signal is valid
Er. 210	Input phase loss fault	Input voltage is too low or wiring bad
Er. 211	Driver overload	Use torque which over rated value to run continuously, accumulation of heat is too large.
Er. 212	Frequency dividing output over-speed	Decrease pulse frequency dividing number P0417; decrease input pulse frequency
Er. 213	Motor overload fault	Driver/motor type error; Frequent acceleration and deceleration can increase acceleration and deceleration time; load is too large
Er. 214	Motor locked-rotor	Motor shaft is stuck or load is too large that can't rotate; UVW wiring error or output break line; encoder break line
Er. 215	Cooling fin overheat	Lowering ambient temperature; Check if fan is working; Check if driver's air intake and air outlet is well-ventilated;
Er. 220	Encoder battery error	Encoder battery is not connected or voltage is too low
Er. 221	Encoder count error	Absolute encoder count error
Er. 222	Encoder multi-circle count overflow	Absolute encoder multi-circle count overflow
Er. 230	Electronic gear ratio set error	Parameters of electronic gear ratio unreasonable setting, please reset to 0.001~4000
Er. 250	Position deviation is too large	Motor locked-rotor; Input pulse frequency is too high; Setting deviation threshold P09-10 is too small; UVW output break line or loss phase; Encoder break line
Er. 251	Position pulse input is too large	Pulse frequency exceed maximum value P09-09 set by user
Er. 252	Full closed loop position deviation is too large	Motor locked-rotor; Input pulse frequency is too high; Setting deviation threshold P0E-08 is too small; UVW output break line or loss phase; Encoder break line
Er. 300	Frequency dividing output setting fault	Pulse dividing setting exceed motor encoder line number, reset P04-17
Er. 301	Origin point back to zero overtime fault	No valid limit switch signal or searching time too long, please confirm DI input is valid; Searching time is too long, please increase P04-35 original point searching time
Er. 302	AI zero offset too large fault	AI wiring error or zero drift exceed 50mV because of interference
Er. 303	Emergency shutdown warning	Detected DI emergency shut signal valid
Er. 310	Regeneration overload warning	Brake resistance has a bad contact or a external brake resistance which is larger; Deceleration time is too short when rotate speed is too high; Load is too large
Er. 312	External brake resistance is too small	Change to bigger brake resistance and set P01-27 correctly.
Er. 313	Motor power line break	Motor power line don't connect good or it has broken
Er. 315	Motor overload warning	Driver/motor type error; Frequent acceleration and deceleration can increase acceleration and deceleration time; load is too large;
Er. 320	Power restart	Modify the function code which need power restart, power on again
Er. 322	Motor forward over	Modify the function code parameter which need power

	range	restart
Er. 323	Motor reverse over range	Detect reverse over range DI signal valid
Er. 324	Input phase loss warning	One phase of three phase main circuit's power is not connected; If use bus joint method, please set P09-00=2.

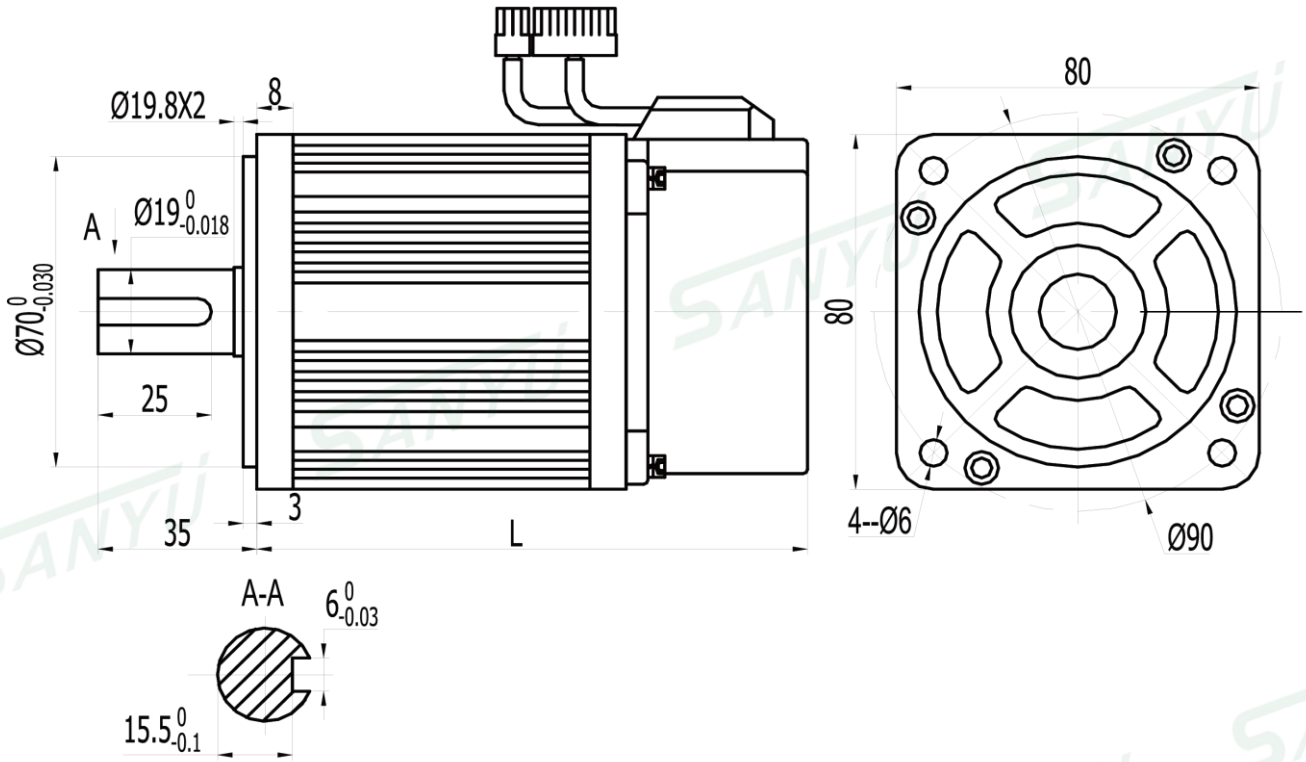
Chapter 9 Motor Adaptation Table

Motor model	Rated power(kW)	Rated line voltage(V)	Rated line Current(A)	Rated speed(rpm)	Rated torque(N M)	Max rated torque(N M)	Rotor inertia (Kg M ²)
SY-60KP20A30□□YYB	0.2	220	1.3	3000	0.64	1.91	0.0264×10^{-3}
SY-60KP40A30□□YYB	0.4	220	2.6	3000	1.3	3.8	0.028×10^{-3}



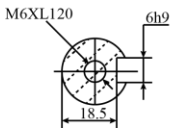
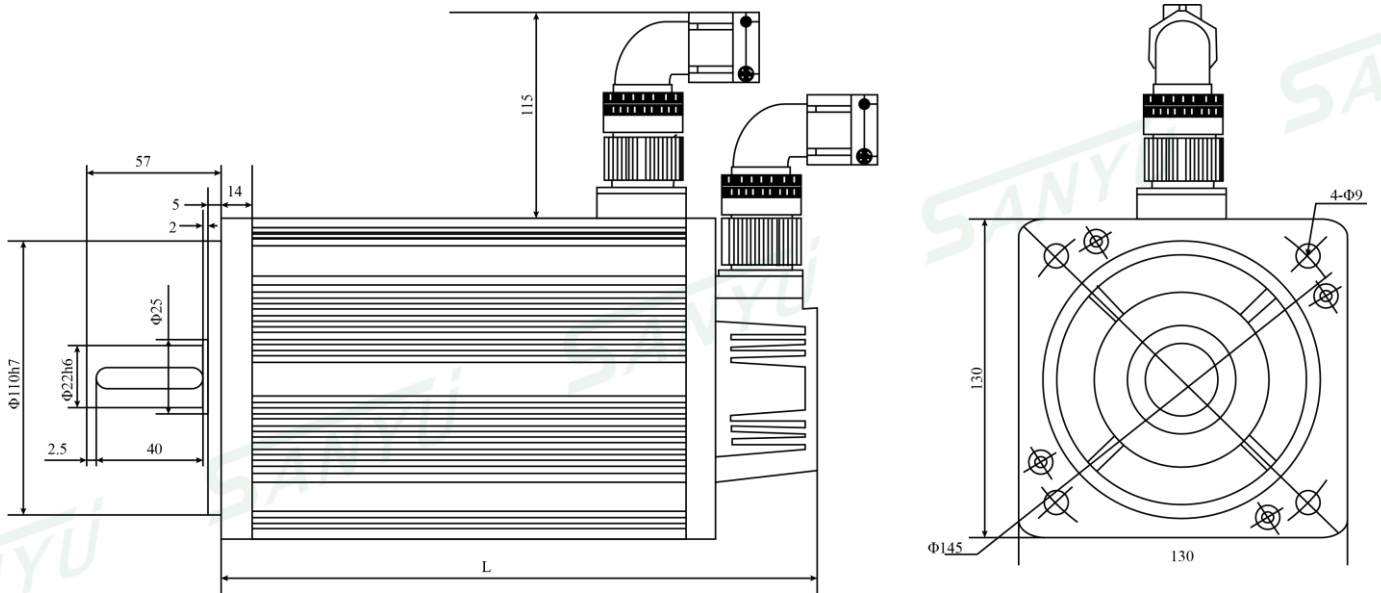
Model	SY-60KP20A30	SY-60KP40A30
Without brake size(L)	109	108

Motor model	Rated power(kW)	Rated line voltage(V)	Rated line Current(A)	Rated speed(rpm)	Rated torque(N M)	Max torque(N M)	Rotor inertia (Kg M ²)
SY-80KP40A30□□YYB	0.4	220	2.0	3000	1.27	3.8	1.05×10^{-4}
SY-80KP75A30□□YYB	0.75	220	4.4	3000	2.39	7.16	0.9×10^{-4}
SY-80KP73A20□□YYB	0.73	220	3.0	2000	3.50	10.5	2.63×10^{-4}
SY-80KP100A25□□YYB	1	220	4.4	2500	4.00	12	2.97×10^{-4}



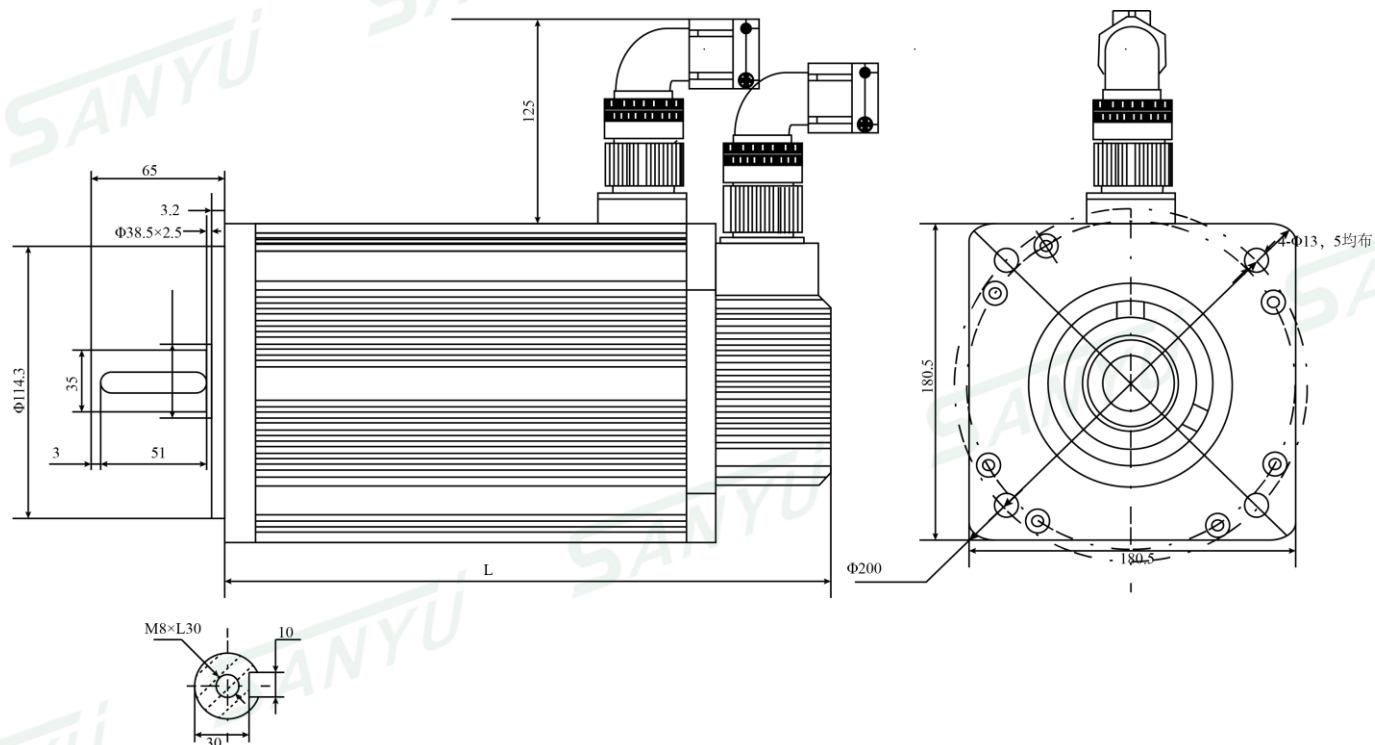
Model	SY-80KP40A30	SY-80KP73A20	SY-80KP75A30	SY-80KP100A25
Without brake size(L)	124	119	122.5	191

Motor model	Rated power(kW)	Rated line voltage(V)	Rated line Current(A)	Rated speed(rpm)	Rated torque(N M)	Max torque(N M)	Rotor inertia (Kg M ²)
SY-130SP100A25□□YYB	1.0	220	4.0	2500	4.0	12	0.85×10^{-3}
SY-130SP100A20□□YYB	1.0	220	5.0	2000	5.0	15	1.06×10^{-3}
SY-130SP150A15□□YYB	1.5	220	6.0	1500	10.0	25	1.94×10^{-3}
SY-130SP150A20□□YYB	1.5	220	7.5	2000	7.7	22	1.53×10^{-3}
SY-130SP150A25□□YYB	1.5	220	6.0	2500	6.0	18	1.26×10^{-3}
SY-130SP200A20□□YYB	2.0	220	10.0	2000	10.0	25	1.94×10^{-3}
SY-130SP200A25□□YYB	2.0	220	7.5	2500	7.7	22	1.53×10^{-3}
SY-130SP200A20□□YYD	2.0	380	6.0	2000	10.0	30	2.77×10^{-3}
SY-130SP200A25□□YYD	2.0	380	6.0	2500	10.0	25	1.94×10^{-3}
SY-130SP380A25□□YYD	3.8	380	8.8	2500	15.0	30	2.77×10^{-3}



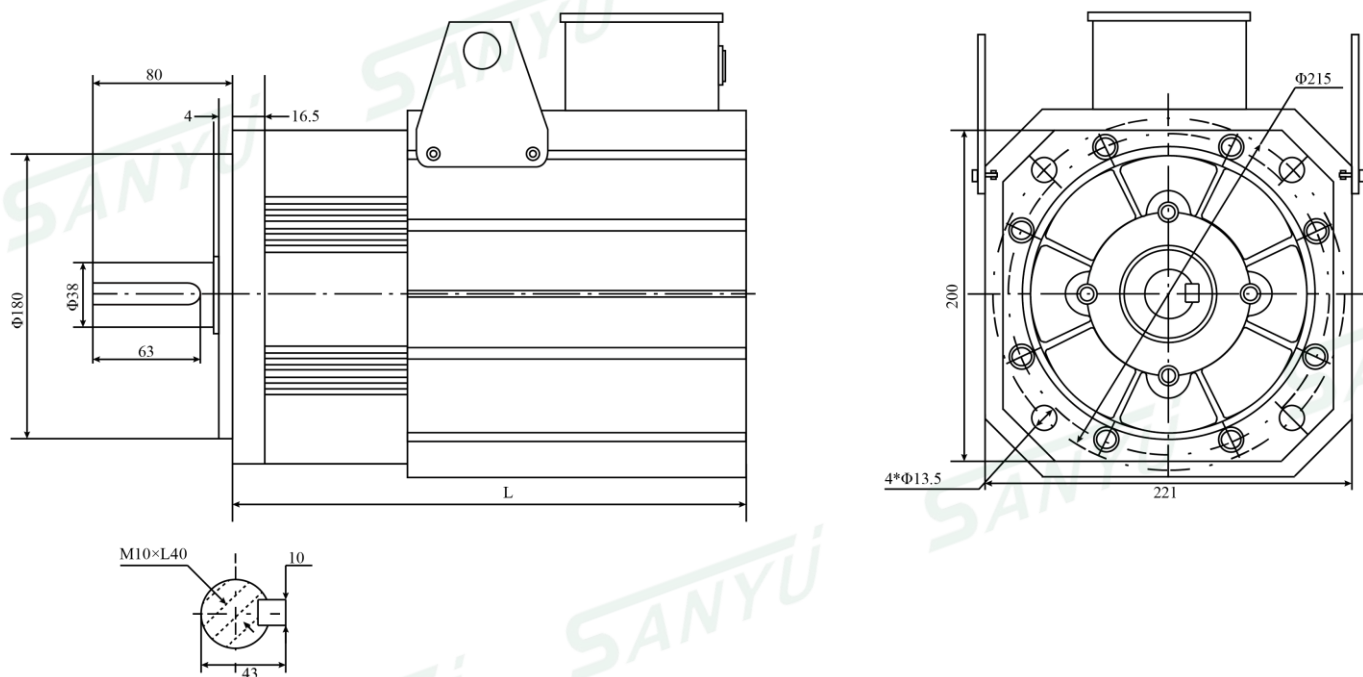
Rated torque(N M)	130 Series						
	4	5	6	7.7	10		15
					1500rpm	2500rpm	2500rpm
Without brake(mm)	166	171	179	192	213	209	231
With electromagnetic brake(mm)	229	234	242	255	294	290	312

Motor model	Rated power(kW)	Rated line voltage(V)	Rated line Current(A)	Rated speed(rpm)	Rated torque(N·M)	Max torque(N·M)	Rotor inertia (Kg·M ²)
SY-180SP300A15□□YYD	3.0	380	7.5	1500	19.0	47	7.0×10^{-3}
SY-180SP400A15□□YYD	4.0	380	10.0	1500	25.5	62	9.64×10^{-3}
SY-180SP450A20□□YYD	4.5	380	9.5	2000	21.5	53	7.96×10^{-3}
SY-180SP450A15□□YYD	4.5	380	10.0	1500	28.0	69	9.64×10^{-3}
SY-180SP550A15□□YYD	5.5	380	12.0	1500	35.0	70	12.25×10^{-3}
SY-180SP750A15□□YYD	7.5	380	20.0	1500	48.0	96	16.72×10^{-3}



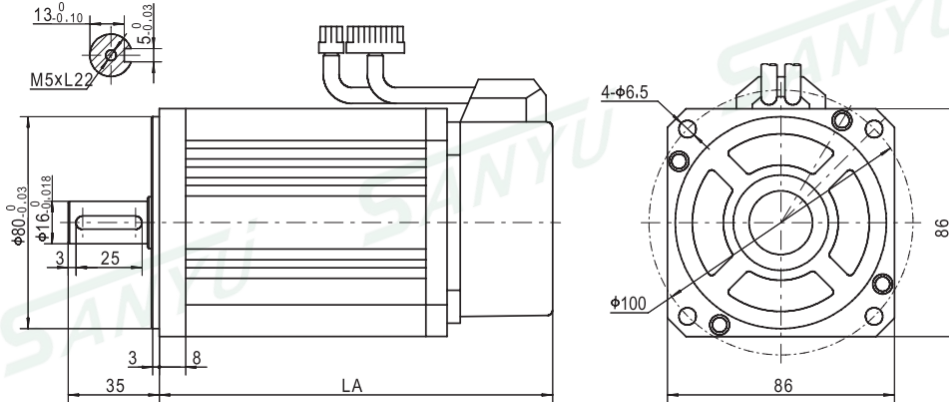
	180 Series					
Rated torque(N·M)	19	21.5	25.5	27	35	48
Without brake(mm)	232	243	262	262	292	346
With electromagnetic brake(mm)	304	315	334	334	364	418

Motor model	Rated power(kW)	Rated line voltage(V)	Rated line Current(A)	Rated speed(rpm)	Rated torque(N M)	Max torque(N M)	Rotor inertia (Kg m ²)
SY-200SP11KA15□□YYD	11	380.0	21	1500	70.0	105	9.77×10 ⁻³
SY-200SP14KA20□□YYD	14.7	380.0	28	2000	70.0	105	9.77×10 ⁻³
SY-200SP17KA20□□YYD	17.6	380.0	32	2000	84.0	126	13.08×10 ⁻³



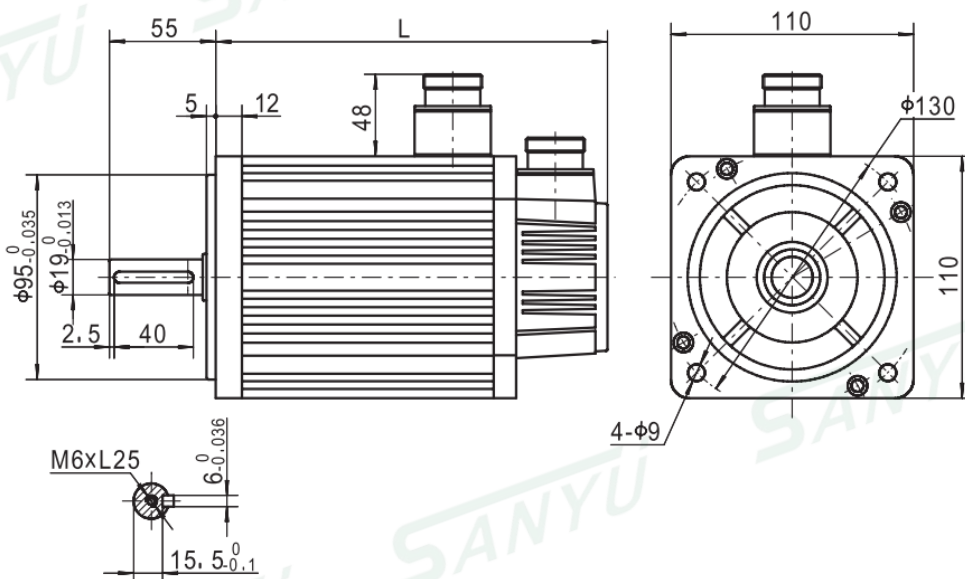
	200 Series	
Rated torque(N M)	70	84
Without brake(mm)	413	451

Motor model	Rated power(kW)	Rated line voltage(V)	Rated line Current(A)	Rated speed(rpm)	Rated torque(N M)	Max torque(N M)	Rotor inertia (Kg M ²)
SY-90KP073A20□□YYB	0.7	220	3.0	2000	3.5	10.5	3.4×10^{-4}
SY-90KP100A25□□YYB	1.0	220	4.0	2500	4.0	12	3.7×10^{-4}



	90 Series	
Torque (N M)	3.5	4
Without electromagnetic brake(mm)	172.0	182
With electromagnetic brake(mm)	214.0	224

Motor model	Rated power(kW)	Rated line voltage(V)	Rated line Current(A)	Rated speed(rpm)	Rated torque(N M)	Max torque(N M)	Rotor inertia (Kg M ²)
SY-110KP120A30□□YYB	1.2	220	5.0	3000	4.0	12	5.4×10^{-4}
SY-110KP180A30□□YYB	1.8	220	6.0	3000	6.0	18	7.6×10^{-4}

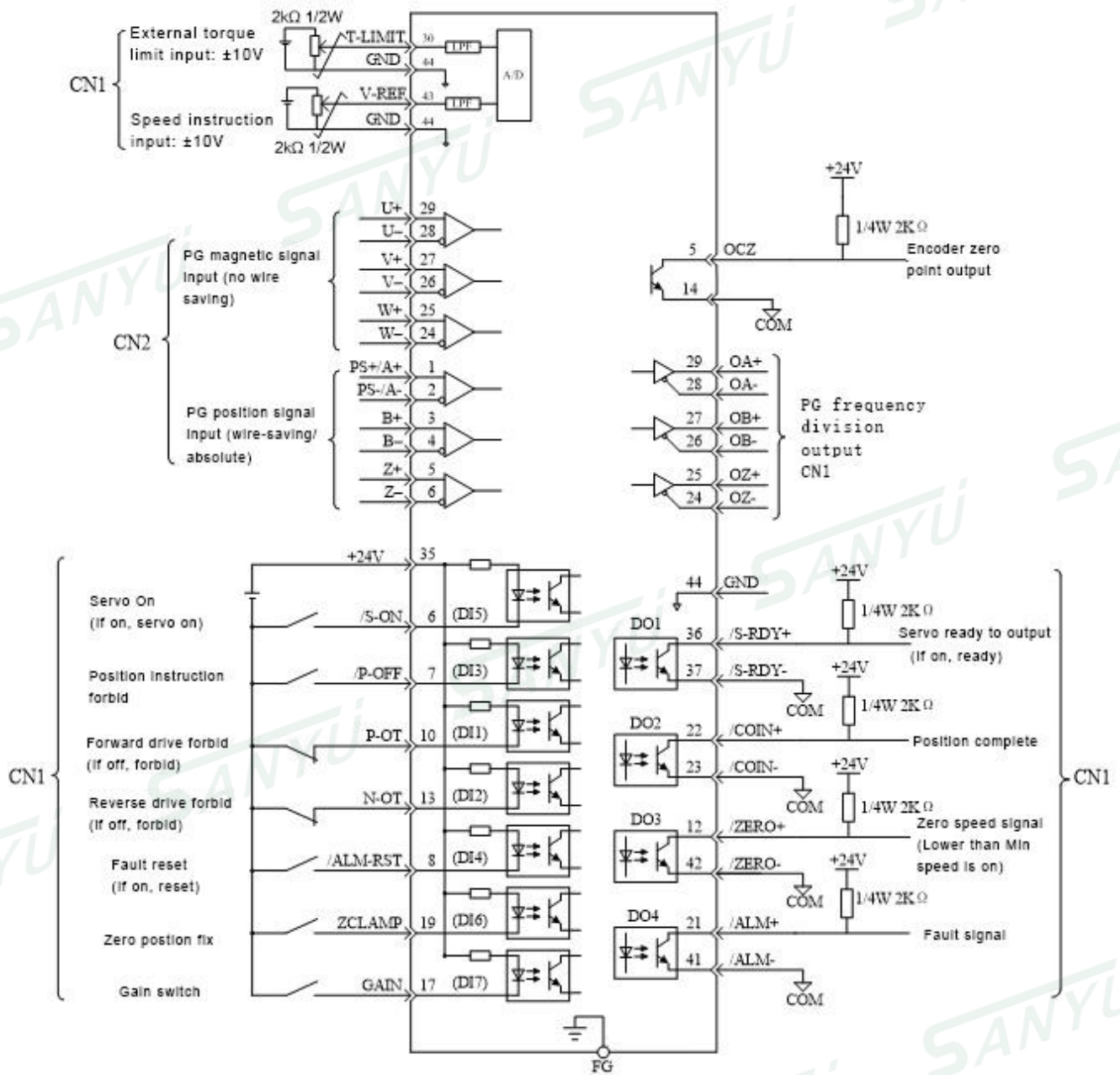


	110 Series	
Torque (N M)	4	6
Without electromagnetic brake(mm)	189	219.0
With electromagnetic brake(mm)	254	284.0

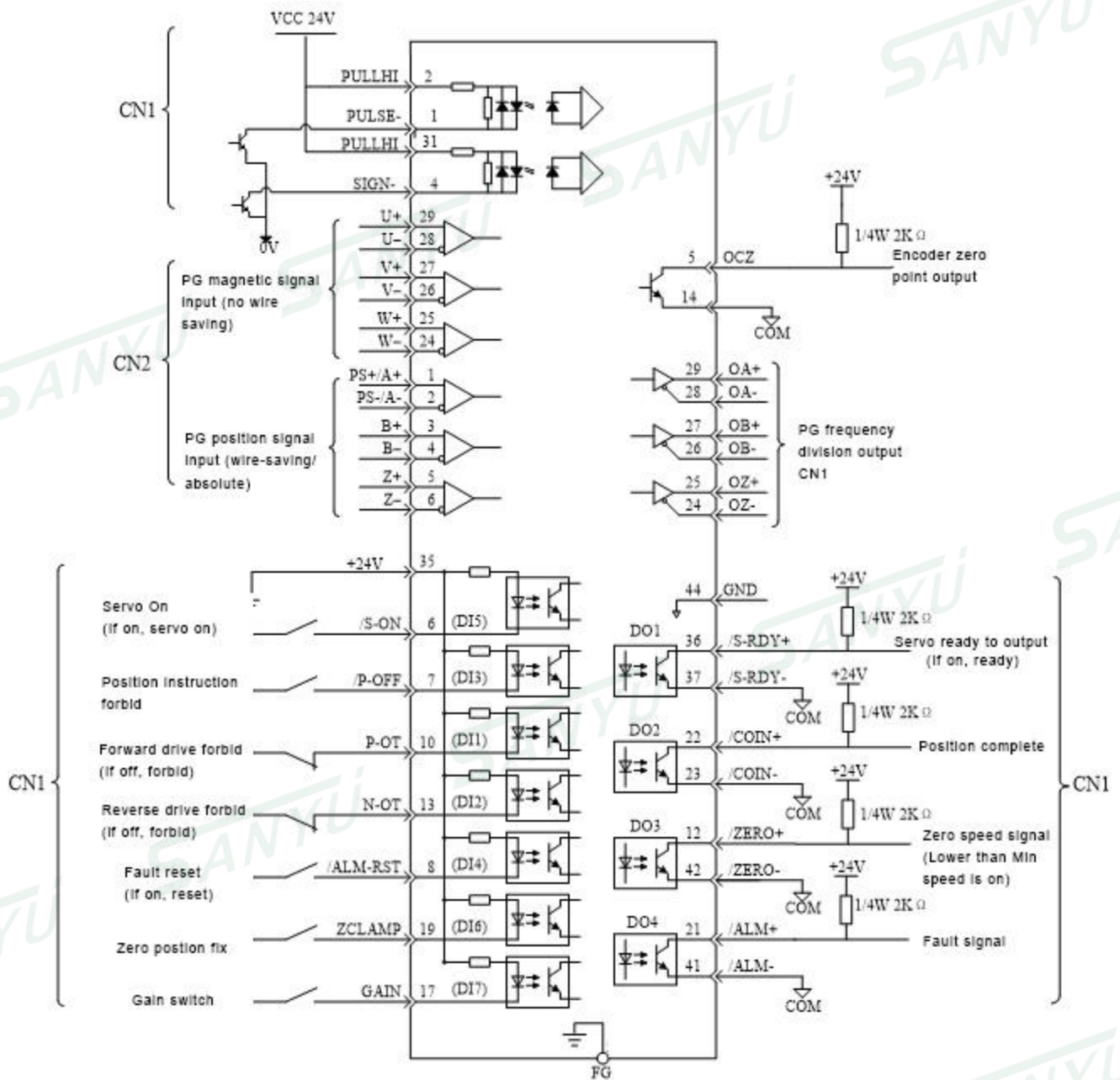
Chapter 10 Appendices

10.1 Standard wiring of control mode

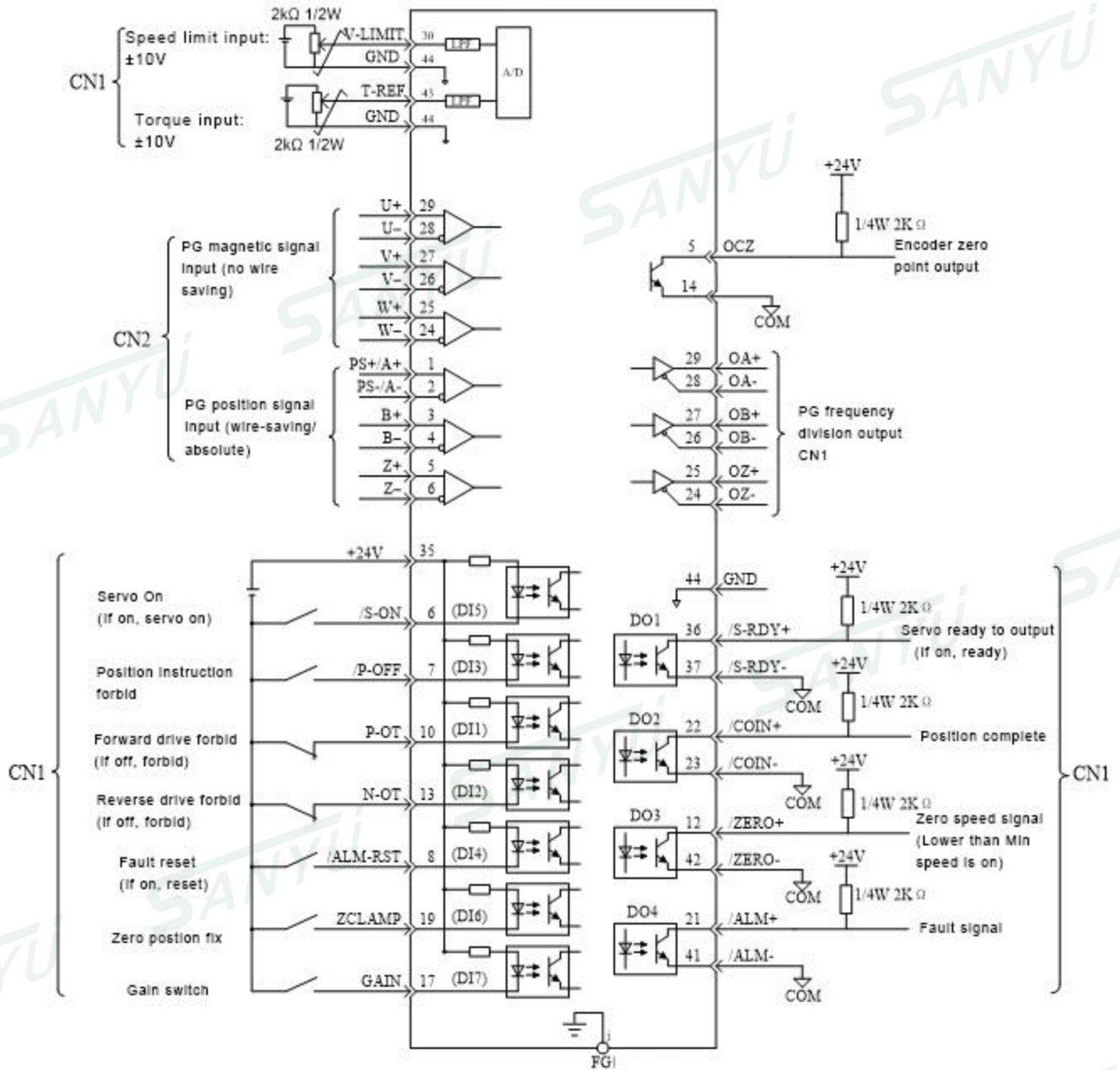
10.1.1 Speed control mode



10.1.2 Position control mode



10.1.3 Torque control mode



10.2 Wiring port definition (220V 200W-3kW)

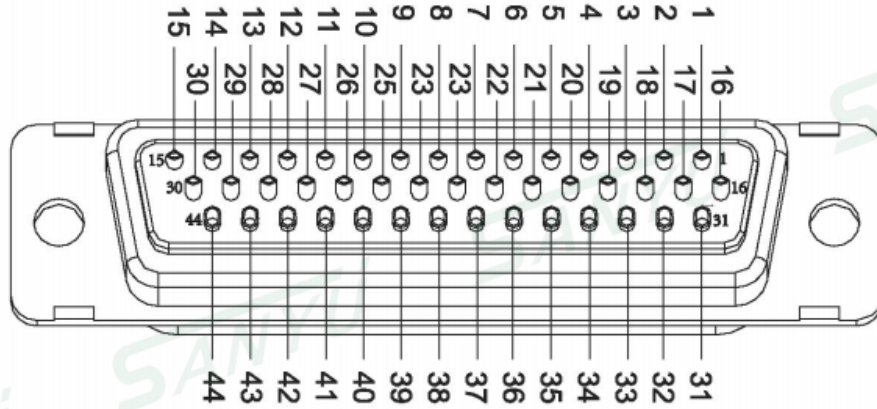
10.2.1 Strong power terminals instructions

Terminal symbol	Signal Name	Function
L1	The main circuit power input single-phase or three phase interface terminal	187V - 242V(-15% ~ 10%) 50/60Hz The maximum inrush current is 20A
L2		
L3		
U	Servo motor connection terminals	Connect correspondingly to servo motor's U, V, W
V		
W		
L1C	The control circuit power input terminal	Single-phase AC200V ~ 230V (-15 ~ +10%) 50Hz/60Hz
L2C		
PB	External regenerative resistor connection terminals	Server built-in regenerative resistor, so the factory must disconnect between B-P, insufficient regeneration ,connect an external regenerative resistor between B-P.Please purchase external regeneration resistor separately.
P		

10.2.2 Input and output signal connection (CN1) terminal definition

Pin number of interface terminal	Signal Name	Function Description	Pin number of interface terminal	Signal Name	Function Description
1	PULSE-	Instruction pulse input -	2	PULLHI	Instruction pulse External power input
3	SIGN+	Instruction symbol input +5V	4	SIGN-	Instruction symbol input-
5	OCZ	Encoder zero output	6	DI	Digital signal 5 input
7	DI3	Digital signal 3 input	8	DI4	Digital signal 4 input
9	COM-	Interior 24V power gnd	10	DI1	Digital signal 1 input
11	DI9	Digital signal 9 input	12	DO3+	Digital signal 3 output +
13	DI2	Digital signal 2 input	14	GND	Common ground
15	+24V	Interior 24V power positive	16	PULSE+	Instruction pulse input +5V
17	DI7	Digital signal 7 input	18	DO5+	Digital signal 5 output +
19	DI6	Digital signal 6 input	20	HSIGN+	High speed pulse instruction symbol input +
21	DO4+	Digital signal 4 output +	22	DO2+	Digital signal 2 output +
23	DO2-	Digital signal 2 output -	24	PZO-	PG frequency division output Z signal-
25	PZO+	PG frequency division output Z signal +	26	PBO	PG frequency division output B signal
27	PBO+	PG frequency division output B signal +	28	PAO-	PG frequency division output A signal
29	PAO+	PG frequency division output A signal+	30	AI2	Analog 2 input
31	PULLHI	Instruction pulse External power input connector	32	HPULSE-	High speed pulse instruction input
33	HPULSE+	High speed pulse instruction input +	34	HSIGN-	High speed pulse instruction symbol input -
35	COM+	External+24V	36	DO1+	Digital signal 1 output +
37	DO1-	Digital signal 1 output -	38	+5V	5V power+
39	DI8	Digital signal 8 input -	40	DO5-	Digital signal 5 output
41	DO4-	Digital signal 4 output -	42	DO3-	Digital signal 3 output
43	AI1	Analog 1 input	44	GND	Common ground

(NOTE)Please make input and output signals connect to the connector with cable shielding, Servo unit side connects to the FG (frame ground)

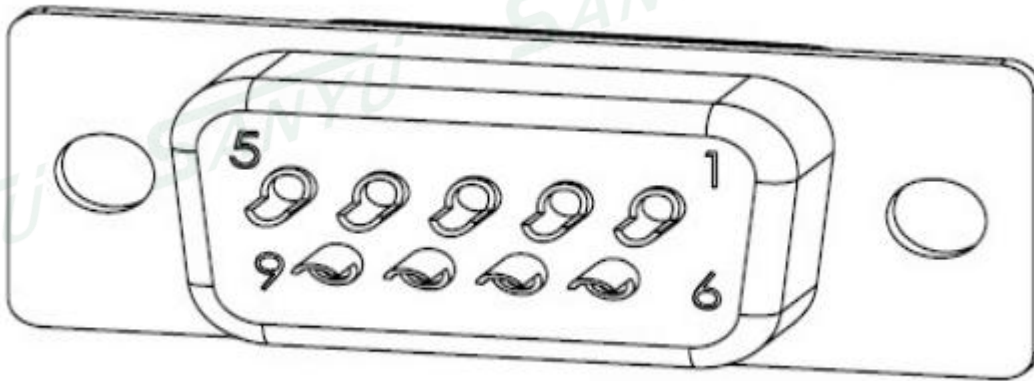


10.2.3 Feedback signal connection (CN2) terminal definition

10.2.3.1 Wire-saving increment encoder interface definition

Pin number of interface terminal	Signal name	Function description	Pin number of interface terminal	Signal name	Function description
1	PGA+	Differential signal A input +	2	PGA-	Differential signal A input -
3	PGB+	Differential signal B input +	4	PGB-	Differential signal B input -
5	PGZ+	Differential signal Z input +	6	PGZ-	Differential signal Z input -
7	+5V	5V power	8	GND	Power ground wire
9	PE	Shielded wire grounding			

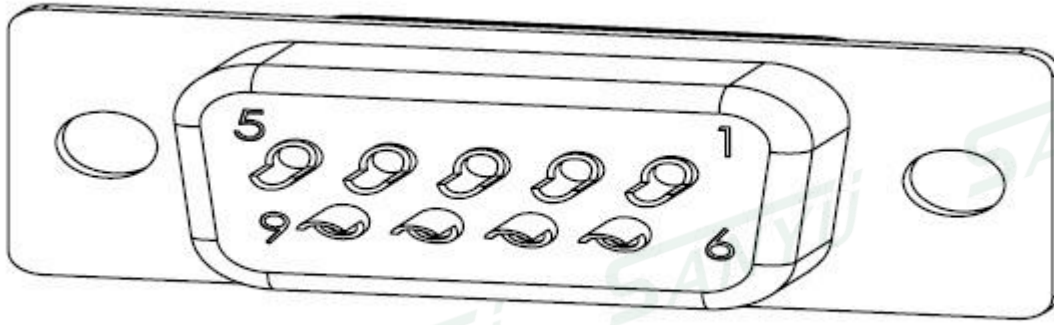
(NOTE)Please connect the shielded wire to the DB9 metal shell



10.2.3.2 Bus-type encoder interface definition

Pin number of interface terminal	Signal name	Function description	Pin number of interface terminal	Signal name	Function description
1	PS+	Bus differential signal input +	2	PS-	Bus differential signal input -
3	NC	NULL	4	NC	NULL
5	NC	NULL	6	NC	NULL
7	+5V	5V power	8	GND	Power ground wire
9					

(NOTE)Please connect the shielded wire to the DB9 metal shell



10.2.4 Communication signal connection (CN3) terminal definitions

Pin number of interface terminal	Signal name	Function description	Pin number of interface terminal	Signal name	Function description
1	RS232R	RS232 receiving line	2	RS232T	RS232 output line
3	RS485+	RS485+ insert	4	RS485-	RS485- insert
5	GND	Ground	6	NC	-
7	NC	-	8	GND	Ground

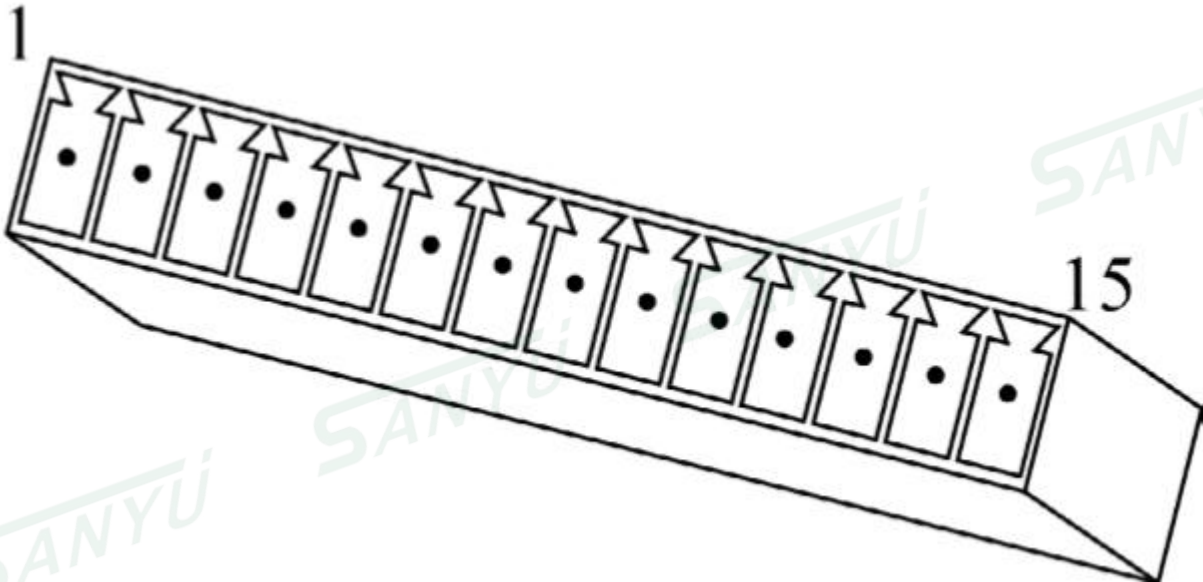
10.3 Wiring port definition(3kW-7kW)

10.3.1 Strong power terminals instructions

Terminal symbol	Signal Name	Function
R	The main circuit power input single-phase or three phase interface terminal	323V - 418V(-15% ~ 10%) 50/60Hz The maximum inrush current is 20A
S		
T		
U	Servo motor connection terminals	connect correspondingly to servo motor's U, V, W
V		
W		
-	Bus Voltage-	
PB	External regenerative resistor connection terminals	Connect an external regenerative resistor
+		

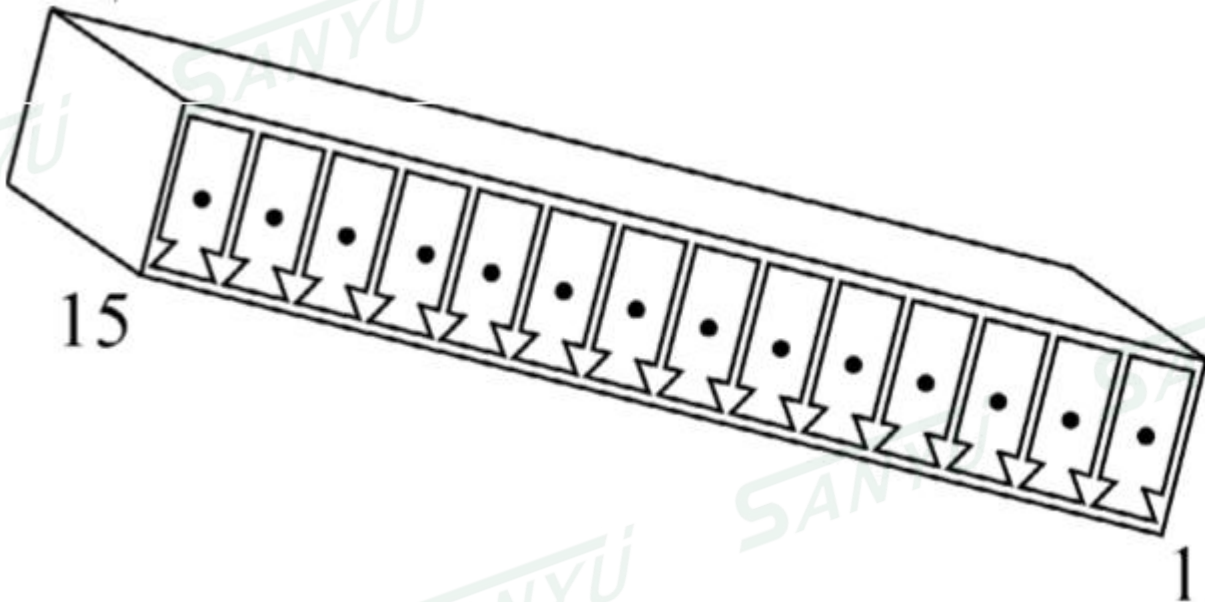
10.3.2 Input and output signal connection (CN1、CN2、CN5) terminal definition

1) CN1



Pin number of interface terminal	Signal name	Function description	Pin number of interface terminal	Signal name	Function description
1	COM-	outside 24V power GND	2	DI1	Digital signal 1 input
3	DI2	Digital signal 2 input	4	DI3	Digital signal 3 input
5	DI4	Digital signal 4 input	6	DI5	Digital signal 5 input
7	DI6	Digital signal 6 input	8	DI7	Digital signal 7 input
9	DI8	Digital signal 8 input	10	DI9	Digital signal 9 input
11	COM+	outside 24V power	12	24V+	interior 24V power positive
13	AI1	Analog 1 input	14	GND	GND
15					

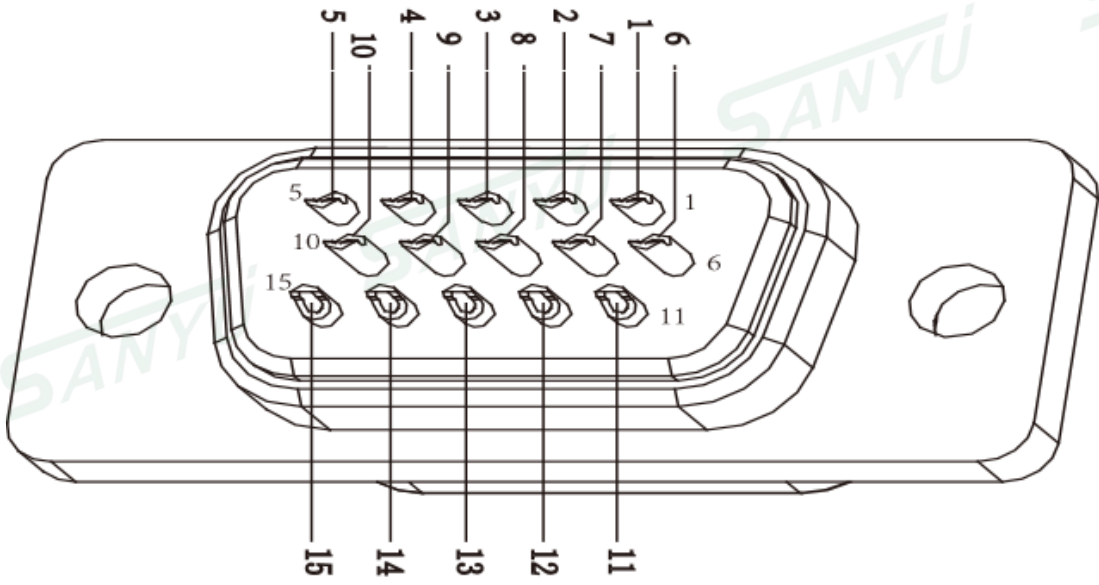
2) CN2



Pin number of interface terminal	Signal name	Function description	Pin number of interface terminal	Signal name	Function description
1	SIGN+	Instruction symbol input +	2	SIGN-	Instruction symbol input -
3	PULLHI	Instruction pulse outside source's input interface	4	PULSE+	Instruction pulse input +
5	PULSE-	Instruction pulse input -	6	DO5-	Digital signal 5 output -
7	DO5+	Digital signal 5 output +	8	DO4-	Digital signal 4 output -

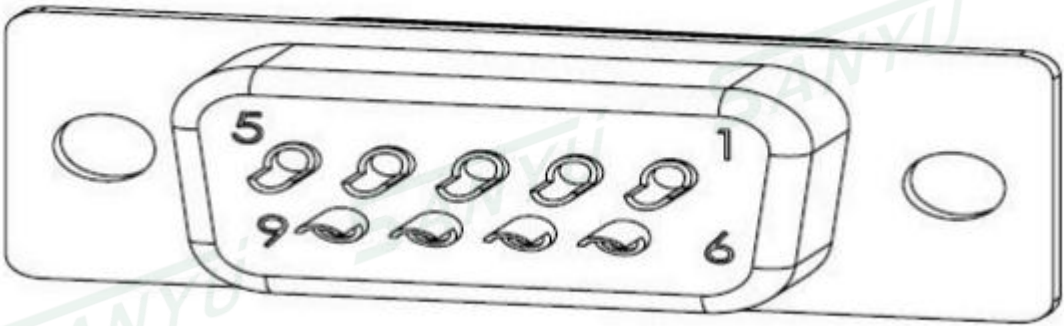
9	DO4+	Digital signal 4 output +	10	DO3-	Digital signal 3 output -
11	DO3+	Digital signal 3 output +	12	DO2-	Digital signal 2 output -
13	DO2+	Digital signal 2 output +	14	DO1-	Digital signal 1 output -
15	DO1+	Digital signal 1 output +			

3) CN5



Pin number of interface terminal	Signal name	Function description	Pin number of interface terminal	Signal name	Function description
1	HPULSE-	High speed pulse instruction input -	2	HPULSE+	High speed pulse instruction input +
3	HSIGN	High speed pulse instruction symbol input	4	HSIGN+	High speed pulse instruction symbol input +
5	GND	GND	6	PAO	PG frequency division output A signal-
7	PBO-	PG frequency division output B signal-	8	PZO-	PG frequency division output Z signal-
9	NC	Not Connected	10	NC	Not Connected
11	PAO+	PG frequency division output A signal+	12	PBO+	PG frequency division output B signal +
13	PZO+	PG frequency division output Z signal +	14	GND	GND
15	+5V	5V Power			

10.3.3 Feedback signal connection (CN3) terminal definition



Pin number of interface terminal	Signal name	Function description	Pin number of interface terminal	Signal name	Function description
1	PGA+/PS+	Differential signal A input + / Bus differential signal input +	2	PGA-/PS-	Differential signal A input- /Bus differential signal input -
3	PGB+	Differential signal B input +	4	PGB-	Differential signal B input
5	PGZ+	Differential signal Z input +	6	PGZ-	Differential signal Z input -
7	+5V	5V power	8	GND	Power ground wire
9					

Note: Please connect the shielded wire to the DB9 metal shell

10.3.4 Communication signal connection (CN6、CN7) terminal definitions

Pin number of interface terminal	Signal name	Function description	Pin number of interface terminal	Signal name	Function description
1	RS232R	RS232 receiving line	2	RS232T	RS232 output line
3	RS485+	RS485+ insert	4	RS485-	RS485- insert
5	GND	Ground	6	CANH	CAN+ insert
7	CANL	CAN- insert	8	GND	GROUND

Note: CN6 is the same as CN7

10.4 Connector port circuit

Servo unit's input output signal and the instruction controller's connection example is as follows.

10.4.1 Wiring diagram(200w-3kW)

(1) Instruction input circuit's port.

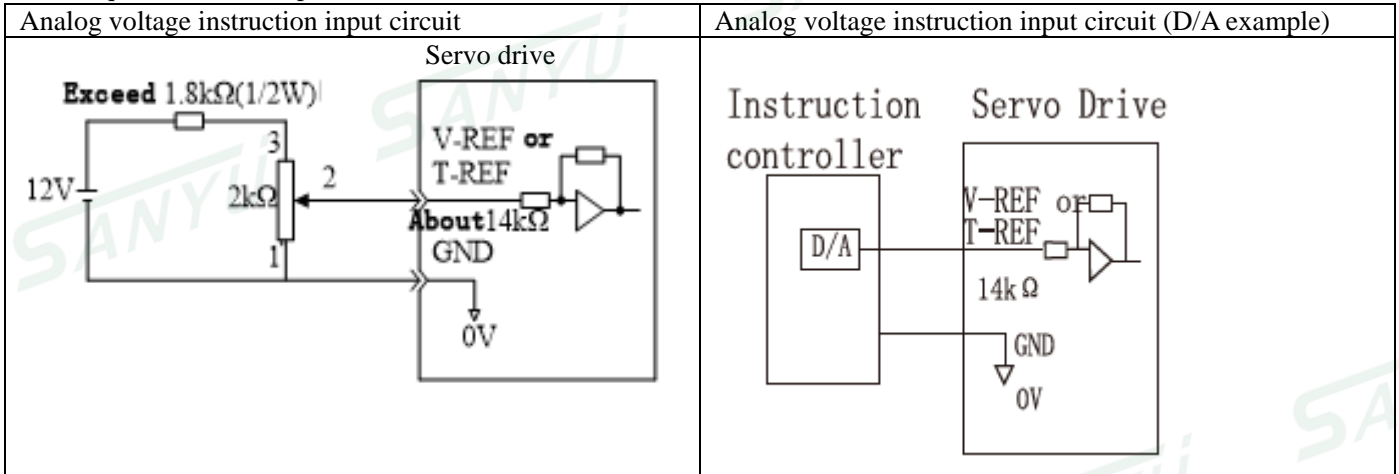
1. Analog input circuit

CN1 connector's 30-44 (the speed instruction input) 、 43-14 (the torque instruction input) terminal

Analog signal is the speed instruction or the torque instruction signal, the input impedance is as follows.

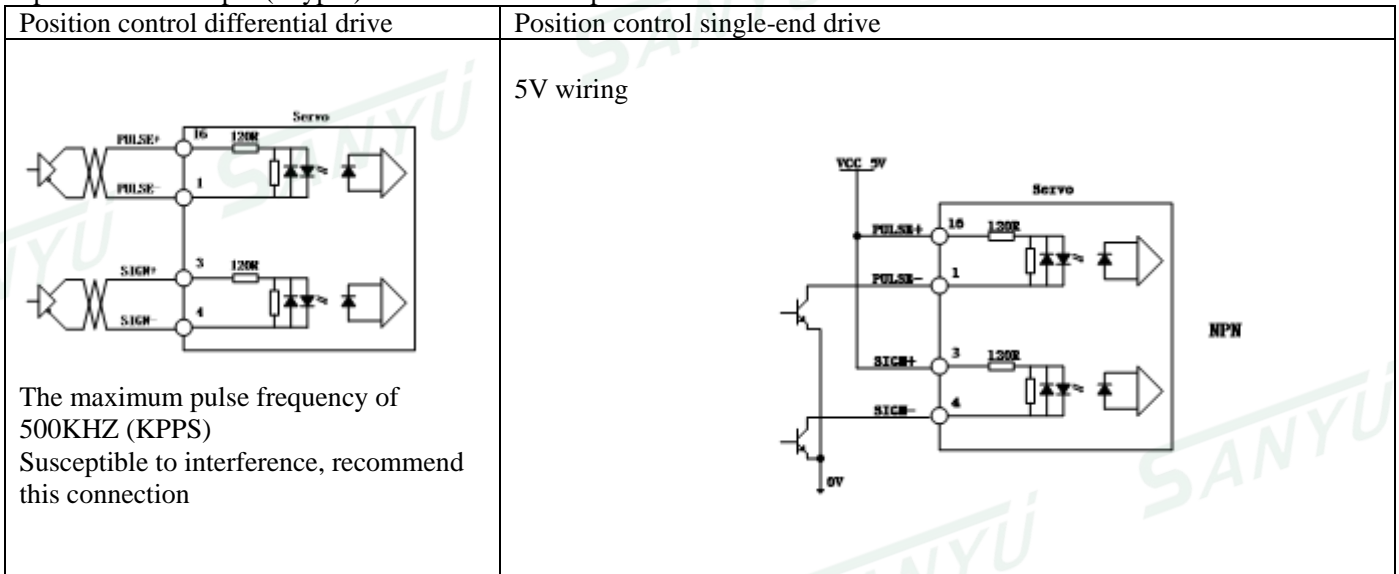
The speed instruction input: about 14kΩ

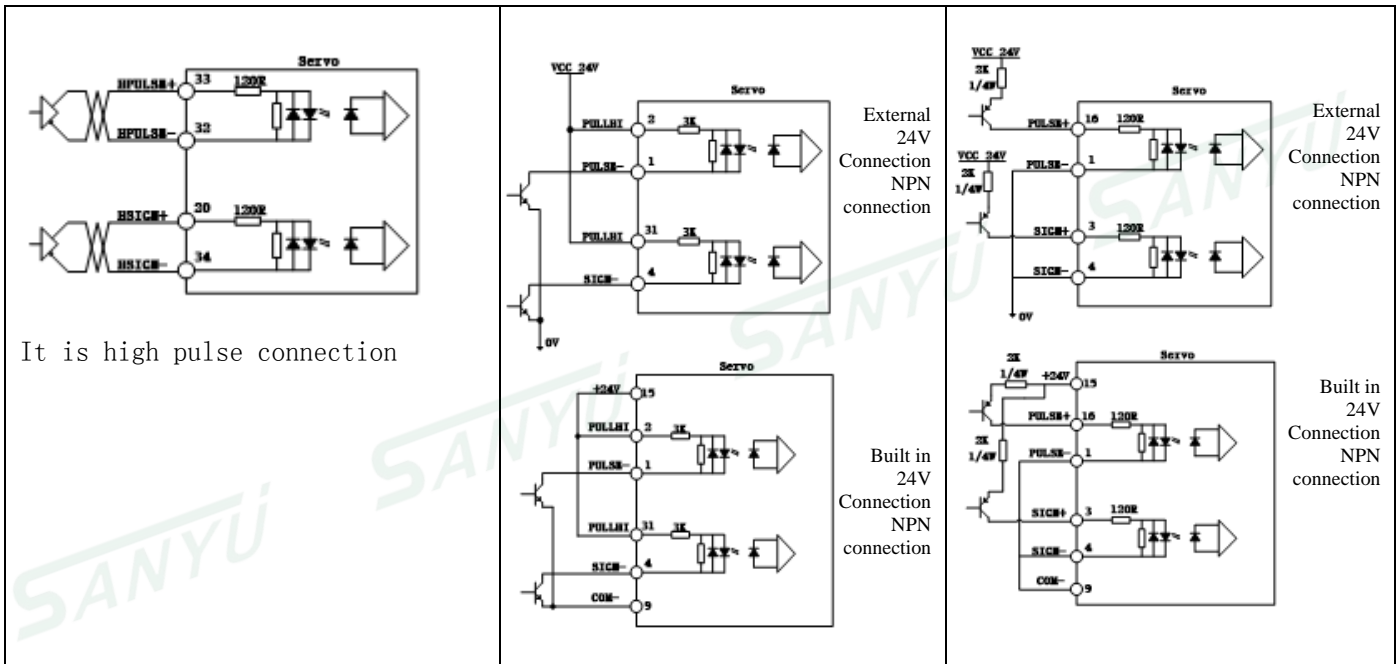
The torque instruction input: about 14kΩ



3. 2. Position instruction input circuit

Command controller side's command pulse, offset pulse cleared signal's output circuit, can output from the bus driver, open collector output (2 types). Classification is expressed as follows.

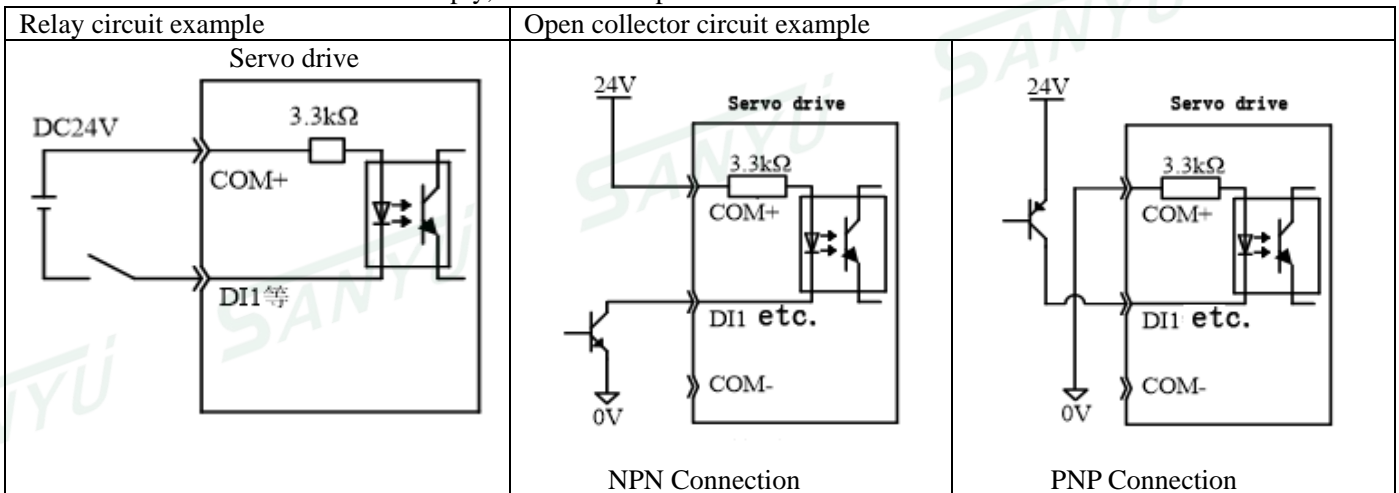




(2) The control input circuit's port

Explain CN1 connector's 32, 22, 34, 36, 19, 33, 18 terminal.

Connected by a relay or open collector transistor circuit. The use of relay connection, select the micro current relay, if don't use the micro current relay, it will lead to poor contact.



(3) Output circuit's connection port

Servo unit's signal output circuit has the following 3 kinds.

1. Servo unit's signal output circuit has the following 3 kinds.

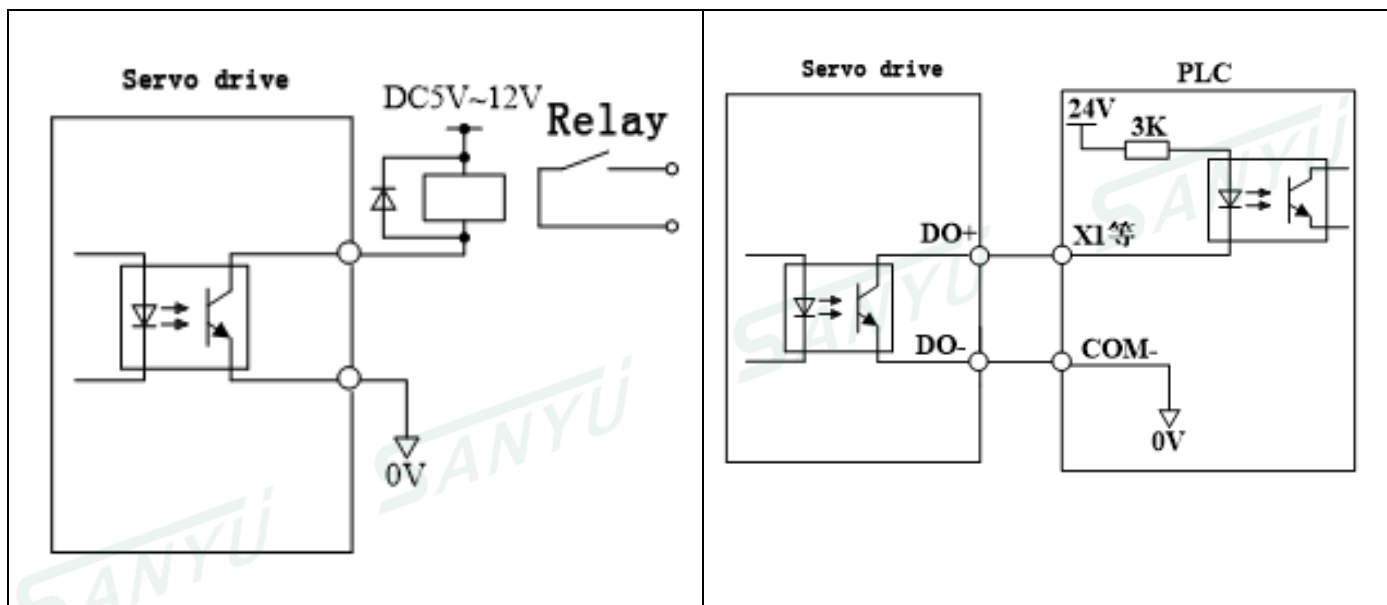
Following, to explain the CN1 connector's 29-28 (A phase signal)、27-26 (B phase)、25-24 (Z phase signal) signals.

Conduct 2 phase (A phase、B phase) transform output signal (OA+, OA-, OB+, OB-) for the encoder's serial data and the origin of the pulse signal(OZ+, OZ-) is output by the bus driver circuit. in general, use when the servo unit by speed control, constituting position control at the side of command controller. when at the side of command controller, please receive using the bus receiver circuit.

2.2. Photoelectric encoder's output circuit

Servo alarm(ALM)、servo ready(/S-RDY) and other output signals related with the output circuit signal, and is connected by the relay or the PLC receiver.

Relay circuit example	PLC example
-----------------------	-------------



**(NOTE) Photoelectric encoder's maximum allowable voltage、 current capacity is as follows.
 Maximum voltage: DC30V Maximum current: DC50mA**

10.4.2 Wiring diagram(4.5kw-18.5kW)

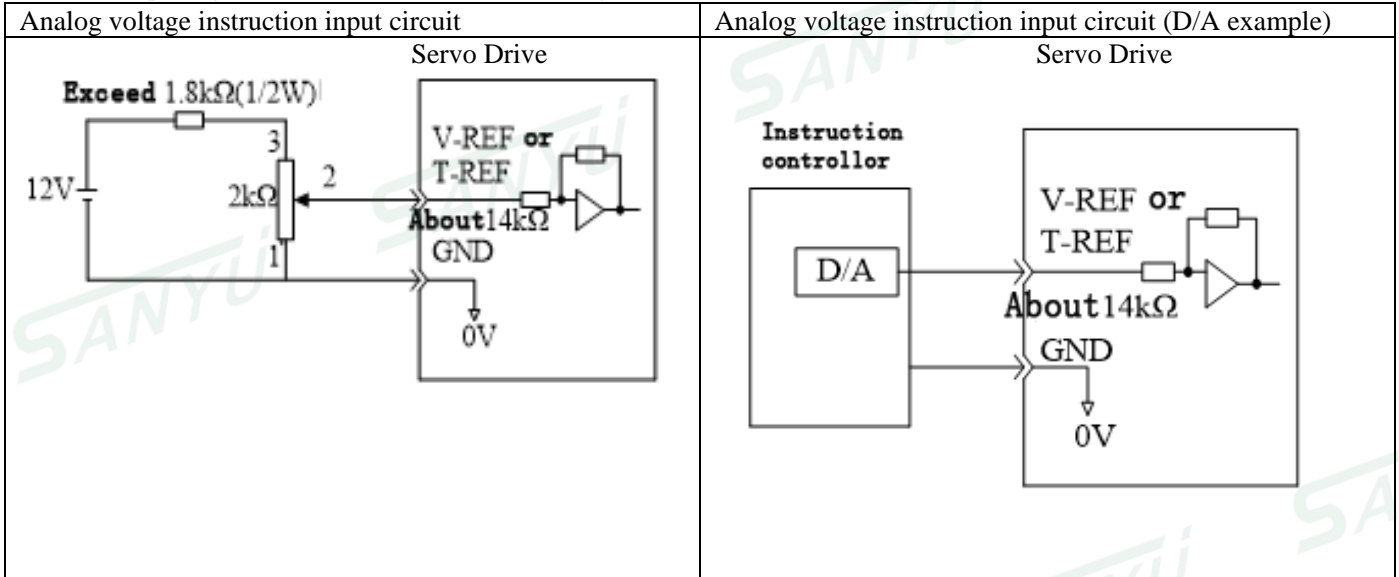
1. Analog input circuit

CN1 connector' s 13-14 (the speed instruction input) 、 15-14 (the torque instruction input) terminal
Analog signal is the speed instruction or the torque instruction signal, the input impedance is as follows.

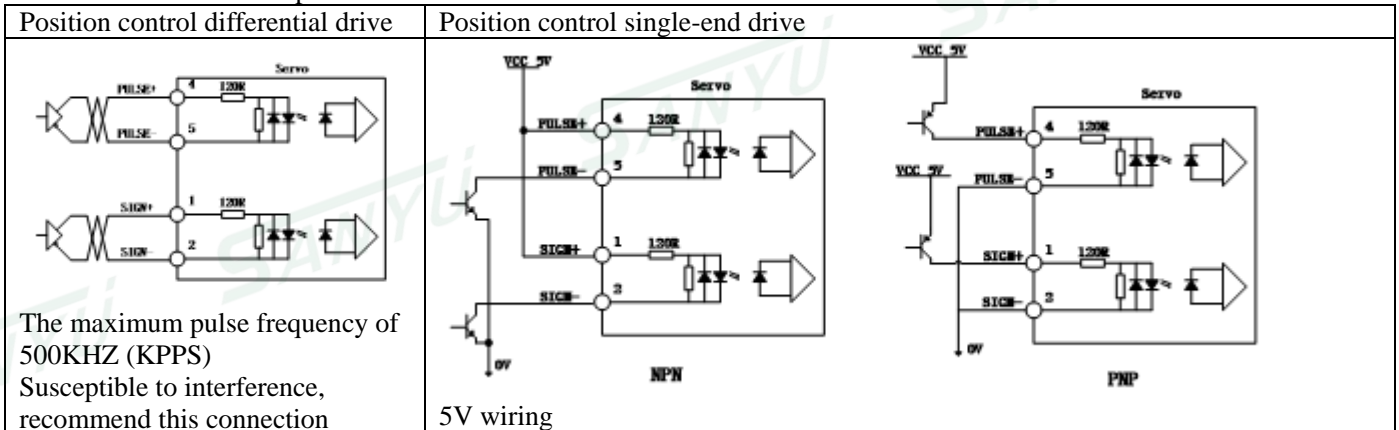
The speed instruction input: about 14kΩ

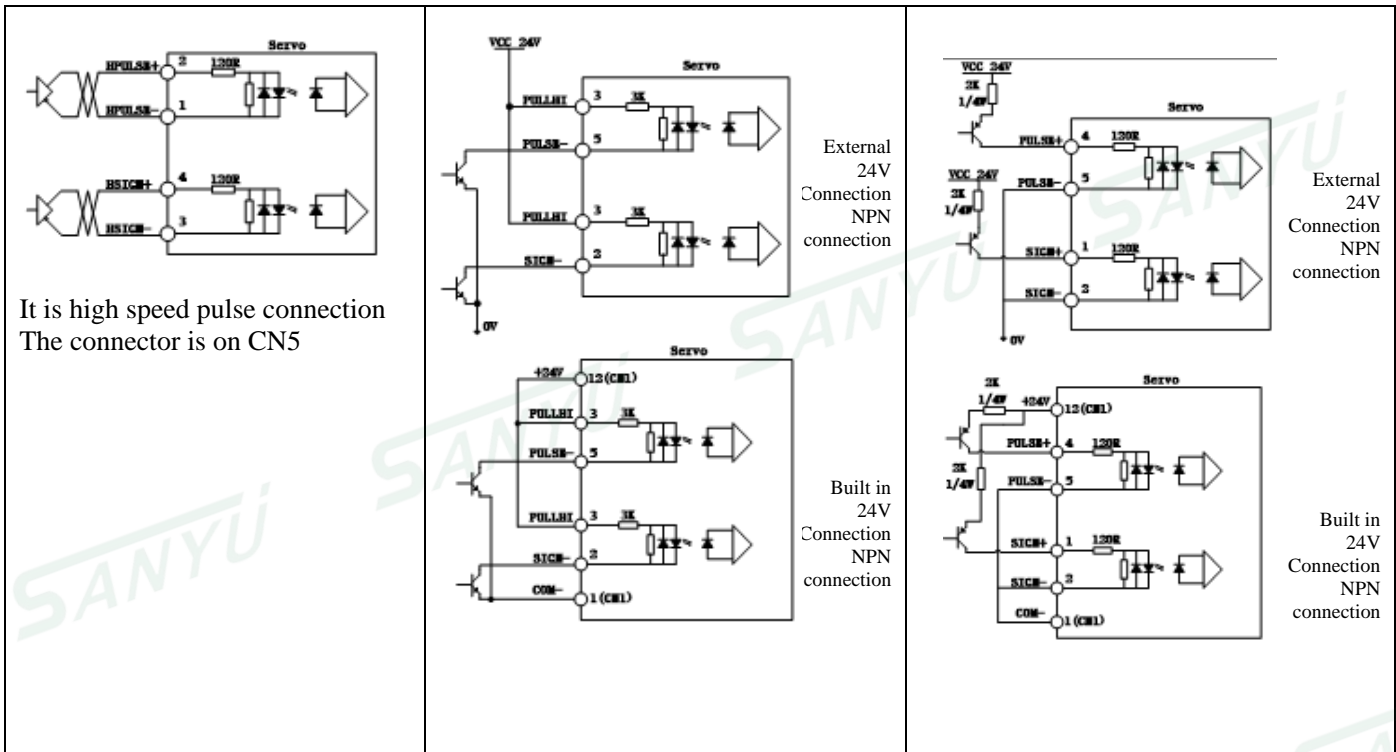
The torque instruction input: about 14kΩ

The input signal' s maximum allowable voltage is 12V



2. Position instruction input circuit



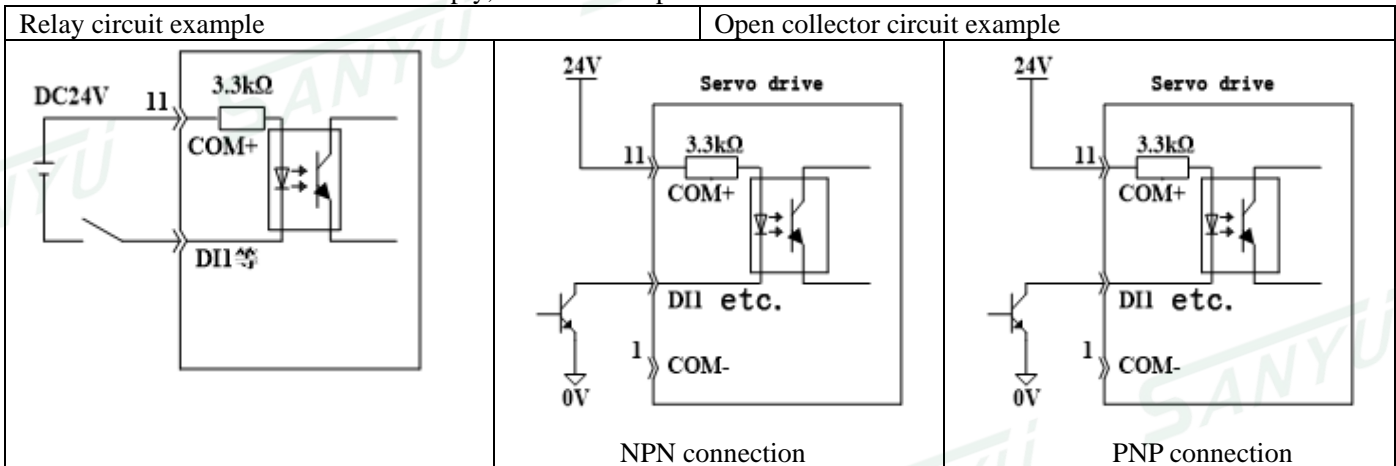


Command controller side's command pulse, offset pulse cleared signal's output circuit, can output from the bus driver, open collector output (2 types). Classification is expressed as follows.

(2)Control input circuit connector

Explain CN1 connector's 2、3、4、5、6、7、9、10 terminal.

Connected by a relay or open collector transistor circuit. The use of relay connection, select the micro current relay, if don't use the micro current reply, it will lead to poor contact.



(3)Output circuit connector

There are 3 types of output signal circuit:

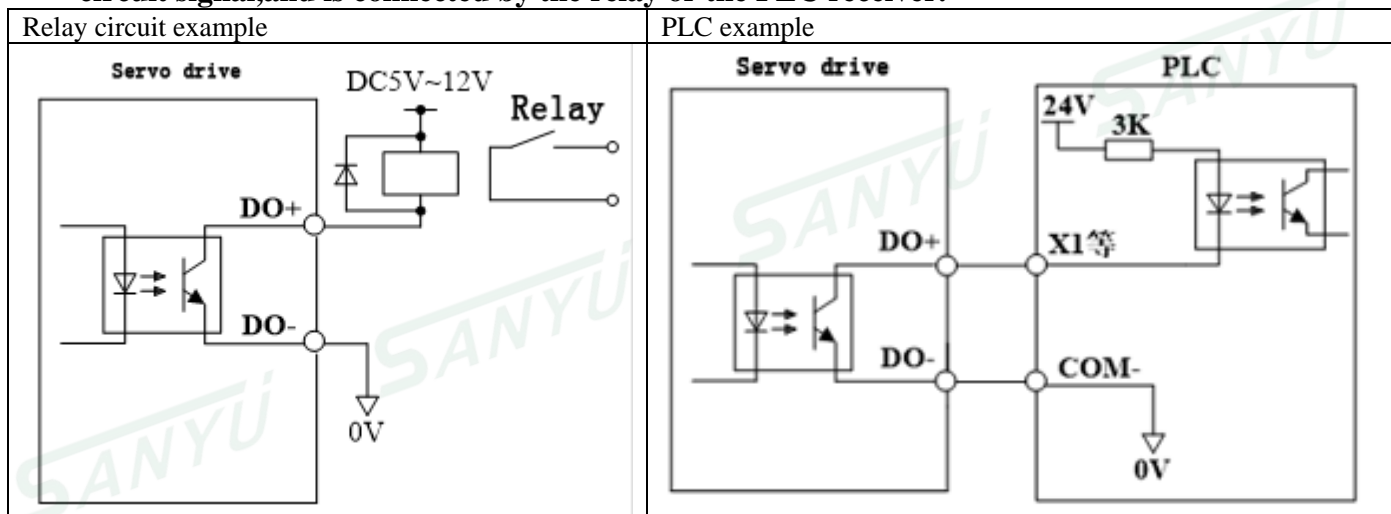
1.Differential driver output circuit

Following, to explain the CN5 connector's 11-6 (A phase signal)、12-7 (B phase)、13-8 (Z phase signal)signals.

Conduct 2 phase (A phase、B phase)transform output signal (OA+, OA-, OB+, OB-) for the encoder's serial data and the origin of the pulse signal(OZ+, OZ-)is output by the bus driver circuit. in general,use when the servo unit by speed control,constituting position control at the side of command controller.when at the side of command controller,please receive using the bus receiver circuit.

2. Photoelectric encoder's output circuit

Servo alarm(ALM)、 servo ready(/S-RDY)and other output signals related with the output circuit signal, and is connected by the relay or the PLC receiver.



(NOTE) Photoelectric encoder's maximum allowable voltage、 current capacity is as follows.

Maximum voltage: DC30V Maximum current: DC50mA

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