MITSUBISHI
ELECTRIC

General-Purpose AC Servo

MELSERVO-J3 Series

General-Purpose Interface

MODEL

MR-J3-□A

SERVO AMPLIFIER
INSTRUCTION MANUAL

K

● Safety Instructions ●

(Always read these instructions before using the equipment.)

Do not attempt to install, operate, maintain or inspect the converter unit, servo amplifier (drive unit) and servo motor until you have read through this Instruction Manual, Installation guide, Servo motor Instruction Manual (Vol.2) and appended documents carefully and can use the equipment correctly. Do not use the converter unit, servo amplifier (drive unit) and servo motor until you have a full knowledge of the equipment, safety information and instructions.
In this Instruction Manual, the safety instruction levels are classified into "WARNING" and "CAUTION".

⚠ WARNING	Indicates that incorrect handling may cause hazardous conditions, resulting in death or severe injury.
⚠ CAUTION	Indicates that incorrect handling may cause hazardous conditions, resulting in medium or slight injury to personnel or may cause physical damage.

Note that the CAUTION level may lead to a serious consequence according to conditions. Please follow the instructions of both levels because they are important to personnel safety.
What must not be done and what must be done are indicated by the following diagrammatic symbols.

⊘: Indicates what must not be done. For example, "No Fire" is indicated by ⊘ .

●: Indicates what must be done. For example, grounding is indicated by ⏚ .

In this Instruction Manual, instructions at a lower level than the above, instructions for other functions, and so on are classified into "POINT".
After reading this installation guide, always keep it accessible to the operator.

1. To prevent electric shock, note the following

⚠ WARNING

- Before wiring or inspection, turn off the power and wait for 15 minutes or more (20 minutes or for drive unit 30kW or more) until the charge lamp turns off. Then, confirm that the voltage between P(＋) and N(－) (L＋ and L－ for drive unit 30kW or more) is safe with a voltage tester and others. Otherwise, an electric shock may occur. In addition, always confirm from the front of the servo amplifier (converter unit), whether the charge lamp is off or not.
- Connect the converter unit, servo amplifier (drive unit) and servo motor to ground.
- Any person who is involved in wiring and inspection should be fully competent to do the work.
- Do not attempt to wire the converter unit, servo amplifier (drive unit) and servo motor until they have been installed. Otherwise, you may get an electric shock.
- Operate the switches with dry hand to prevent an electric shock.
- The cables should not be damaged, stressed, loaded, or pinched. Otherwise, you may get an electric shock.
- During power-on or operation, do not open the front cover. You may get an electric shock.
- Do not operate the converter unit and servo amplifier (drive unit) with the front cover removed. High-voltage terminals and charging area are exposed and you may get an electric shock.
- Except for wiring or periodic inspection, do not remove the front cover even if the power is off. The servo amplifier (drive unit) is charged and you may get an electric shock.

2. To prevent fire, note the following

⚠ CAUTION

- Install the converter unit, servo amplifier (drive unit), servo motor and regenerative resistor on incombustible material. Installing them directly or close to combustibles will lead to a fire.
- Always connect a magnetic contactor between the main circuit power supply and L_1, L_2, and L_3 of the converter unit, servo amplifier (drive unit), and configure the wiring to be able to shut down the power supply on the side of the converter unit, servo amplifier (drive unit) power supply. If a magnetic contactor is not connected, continuous flow of a large current may cause a fire when the converter unit, servo amplifier (drive unit) malfunctions.
- When a regenerative resistor is used, use an alarm signal to switch main power off. Otherwise, a regenerative transistor fault or the like may overheat the regenerative resistor, causing a fire.
- Provide adequate protection to prevent screws and other conductive matter, oil and other combustible matter from entering the converter unit, servo amplifier (drive unit), and servo motor.
- Always connect a no-fuse breaker to the power supply of the servo amplifier (converter unit).

3. To prevent injury, note the follow

⚠ CAUTION

- Only the voltage specified in the Instruction Manual should be applied to each terminal, Otherwise, a burst, damage, etc. may occur.
- Connect the terminals correctly to prevent a burst, damage, etc.
- Ensure that polarity (＋, －) is correct. Otherwise, a burst, damage, etc. may occur.
- Take safety measures, e.g. provide covers, to prevent accidental contact of hands and parts (cables, etc.) with the converter unit and servo amplifier (drive unit) heat sink, regenerative resistor, servo motor, etc. since they may be hot while power is on or for some time after power-off. Their temperatures may be high and you may get burnt or a parts may damaged.
- During operation, never touch the rotating parts of the servo motor. Doing so can cause injury.

4. Additional instructions

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

(1) Transportation and installation

⚠ CAUTION

- Transport the products correctly according to their mass.
- Stacking in excess of the specified number of products is not allowed.
- Do not carry the servo motor by the cables, shaft or encoder.
- Do not hold the front cover to transport the converter unit and servo amplifier (drive unit). The converter unit and servo amplifier (drive unit) may drop.
- Install the converter unit and servo amplifier (drive unit) in a load-bearing place in accordance with the Instruction Manual.
- Do not climb or stand on servo equipment. Do not put heavy objects on equipment.
- The converter unit, servo amplifier (drive unit), and servo motor must be installed in the specified direction.
- Leave specified clearances between the converter unit, servo amplifier (drive unit), and control enclosure walls or other equipment.
- Do not install or operate the converter unit, servo amplifier (drive unit), and servo motor which has been damaged or has any parts missing.
- Do not block the intake and exhaust areas of the converter unit, servo amplifier (drive unit) and servo motor which has a cooling fan. Doing so may cause faults.
- Do not drop or strike converter unit, servo amplifier (drive unit), or servo motor. Isolate from all impact loads.
- Securely attach the servo motor to the machine. If attach insecurely, the servo motor may come off during operation.
- The servo motor with reduction gear must be installed in the specified direction to prevent oil leakage.
- Take safety measures, e.g. provide covers, to prevent accidental access to the rotating parts of the servo motor during operation.
- Never hit the servo motor or shaft, especially when coupling the servo motor to the machine. The encoder may become faulty.
- Do not subject the servo motor shaft to more than the permissible load. Otherwise, the shaft may break.

⚠ CAUTION

- When you keep or use it, please fulfill the following environmental conditions.

Item			Environmental conditions		
			Converter unit・servo amplifier (drive unit)	Servo motor	
Ambient temperature	In operation	[°C]	0 to 55 (non-freezing)	0 to 40 (non-freezing)	
		[°F]	32 to 131 (non-freezing)	32 to 104 (non-freezing)	
	In storage	[°C]	−20 to 65 (non-freezing)	−15 to 70 (non-freezing)	
		[°F]	−4 to 149 (non-freezing)	5 to 158 (non-freezing)	
Ambient humidity	In operation		90%RH or less (non-condensing)	80%RH or less (non-condensing)	
	In storage		90%RH or less (non-condensing)		
Ambience			Indoors (no direct sunlight) Free from corrosive gas, flammable gas, oil mist, dust and dirt		
Altitude			Max. 1000m (3280 ft) above sea level		
(Note) Vibration	[m/s²]		5.9 or less at 10 to 55Hz (directions of X, Y and Z axes)	HF-MP series HF-KP series	X, Y: 49 m/s²
				HF-SP51・81 HF-SP52 to 152 HF-SP524 to 1524 HC-RP Series HC-UP72・152 HF-JP Series	X, Y: 24.5 m/s²
				HF-SP121・201 HF-SP202・352 HF-SP2024・3524 HC-UP202 to 502	X: 24.5 m/s² Y: 49 m/s²
				HF-SP301・421 HF-SP502・702 HF-SP5024・7024	X: 24.5 m/s² Y: 29.4 m/s²
				HC-LP52 to 152	X: 9.8 m/s² Y: 24.5 m/s²
				HC-LP202 to 302	X: 19.6 m/s² Y: 49 m/s²
				HA-LP601 to 12K1 HA-LP701M to 15K1M HA-LP502 to 22K2 HA-LP6014・12K14 HA-LP701M4・15K1M4 HA-LP11K24 to 22K24	X: 11.7 m/s² Y: 29.4 m/s²
				HA-LP15K1 to 37K1 HA-LP22K1M to 37K1M HA-LP30K2・37K2 HA-LP15K14 to 37K14 HA-LP22K1M4 to 50K1M4 HA-LP30K24 to 55K24	X, Y: 9.8 m/s²

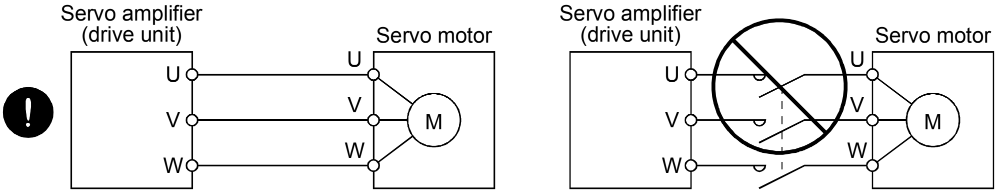
Note. Except the servo motor with reduction gear.

- When the equipment has been stored for an extended period of time, contact your local sales office.

(2) Wiring

⚠ CAUTION

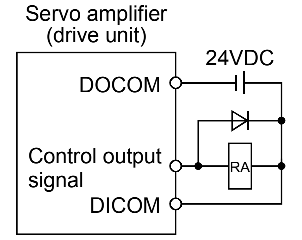
- Wire the equipment correctly and securely. Otherwise, the servo motor may operate unexpectedly.
- Do not install a power capacitor, surge absorber or radio noise filter (FR-BIF-(H) option) between the servo motor and servo amplifier (drive unit).
- Connect the wires to the correct phase terminals (U, V, W) of the servo amplifier (drive unit) and servo motor.
  Not doing so may cause unexpected operation.
- Connect the servo motor power terminal (U, V, W) to the servo motor power input terminal (U, V, W) directly. Do not let a magnetic contactor, etc. intervene.



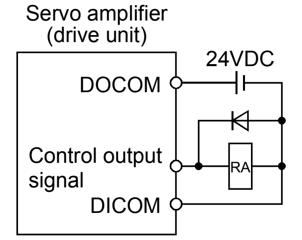
- Do not connect AC power directly to the servo motor. Otherwise, a fault may occur.

CAUTION

- The surge absorbing diode installed to the DC relay for control output should be fitted in the specified direction. Otherwise, the emergency stop and other protective circuits may not operate.



For sink output interface



For source output interface

- When the cable is not tightened enough to the terminal block (connector), the cable or terminal block (connector) may generate heat because of the poor contact. Be sure to tighten the cable with specified torque.

(3) Test run adjustment

CAUTION

- Before operation, check the parameter settings. Improper settings may cause some machines to perform unexpected operation.
- The parameter settings must not be changed excessively. Operation will be insatiable.

(4) Usage

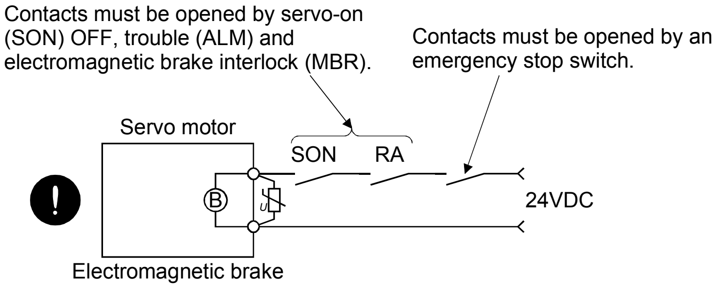
CAUTION

- Provide an external emergency stop circuit to ensure that operation can be stopped and power switched off immediately.
- Any person who is involved in disassembly and repair should be fully competent to do the work.
- Before resetting an alarm, make sure that the run signal of the servo amplifier (drive unit) is off to prevent an accident. A sudden restart is made if an alarm is reset with the run signal on.
- Do not modify the equipment.
- Use a noise filter, etc. to minimize the influence of electromagnetic interference, which may be caused by electronic equipment used near the converter unit and servo amplifier (drive unit).
- Burning or breaking a converter unit and servo amplifier (drive unit) may cause a toxic gas. Do not burn or break a converter unit and servo amplifier (drive unit).
- Use the converter unit and servo amplifier (drive unit) with the specified servo motor.
- The electromagnetic brake on the servo motor is designed to hold the motor shaft and should not be used for ordinary braking.
- For such reasons as service life and mechanical structure (e.g. where a ball screw and the servo motor are coupled via a timing belt), the electromagnetic brake may not hold the motor shaft. To ensure safety, install a stopper on the machine side.

(5) Corrective actions

⚠ CAUTION

- When it is assumed that a hazardous condition may take place at the occur due to a power failure or a product fault, use a servo motor with an electromagnetic brake or an external brake mechanism for the purpose of prevention.
- Configure an electromagnetic brake circuit so that it is activated also by an external emergency stop switch.



- When any alarm has occurred, eliminate its cause, ensure safety, and deactivate the alarm before restarting operation.
- When power is restored after an instantaneous power failure, keep away from the machine because the machine may be restarted suddenly (design the machine so that it is secured against hazard if restarted).

(6) Maintenance, inspection and parts replacement

⚠ CAUTION

- With age, the electrolytic capacitor of the converter unit and servo amplifier (drive unit) will deteriorate. To prevent a secondary accident due to a fault, it is recommended to replace the electrolytic capacitor every 10 years when used in general environment. Please contact your local sales office.

(7) General instruction

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

● DISPOSAL OF WASTE ●

Please dispose a converter unit, servo amplifier (drive unit), battery (primary battery) and other options according to your local laws and regulations.

⚠ EEP-ROM life

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

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

Precautions for Choosing the Products

Mitsubishi will not be held liable for damage caused by factors found not to be the cause of Mitsubishi; machine damage or lost profits caused by faults in the Mitsubishi products; damage, secondary damage, accident compensation caused by special factors unpredictable by Mitsubishi; damages to products other than Mitsubishi products; and to other duties.

COMPLIANCE WITH THE EUROPEAN EC DIRECTIVES

Refer to Appendix 9 for the compliance with EC Directives.

COMPLIANCE WITH UL/C-UL STANDARD

Refer to Appendix 10 for the compliance with UL/C-UL standard.

<<About the manuals>>

This Instruction Manual and the MELSERVO Servo Motor Instruction Manual (Vol.2) are required if you use the General-Purpose AC servo MR-J3-A for the first time.

Relevant manuals

Manual name	Manual No.
MELSERVO-J3 Series Instructions and Cautions for Safe Use of AC Servos (Enclosed in converter unit and servo amplifier (drive unit).)	IB(NA)0300077
MELSERVO Servo Motor Instruction Manual (Vol.2)	SH(NA)030041
EMC Installation Guidelines	IB(NA)67310

Details of MR-J3-CR55K(4) and MR-J3-DU30KA(4) to MR-J3-DU55KA4 are described in chapter 13 of this instruction manual.
For the products of 30kW or more, refer to chapter 15.

<<Wiring>>

Wires mentioned in this instruction manual are selected based on the ambient temperature of 40℃ (104℉).

MEMO

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1. FUNCTIONS AND CONFIGURATION

1.1 Summary

The Mitsubishi MELSERVO-J3 series general-purpose AC servo is based on the MELSERVO-J2-Super series and has further higher performance and higher functions.
It has position control, speed control and torque control modes. Further, it can perform operation with the control modes changed, e.g. position/speed control, speed/torque control and torque/position control. Hence, it is applicable to a wide range of fields, not only precision positioning and smooth speed control of machine tools and general industrial machines but also line control and tension control.
As this new series has the USB or RS-422 serial communication function, a MR Configurator installed personal computer or the like can be used to perform parameter setting, test operation, status display monitoring, gain adjustment, etc.
With real-time auto tuning, you can automatically adjust the servo gains according to the machine.
The MELSERVO-J3 series servo motor with an absolute position encoder which has the resolution of 262144 pulses/rev to ensure more accurate control as compared to the MELSERVO-J2-Super series. Simply adding a battery to the servo amplifier makes up an absolute position detection system. This makes home position return unnecessary at power-on or alarm occurrence by setting a home position once.

(1) Position control mode

An up to 1Mpps high-speed pulse train is used to control the speed and direction of a motor and execute precision positioning of 262144 pulses/rev resolution.
The position smoothing function provides a choice of two different modes appropriate for a machine, so a smoother start/stop can be made in response to a sudden position command.
A torque limit is imposed on the servo amplifier by the clamp circuit to protect the power transistor in the main circuit from overcurrent due to sudden acceleration/deceleration or overload. This torque limit value can be changed to any value with an external analog input or the parameter.

(2) Speed control mode

An external analog speed command (0 to ±10VDC) or parameter-driven internal speed command (max. 7 speeds) is used to control the speed and direction of a servo motor smoothly.
There are also the acceleration/deceleration time constant setting in response to speed command, the servo lock function at a stop time, and automatic offset adjustment function in response to external analog speed command.

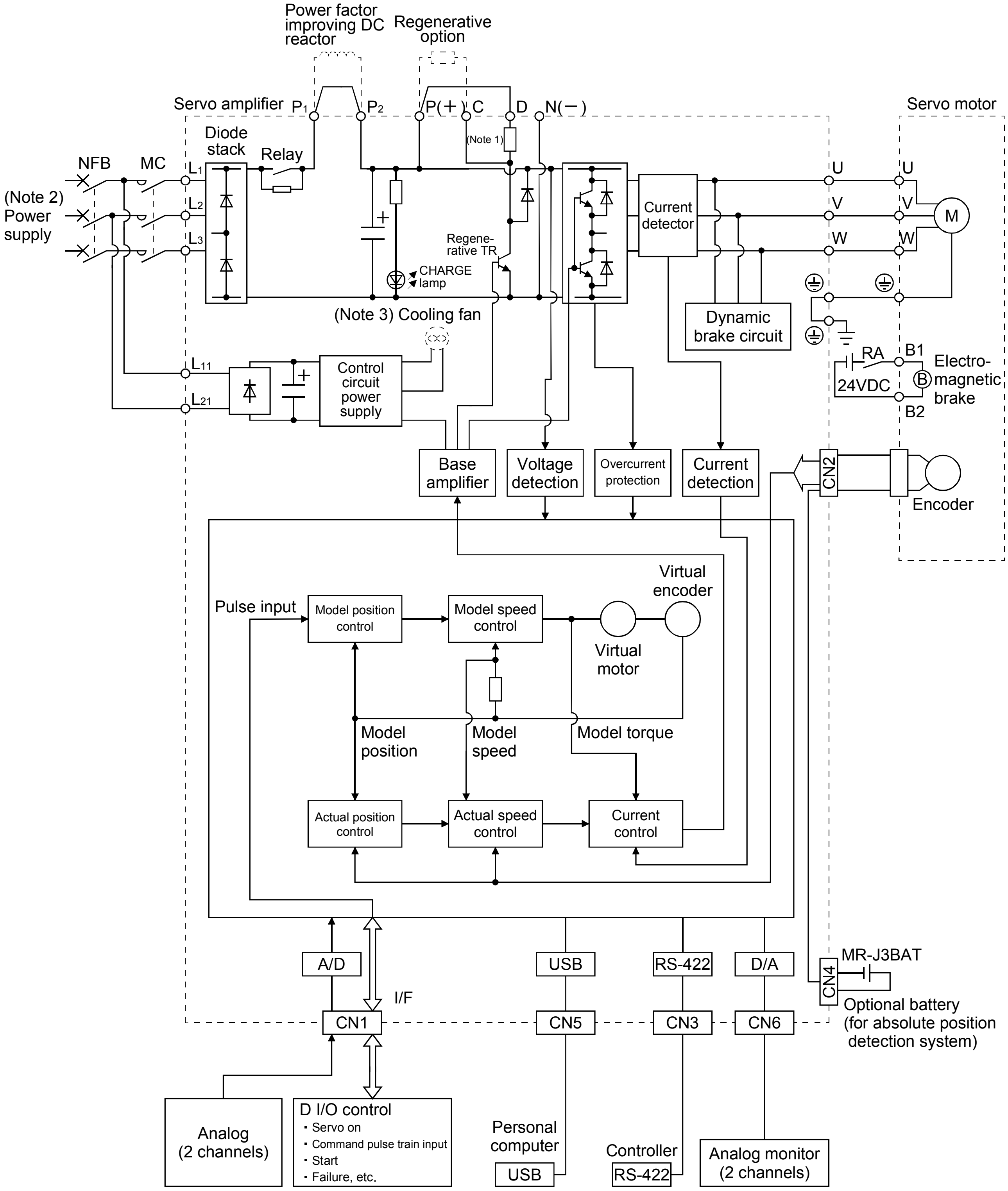
(3) Torque control mode

An external analog torque command (0 to ±8VDC) is used to control the torque output by the servo motor.
To prevent unexpected operation under no load, the speed limit function (external or internal setting) is also available for application to tension control, etc.

1.2 Function block diagram

The function block diagram of this servo is shown below.

(1) MR-J3-350A or less・MR-J3-200A4 or less

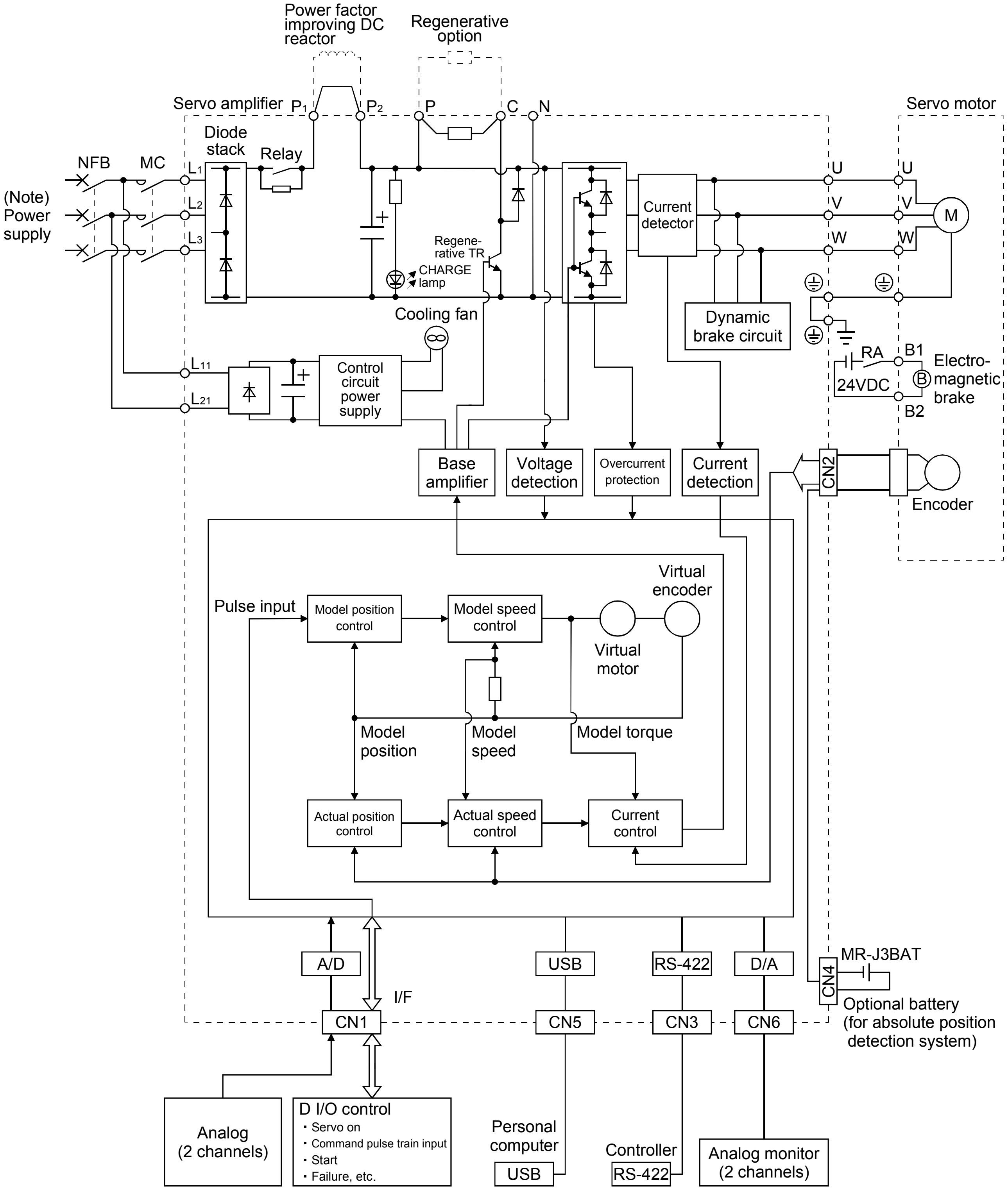


Note 1. The built-in regenerative resistor is not provided for the MR-J3-10A(1).

2. For 1-phase 200 to 230VAC, connect the power supply to L_1, L_2 and leave L_3 open.
There is no L_3 for 1-phase 100 to 120VAC power supply. For the specification of power supply, refer to section 1.3.

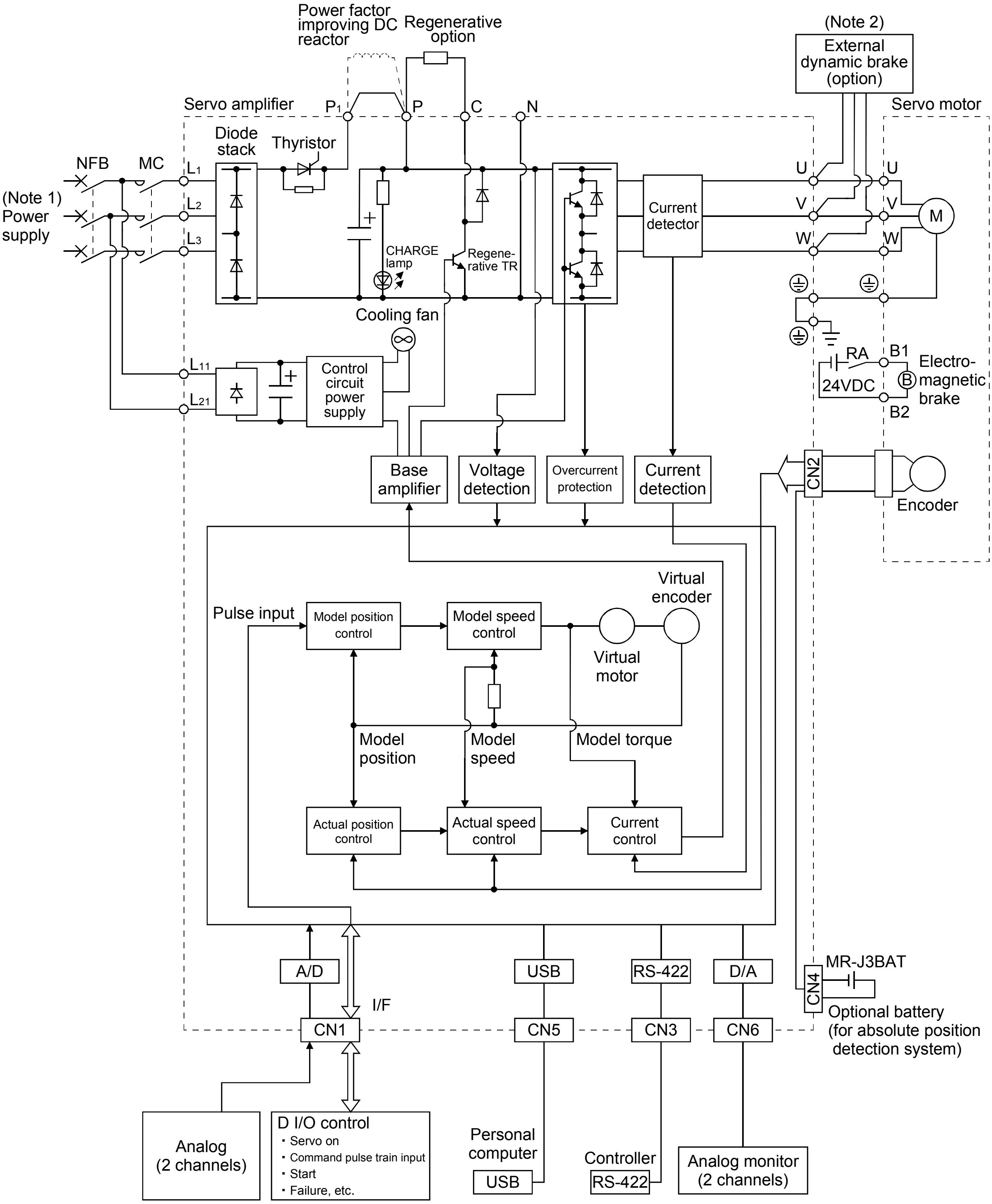
3. Servo amplifiers MR-J3-70A or greater have a cooling fan.

(2) MR-J3-350A4 · MR-J3-500A(4) · MR-J3-700A(4)



Note. For the specification of power supply, refer to section 1.3.

(3) MR-J3-11KA(4) to 22KA(4)



Note 1. For the specification of power supply, refer to section 1.3.

2. Use an external dynamic brake for this servo amplifier. Failure to do so will cause an accident because the servo motor does not stop immediately but coasts at an emergency stop and such conditions. Ensure the safety in the entire system.

1.3 Servo amplifier standard specifications

(1) 200V class, 100V class

Item		Servo amplifier MR-J3-□	10A	20A	40A	60A	70A	100A	200A	350A	500A	700A	11KA	15KA	22KA	10A1	20A1	40A1
Output	Rated voltage		3-phase 170VAC															
Output	Rated current [A]		1.1	1.5	2.8	3.2	5.8	6.0	11.0	17.0	28.0	37.0	68.0	87.0	126.0	1.1	1.5	2.8
Main circuit power supply	Voltage, frequency		3-phase or 1-phase 200 to 230VAC, 50/60Hz					3-phase 200 to 230VAC, 50/60Hz								1-phase 100 to 120VAC, 50/60Hz		
Main circuit power supply	Rated current [A]		0.9	1.5	2.6	(Note 3) 3.2	3.8	5.0	10.5	16.0	21.7	28.9	46.0	64.0	95.0	3.0	5.0	9.0
Main circuit power supply	Permissible voltage fluctuation		3-phase or 1-phase 170 to 253VAC					3-phase 170 to 253VAC								1-phase 85 to 132VAC		
Main circuit power supply	Permissible frequency fluctuation		Within ±5%															
Main circuit power supply	Power supply capacity		Refer to section 11.2															
Main circuit power supply	Inrush current		Refer to section 11.5															
Control circuit power supply	Voltage, frequency		1-phase 200 to 230VAC, 50/60Hz													1-phase 100 to 120VAC, 50/60Hz		
Control circuit power supply	Rated current [A]		0.2								0.3					0.4		
Control circuit power supply	Permissible voltage fluctuation		1-phase 170 to 253VAC													1-phase 85 to 132VAC		
Control circuit power supply	Permissible frequency fluctuation		Within ±5%															
Control circuit power supply	Power consumption [W]		30								45					30		
Control circuit power supply	Inrush current		Refer to section 11.5															
Interface power supply	Voltage		24VDC±10%															
Interface power supply	Power supply capacity		(Note 1) 0.3A															
Control System			Sine-wave PWM control, current control system															
Dynamic brake			Built-in										External option (Note 4)			Built-in		
Protective functions			Overcurrent shut-off, regenerative overvoltage shut-off, overload shut-off (electronic thermal relay), servo motor overheat protection, encoder error protection, regenerative error protection, undervoltage, instantaneous power failure protection, overspeed protection, excessive error protection															
Position control mode	Max. input pulse frequency		1Mpps (for differential receiver), 200kpps (for open collector)															
Position control mode	Command pulse multiplying factor		Electronic gear A:1 to 1048576, B:1 to 1048576, 1/10 < A/B < 2000															
Position control mode	In-position range setting		0 to ±10000 pulse (command pulse unit)															
Position control mode	Error excessive		±3 revolutions															
Position control mode	Torque limit		Set by parameter setting or external analog input (0 to ＋10VDC/maximum torque)															
Speed control mode	Speed control range		Analog speed command 1: 2000, internal speed command 1: 5000															
Speed control mode	Analog speed command input		0 to ±10VDC / Rated speed															
Speed control mode	Speed fluctuation ratio		±0.01% or less (load fluctuation 0 to 100%) 0% (power fluctuation ±10%) ±0.2% or less (ambient temperature 25±10°C (59 to 95℉)) when using analog speed command															
Speed control mode	Torque limit		Set by parameter setting or external analog input (0 to ＋10VDC/maximum torque)															
Torque control mode	Analog torque command input		0 to ±8VDC / Maximum torque (input impedance 10 to 12kΩ)															
Torque control mode	Speed limit		Set by parameter setting or external analog input (0 to ±10VDC/Rated speed)															
Compliance to standards			CE (LVD: IEC/EN 50178, EMC: IEC/EN 61800-3) UL (UL 508C)															
Structure			Natural-cooling, open (IP rating: IP00)				Force-cooling, open (IP rating: IP00)									Natural-cooling, open (IP rating: IP00)		
Environmental conditions	Ambient temperature	In operation [°C]	(Note 2) 0 to 55 (non-freezing)															
Environmental conditions	Ambient temperature	In operation [°F]	(Note 2) 32 to 131 (non-freezing)															
Environmental conditions	Ambient temperature	In storage [°C]	−20 to 65 (non-freezing)															
Environmental conditions	Ambient temperature	In storage [°F]	−4 to 149 (non-freezing)															
Environmental conditions	Ambient humidity	In operation In storage	90%RH or less (non-condensing)															
Environmental conditions	Ambient		Indoors (no direct sunlight), Free from corrosive gas, flammable gas, oil mist, dust and dirt															
Environmental conditions	Altitude		Max. 1000m above sea level															
Environmental conditions	Vibration		5.9m/s^2 or less at 10 to 55Hz (directions of X, Y and Z axes)															
Mass		[kg]	0.8	0.8	1.0	1.0	1.4	1.4	2.1	2.3	4.6	6.2	18	18	19	0.8	0.8	1.0
Mass		[lb]	1.76	1.76	2.21	2.21	3.09	3.09	4.63	5.07	10.1	13.7	39.7	39.7	41.9	1.76	1.76	2.21

Note 1. 0.3A is the value applicable when all I/O signals are used. The current capacity can be decreased by reducing the number of I/O points.
2. When closely mounting the servo amplifier of 3.5kW or less, operate them at the ambient temperatures of 0 to 45°C or at 75% or smaller effective load ratio.
3. When a UL/C-UL-compliant servo motor is used in combination, the value is 2.9A.
4. Use an external dynamic brake for this servo amplifier. Failure to do so will cause an accident because the servo motor does not stop immediately but coasts at an emergency stop and such conditions. Ensure the safety in the entire system.

(2) 400V class

Item		Servo amplifier MR-J3-□	60A4	100A4	200A4	350A4	500A4	700A4	11KA4	15KA4	22KA4
Output	Rated voltage		3-phase 323VAC								
	Rated current	[A]	1.5	2.8	5.4	8.6	14.0	17.0	32.0	41.0	63.0
Main circuit power supply	Voltage, frequency		3-phase 380 to 480VAC, 50/60Hz								
	Rated current	[A]	1.4	2.5	5.1	7.9	10.8	14.4	23.1	31.8	47.6
	Permissible voltage fluctuation		3-phase 323 to 528VAC								
	Permissible frequency fluctuation		Within ±5%%								
	Power supply capacity		Refer to section 11.2								
	Inrush current		Refer to section 11.5								
Control circuit power supply	Voltage, frequency		1-phase 380 to 480VAC, 50/60Hz								
	Rated current	[A]	0.1			0.2					
	Permissible voltage fluctuation		1-phase 323 to 528VAC								
	Permissible frequency fluctuation		Within ±5%%								
	Power consumption	[W]	30			45					
	Inrush current		Refer to section 11.5								
Interface power supply	Voltage		24VDC±10%%								
	Power supply capacity		(Note 1) 0.3A								
Control System			Sine-wave PWM control, current control system								
Dynamic brake			Built-in						External option (Note 2)		
Protective functions			Overcurrent shut-off, regenerative overvoltage shut-off, overload shut-off (electronic thermal relay), servo motor overheat protection, encoder error protection, regenerative error protection, undervoltage, instantaneous power failure protection, overspeed protection, excessive error protection								
Position control mode	Max. input pulse frequency		1Mpps (for differential receiver), 200kpps (for open collector)								
	Command pulse multiplying factor		Electronic gear A:1 to 1048576, B:1 to 1048576, 1/10 < A/B < 2000								
	In-position range setting		0 to ±10000 pulse (command pulse unit)								
	Error excessive		±3 revolutions								
	Torque limit		Set by parameter setting or external analog input (0 to ＋10VDC/maximum torque)								
Speed control mode	Speed control range		Analog speed command 1: 2000, internal speed command 1: 5000								
	Analog speed command input		0 to ±10VDC / Rated speed								
	Speed fluctuation ratio		±0.01% or less (load fluctuation 0 to 100%) 0% (power fluctuation ±10%) ±0.2% or less (ambient temperature 25±10°C (59 to 95℉)) when using analog speed command								
	Torque limit		Set by parameter setting or external analog input (0 to ＋10VDC/maximum torque)								
Torque control mode	Analog torque command input		0 to ±8VDC / Maximum torque (input impedance 10 to 12kΩ)								
	Speed limit		Set by parameter setting or external analog input (0 to ±10VDC/Rated speed)								
Compliance to standards			CE (LVD: IEC/EN 50178, EMC: IEC/EN 61800-3) UL (UL 508C)								
Structure			Natural-cooling, open (IP rating: IP00)		Force-cooling, open (IP rating: IP00)						
Environmental conditions	Ambient temperature	In operation [°C]	0 to 55 (non-freezing)								
		In operation [°F]	32 to 131 (non-freezing)								
		In storage [°C]	−20 to 65 (non-freezing)								
		In storage [°F]	−4 to 149 (non-freezing)								
	Ambient humidity	In operation	90%RH or less (non-condensing)								
		In storage									
	Ambient		Indoors (no direct sunlight), Free from corrosive gas, flammable gas, oil mist, dust and dirt								
	Altitude		Max. 1000m above sea level								
	Vibration		5.9m/s^2 or less at 10 to 55Hz (directions of X, Y and Z axes)								
Mass		[kg]	1.7	1.7	2.1	4.6	4.6	6.2	18	18	19
		[lb]	3.75	3.75	4.63	10.1	10.1	13.7	39.7	39.7	41.9

Note 1. 0.3A is the value applicable when all I/O signals are used. The current capacity can be decreased by reducing the number of I/O points.
2. Use an external dynamic brake for this servo amplifier. Failure to do so will cause an accident because the servo motor does not stop immediately but coasts at an emergency stop and such conditions. Ensure the safety in the entire system.

1.4 Function list

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

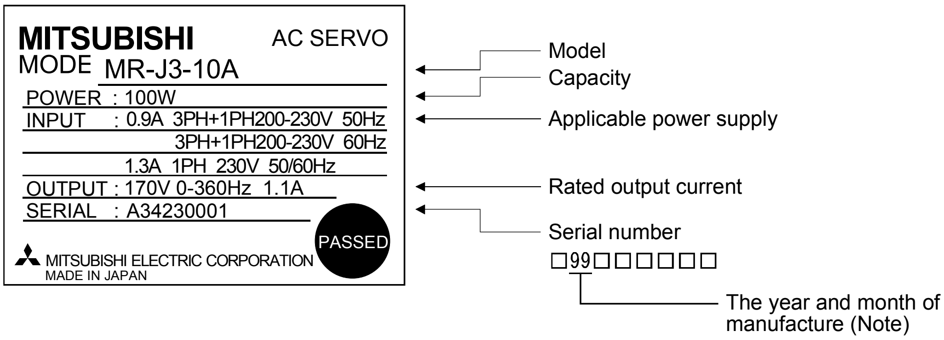
Function	Description	(Note) Control mode	Reference
Position control mode	This servo is used as position control servo.	P	Section 3.2.1 Section 3.6.1 Section 4.2
Speed control mode	This servo is used as speed control servo.	S	Section 3.2.2 Section 3.6.2 Section 4.3
Torque control mode	This servo is used as torque control servo.	T	Section 3.2.3 Section 3.6.3 Section 4.4
Position/speed control change mode	Using input device, control can be switched between position control and speed control.	P/S	Section 3.6.4
Speed/torque control change mode	Using input device, control can be switched between speed control and torque control.	S/T	Section 3.6.5
Torque/position control change mode	Using input device, control can be switched between torque control and position control.	T/P	Section 3.6.6
High-resolution encoder	High-resolution encoder of 262144 pulses/rev is used as a servo motor encoder.	P, S, T	
Absolute position detection system	Merely setting a home position once makes home position return unnecessary at every power-on.	P	Chapter 14
Gain changing function	You can switch between gains during rotation and gains during stop or use an input device to change gains during operation.	P, S	Section 8.6
Advanced vibration suppression control	This function suppresses vibration at the arm end or residual vibration.	P	Section 8.4
Adaptive filter Ⅱ	Servo amplifier detects mechanical resonance and sets filter characteristics automatically to suppress mechanical vibration.	P, S, T	Section 8.2
Low-pass filter	Suppresses high-frequency resonance which occurs as servo system response is increased.	P, S, T	Section 8.5
Machine analyzer function	Analyzes the frequency characteristic of the mechanical system by simply connecting a personal computer installed MR Configurator with a servo amplifier. MR Configurator is necessary for this function.	P	
Machine simulation	Can simulate machine motions on a personal computer screen on the basis of the machine analyzer results. MR Configurator is necessary for this function.	P	
Gain search function	Personal computer changes gains automatically and searches for overshoot-free gains in a short time. MR Configurator is necessary for this function.	P	
Robust disturbance compensation	This function provides better disturbance response in case of low response level due to high load inertia moment ratio for the roll send axes. MR Configurator is necessary for this function.	P, S, T	
Advanced Gain search	Advanced Gain search automatically searches for the optimum parameter for settle time to be short. The gain can be adjusted by setting sequentially in accordance with wizard screens. MR Configurator is necessary for this function.	P	
Slight vibration suppression control	Suppresses vibration of ±1 pulse produced at a servo motor stop.	P	Parameters No.PB24
Electronic gear	Input pulses can be multiplied by 1/50 to 50.	P	Parameters No.PA06, PA07
Auto tuning	Automatically adjusts the gain to optimum value if load applied to the servo motor shaft varies. Higher in performance than MR-J2-Super series servo amplifier.	P, S	Chapter 7

Function	Description	(Note) Control mode	Reference
Position smoothing	Speed can be increased smoothly in response to input pulse.	P	Parameter No.PB03
S-pattern acceleration/ deceleration time constant	Speed can be increased and decreased smoothly.	S, T	Parameter No.PC03
Regenerative option	Used when the built-in regenerative resistor of the servo amplifier does not have sufficient regenerative capability for the regenerative power generated.	P, S, T	Section 12.2
Brake unit	Used when the regenerative option cannot provide enough regenerative power. Can be used with the MR-J3-500A ▪ MR-J3-700A.	P, S, T	Section 12.3
Return converter	Used when the regenerative option cannot provide enough regenerative power. Can be used with the MR-J3-500A ▪ MR-J3-700A.	P, S, T	Section 12.4
Alarm history clear	Alarm history is cleared.	P, S, T	Parameter No.PC18
Restart after instantaneous power failure	If the input power supply voltage had reduced to cause an alarm but has returned to normal, the servo motor can be restarted by merely switching on the start signal.	S	Parameter No.PC22
Command pulse selection	Command pulse train form can be selected from among three different types.	P	Section 5.1.12
Input signal selection (Device settings)	Forward rotation start, reverse rotation start, servo-on (SON) and other input device can be assigned to certain pins of the CN1 connectors.	P, S, T	Parameters No.PD03 to PD08, PD10 to PD12
Output signal selection (Device settings)	Trouble (ALM), dynamic brake interlock (MBR) and other output device can be assigned to certain pins of the CN1 connectors.	P, S, T	Parameters No.PD13 to PD16, PD18
Torque limit	Servo motor torque can be limited to any value.	P, S	Section 3.6.1 (5) Section 5.1.11
Speed limit	Servo motor speed can be limited to any value.	T	Section 3.6.3 (3) Parameter No.PC05 to PC11
Status display	Servo status is shown on the 5-digit, 7-segment LED display	P, S, T	Section 6.3
External I/O signal display	ON/OFF statuses of external I/O signals are shown on the display.	P, S, T	Section 6.7
Output signal (DO) forced output	Output signal can be forced on/off independently of the servo status. Use this function for output signal wiring check, etc.	P, S, T	Section 6.8
Automatic VC offset	Voltage is automatically offset to stop the servo motor if it does not come to a stop at the analog speed command (VC) or analog speed limit (VLA) of 0V.	S, T	Section 6.4
Test operation mode	JOG operation, positioning operation, motor-less operation, DO forced output and program operation. However, MR Configurator is necessary for positioning operation and program operation.	P, S, T	Section 6.9
Analog monitor output	Servo status is output in terms of voltage in real time.	P, S, T	Parameter No.PC14
MR Configurator	Using a personal computer, parameter setting, test operation, status display, etc. can be performed.	P, S, T	Section 12.8
Alarm code output	If an alarm has occurred, the corresponding alarm number is output in 3-bit code.	P, S, T	Section 9.1
Amplifier diagnosis function	The DI/DO signals, analog monitor input I/F, analog monitor output, command pulse I/F and encoder pulse output are checked. The diagnosis cable (MR-J3ACHECK) and MR Configurator are necessary for this function.	P, S, T	Section 12.8 (2)(C)

Note. P: Position control mode, S: Speed control mode, T: Torque control mode
P/S: Position/speed control change mode, S/T: Speed/torque control change mode, T/P: Torque/position control change mode

1.5 Model code definition

(1) Rating plate



Note. Production year and month of the servo amplifier are indicated in a serial number on the rating plate. The year and month of manufacture are indicated by the last one digit of the year and 1 to 9, X(10), Y(11), Z(12).
For September 2009, the Serial No. is like, "SERIAL □99□□□□□□".

(2) Model

MR－J3－□A□□

Series

Special specification

Symbol	Special specification	Regenerative resistor equipped as standard
-PX	Servo amplifiers of 11k to 22kW (Except the ones that support the HF-JP series servo motors)	Not available
-LR	HF-JP series Servo amplifiers dedicated to the 11kW and 15kW servo motors	Equipped
-LW		Not available
-U1□□	HF-JP series Servo amplifiers for the 0.5k to 5kW servo motors that support the 400% maximum torque setting	Built-in regenerative resistor

Rated output

Symbol	Rated output [kW]
10	0.1
20	0.2
40	0.4
60	0.6
70	0.75
100	1
200	2
350	3.5
500	5
700	7
11K	11
15K	15
22K	22

Power supply

Symbol	Power supply
None (Note 1)	3-phase or 1-phase 200 to 230VAC
(Note 2) 1	1-phase 100 to 120VAC
(Note 3) 4	3-phase 380 to 480VAC

Note 1. 1-phase 200 to 230VAC is supported by 750W or less.
2. 1-phase 100 to 120VAC is supported by 400W or less.
3. 3-phase 380 to 480VAC is supported by 600W and 1kW or more.

General purpose interface

1.6 Combination with servo motor

The following table lists combinations of servo amplifiers and servo motors. The same combinations apply to the models with an electromagnetic brake and the models with a reduction gear.

Servo amplifier	Servo motors						
	HF-MP□	HF-KP□	HF-SP□		HC-RP□	HC-UP□	HC-LP□
			1000r/min	2000r/min			
MR-J3-10A (1)	053・13	053・13					
MR-J3-20A (1)	23	23					
MR-J3-40A (1)	43	43					
MR-J3-60A			51	52			52
MR-J3-70A	73	73				72	
MR-J3-100A			81	102			102
MR-J3-200A			121・201	152・202	103・153	152	152
MR-J3-350A			301	352	203	202	202
MR-J3-500A			421	502	353・503	352・502	302
MR-J3-700A				702			
MR-J3-11KA							
MR-J3-15KA							
MR-J3-22KA							

Servo amplifier	Servo motors				
	HA-LP□			HF-JP□	
	1000r/min	1500r/min	2000r/min	1500r/min	3000r/min
MR-J3-60A					53
MR-J3-70A					73
MR-J3-100A					103
MR-J3-200A					153・203
MR-J3-350A					353
MR-J3-500A			502		503
MR-J3-700A	601	701M	702		
MR-J3-11KA	801・12K1	11K1M	11K2	11K1M (Note)	
MR-J3-15KA	15K1	15K1M	15K2	15K1M (Note)	
MR-J3-22KA	20K1・25K1	22K1M	22K2		

Servo amplifier	Servo motors					
	HF-SP□	HA-LP□			HF-JP□	
		1000r/min	1500r/min	2000r/min	1500r/min	3000r/min
MR-J3-60A4	524					534
MR-J3-100A4	1024					734・1034
MR-J3-200A4	1524・2024					1534・2034
MR-J3-350A4	3524					3534
MR-J3-500A4	5024					5034
MR-J3-700A4	7024	6014	701M4			
MR-J3-11KA4		8014・12K14	11K1M4	11K24	11K1M4 (Note)	
MR-J3-15KA4		15K14	15K1M4	15K24	15K1M4 (Note)	
MR-J3-22KA4		20K14	22K1M4	22K24		

Note. The servo amplifiers, which support these servo motors, have "-LR" at the end of their model names.

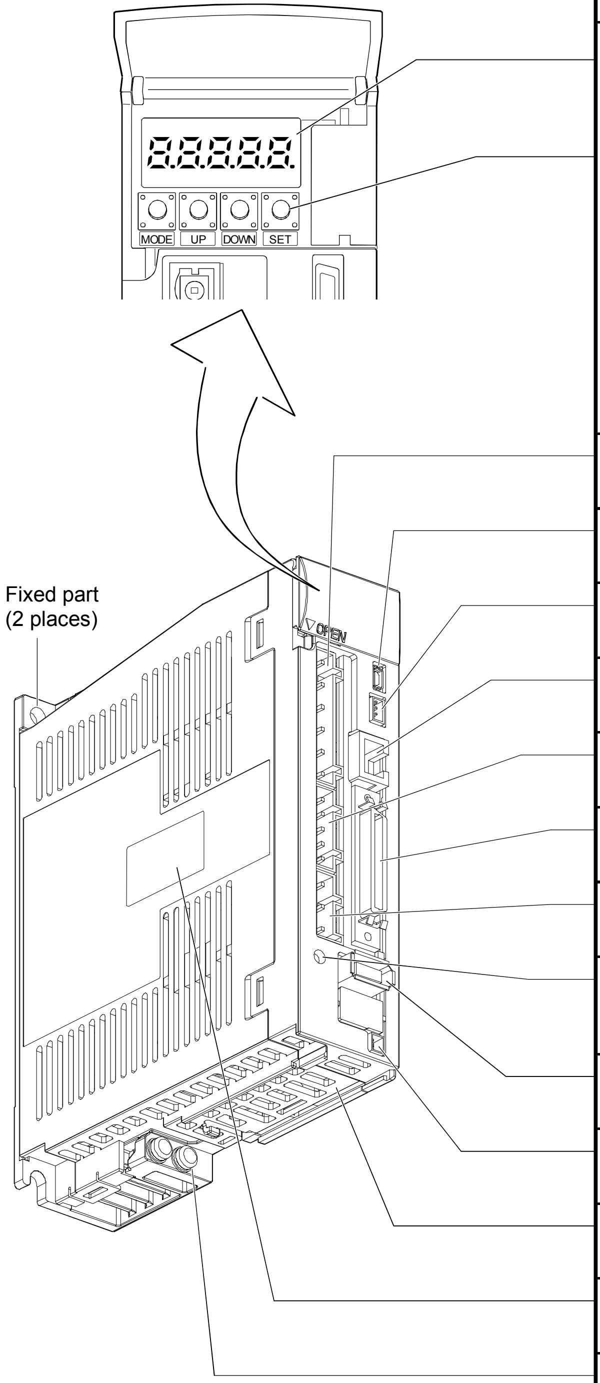
Servo amplifiers supporting the 400% maximum torque setting	Servo motor
	HF-JP□
MR-J3-100A-U100	53
MR-J3-200A-U101	73
MR-J3-200A-U102	103
MR-J3-350A-U103	153
MR-J3-350A-U104	203
MR-J3-500A-U105	353
MR-J3-700A-U106	503

Servo amplifiers supporting the 400% maximum torque setting	Servo motor
	HF-JP□
MR-J3-100A4-U110	534
MR-J3-200A4-U111	734
MR-J3-200A4-U112	1034
MR-J3-350A4-U113	1534
MR-J3-350A4-U114	2034
MR-J3-500A4-U115	3534
MR-J3-700A4-U116	5034

1.7 Structure

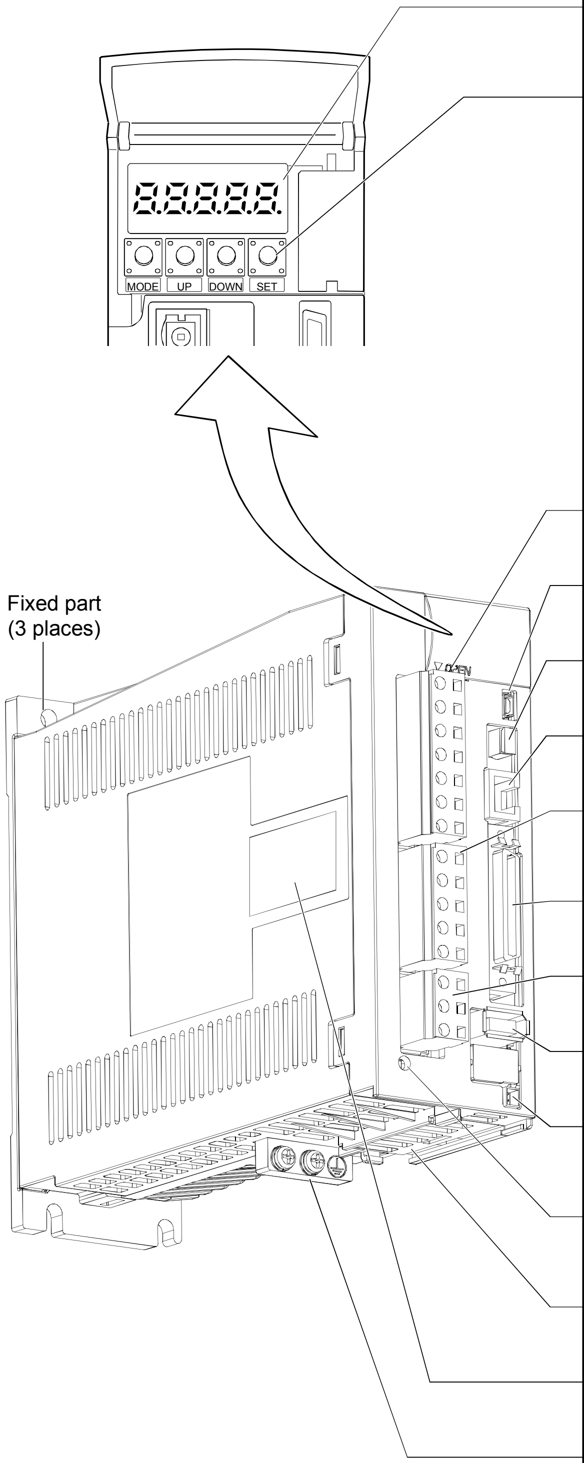
1.7.1 Parts identification

(1) MR-J3-100A or less



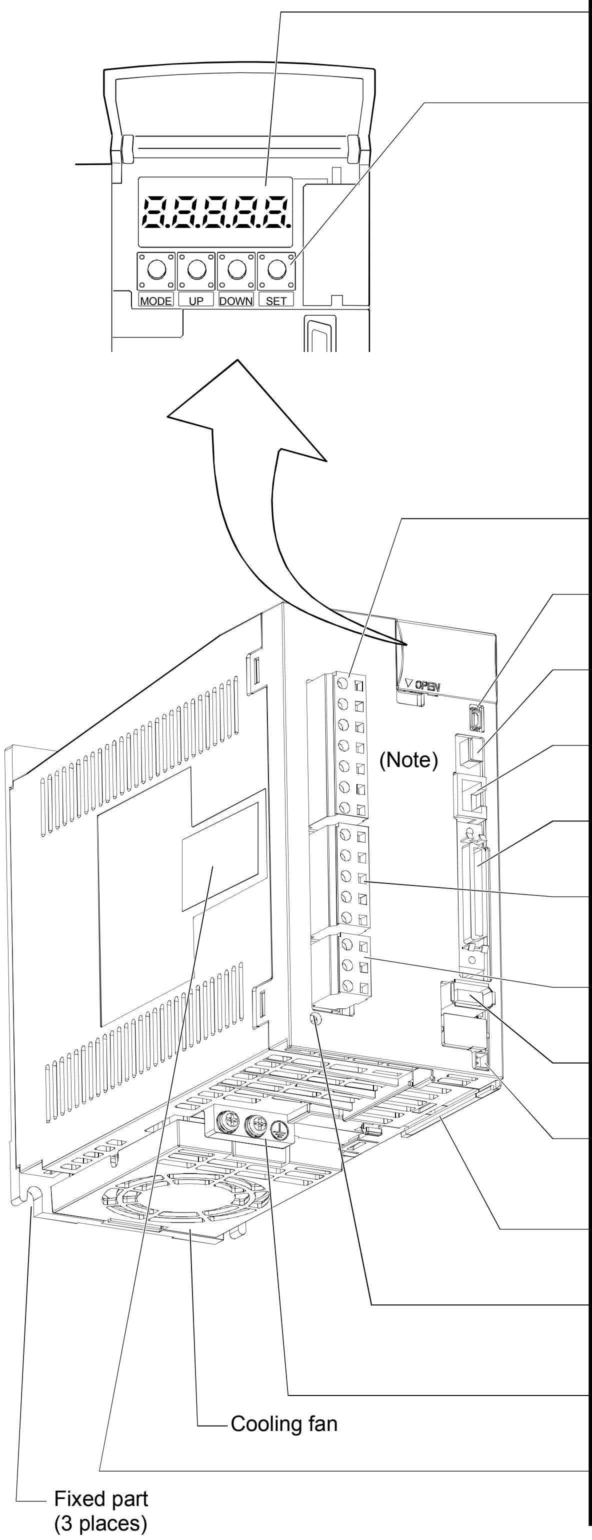
Name/Application	Detailed explanation
Display The 5-digit, seven-segment LED shows the servo status and alarm number.	Chapter 6
Operation section Used to perform status display, diagnostic, alarm and parameter setting operations. ⦿ MODE ⦿ UP ⦿ DOWN ⦿ SET SET: Used to set data. UP, DOWN: Used to change the display or data in each mode. MODE: Used to change the mode.	Chapter 6
Main circuit power supply connector (CNP1) Connect the input power supply.	Section 3.1 Section 3.3
USB communication connector (CN5) Connect the personal computer.	Section 12.8
Analog monitor connector (CN6) Outputs the analog monitor.	Section 3.2 Section 3.4
RS-422 communication connector (CN3) Connect the personal computer.	Section 12.8 Chapter 13
Control circuit connector (CNP2) Connect the control circuit power supply/regenerative option.	Section 3.1 Section 3.3
I/O signal connector (CN1) Used to connect digital I/O signals.	Section 3.2 Section 3.4
Servo motor power connector (CNP3) Connect the servo motor.	Section 3.1 Section 3.3
Charge lamp Lit to indicate that the main circuit is charged. While this lamp is lit, do not reconnect the cables.	
Encoder connector (CN2) Used to connect the servo motor encoder.	Section 3.4 Section 12.1
Battery connector (CN4) Used to connect the battery for absolute position data backup.	Section 12.9 Chapter 14
Battery holder Contains the battery for absolute position data backup.	Section 14.3
Rating plate	Section 1.5
Protective earth (PE) terminal (⏚) Ground terminal.	Section 3.1 Section 3.3

(2) MR-J3-60A4・MR-J3-100A4



Name/Application	Detailed explanation
Display The 5-digit, seven-segment LED shows the servo status and alarm number.	Chapter 6
Operation section Used to perform status display, diagnostic, alarm and parameter setting operations. ● MODE ● UP ● DOWN ● SET SET: Used to set data. UP, DOWN: Used to change the display or data in each mode. MODE: Used to change the mode.	Chapter 6
Main circuit power supply connector (CNP1) Connect the input power supply.	Section 3.1 Section 3.3
USB communication connector (CN5) Connect the personal computer.	Section 12.8
Analog monitor connector (CN6) Outputs the analog monitor.	Section 3.2 Section 3.4
RS-422 communication connector (CN3) Connect the personal computer.	Section 12.8 Chapter 13
Control circuit connector (CNP2) Connect the control circuit power supply/regenerative option.	Section 3.1 Section 3.3
I/O signal connector (CN1) Used to connect digital I/O signals.	Section 3.2 Section 3.4
Servo motor power connector (CNP3) Connect the servo motor.	Section 3.1 Section 3.3
Encoder connector (CN2) Used to connect the servo motor encoder.	Section 3.4 Section 12.1
Battery connector (CN4) Used to connect the battery for absolute position data backup.	Section 12.9 Chapter 14
Charge lamp Lit to indicate that the main circuit is charged. While this lamp is lit, do not reconnect the cables.	
Battery holder Contains the battery for absolute position data backup.	Section 14.3
Rating plate	Section 1.5
Protective earth (PE) terminal (⏚) Ground terminal.	Section 3.1 Section 3.3

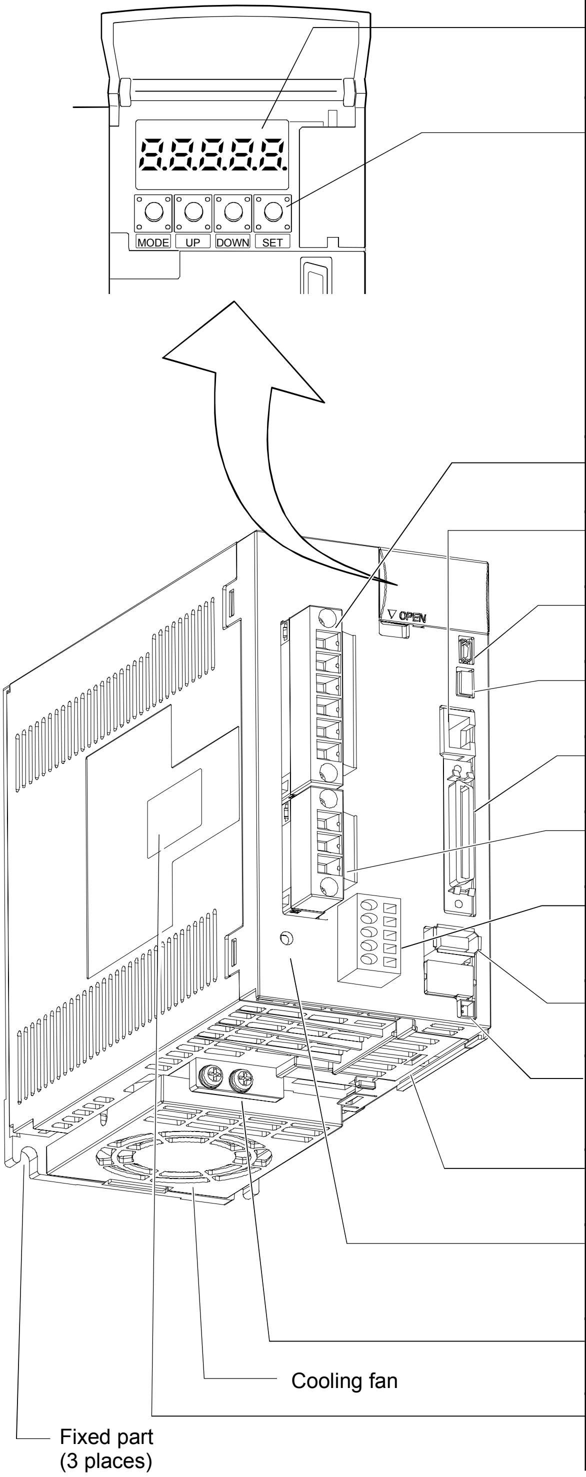
(3) MR-J3-200A(4)



Name/Application	Detailed explanation
Display The 5-digit, seven-segment LED shows the servo status and alarm number.	Chapter 6
Operation section Used to perform status display, diagnostic, alarm and parameter setting operations. ● MODE ● UP ● DOWN ● SET SET: Used to set data. UP, DOWN: Used to change the display or data in each mode. MODE: Used to change the mode.	Chapter 6
Main circuit power supply connector (CNP1) Connect the input power supply.	Section 3.1 Section 3.3
USB communication connector (CN5) Connect the personal computer.	Section 12.8
Analog monitor connector (CN6) Outputs the analog monitor.	Section 3.2 Section 3.4
RS-422 communication connector (CN3) Connect the personal computer.	Section 12.8 Chapter 13
I/O signal connector (CN1) Used to connect digital I/O signals.	Section 3.2 Section 3.4
Control circuit connector (CNP2) Connect the control circuit power supply/regenerative option.	Section 3.1 Section 3.3
Servo motor power connector (CNP3) Connect the servo motor.	Section 3.1 Section 3.3
Encoder connector (CN2) Used to connect the servo motor encoder.	Section 3.4 Section 12.1
Battery connector (CN4) Used to connect the battery for absolute position data backup.	Section 12.9 Chapter 14
Battery holder Contains the battery for absolute position data backup.	Section 14.3
Charge lamp Lit to indicate that the main circuit is charged. While this lamp is lit, do not reconnect the cables.	
Protective earth (PE) terminal (⏚) Ground terminal.	Section 3.1 Section 3.3
Rating plate	Section 1.5

Note. Connectors (CNP1, CNP2, and CNP3) and appearance of MR-J3-200A servo amplifier have been changed from April 2008 production. Model name of the servo amplifier before March 2008 is changed to MR-J3-200A-RT. For MR-J3-200A-RT, refer to appendix 5.

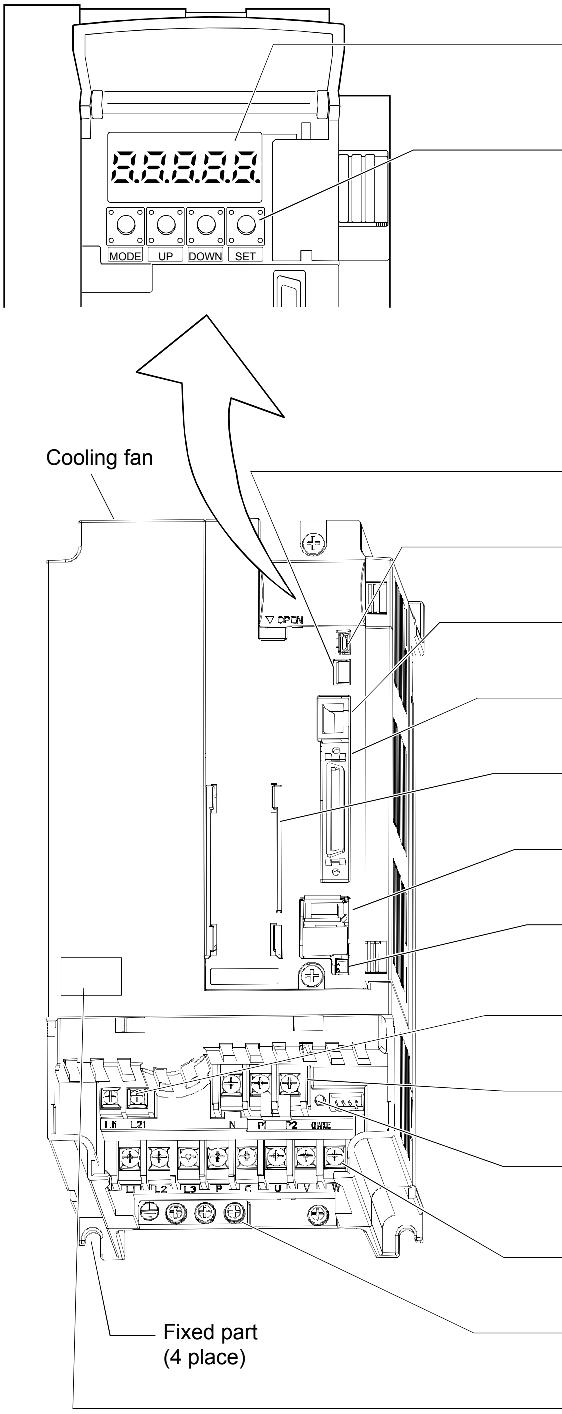
(4) MR-J3-350A



Name/Application	Detailed explanation
Display The 5-digit, seven-segment LED shows the servo status and alarm number.	Chapter 6
Operation section Used to perform status display, diagnostic, alarm and parameter setting operations. ⦿ ⦿ ⦿ ⦿ MODE UP DOWN SET Used to set data. Used to change the display or data in each mode. Used to change the mode.	Chapter 6
Main circuit power supply connector (CNP1) Connect the input power supply.	Section 3.1 Section 3.3
RS-422 communication connector (CN3) Connect the personal computer.	Section 12.8 Chapter 13
USB communication connector (CN5) Connect the personal computer.	Section 12.8
Analog monitor connector (CN6) Outputs the analog monitor.	Section 3.2 Section 3.4
I/O signal connector (CN1) Used to connect digital I/O signals.	Section 3.2 Section 3.4
Servo motor power connector (CNP3) Connect the servo motor.	Section 3.1 Section 3.3
Control circuit connector (CNP2) Connect the control circuit power supply/regenerative option.	Section 3.1 Section 3.3
Encoder connector (CN2) Used to connect the servo motor encoder.	Section 3.4 Section 12.1
Battery connector (CN4) Used to connect the battery for absolute position data backup.	Section 12.9 Chapter 14
Battery holder Contains the battery for absolute position data backup.	Section 14.3
Charge lamp Lit to indicate that the main circuit is charged. While this lamp is lit, do not reconnect the cables.	
Protective earth (PE) terminal (⏚) Ground terminal.	Section 3.1 Section 3.3
Rating plate	Section 1.5

(5) MR-J3-350A4 · MR-J3-500A(4)

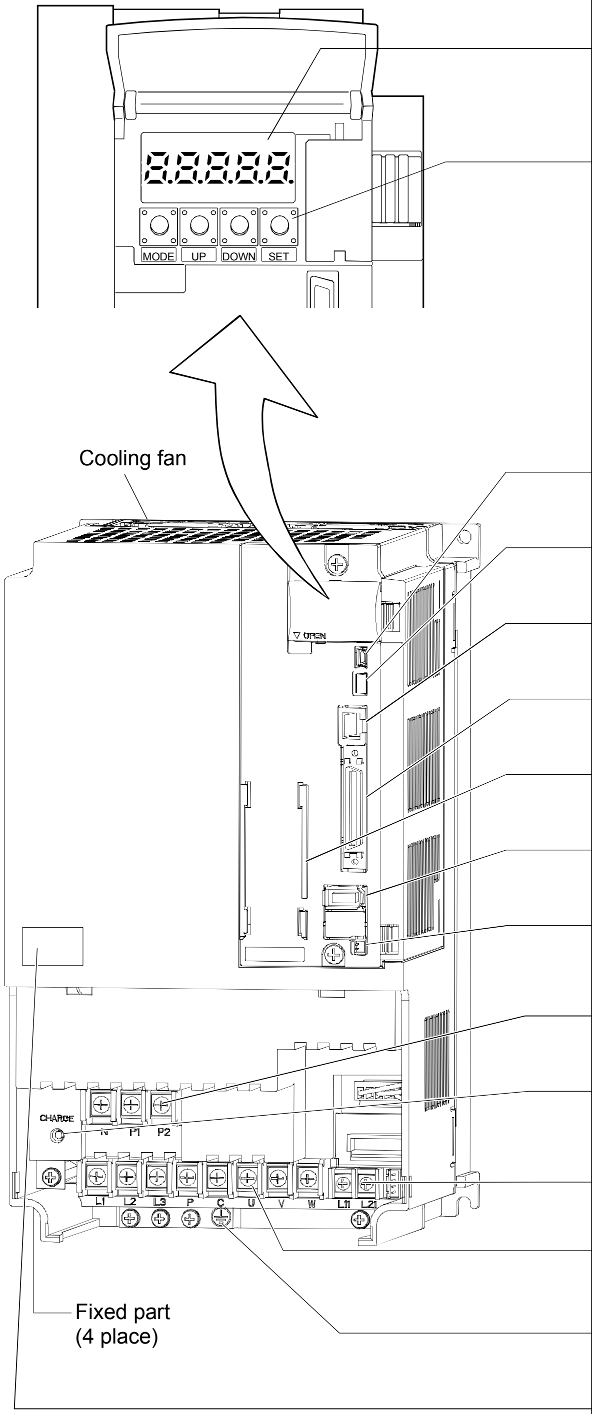
POINT
· The servo amplifier is shown without the front cover. For removal of the front cover, refer to section 1.7.2.



Name/Application	Detailed explanation
Display The 5-digit, seven-segment LED shows the servo status and alarm number.	Chapter 6
Operation section Used to perform status display, diagnostic, alarm and parameter setting operations. ⊙ MODE ⊙ UP ⊙ DOWN ⊙ SET Used to set data. Used to change the display or data in each mode. Used to change the mode.	Chapter 6
Analog monitor connector (CN6) Outputs the analog monitor.	Section 3.2 Section 3.4
USB communication connector (CN5) Connect the personal computer.	Section 12.8
RS-422 communication connector (CN3) Connect the personal computer.	Section 12.8 Chapter 13
I/O signal connector (CN1) Used to connect digital I/O signals.	Section 3.2 Section 3.4
Battery holder Contains the battery for absolute position data backup.	Section 14.3
Encoder connector (CN2) Used to connect the servo motor encoder.	Section 3.4 Section 12.1
Battery connector (CN4) Used to connect the battery for absolute position data backup.	Section 12.9 Chapter 14
Control circuit terminal block (TE2) Used to connect the control circuit power supply.	Section 3.1 Section 3.3
Power factor improving DC reactor terminal block (TE3) Used to connect the power factor improving DC reactor.	Section 3.1 Section 3.3
Charge lamp Lit to indicate that the main circuit is charged. While this lamp is lit, do not reconnect the cables.	
Main circuit terminal block (TE1) Used to connect the input power supply and servo motor.	Section 3.1 Section 3.3
Protective earth (PE) terminal (⏚) Ground terminal.	Section 3.1 Section 3.3
Rating plate	Section 1.5

(6) MR-J3-700A(4)

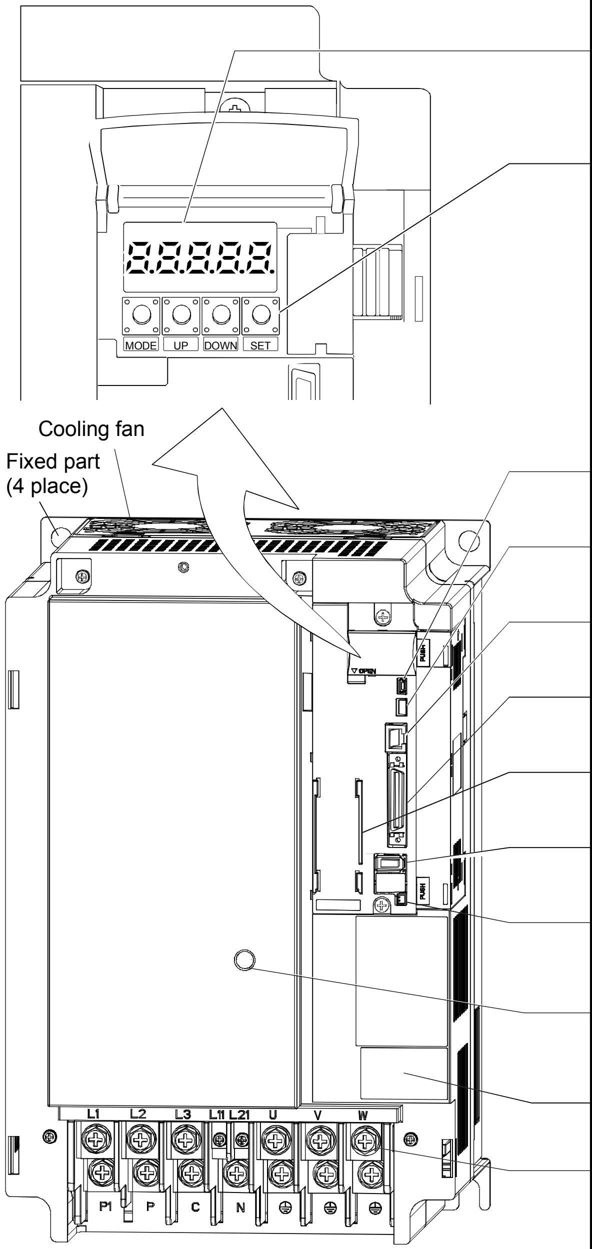
POINT
- The servo amplifier is shown without the front cover. For removal of the front cover, refer to section 1.7.2.



Name/Application	Detailed explanation
Display The 5-digit, seven-segment LED shows the servo status and alarm number.	Chapter 6
Operation section Used to perform status display, diagnostic, alarm and parameter setting operations. ⦿ ⦿ ⦿ ⦿ MODE UP DOWN SET Used to set data. Used to change the display or data in each mode. Used to change the mode.	Chapter 6
USB communication connector (CN5) Connect the personal computer.	Section 12.8
Analog monitor connector (CN6) Outputs the analog monitor.	Section 3.2 Section 3.4
RS-422 communication connector (CN3) Connect the personal computer.	Section 12.8 Chapter 13
I/O signal connector (CN1) Used to connect digital I/O signals.	Section 3.2 Section 3.4
Battery holder Contains the battery for absolute position data backup.	Section 14.3
Encoder connector (CN2) Used to connect the servo motor encoder.	Section 3.4 Section 12.1
Battery connector (CN4) Used to connect the battery for absolute position data backup.	Section 12.9 Chapter 14
Power factor improving DC reactor terminal block (TE3) Used to connect the power factor improving DC reactor.	Section 3.1 Section 3.3
Charge lamp Lit to indicate that the main circuit is charged. While this lamp is lit, do not reconnect the cables.	
Control circuit terminal block (TE2) Used to connect the control circuit power supply.	Section 3.1 Section 3.3
Main circuit terminal block (TE1) Used to connect the input power supply and servo motor.	Section 3.1 Section 3.3
Protective earth (PE) terminal (⏚) Ground terminal.	Section 3.1 Section 3.3
Rating plate	Section 1.5

(7) MR-J3-11KA(4) to MR-J3-22KA(4)

> **POINT**
>
> - The servo amplifier is shown without the front cover. For removal of the front cover, refer to section 1.7.2.



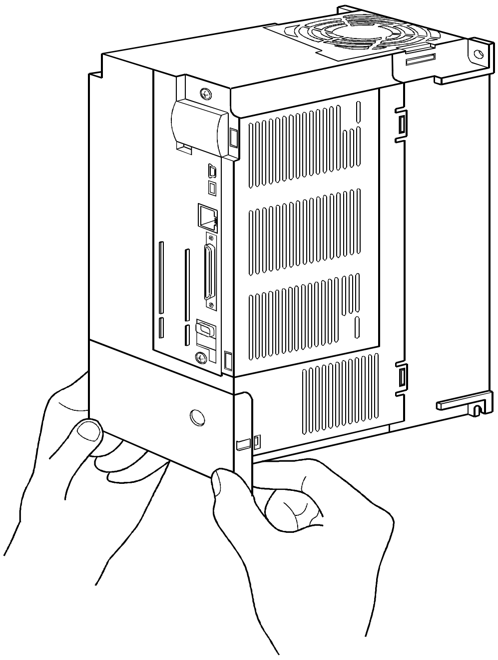
Name/Application	Detailed explanation
Display The 5-digit, seven-segment LED shows the servo status and alarm number.	Chapter 6
Operation section Used to perform status display, diagnostic, alarm and parameter setting operations. ● MODE ● UP ● DOWN ● SET SET: Used to set data. UP, DOWN: Used to change the display or data in each mode. MODE: Used to change the mode.	Chapter 6
USB communication connector (CN5) Connect the personal computer.	Section 12.8
Analog monitor connector (CN6) Outputs the analog monitor.	Section 3.2 Section 3.4
RS-422 communication connector (CN3) Connect the personal computer.	Section 12.8 Chapter 13
I/O signal connector (CN1) Used to connect digital I/O signals.	Section 3.2 Section 3.4
Battery holder Contains the battery for absolute position data backup.	Section 14.3
Encoder connector (CN2) Used to connect the servo motor encoder.	Section 3.4 Section 12.1
Battery connector (CN4) Used to connect the battery for absolute position data backup.	Section 12.9 Chapter 14
Charge lamp Lit to indicate that the main circuit is charged. While this lamp is lit, do not reconnect the cables.	
Rating plate	Section 1.5
Main circuit, control circuit and protective earth (PE)⏚ terminal block Used to connect the input power supply, servo motor, regenerative option and ground.	Section 3.1 Section 3.3

1.7.2 Removal and reinstallation of the front cover

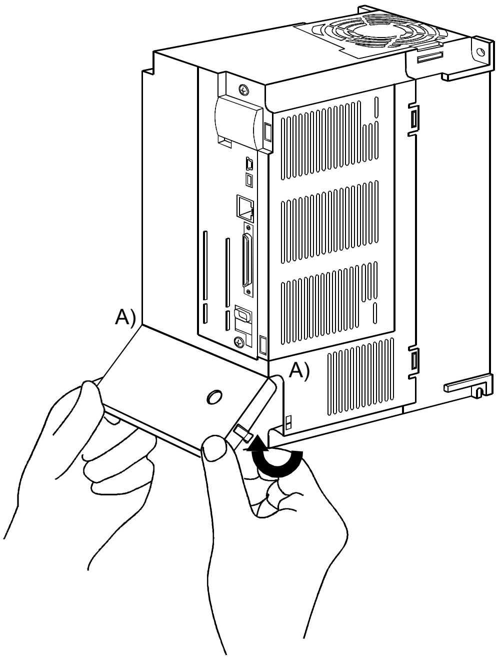
⚠WARNING	・Before removing or installing the front cover, turn off the power and wait for 15 minutes or longer until the charge lamp turns off. Then, confirm that the voltage between P(＋) and N(－) is safe with a voltage tester and others. Otherwise, an electric shock may occur. In addition, always confirm from the front of the servo amplifier whether the charge lamp is off or not.

(1) For MR-J3-350A4・MR-J3-500A(4)・MR-J3-700A(4)

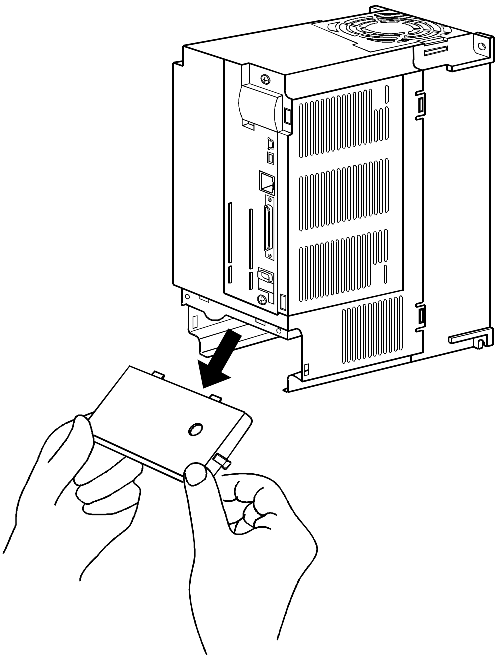
Removal of the front cover



1) Hold the ends of lower side of the front cover with both hands.

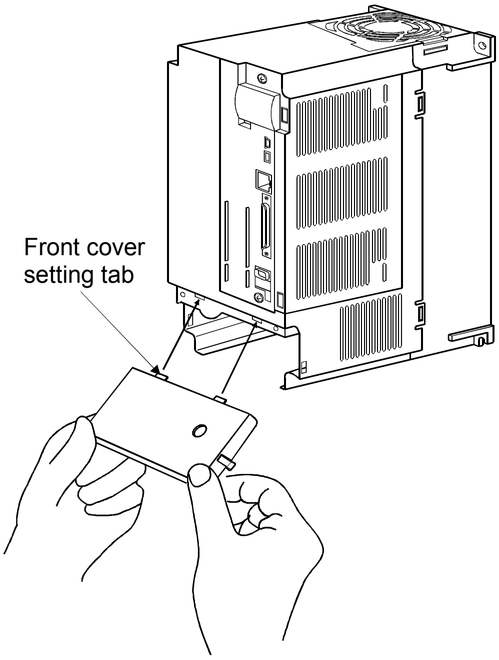


2) Pull up the cover, supporting at point A).

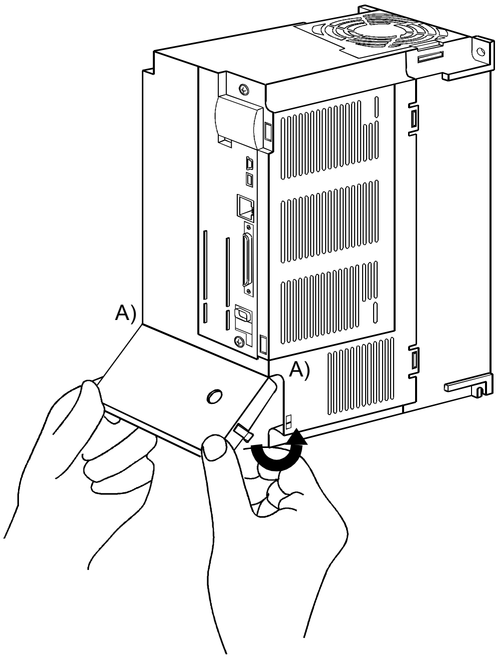


3) Pull out the front cover to remove.

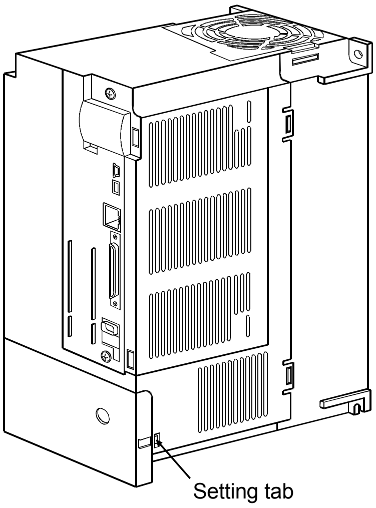
Reinstallation of the front cover



1) Insert the front cover setting tabs into the sockets of servo amplifier (2 places).



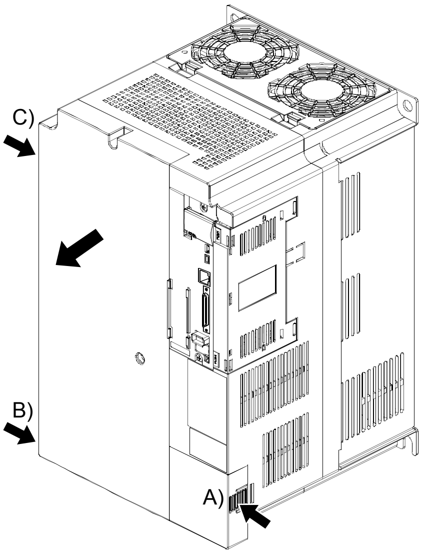
2) Pull up the cover, supporting at point A).

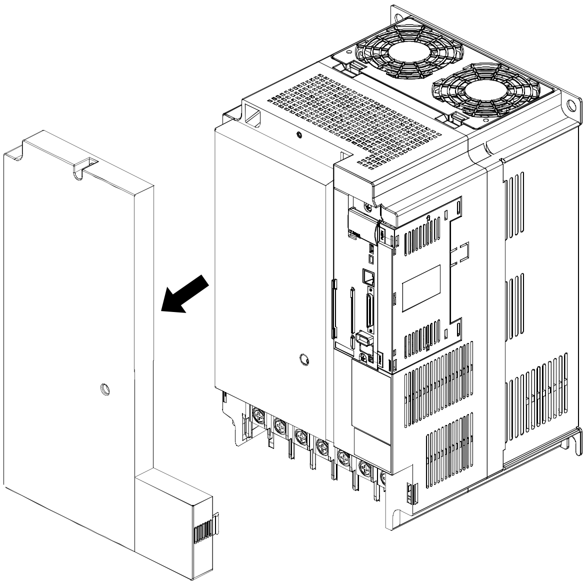


3) Push the setting tabs until they click.

(2) For MR-J3-11KA(4) to MR-J3-22KA(4)

Removal of the front cover

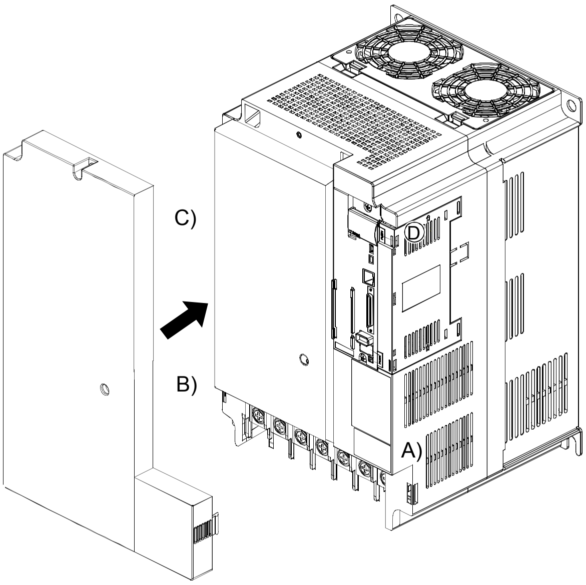


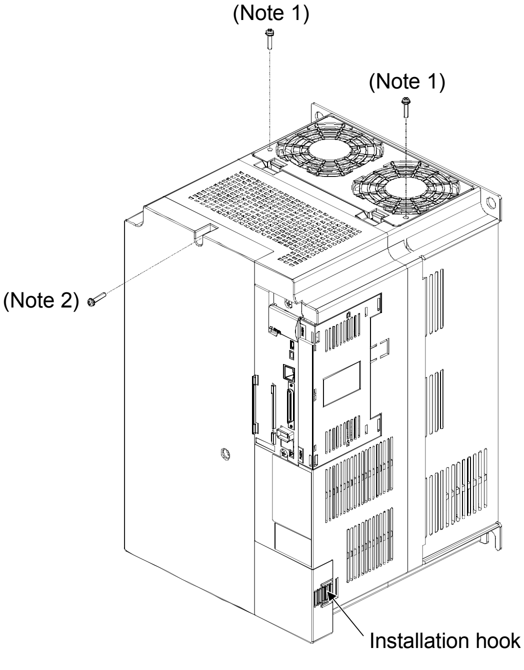


1) Press the removing knob on the lower side of the front cover (A) and B)) and release the installation hook.
2) Press the removing knob of C) and release the installation hook.

3) Pull it to remove the front cover.

Reinstallation of the front cover





1) Fit the front cover installation hooks on the sockets of body cover (A) to B)) to reinstall it.

2) Push the front cover until your hear the clicking noise of the installation hook.

Note 1. The cooling fan cover can be locked with enclosed screws (M4 × 40).

2. By drilling approximately φ4 of a hole on the front cover, the front cover can be locked on the body with an enclosed screw (M4 × 14).

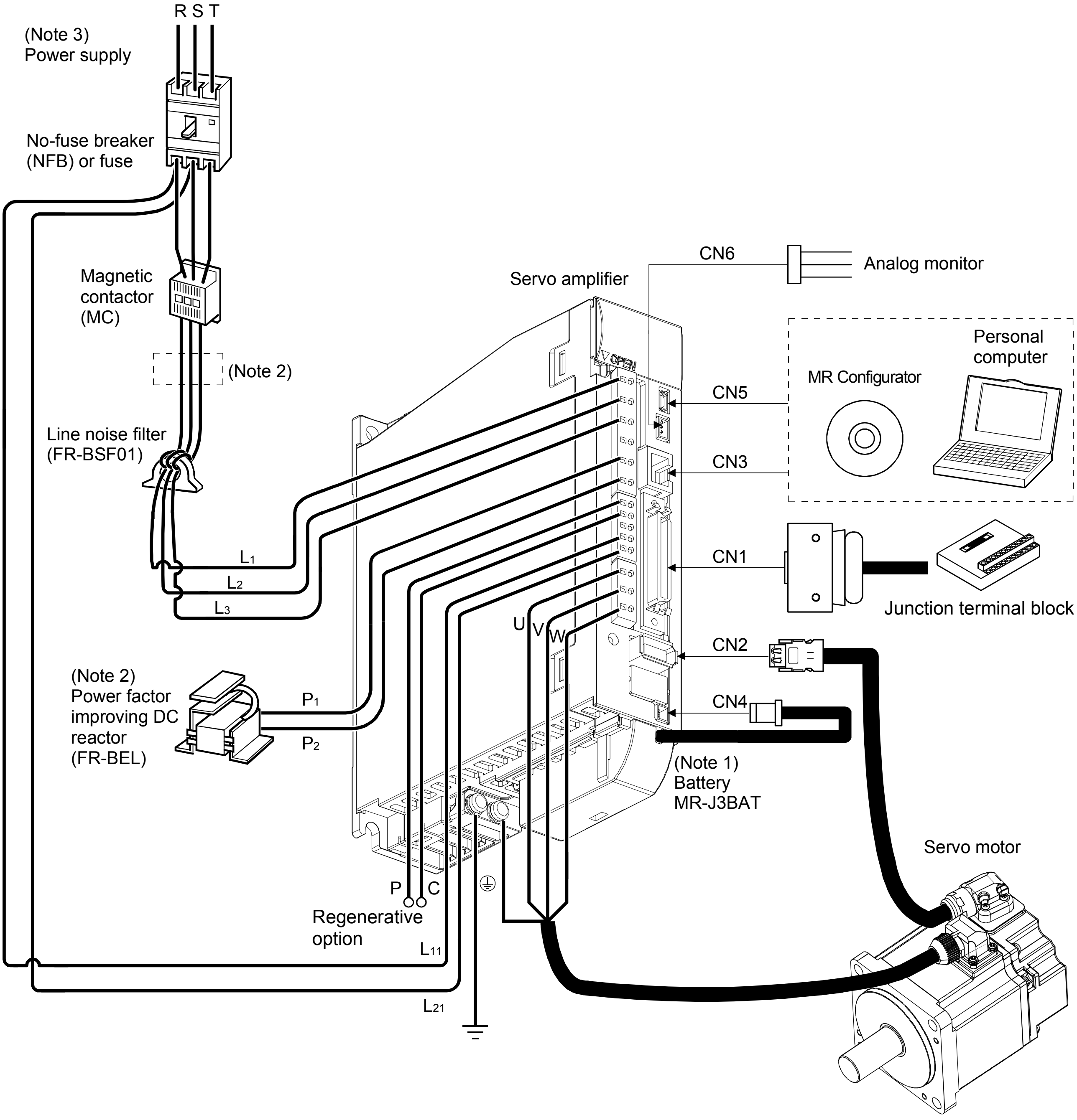
1.8 Configuration including auxiliary equipment

POINT

- Equipment other than the servo amplifier and servo motor are optional or recommended products.

(1) MR-J3-100A or less

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

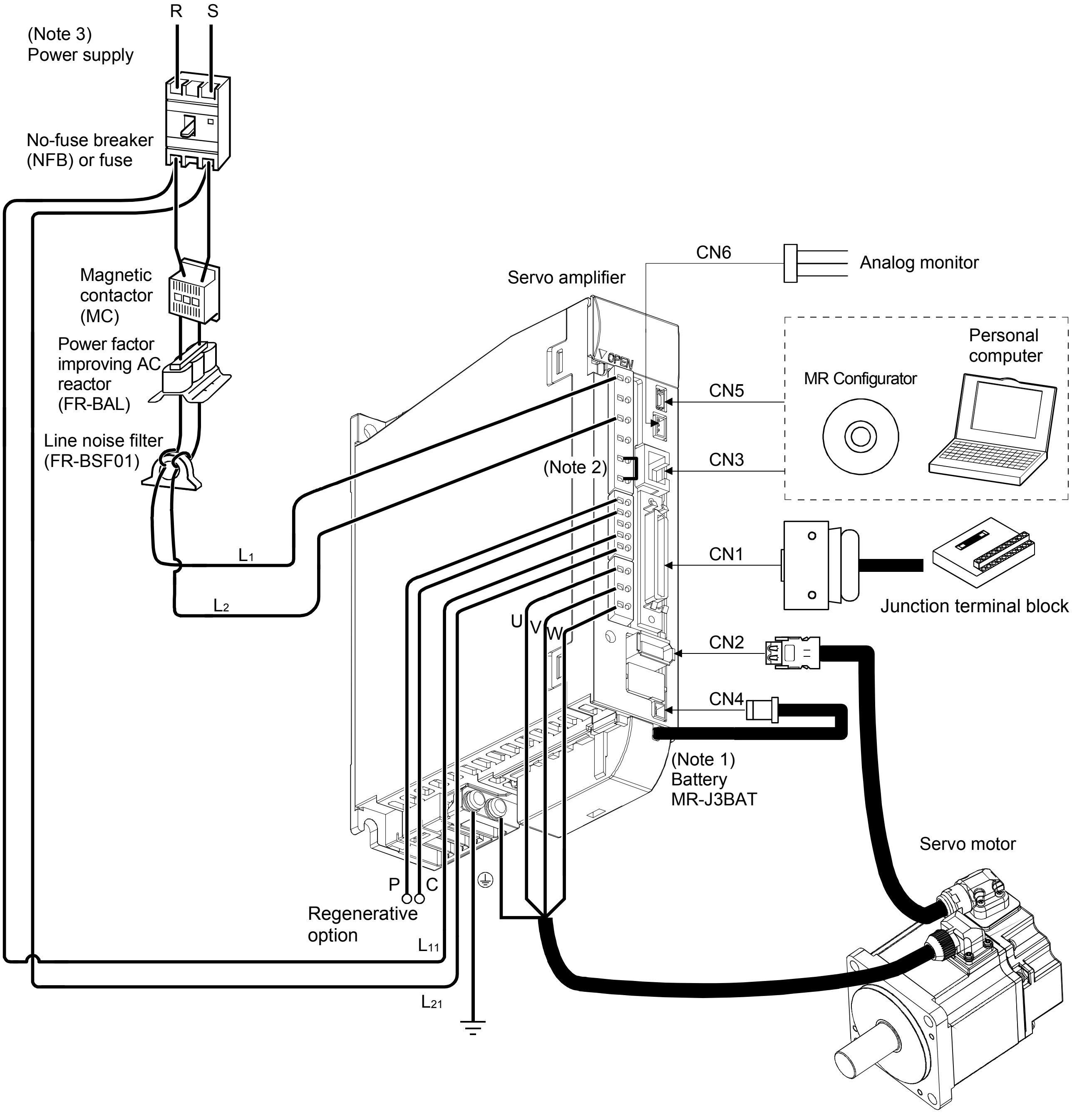


Note 1. The battery (option) is used for the absolute position detection system in the position control mode.

2. The power factor improving AC reactor can also be used. In this case, the power factor improving DC reactor cannot be used. When not using the power factor improving DC reactor, short P_1 and P_2.

3. A 1-phase 200 to 230VAC power supply may be used with the servo amplifier of MR-J3-70A or less. For 1-phase 200 to 230VAC, connect the power supply to L_1 ・ L_2 and leave L_3 open. Refer to section 1.3 for the power supply specification.

(b) For 1-phase 100 to 120VAC

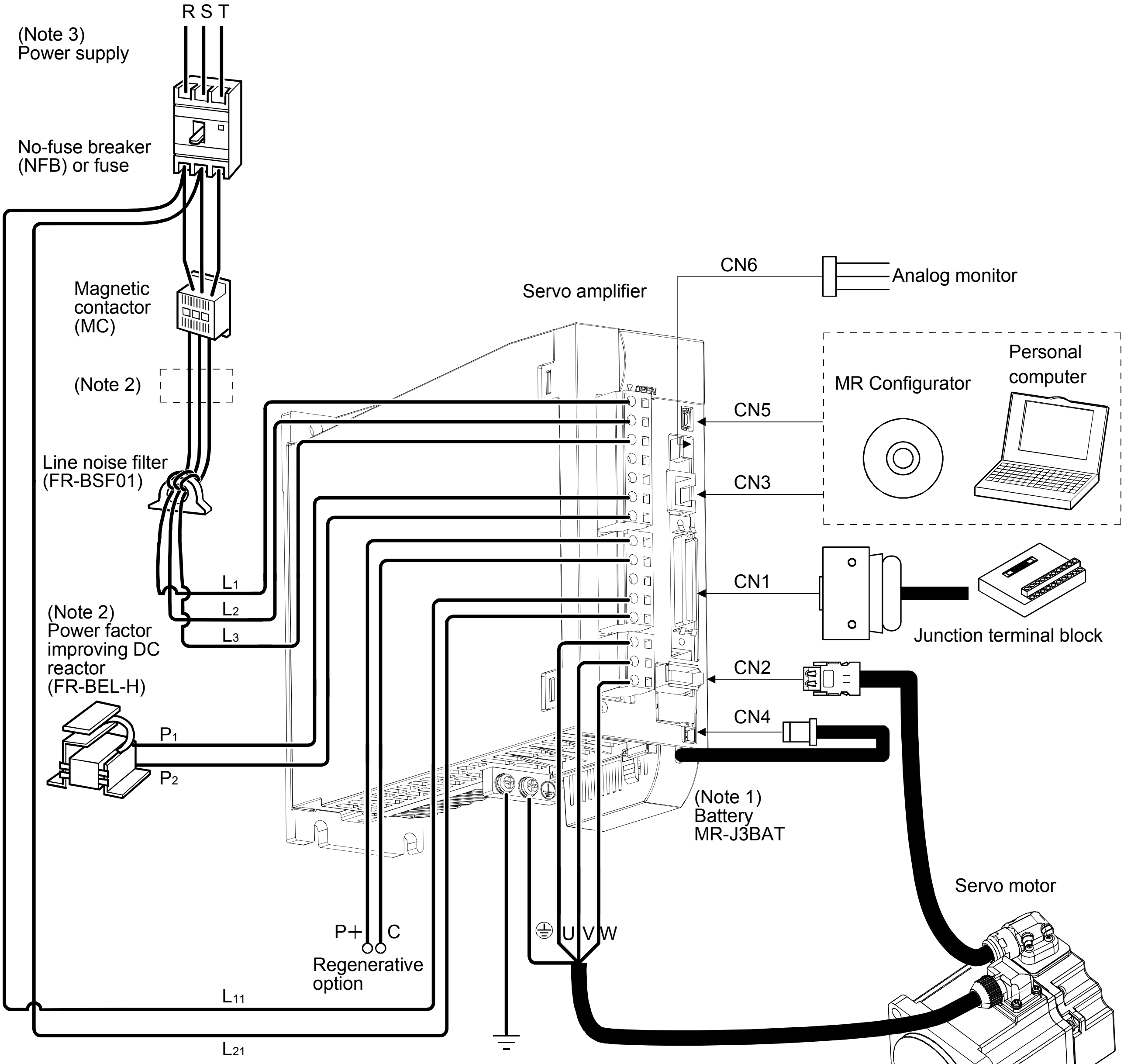


Note 1. The battery (option) is used for the absolute position detection system in the position control mode.

2. The power factor improving DC reactor cannot be used.

3. Refer to section 1.3 for the power supply specification.

(2) MR-J3-60A4 · MR-J3-100A4

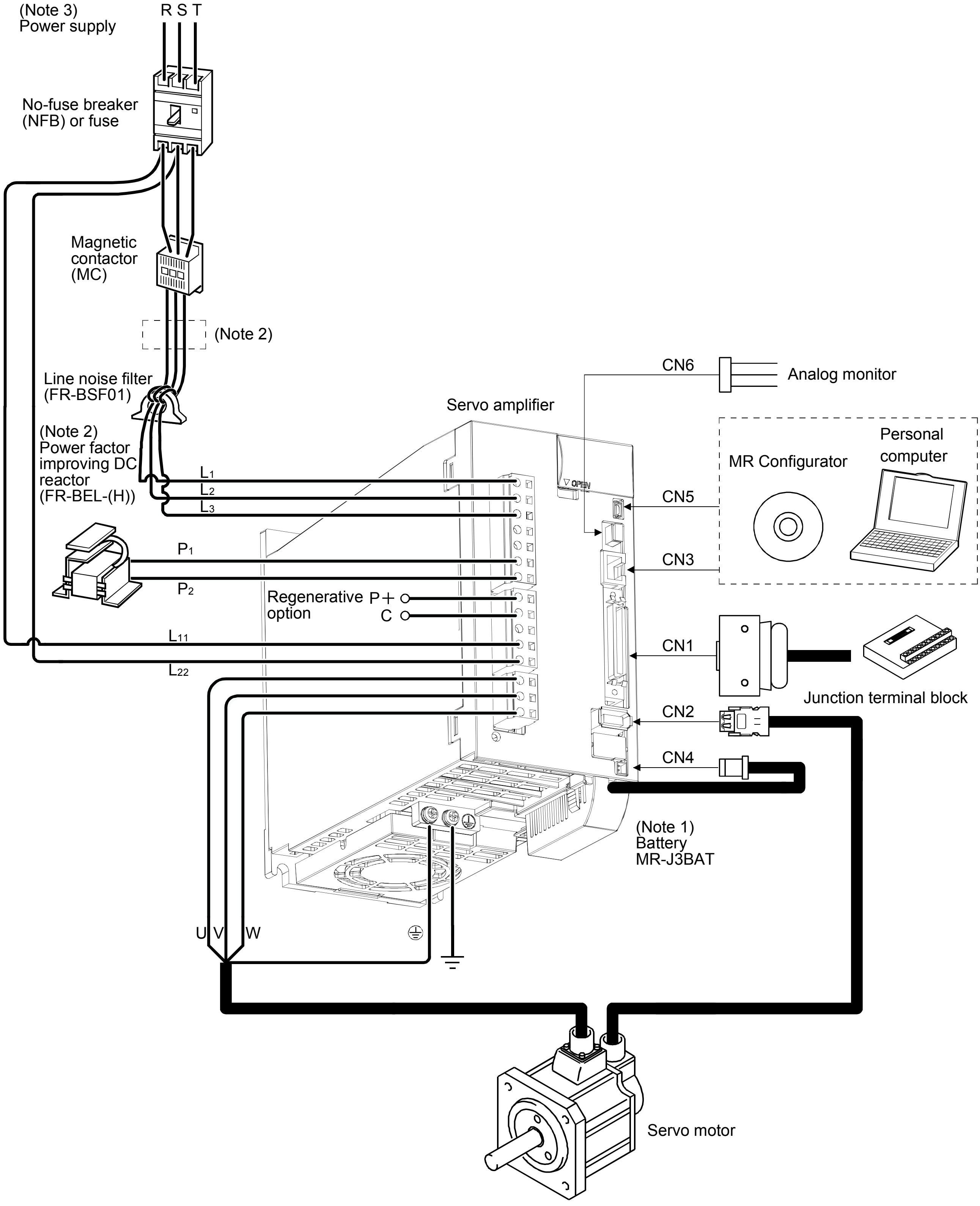


Note 1. The battery (option) is used for the absolute position detection system in the position control mode.

2. The power factor improving AC reactor can also be used. In this case, the power factor improving DC reactor cannot be used. When not using the power factor improving DC reactor, short P_1 and P_2.

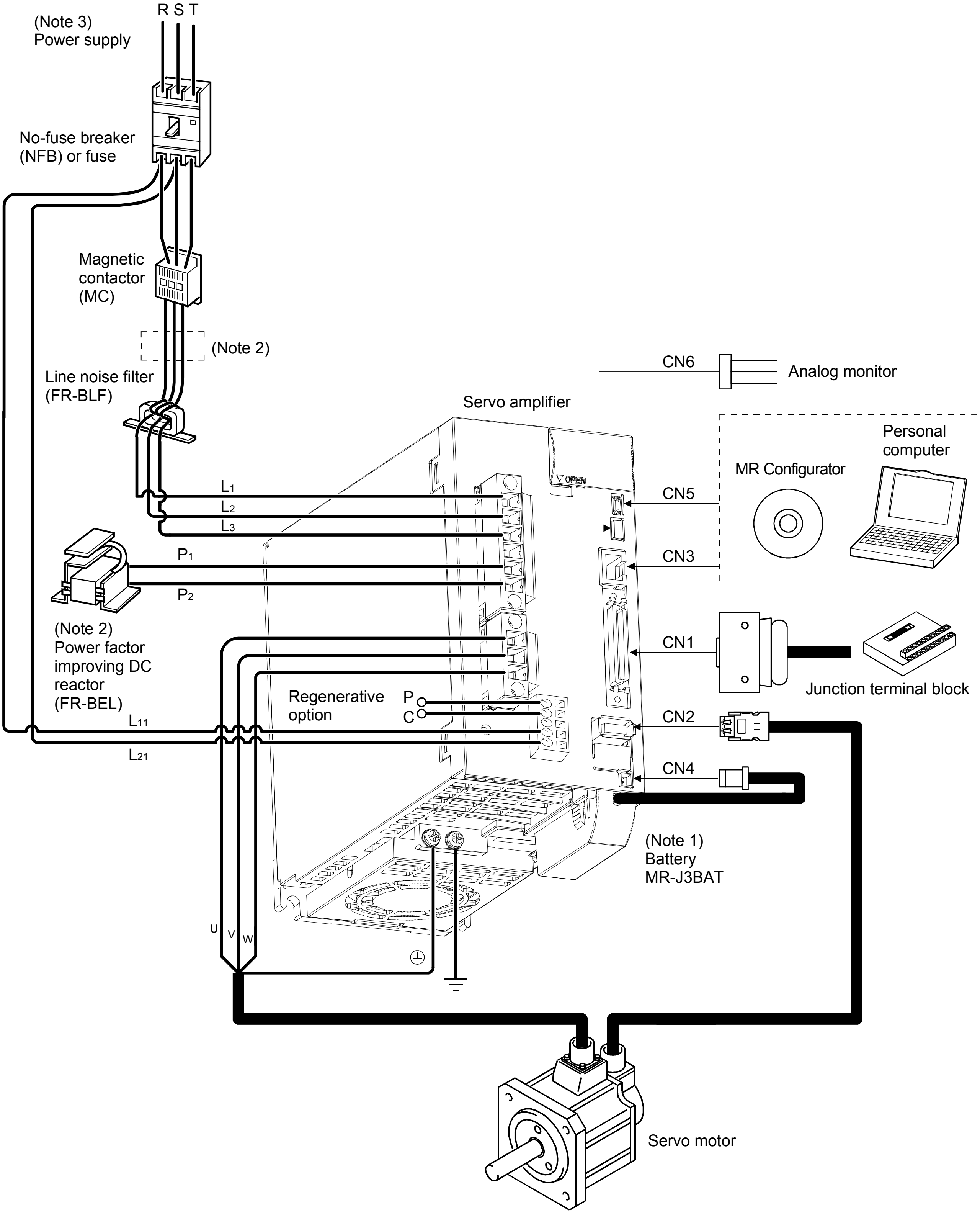
3. Refer to section 1.3 for the power supply specification.

(3) MR-J3-200A(4)



Note 1. The battery (option) is used for the absolute position detection system in the position control mode.
2. The power factor improving AC reactor can also be used. In this case, the power factor improving DC reactor cannot be used. When not using the power factor improving DC reactor, short P_1 and P_2.
3. Refer to section 1.3 for the power supply specification.
4. Connectors (CNP1, CNP2, and CNP3) and appearance of MR-J3-200A servo amplifier have been changed from April 2008 production. Model name of the servo amplifier before March 2008 is changed to MR-J3-200A-RT. For MR-J3-200A-RT, refer to appendix 5.

(4) MR-J3-350A

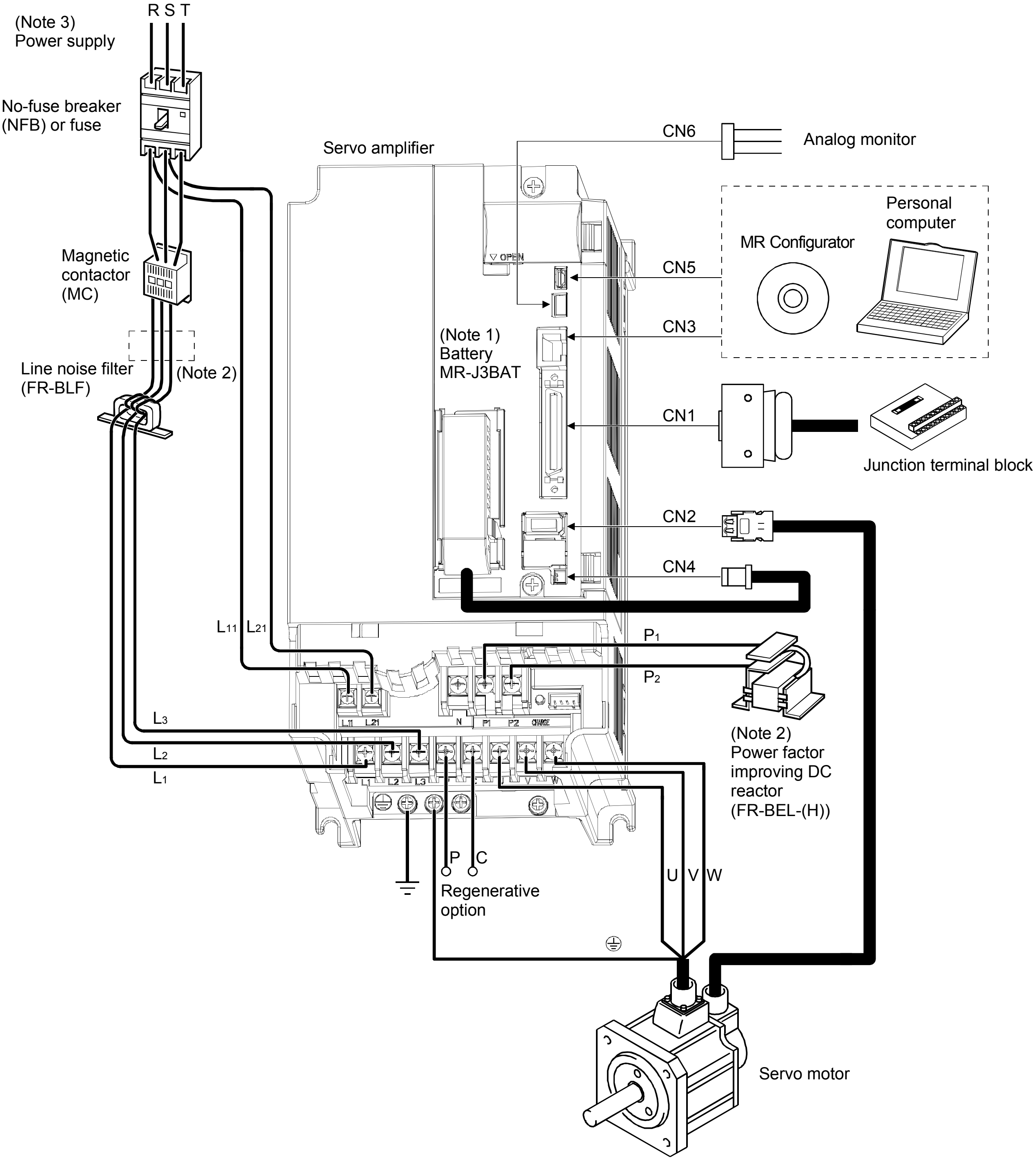


Note 1. The battery (option) is used for the absolute position detection system in the position control mode.

2. The power factor improving AC reactor can also be used. In this case, the power factor improving DC reactor cannot be used. When not using the power factor improving DC reactor, short P_1 and P_2.

3. Refer to section 1.3 for the power supply specification.

(5) MR-J3-350A4・MR-J3-500A(4)

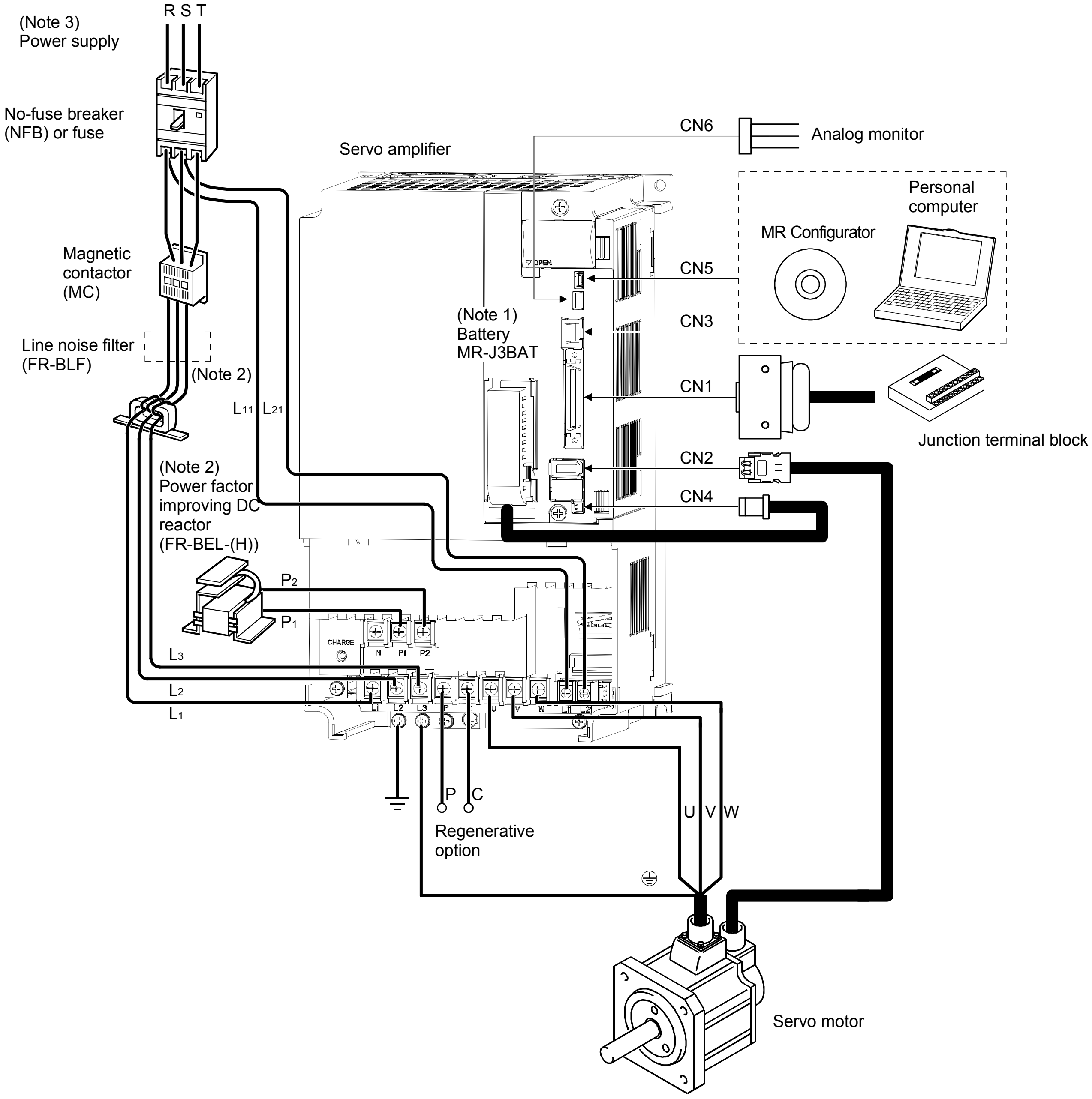


Note 1. The battery (option) is used for the absolute position detection system in the position control mode.

2. The power factor improving AC reactor can also be used. In this case, the power factor improving DC reactor cannot be used. When not using the power factor improving DC reactor, short P_1 and P_2.

3. Refer to section 1.3 for the power supply specification.

(6) MR-J3-700A(4)

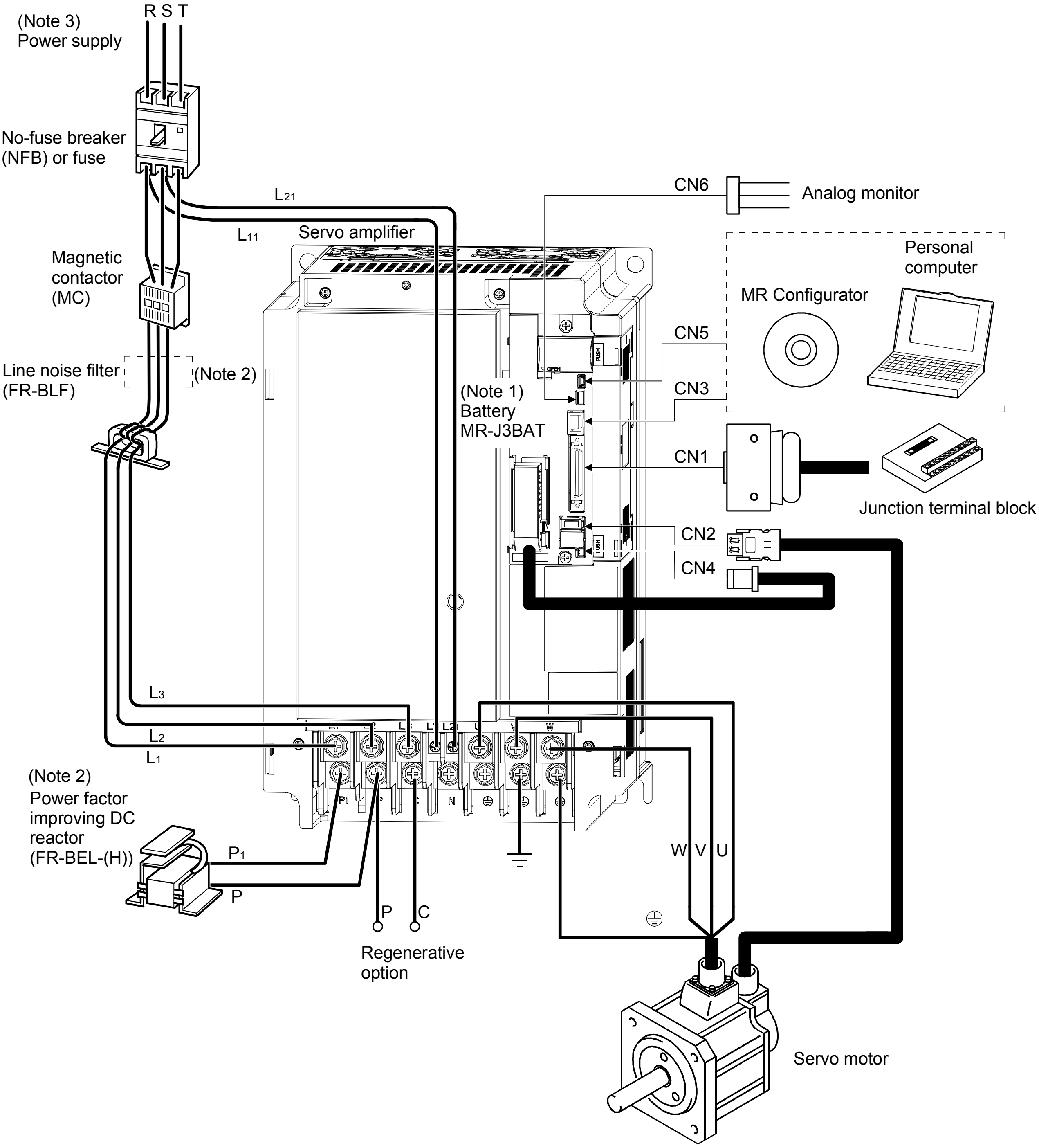


Note 1. The battery (option) is used for the absolute position detection system in the position control mode.

2. The power factor improving AC reactor can also be used. In this case, the power factor improving DC reactor cannot be used. When not using the power factor improving DC reactor, short P_1 and P_2.

3. Refer to section 1.3 for the power supply specification.

(7) MR-J3-11KA(4) to MR-J3-22KA(4)



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

2. The power factor improving AC reactor can also be used. In this case, the power factor improving DC reactor cannot be used. When not using the power factor improving DC reactor, short P_1 and P.

3. Refer to section 1.3 for the power supply specification.

MEMO

2. INSTALLATION

⚠WARNING	・To prevent electric shock, ground each equipment securely.

⚠CAUTION	・Stacking in excess of the limited number of product packages is not allowed. ・Install the equipment to incombustibles. Installing them directly or close to combustibles will led to a fire. ・Install the equipment in a load-bearing place in accordance with this Instruction Manual. ・Do not get on or put heavy load on the equipment to prevent injury. ・Use the equipment within the specified environmental condition range. (For details of the environmental condition, refer to section 1.3.) ・Provide an adequate protection to prevent screws, metallic detritus and other conductive matter or oil and other combustible matter from entering the converter unit and servo amplifier (drive unit). ・Do not block the intake and exhaust areas of the converter unit, servo amplifier (drive unit) and servo motor which has a cooling fan. Doing so may cause faults. ・Do not subject the converter unit and servo amplifier (drive unit) to drop impact or shock loads as they are precision equipment. ・Do not install or operate a faulty converter unit and servo amplifier (drive unit). ・When the product has been stored for an extended period of time, contact your local sales office. ・When handling the converter unit and servo amplifier (drive unit), be careful about the edged parts such as the corners of the each unit. ・The converter unit and servo amplifier (drive unit) must be installed in the metal cabinet (control box).

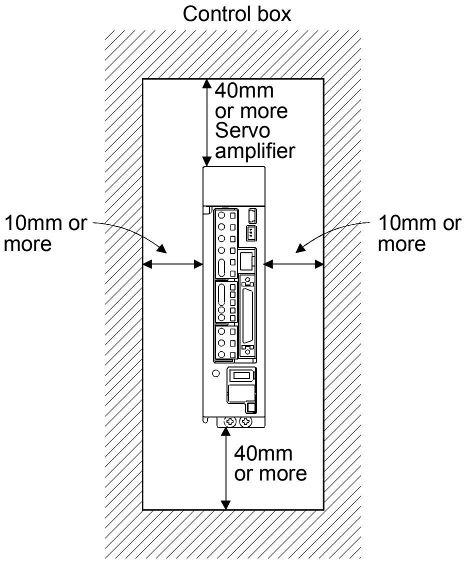
2.1 Installation direction and clearances

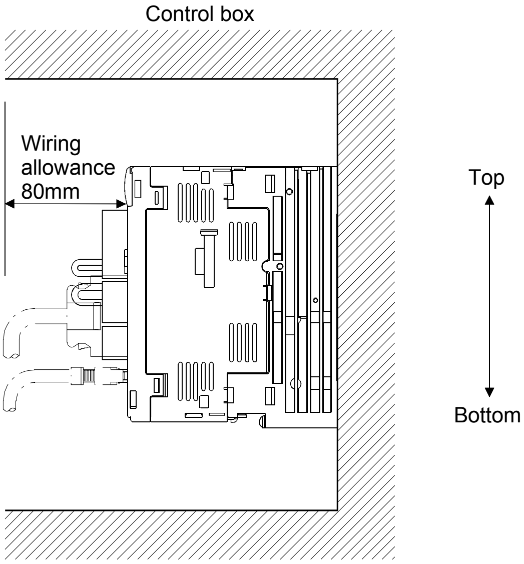
⚠ CAUTION

- The equipment must be installed in the specified direction. Otherwise, a fault may occur.
- Leave specified clearances between the servo amplifier and control box inside walls or other equipment.

(1) 7kW or less

(a) Installation of one servo amplifier



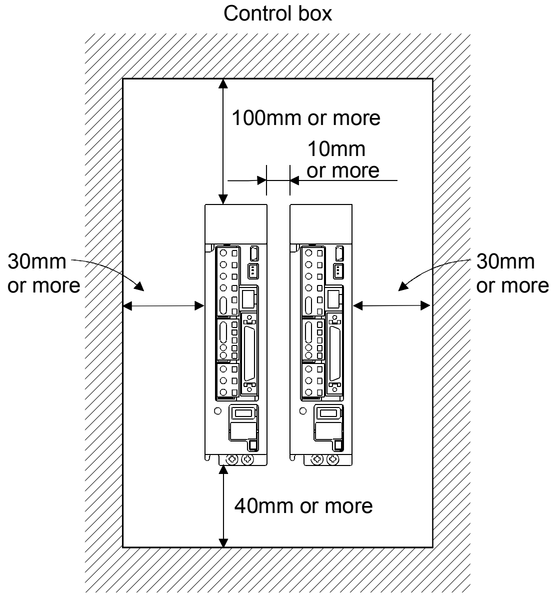


(b) Installation of two or more servo amplifiers

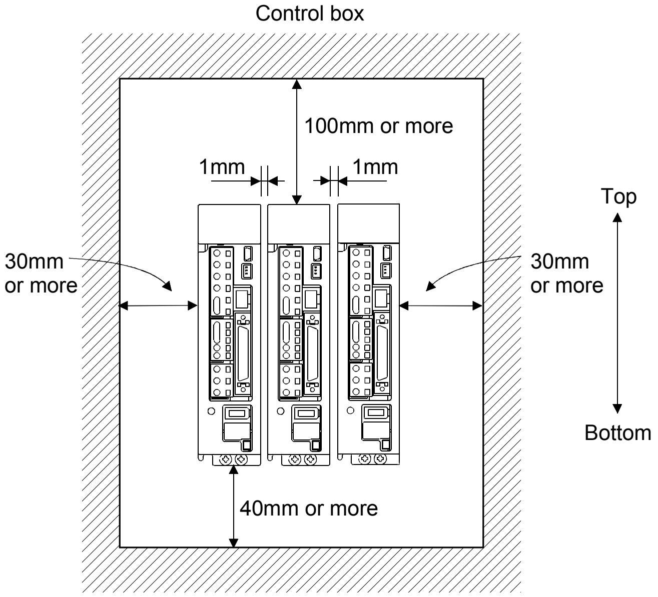
POINT

- Close mounting is available for the servo amplifier of under 3.5kW for 200V class and 400W for 100V class.

Leave a large clearance between the top of the servo amplifier and the internal surface of the control box, and install a cooling fan to prevent the internal temperature of the control box from exceeding the environmental conditions.
When installing the servo amplifiers closely, leave a clearance of 1mm between the adjacent servo amplifiers in consideration of mounting tolerances.
In this case, make circumference temperature into 0 to 45°C, or use it at 75% or a smaller effective load ratio.



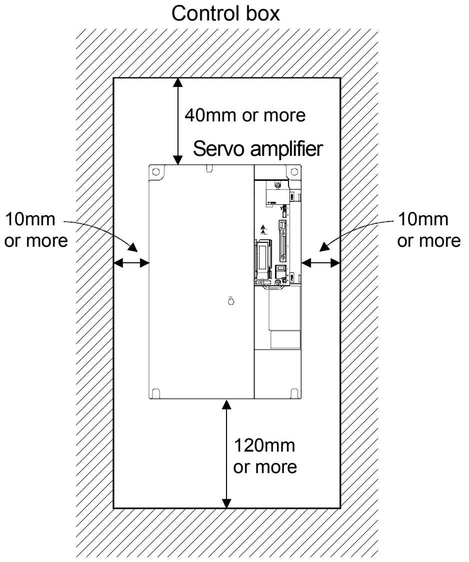
Leaving clearance

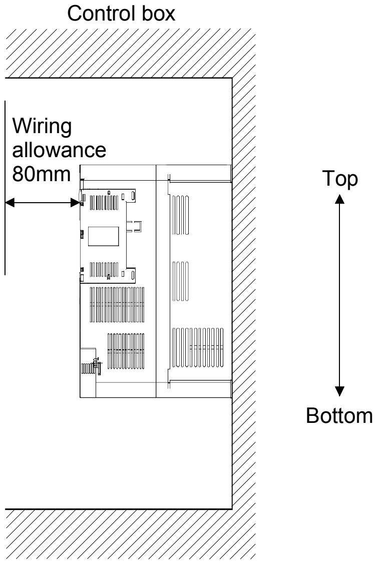


Mounting closely

(2) 11k to 22kW or more

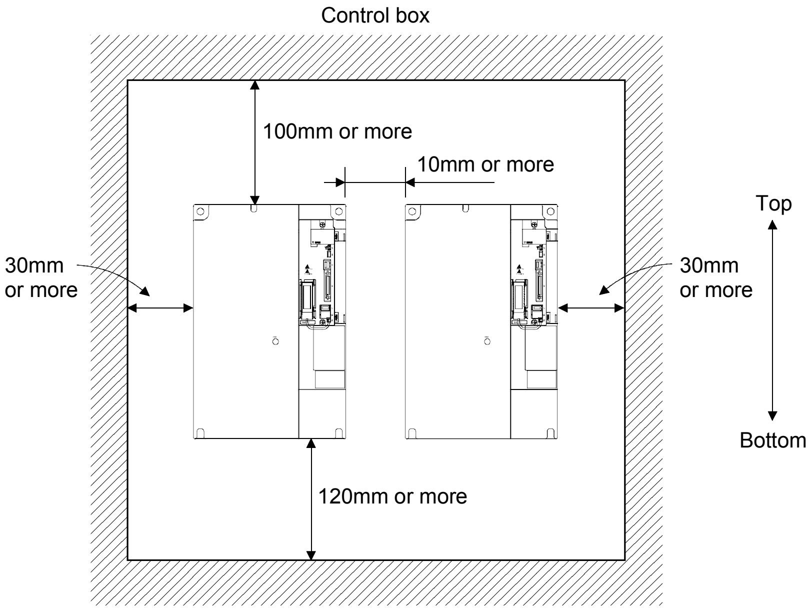
(a) Installation of one servo amplifier





(b) Installation of two or more servo amplifiers

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



(3) Others

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

Install the servo amplifier on a perpendicular wall in the correct vertical direction.

2.2 Keep out foreign materials

(1) When installing the unit in a control box, prevent drill chips and wire fragments from entering the servo amplifier.

(2) Prevent oil, water, metallic dust, etc. from entering the servo amplifier through openings in the control box or a cooling fan installed on the ceiling.

(3) When installing the control box in a place where there are much toxic gas, dirt and dust, conduct an air purge (force clean air into the control box from outside to make the internal pressure higher than the external pressure) to prevent such materials from entering the control box.

2.3 Cable stress

(1) The way of clamping the cable must be fully examined so that flexing stress and cable's own weight stress are not applied to the cable connection.

(2) For use in any application where the servo motor moves, fix the cables (encoder, power supply, brake) with having some slack from the connector connection part of the servo motor to avoid putting stress on the connector connection part. Use the optional encoder cable within the flexing life range. Use the power supply and brake wiring cables within the flexing life of the cables.

(3) Avoid any probability that the cable sheath might be cut by sharp chips, rubbed by a machine corner or stamped by workers or vehicles.

(4) For installation on a machine where the servo motor will move, the flexing radius should be made as large as possible. Refer to section 11.4 for the flexing life.

2.4 Inspection items

⚠WARNING	▪ Before starting maintenance and/or inspection, turn off the power and wait for 15 minutes or longer until the charge lamp turns off. Then, confirm that the voltage between P(＋) and N(－) is safe with a voltage tester and others. Otherwise, an electric shock may occur. In addition, always confirm from the front of the servo amplifier whether the charge lamp is off or not. ▪ Any person who is involved in inspection should be fully competent to do the work. Otherwise, you may get an electric shock. For repair and parts replacement, contact your local sales office.

POINT

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

It is recommended to make the following checks periodically.

(1) Check for loose terminal block screws. Retighten any loose screws.

(2) Check the cables and the wires for scratches and cracks. Perform periodic inspection according to operating conditions.

2.5 Parts having service lives

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

Part name		Life guideline
Servo amplifier	Smoothing capacitor	10 years
	Relay	Number of power-on and number of emergency stop times : 100,000 times
	Cooling fan	10,000 to 30,000hours (2 to 3 years)
	Absolute position battery	Refer to section 14.2

(1) Smoothing capacitor

Affected by ripple currents, etc. and deteriorates in characteristic. The life of the capacitor greatly depends on ambient temperature and operating conditions. The capacitor will reach the end of its life in 10 years of continuous operation in normal air-conditioned environment (40℃ (104℉) surrounding air temperature or less).

(2) Relays

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

(3) Servo amplifier cooling fan

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

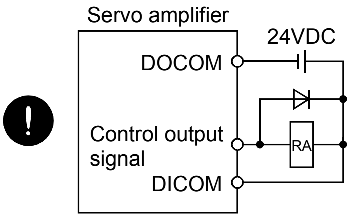
3. SIGNALS AND WIRING

WARNING

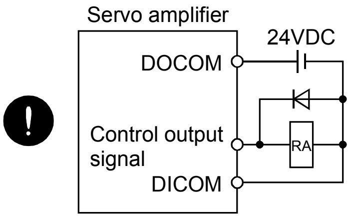
- Any person who is involved in wiring should be fully competent to do the work.
- Before wiring, turn off the power and wait for 15 minutes or longer until the charge lamp turns off. Then, confirm that the voltage between P(+) and N(−) is safe with a voltage tester and others. Otherwise, an electric shock may occur. In addition, always confirm from the front of the servo amplifier whether the charge lamp is off or not.
- Ground the servo amplifier and the servo motor securely.
- Do not attempt to wire the servo amplifier and servo motor until they have been installed. Otherwise, you may get an electric shock.
- The cables should not be damaged, stressed excessively, loaded heavily, or pinched. Otherwise, you may get an electric shock.

CAUTION

- Wire the equipment correctly and securely. Otherwise, the servo motor may operate unexpected resulting in injury.
- Connect cables to correct terminals to prevent a burst, fault, etc.
- Ensure that polarity (+, −) is correct. Otherwise, a burst, damage, etc. may occur.
- The surge absorbing diode installed to the DC relay for control output should be fitted in the specified direction. Otherwise, the emergency stop and other protective circuits may not operate.



For sink output interface



For source output interface

- Use a noise filter, etc. to minimize the influence of electromagnetic interference, which may be given to electronic equipment used near the servo amplifier.
- Do not install a power capacitor, surge killer or radio noise filter (FR-BIF-(H) option) with the power line of the servo motor.
- When using the regenerative resistor, switch power off with the alarm signal. Otherwise, a transistor fault or the like may overheat the regenerative resistor, causing a fire.
- Do not modify the equipment.
- During power-on, do not open or close the motor power line. Otherwise, a malfunction or faulty may occur.

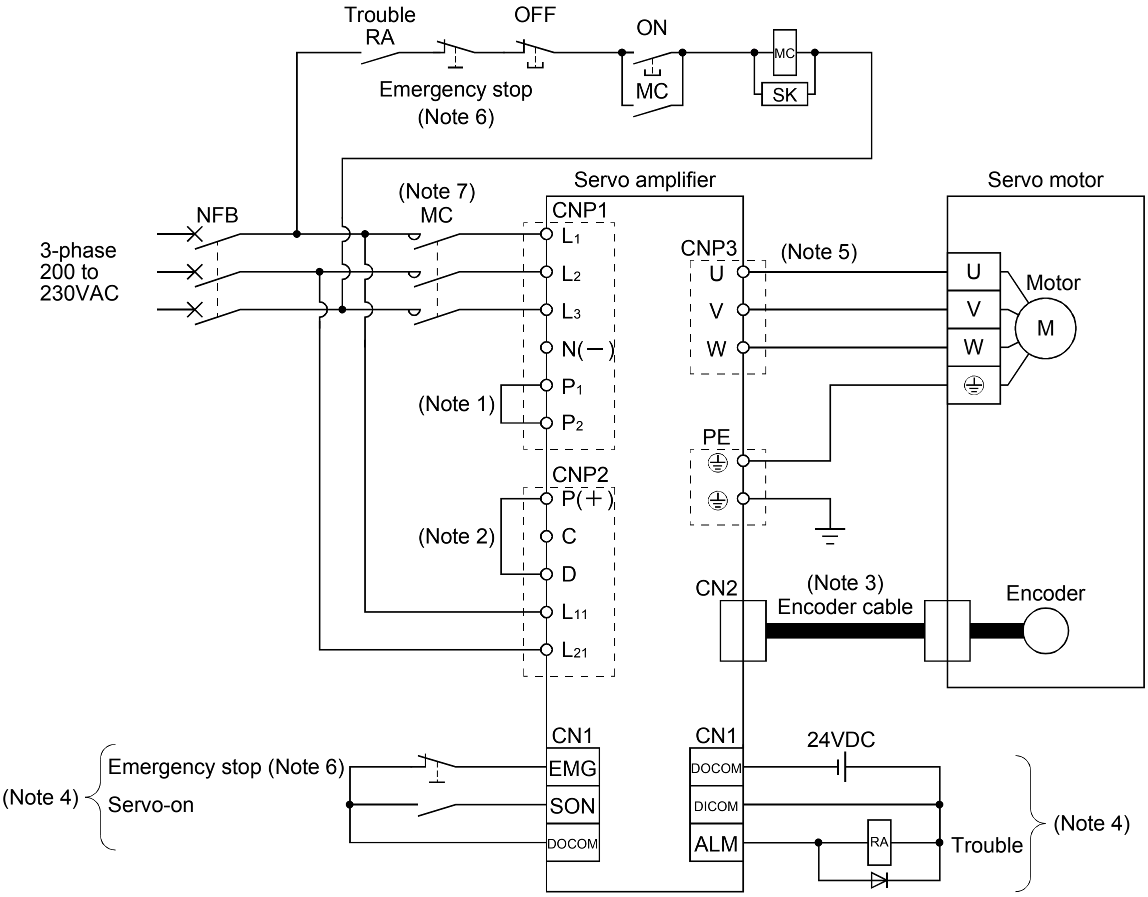
3.1 Input power supply circuit

⚠CAUTION

- Always connect a magnetic contactor between the main circuit power and L_1, L_2, and L_3 of the servo amplifier, and configure the wiring to be able to shut down the power supply on the side of the servo amplifier's power supply. If a magnetic contactor is not connected, continuous flow of a large current may cause a fire when the servo amplifier malfunctions.
- Use the trouble (ALM) to switch power off. Otherwise, a regenerative transistor fault or the like may overheat the regenerative resistor, causing a fire.
- Check the model and input the correct voltage for the power supply of the servo amplifier. When a voltage, which exceeds the maximum input voltage of the servo amplifier specifications, is input, the servo amplifier malfunctions.

Wire the power supply and main circuit as shown below so that the servo-on (SON) turns off as soon as alarm occurrence is detected and power is shut off.
A no-fuse breaker (NFB) must be used with the input cables of the power supply.

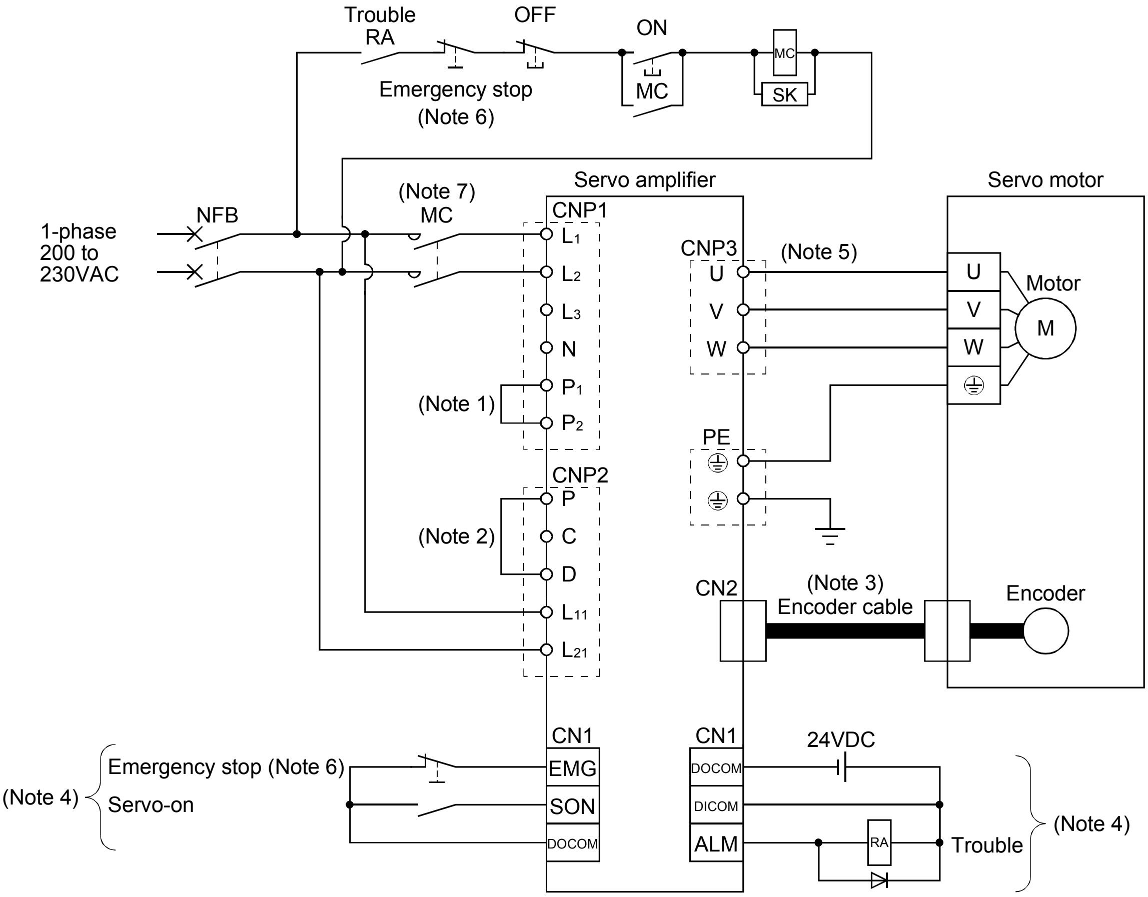
(1) For 3-phase 200 to 230VAC power supply to MR-J3-10A to MR-J3-350A



Note 1. Always connect P_1 and P_2. (Factory-wired.) When using the power factor improving DC reactor, refer to section 12.13. Use only one of power factor improving DC reactor or power factor improving AC reactor.

2. Always connect P(+) and D. (Factory-wired.) When using the regenerative option, refer to section 12.2.
3. For encoder cable, use of the option cable is recommended. Refer to section 12.1 for selection of the cable.
4. For the sink I/O interface.
   For the source I/O interface, refer to section 3.8.3.
5. Refer to section 3.10.
6. Configure the circuit to shut down the main circuit power supply simultaneously with the turn off of emergency stop (EMG) using the external sequence.
7. Be sure to use a magnetic contactor with an operation delay time of 80ms or less. The operation delay time is the time interval between current being applied to the coil until closure of contacts.

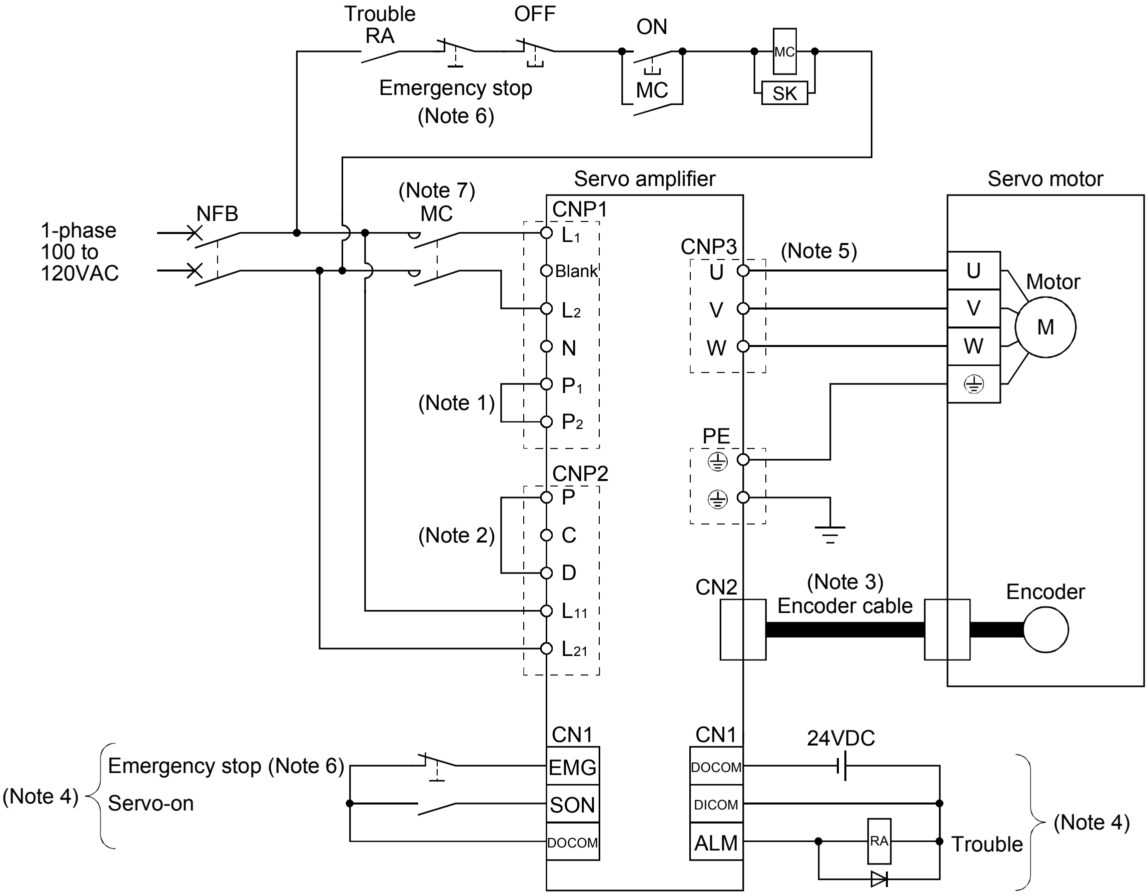
(2) For 1-phase 200 to 230VAC power supply to MR-J3-10A to MR-J3-70A



Note 1. Always connect P_1 and P_2. (Factory-wired.) When using the power factor improving DC reactor, refer to section 12.13. Use only one of power factor improving DC reactor or power factor improving AC reactor.

2. Always connect P and D. (Factory-wired.) When using the regenerative option, refer to section 12.2.
3. For encoder cable, use of the option cable is recommended. Refer to section 12.1 for selection of the cable.
4. For the sink I/O interface. For the source I/O interface, refer to section 3.8.3.
5. Refer to section 3.10.
6. Configure the circuit to shut down the main circuit power supply simultaneously with the turn off of emergency stop (EMG) using the external sequence.
7. Be sure to use a magnetic contactor with an operation delay time of 80ms or less. The operation delay time is the time interval between current being applied to the coil until closure of contacts.

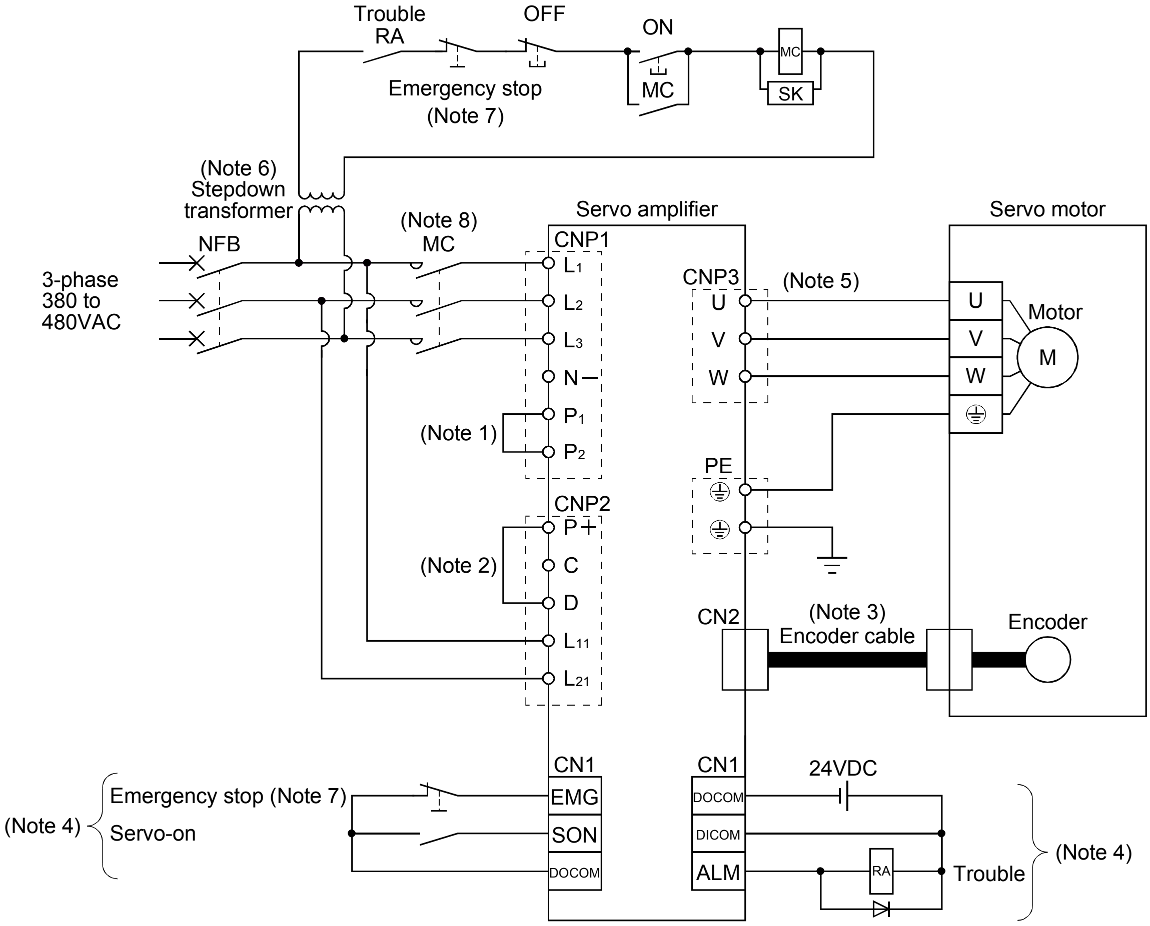
(3) MR-J3-10A1 to MR-J3-40A1



Note 1. Always connect P_1 and P_2. (Factory-wired.) The power factor improving DC reactor cannot be used.

2. Always connect P and D. (Factory-wired.) When using the regenerative option, refer to section 12.2.
3. For encoder cable, use of the option cable is recommended. Refer to section 12.1 for selection of the cable.
4. For the sink I/O interface. For the source I/O interface, refer to section 3.8.3.
5. Refer to section 3.10.
6. Configure the circuit to shut down the main circuit power supply simultaneously with the turn off of emergency stop (EMG) using the external sequence.
7. Be sure to use a magnetic contactor with an operation delay time of 80ms or less. The operation delay time is the time interval between current being applied to the coil until closure of contacts.

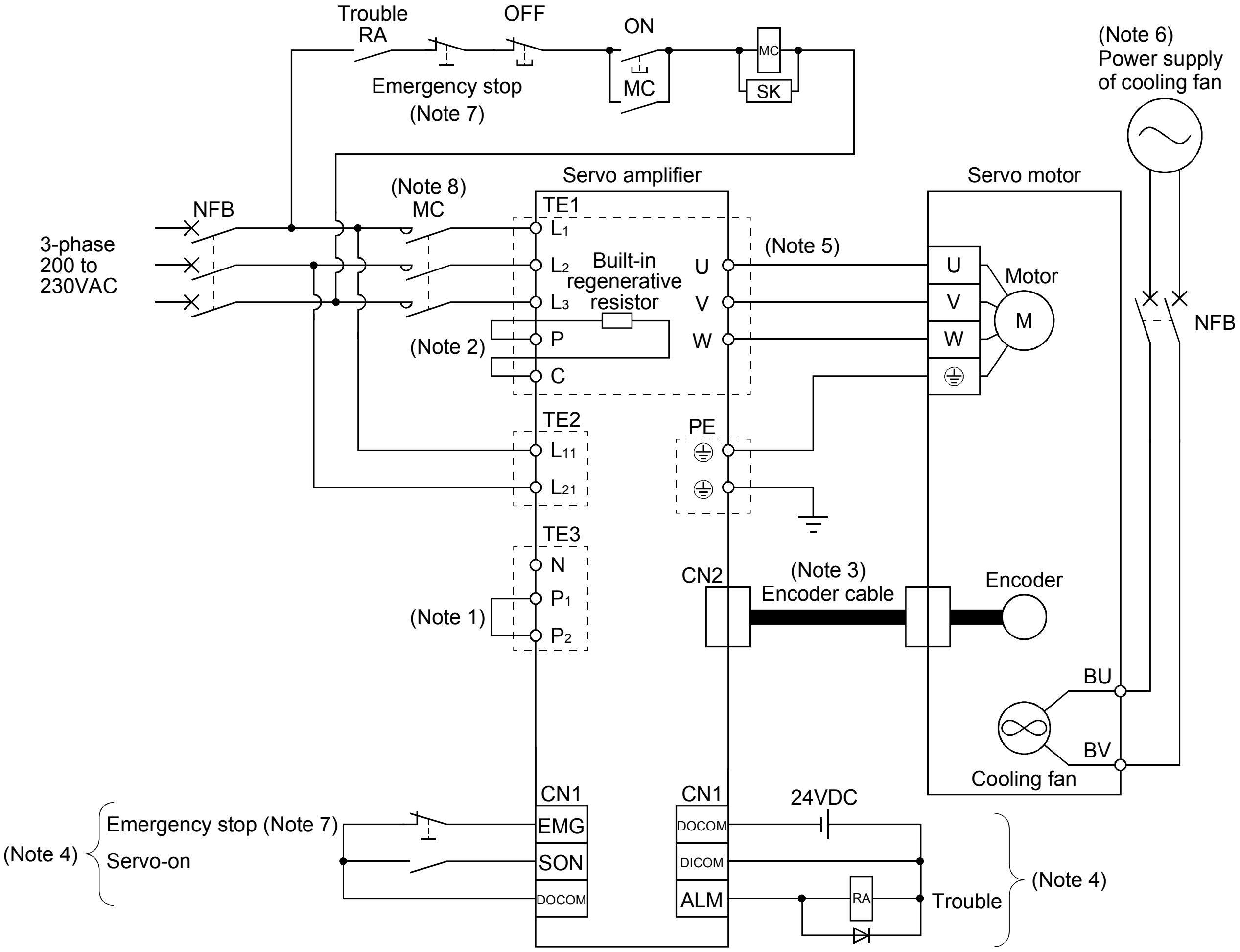
(4) MR-J3-60A4 to MR-J3-200A4



Note 1. Always connect P_1 and P_2. (Factory-wired.) When using the power factor improving DC reactor, refer to section 12.13. Use only one of power factor improving DC reactor or power factor improving AC reactor.

2. Always connect P and D. (Factory-wired.) When using the regenerative option, refer to section 12.2.
3. For encoder cable, use of the option cable is recommended. Refer to section 12.1 for selection of the cable.
4. For the sink I/O interface. For the source I/O interface, refer to section 3.8.3.
5. Refer to section 3.10.
6. Stepdown transformer is required for coil voltage of magnetic contactor more than 200V class.
7. Configure the circuit to shut down the main circuit power supply simultaneously with the turn off of emergency stop (EMG) using the external sequence.
8. Be sure to use a magnetic contactor with an operation delay time of 80ms or less. The operation delay time is the time interval between current being applied to the coil until closure of contacts.

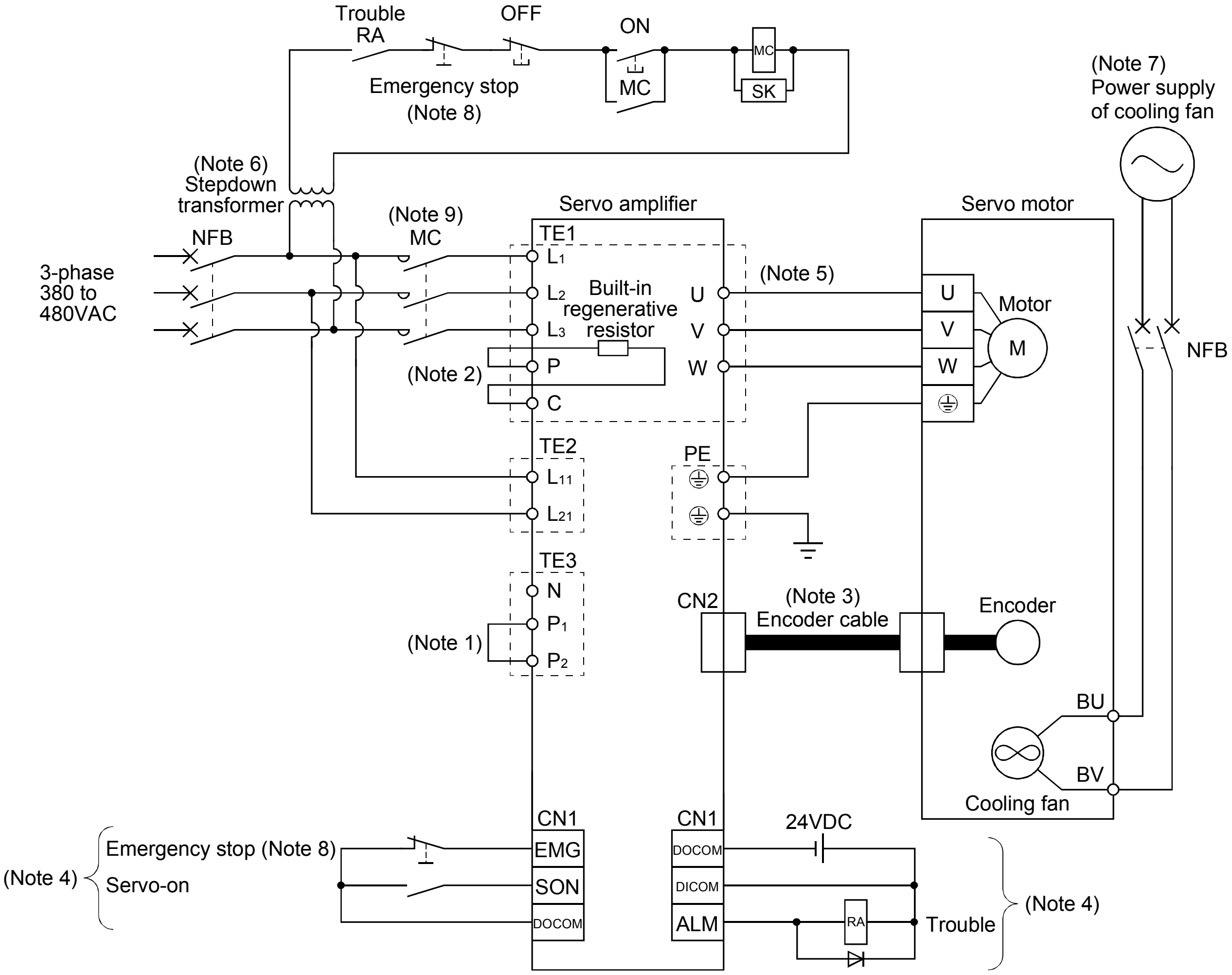
(5) MR-J3-500A・MR-J3-700A



Note 1. Always connect P_1 and P_2. (Factory-wired.) When using the power factor improving DC reactor, refer to section 12.13. Use only one of power factor improving DC reactor or power factor improving AC reactor.

2. When using the regenerative option, refer to section 12.2.
3. For encoder cable, use of the option cable is recommended. Refer to section 12.1 for selection of the cable.
4. For the sink I/O interface. For the source I/O interface, refer to section 3.8.3.
5. Refer to section 3.10.
6. A cooling fan is attached to the HA-LP601 and the HA-LP701M servo motors. For power supply specification of the cooling fan, refer to section 3.10.2 (3) (b).
7. Configure the circuit to shut down the main circuit power supply simultaneously with the turn off of emergency stop (EMG) using the external sequence.
8. Be sure to use a magnetic contactor with an operation delay time of 80ms or less. The operation delay time is the time interval between current being applied to the coil until closure of contacts.

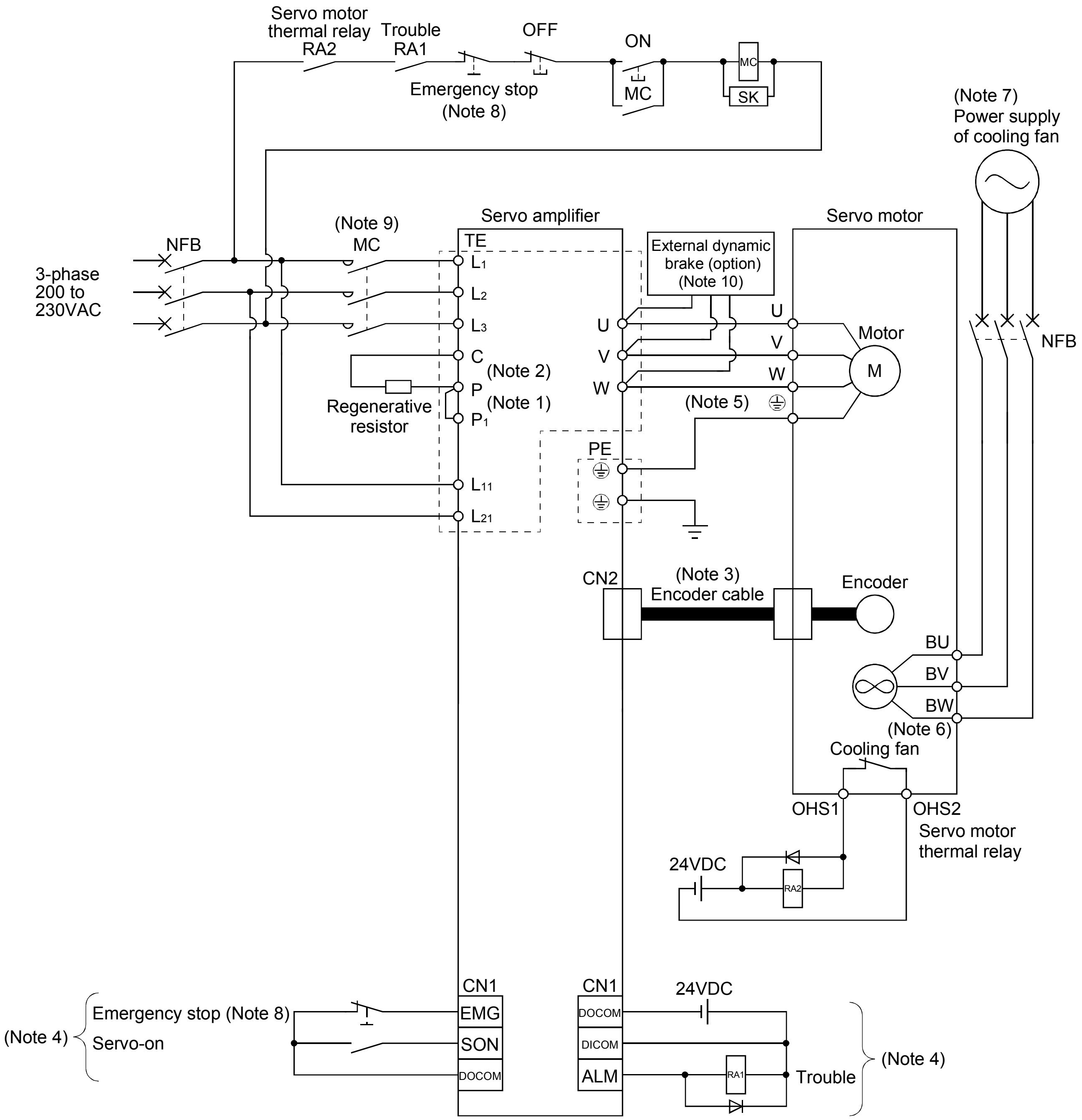
(6) MR-J3-350A4 to MR-J3-700A4



Note 1. Always connect P_1 and P_2. (Factory-wired.) When using the power factor improving DC reactor, refer to section 12.13. Use only one of power factor improving DC reactor or power factor improving AC reactor.

2. When using the regenerative option, refer to section 12.2.
3. For the encoder cable, use of the option cable is recommended. Refer to section 12.1 for selection of the cable.
4. For the sink I/O interface. For the source I/O interface, refer to section 3.8.3.
5. Refer to section 3.10.
6. Stepdown transformer is required for coil voltage of magnetic contactor more than 200V class.
7. A cooling fan is attached to the HA-LP6014 and the HA-LP701N4 servo motors. For power supply specification of the cooling fan, refer to section 3.10.2 (3) (b).
8. Configure the circuit to shut down the main circuit power supply simultaneously with the turn off of emergency stop (EMG) using the external sequence.
9. Be sure to use a magnetic contactor with an operation delay time of 80ms or less. The operation delay time is the time interval between current being applied to the coil until closure of contacts.

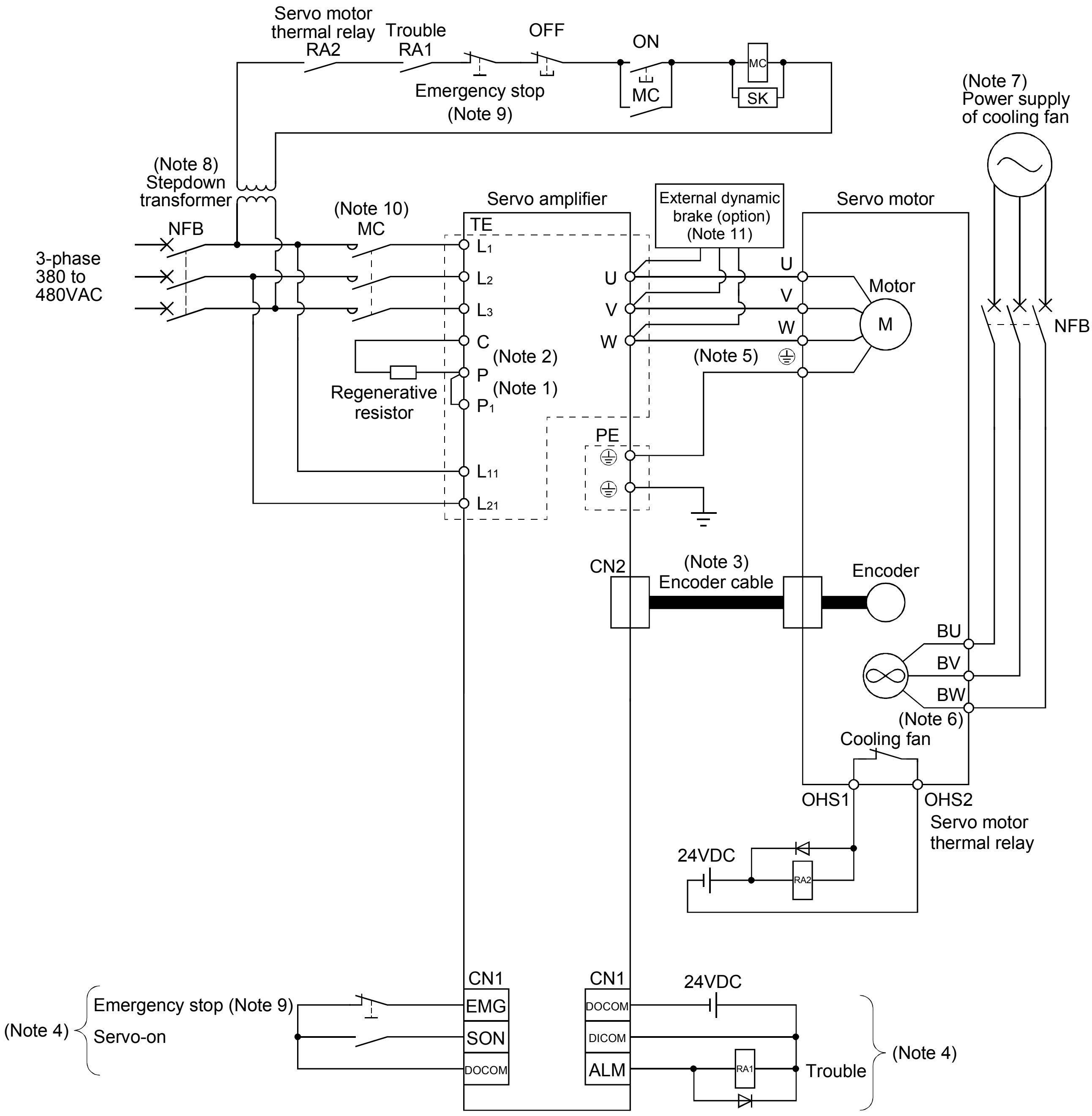
(7) MR-J3-11KA to MR-J3-22KA



Note 1. Always connect P and P1. (Factory-wired.) When using the power factor improving DC reactor, refer to section 12.13. Use only one of power factor improving DC reactor or power factor improving AC reactor.

2. When using the regenerative option, refer to section 12.2.
3. For the encoder cable, use of the option cable is recommended. Refer to section 12.1 for selection of the cable.
4. For the sink I/O interface. For the source I/O interface, refer to section 3.8.3.
5. Refer to section 3.10.
6. When the power supply for the cooling fan is 1-phase, BW does not exist.
7. For the cooling fan power supply, refer to section 3.10.2 (3) (b).
8. Configure the circuit to shut down the main circuit power supply simultaneously with the turn off of emergency stop (EMG) using the external sequence.
9. Be sure to use a magnetic contactor with an operation delay time of 80ms or less. The operation delay time is the time interval between current being applied to the coil until closure of contacts.
10. Use an external dynamic brake for this servo amplifier. Failure to do so will cause an accident because the servo motor does not stop immediately but coasts at an emergency stop and such conditions. Ensure the safety in the entire system.

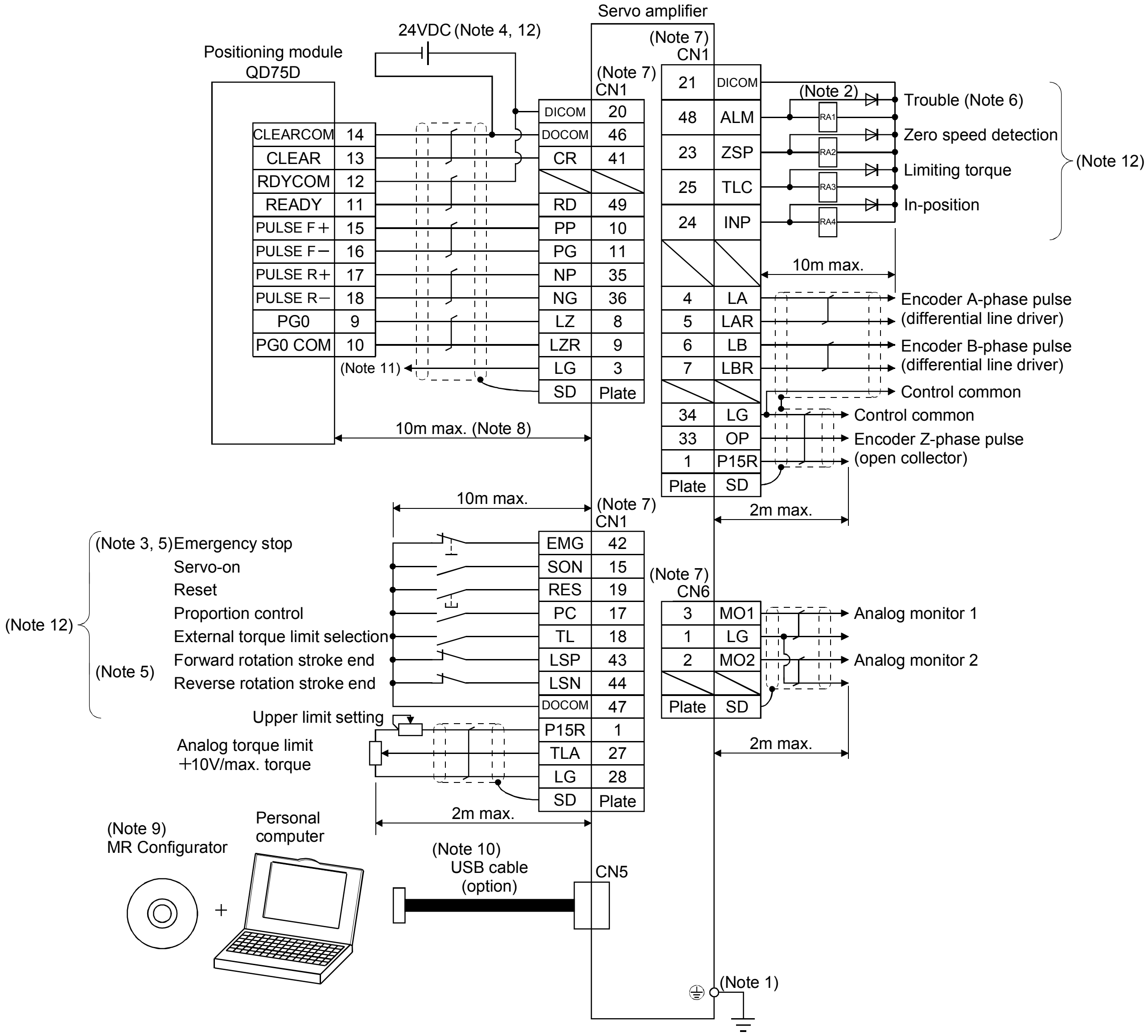
(8) MR-J3-11KA4 to MR-J3-22KA4



Note 1. Always connect P and P_1. (Factory-wired.) When using the power factor improving DC reactor, refer to section 12.13. Use only one of power factor improving DC reactor or power factor improving AC reactor.
2. When using the regenerative option, refer to section 12.2.
3. For the encoder cable, use of the option cable is recommended. Refer to section 12.1 for selection of the cable.
4. For the sink I/O interface. For the source I/O interface, refer to section 3.8.3.
5. Refer to section 3.10.
6. There is no BW if HA-LP11K24 is used.
7. For the cooling fan power supply, refer to section 3.10.2 (3) (b).
8. Stepdown transformer is required for coil voltage of magnetic contactor more than 200V class.
9. Configure the circuit to shut down the main circuit power supply simultaneously with the turn off of emergency stop (EMG) using the external sequence.
10. Be sure to use a magnetic contactor with an operation delay time of 80ms or less. The operation delay time is the time interval between current being applied to the coil until closure of contacts.
11. Use an external dynamic brake for this servo amplifier. Failure to do so will cause an accident because the servo motor does not stop immediately but coasts at an emergency stop and such conditions. Ensure the safety in the entire system.

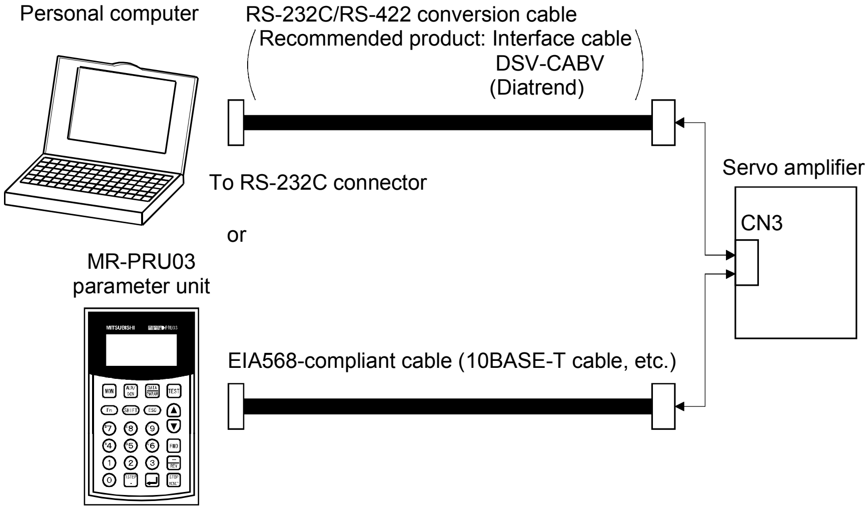
3.2 I/O signal connection example

3.2.1 Position control mode



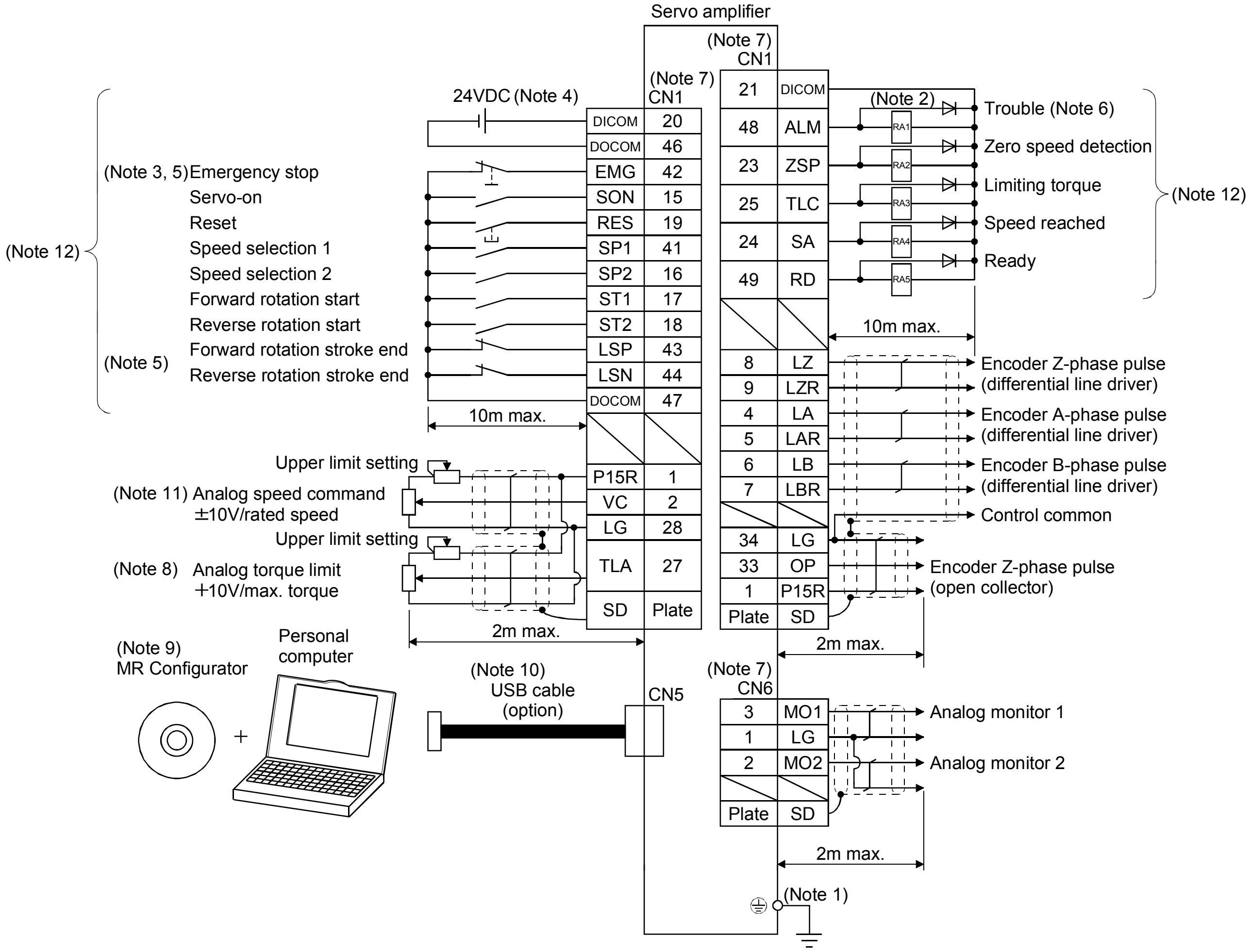
Note 1. To prevent an electric shock, always connect the protective earth (PE) terminal (terminal marked ⏚) of the servo amplifier to the protective earth (PE) of the control box.

2. Connect the diode in the correct direction. If it is connected reversely, the servo amplifier will be faulty and will not output signals, disabling the emergency stop (EMG) and other protective circuits.
3. The emergency stop switch (normally closed contact) must be installed.
4. Supply 24VDC±10% 300mA current for interfaces from the outside. 300mA is the value applicable when all I/O signals are used. The current capacity can be decreased by reducing the number of I/O points. Refer to section 3.8.2 (1) that gives the current value necessary for the interface.
5. When starting operation, always turn on emergency stop (EMG) and Forward/Reverse rotation stroke end (LSP/LSN). (Normally closed contacts)
6. Trouble (ALM) turns on in normal alarm-free condition. When this signal is switched off (at occurrence of an alarm), the output of the programmable controller should be stopped by the sequence program.
7. The pins with the same signal name are connected in the servo amplifier.
8. This length applies to the command pulse train input in the differential line driver system. It is 2m or less in the open collector system.
9. Use MRZJW3-SETUP 221E.
10. Personal computers or parameter units can also be connected via the CN3 connector, enabling RS-422 communication. Note that using the USB communication function (CN5 connector) prevents the RS-422 communication function (CN3 connector) from being used, and vice versa. They cannot be used together.



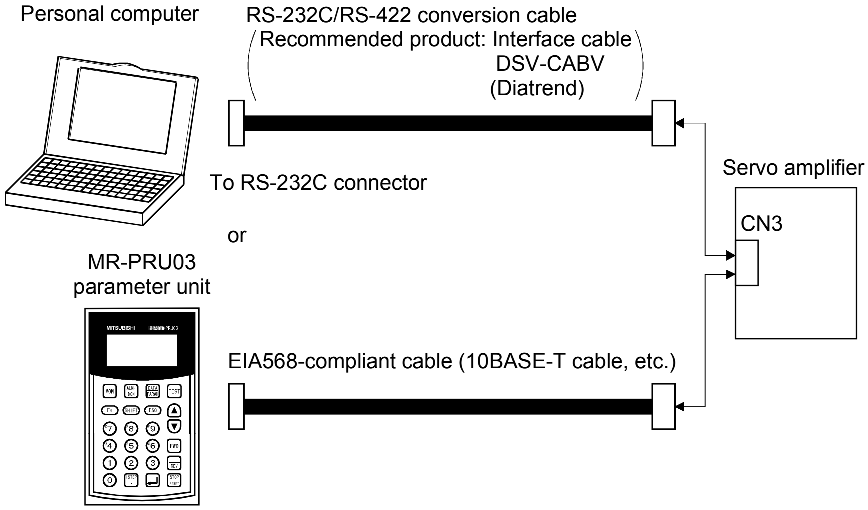
11. This connection is not required for the QD75D. Depending on the used positioning module, however, it is recommended to connect the LG and control common terminals of the servo amplifier to enhance noise immunity.
12. For the sink I/O interface. For the source I/O interface, refer to section 3.8.3.

3.2.2 Speed control mode



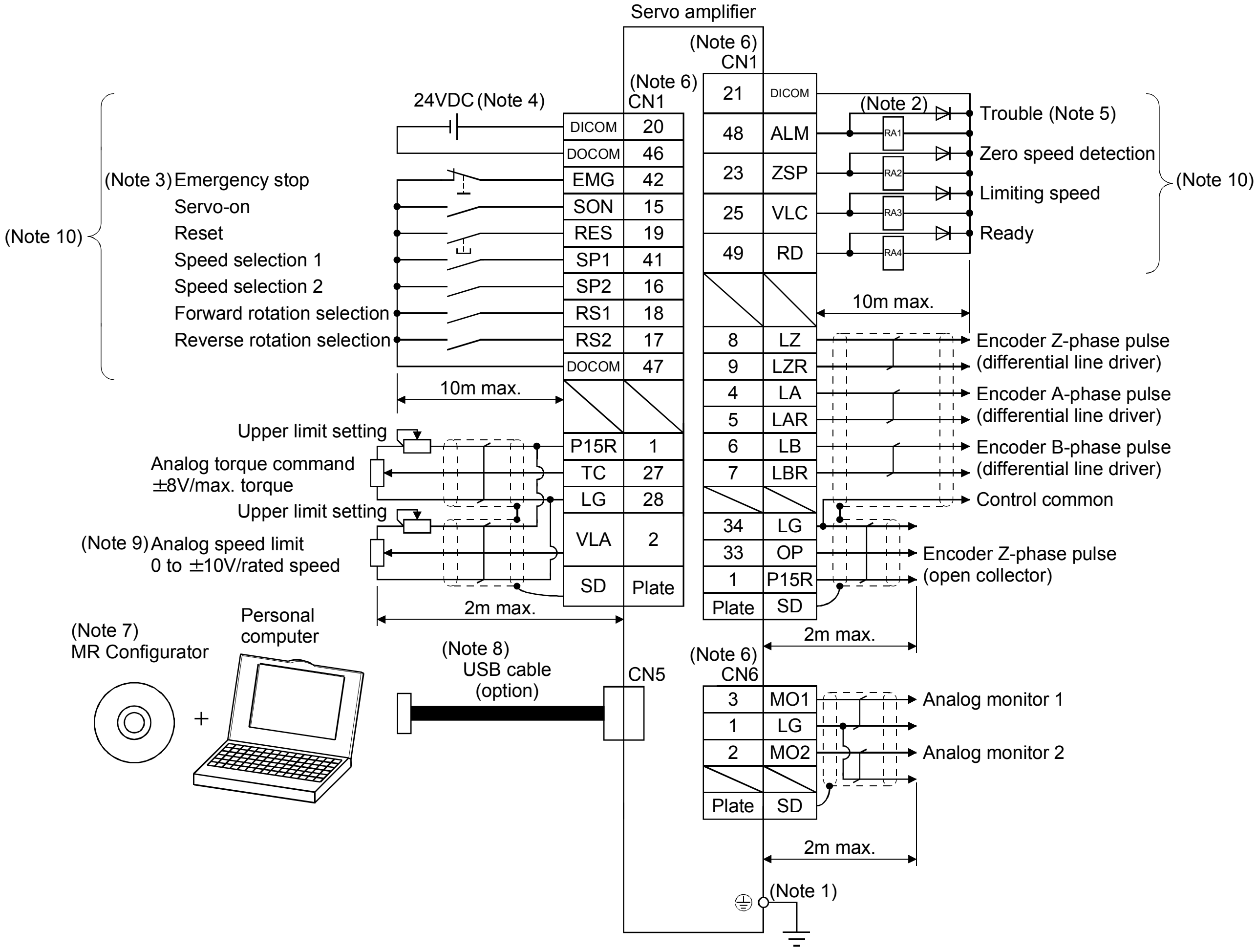
Note 1. To prevent an electric shock, always connect the protective earth (PE) terminal (terminal marked ⏚) of the servo amplifier to the protective earth (PE) of the control box.

2. Connect the diode in the correct direction. If it is connected reversely, the servo amplifier will be faulty and will not output signals, disabling the emergency stop (EMG) and other protective circuits.
3. The emergency stop switch (normally closed contact) must be installed.
4. Supply 24VDC±10% 300mA current for interfaces from the outside. 300mA is the value applicable when all I/O signals are used. The current capacity can be decreased by reducing the number of I/O points. Refer to section 3.8.2 (1) that gives the current value necessary for the interface.
5. When starting operation, always turn on emergency stop (EMG) and forward/reverse rotation stroke end (LSP/LSN). (Normally closed contacts)
6. Trouble (ALM) turns on in normal alarm-free condition.
7. The pins with the same signal name are connected in the servo amplifier.
8. By setting parameters No.PD03 to PD08, PD09 to PD12 to make external torque limit selection (TL) available, TLA can be used.
9. Use MRZJW3-SETUP 221E.
10. Personal computers or parameter units can also be connected via the CN3 connector, enabling RS-422 communication. Note that using the USB communication function (CN5 connector) prevents the RS-422 communication function (CN3 connector) from being used, and vice versa. They cannot be used together.

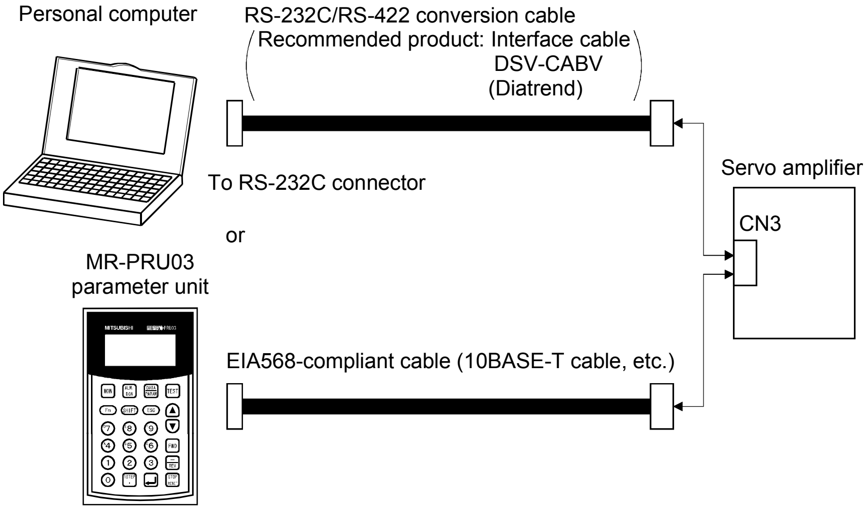


11. Use an external power supply when inputting a negative voltage.
12. For the sink I/O interface. For the source I/O interface, refer to section 3.8.3.

3.2.3 Torque control mode



Note 1. To prevent an electric shock, always connect the protective earth (PE) terminal of the (terminal marked ⏚) servo amplifier to the protective earth (PE) of the control box.
2. Connect the diode in the correct direction. If it is connected reversely, the servo amplifier will be faulty and will not output signals, disabling the emergency stop (EMG) and other protective circuits.
3. The emergency stop switch(normally closed contact) must be installed.
4. Supply 24VDC±10% 300mA current for interfaces from the outside. 300mA is the value applicable when all I/O signals are used. The current capacity can be decreased by reducing the number of I/O points. Refer to section 3.8.2 (1) that gives the current value necessary for the interface.
5. Trouble (ALM) turns on in normal alarm-free condition.
6. The pins with the same signal name are connected in the servo amplifier.
7. Use MRZJW3-SETUP 221E.
8. Personal computers or parameter units can also be connected via the CN3 connector, enabling RS-422 communication. Note that using the USB communication function (CN5 connector) prevents the RS-422 communication function (CN3 connector) from being used, and vice versa. They cannot be used together.



9. Use an external power supply when inputting a negative voltage.
10. For the sink I/O interface. For the source I/O interface, refer to section 3.8.3.

3.3 Explanation of power supply system

3.3.1 Signal explanations

POINT

- For the layout of connector and terminal block, refer to outline drawings in chapter 10.

<table>
<tr><th>Abbreviation</th><th>Connection target (application)</th><th>Description</th></tr>
<tr><td>L_1
L_2
L_3</td><td>Main circuit power supply</td><td>Supply the following power to L_1, L_2, L_3. For the 1-phase 200 to 230VAC power supply, connect the power supply to L_1, L_2, and keep L_3 open.
<table>
<tr><th>Servo amplifier
Power supply</th><th>MR-J3-10A to 70A</th><th>MR-J3-100A to 22KA</th><th>MR-J3-10A1 to 40A1</th></tr>
<tr><td>3-phase 200 to 230VAC, 50/60Hz</td><td></td><td>L_1 ・ L_2 ・ L_3</td><td></td></tr>
<tr><td>1-phase 200 to 230VAC, 50/60Hz</td><td>L_1 ・ L_2</td><td></td><td></td></tr>
<tr><td>1-phase 100 to 120VAC, 50/60Hz</td><td></td><td></td><td>L_1 ・ L_2</td></tr>
</table>
<table>
<tr><th>Servo amplifier
Power supply</th><th>MR-J3-60A4 to 22KA4</th></tr>
<tr><td>3-phase 380 to 480VAC, 50/60Hz</td><td>L_1 ・ L_2 ・ L_3</td></tr>
</table></td></tr>
<tr><td>P_1
P_2</td><td>Power factor improving DC reactor</td><td>1) MR-J3-700A or less
When not using the power factor improving DC reactor, connect P_1 and P_2. (Factory-wired.)
When using the power factor improving DC reactor, disconnect P_1 and P_2, and connect the power factor improving DC reactor to P_1 and P_2.
2) MR-J3-11KA(4) to 22KA(4)
MR-J3-11KA(4) to 22KA(4) do not have P_2.
When not using the power factor improving reactor, connect P_1 and P. (Factory-wired)
When using the power factor improving reactor, connect it to P and P_1.
Refer to section 12.13.</td></tr>
<tr><td>P
C
D</td><td>Regenerative option</td><td>1) MR-J3-350A or less ・ MR-J3-200A4 or less
When using servo amplifier built-in regenerative resistor, connect P(＋) and D. (Factory-wired)
When using regenerative option, disconnect P(＋) and D, and connect regenerative option to P and C.
2) MR-J3-350A4 ・ 500A(4) ・ 700A(4)
MR-J3-350A4 ・ 500A(4) ・ 700A(4) do not have D.
When using servo amplifier built-in regenerative resistor, connect P and C. (Factory-wired)
When using regenerative option, disconnect P and C, and connect regenerative option to P and C.
3) MR-J3-11KA(4) to 22KA(4)
MR-J3-11KA(4) to 22KA(4) do not have D.
When not using the power regenerative converter and the brake unit, make sure to connect the regenerative option to P and C.
Refer to section 12.2 to 12.5.</td></tr>
<tr><td>L_{11}
L_{21}</td><td>Control circuit power supply</td><td>Supply the following power to L_{11} ・ L_{21}.
<table>
<tr><th>Servo amplifier
Power supply</th><th>MR-J3-10A to 22KA</th><th>MR-J3-10A1 to 40A1</th><th>MR-J3-60A4 to 22KA4</th></tr>
<tr><td>1-phase 200 to 230VAC, 50/60Hz</td><td>L_{11} ・ L_{21}</td><td></td><td></td></tr>
<tr><td>1-phase 100 to 120VAC, 50/60Hz</td><td></td><td>L_{11} ・ L_{21}</td><td></td></tr>
<tr><td>1-phase 380 to 480VAC, 50/60Hz</td><td></td><td></td><td>L_{11} ・ L_{21}</td></tr>
</table></td></tr>
</table>

Abbreviation	Connection target (application)	Description
U V W	Servo motor power	Connect to the servo motor power supply terminals (U, V, W). During power-on, do not open or close the motor power line. Otherwise, a malfunction or faulty may occur.
N	Return converter Brake unit	When using the power regenerative converter/brake unit, connect it to P and N. Do not connect to servo amplifier MR-J3-350A(4) or less. For details, refer to section 12.3 to 12.5.
⏚	Protective earth (PE)	Connect to the earth terminal of the servo motor and to the protective earth (PE) of the control box to perform grounding.

3.3.2 Power-on sequence

(1) Power-on procedure

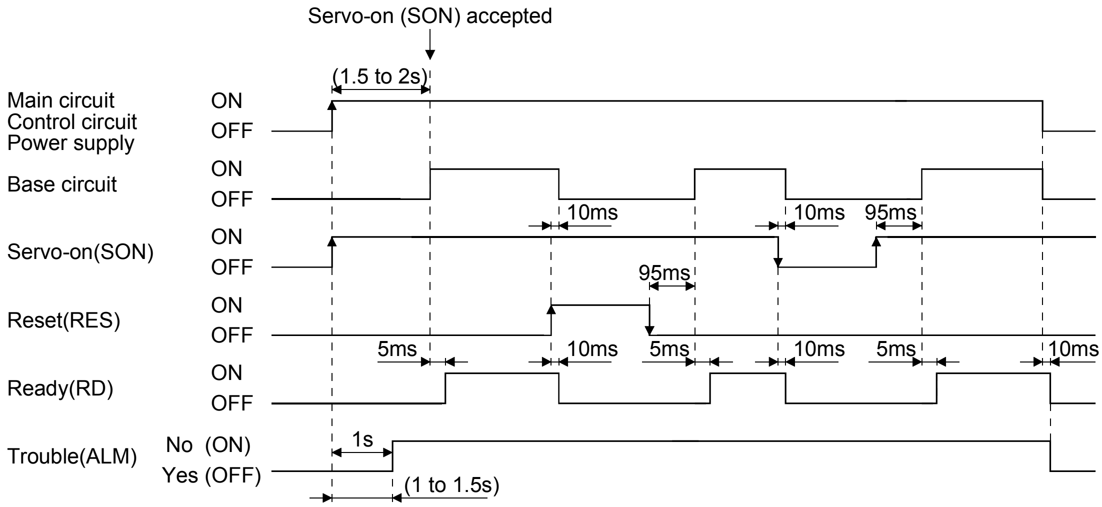
1) Always wire the power supply as shown in above section 3.1 using the magnetic contactor with the main circuit power supply (3-phase: L_1, L_2, L_3, 1-phase: L_1, L_2). Configure up an external sequence to switch off the magnetic contactor as soon as an alarm occurs.

2) Switch on the control circuit power supply L_{11}, L_{21} simultaneously with the main circuit power supply or before switching on the main circuit power supply. If the main circuit power supply is not on, the display shows the corresponding warning. However, by switching on the main circuit power supply, the warning disappears and the servo amplifier will operate properly.

3) The servo amplifier can accept the servo-on (SON) about 1 to 2s after the main circuit power supply is switched on. Therefore, when SON is switched on simultaneously with the main circuit power supply, the base circuit will switch on in about 1 to 2s, and the ready (RD) will switch on in further about 5ms, making the servo amplifier ready to operate. (Refer to paragraph (2) of this section.)

4) When the reset (RES) is switched on, the base circuit is shut off and the servo motor shaft coasts.

(2) Timing chart



Power-on timing chart

(3) Emergency stop

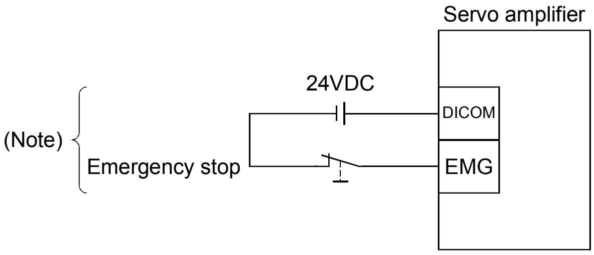
⚠CAUTION	▪ Provide an external emergency stop circuit to ensure that operation can be stopped and power switched off immediately.

Make up a circuit that shuts off main circuit power as soon as EMG is turned off at an emergency stop. When EMG is turned off, the dynamic brake is operated to bring the servo motor to a sudden stop. At this time, the display shows the servo emergency stop warning (AL.E6).

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

The servo amplifier life may be shortened.

Also, if the forward rotation start (ST1) and reverse rotation start (ST2) are on or a pulse train is input during an emergency stop, the servo motor will rotate as soon as the warning is reset. During an emergency stop, always shut off the run command.



Note. For the sink I/O interface. For the source I/O interface, refer to section 3.8.3.

3.3.3 CNP1, CNP2, CNP3 wiring method

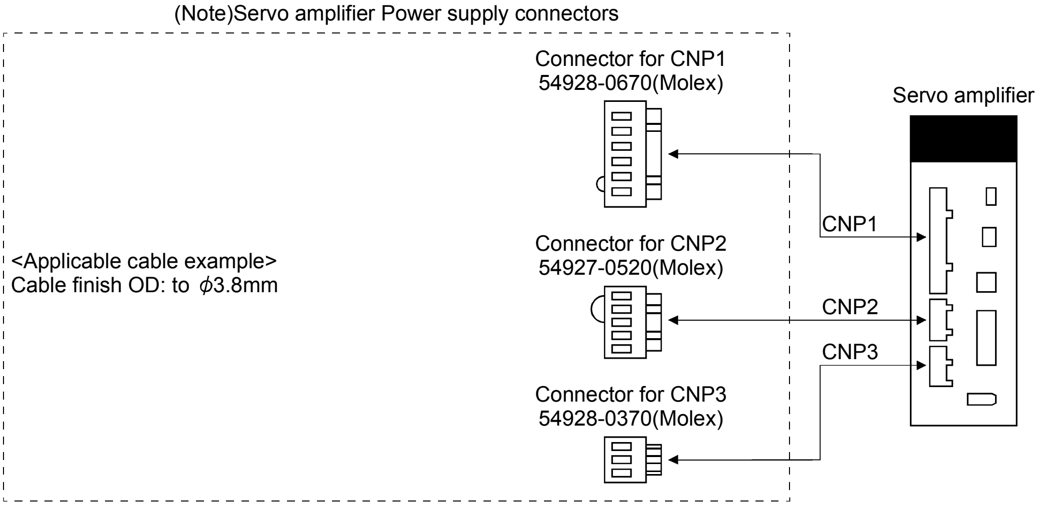
POINT

- Refer to section 12.11 for the wire sizes used for wiring.
- MR-J3-500A or more · MR-J3-350A4 or more does not have these connectors.

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

(1) MR-J3-10A to MR-J3-100A

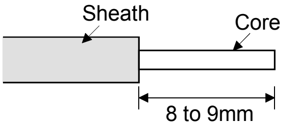
(a) Servo amplifier power supply connectors



Note. These connectors are of insert type. As the crimping type, the following connectors (Molex) are recommended.
For CNP1: 51241-0600 (connector), 56125-0128 (terminal)
For CNP2: 51240-0500 (connector), 56125-0128 (terminal)
For CNP3: 51241-0300 (connector), 56125-0128 (terminal)
Crimping tool: CNP57349-5300
<Connector applicable cable example>
Cable finish OD: to ϕ3.8mm

(b) Termination of the cables

Solid wire: After the sheath has been stripped, the cable can be used as it is.



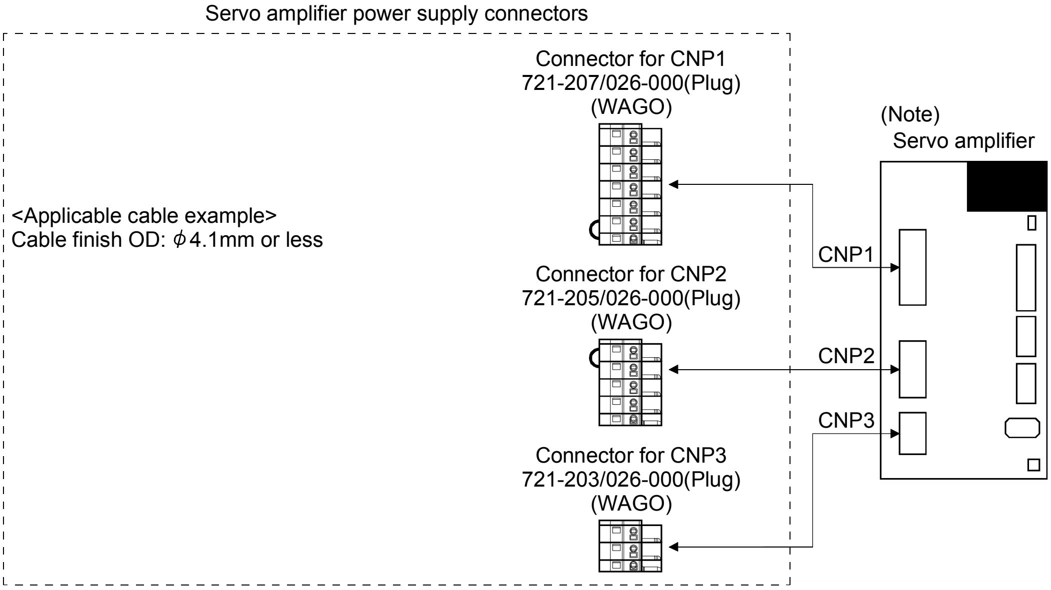
Twisted wire: Use the cable after stripping the sheath and twisting the core. At this time, take care to avoid a short caused by the loose wires of the core and the adjacent pole. Do not solder the core as it may cause a contact fault. Alternatively, a ferrule may be used to put the wires together.

Cable size		Ferrule type (Note 1)		Crimping tool (Note 2)
[mm^2]	AWG	For 1 cable	For 2 cable	
1.25/1.5	16	AI 1,5-10 BK	AI-TWIN2 × 1,5-10 BK	Variocrimp 4 206-204
2/2.5	14	AI 2,5-10 BU		

Note 1. Manufacturer: Phoenix Contact
2. Manufacturer: WAGO

(2) MR-J3-200A・MR-J3-60A4 to MR-J3-200A4

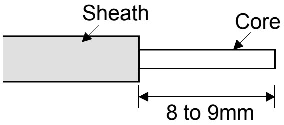
(a) Servo amplifier power supply connectors



Note. Connectors (CNP1, CNP2, and CNP3) and appearance of MR-J3-200A servo amplifier have been changed from April 2008 production. Model name of the servo amplifier before March 2008 is changed to MR-J3-200A-RT. For MR-J3-200A-RT, refer to appendix 5.

(b) Termination of the cables

Solid wire: After the sheath has been stripped, the cable can be used as it is.



Twisted wire: Use the cable after stripping the sheath without twisting the core. At this time, take care to avoid a short caused by the loose wires of the core and the adjacent pole. Do not solder the core as it may cause a contact fault. Alternatively, a ferrule may be used to put the wires together.

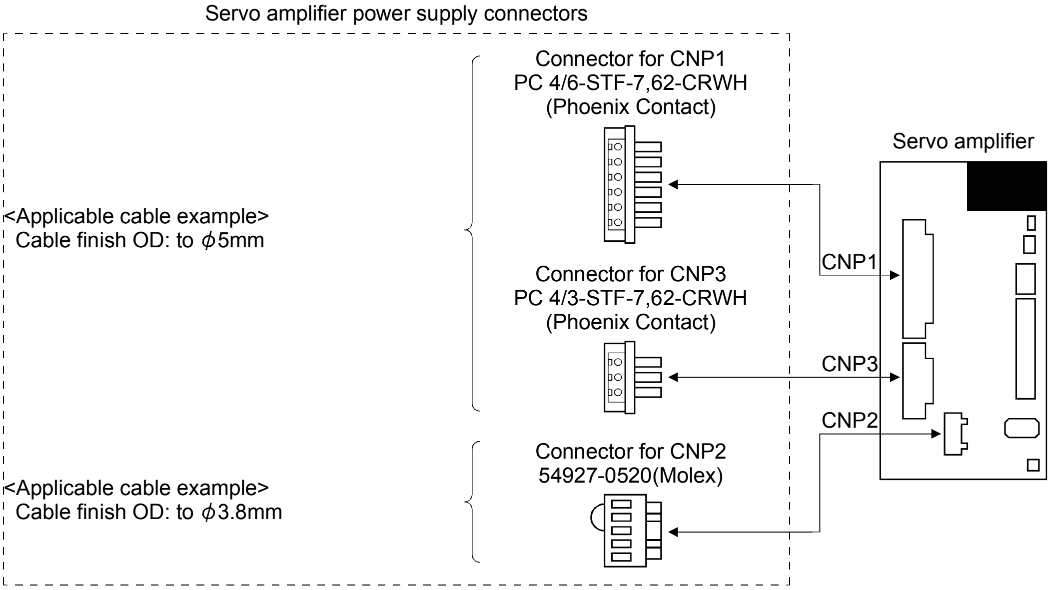
Cable size		Ferrule type		Crimping tool (Note 2)
[mm^2]	AWG	For 1 cable	For 2 cable	
1.25/1.5	16	AI 1,5-10 BK (Note 1)	AI-TWIN2×1,5-10 BK (Note 1)	Variocrimp 4 206-204
2	14	216-246 (Note 2)		

Note 1. Manufacturer: Phoenix Contact

2. Manufacturer: WAGO

(3) MR-J3-350A

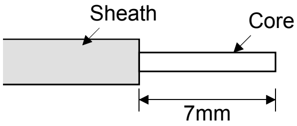
(a) Servo amplifier power supply connectors



(b) Termination of the cables

1) CNP1・CNP3

Solid wire: After the sheath has been stripped, the cable can be used as it is.



Twisted wire: Use the cable after stripping the sheath and twisting the core. At this time, take care to avoid a short caused by the loose wires of the core and the adjacent pole. Do not solder the core as it may cause a contact fault. Alternatively, a ferrule may be used to put the wires together.

Cable size		Ferrule type		Crimping tool	Manufacturer
[mm^2]	AWG	For 1 cable	For 2 cables		
1.25/1.5	16	AI 1,5-8 BK	AI-TWIN2×1,5-8 BK	CRIMPFOX-ZA3	Phoenix Contact
2.0/2.5	14	AI 2,5-8 BU	AI-TWIN2×2,5-10 BU		
3.5	12	AI 4-10 GY			

2) CNP2

CNP2 is the same as MR-J3-100A or smaller capacities. Refer to (1) (b) of this section.

(4) Insertion of cable into Molex and WAGO connectors

Insertion of cable into 54928-0670, 54927-0520, 54928-0370 (Molex) connectors and 721-207/026-000, 721-205/026-000 and 721-203/026-000 (WAGO) connectors are as follows.

The following explains for Molex, however use the same procedures for inserting WAGO connectors as well.

POINT

- It may be difficult for a cable to be inserted to the connector depending on wire size or ferrule configuration. In this case, change the wire type or correct it in order to prevent the end of ferrule from widening, and then insert it.

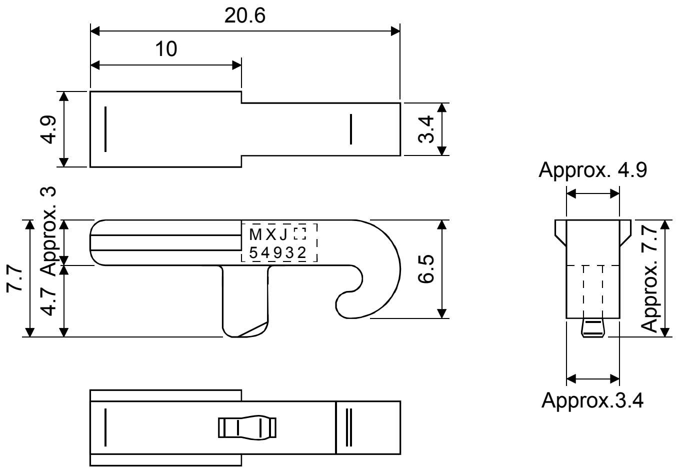
How to connect a cable to the servo amplifier power supply connector is shown below.

(a) When using the supplied cable connection lever

1) The servo amplifier is packed with the cable connection lever.

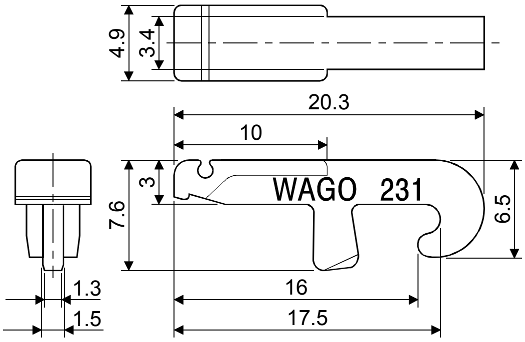
a) 54932-0000 (Molex)

[Unit: mm]

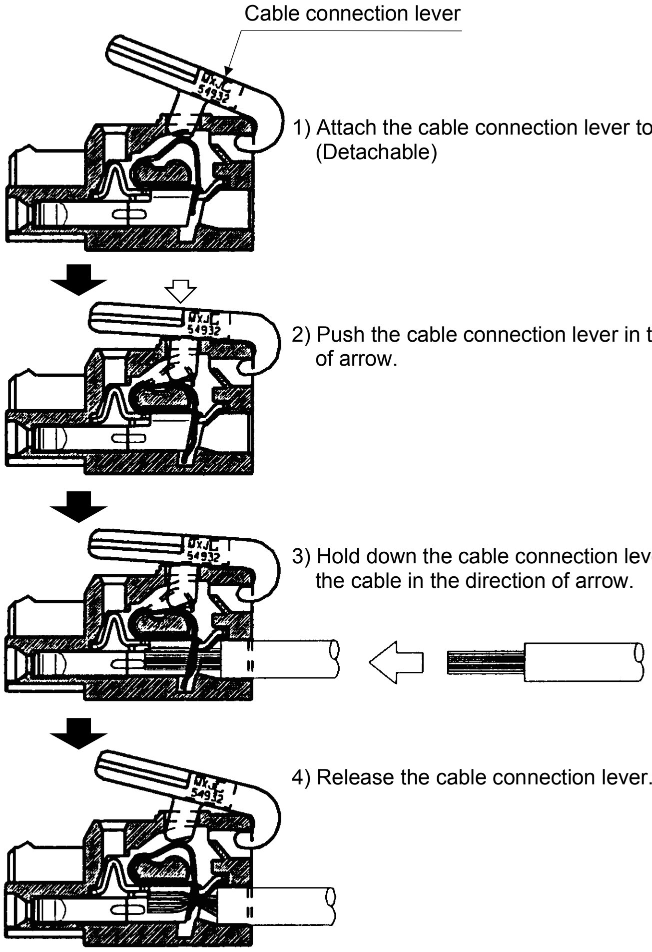


b) 231-131 (WAGO)

[Unit: mm]



2) Cable connection procedure



1) Attach the cable connection lever to the housing. (Detachable)

2) Push the cable connection lever in the direction of arrow.

3) Hold down the cable connection lever and insert the cable in the direction of arrow.

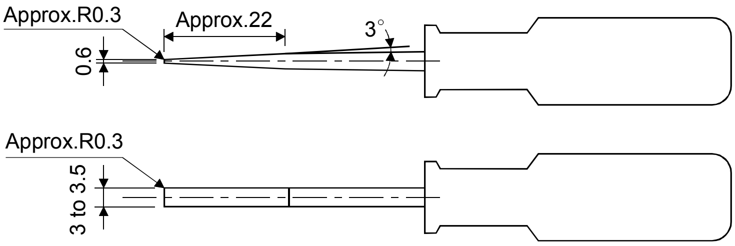
4) Release the cable connection lever.

(b) Inserting the cable into the connector

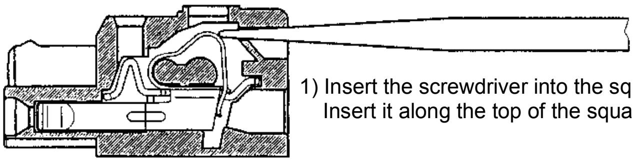
1) Applicable flat-blade screwdriver dimensions

Always use the screwdriver shown here to do the work.

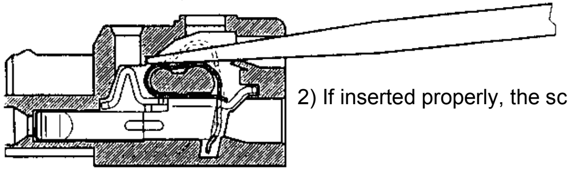
[Unit: mm]



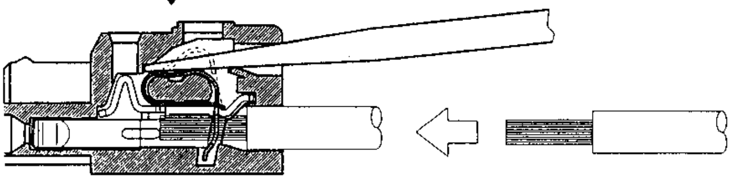
2) When using the flat-blade screwdriver - part 1



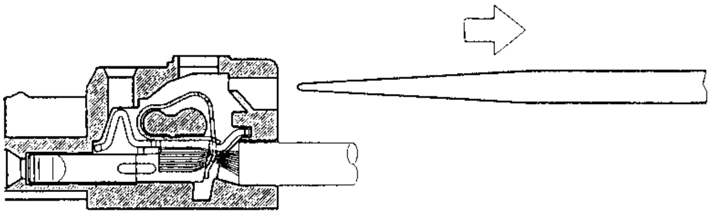
1) Insert the screwdriver into the square hole.
Insert it along the top of the square hole to insert it smoothly.



2) If inserted properly, the screwdriver is held.

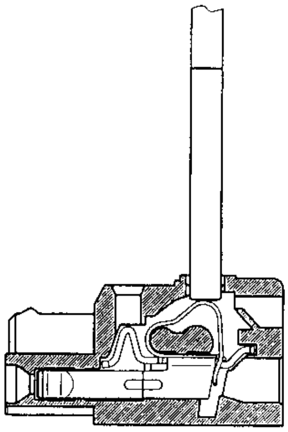


3) With the screwdriver held, insert the cable in the direction of arrow. (Insert the cable as far as it will go.)

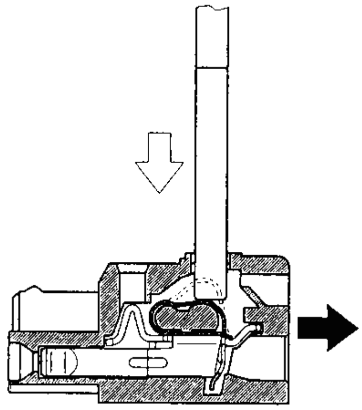


4) Releasing the screwdriver connects the cable.

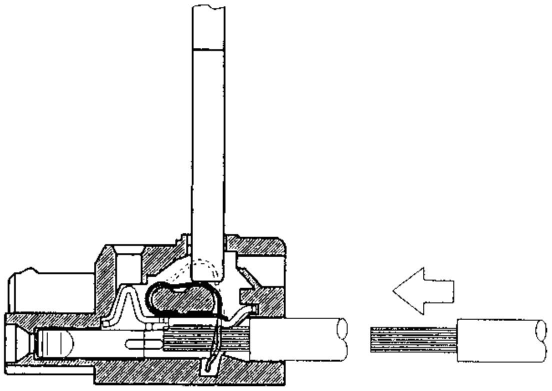
3) When using the flat-blade screwdriver - part 2



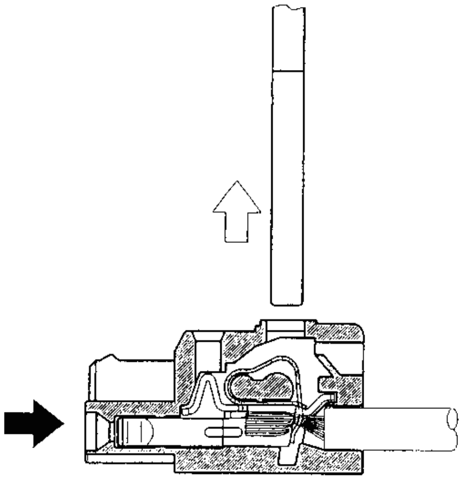
1) Insert the screwdriver into the square window at top of the connector.



2) Push the screwdriver in the direction of arrow.



3) With the screwdriver pushed, insert the cable in the direction of arrow. (Insert the cable as far as it will go.)



4) Releasing the screwdriver connects the cable.

(5) How to insert the cable into Phoenix Contact connector

POINT
▪ Do not use a precision driver because the cable cannot be tightened with enough torque.

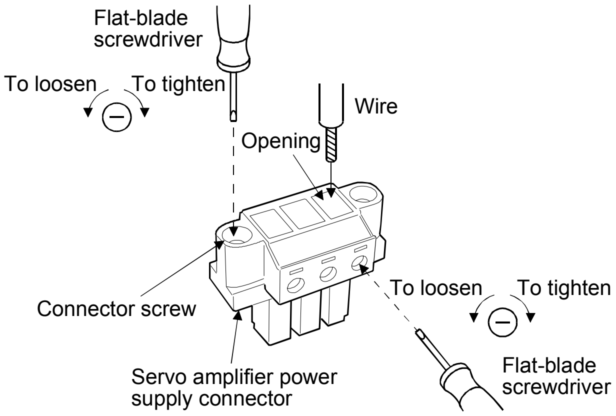
Insertion of cables into Phoenix Contact connector PC 4/6-STF-7,62-CRWH or PC 4/3-STF-7,62-CRWH is shown as follows.

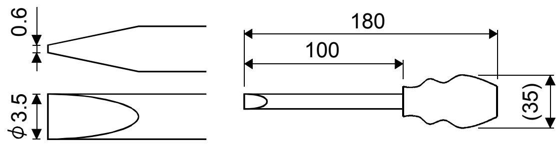
Before inserting the cable into the opening, make sure that the screw of the terminal is fully loose. Insert the core of the cable into the opening and tighten the screw with a flat-blade screwdriver. When the cable is not tightened enough to the connector, the cable or connector may generate heat because of the poor contact. (When using a cable of 1.5mm^2 or less, two cables may be inserted into one opening.)

Secure the connector to the servo amplifier by tightening the connector screw.

For securing the cable and the connector, use a flat-blade driver with 0.6mm blade edge thickness and 3.5mm diameter (Recommended flat-blade screwdriver. Phoenix Contact SZS 0.6×3.5). Apply 0.5 to 0.6 N・m torque to screw.

[Unit: mm]





Recommended flat-blade screwdriver dimensions

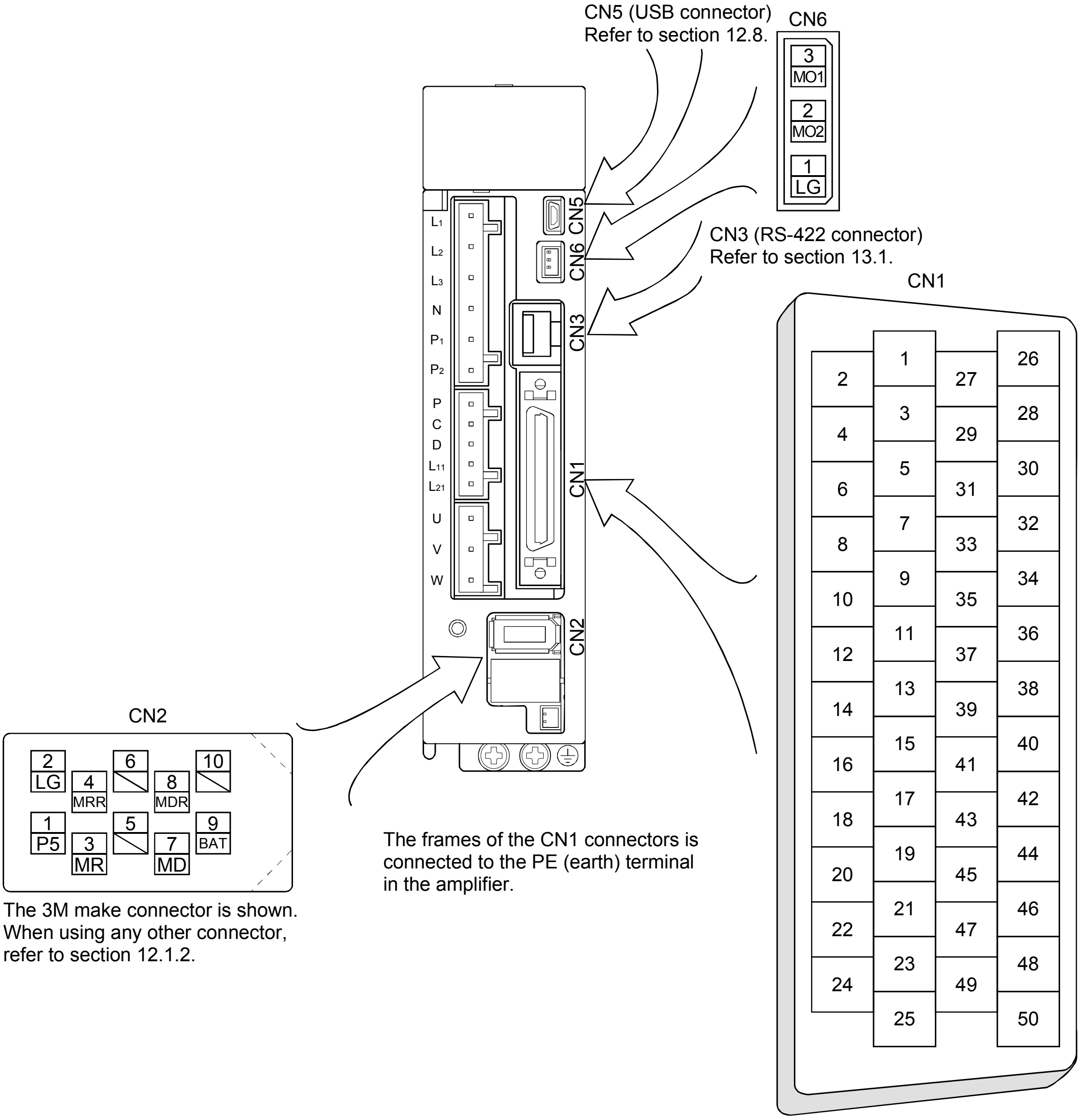
3.4 Connectors and signal arrangements

POINT

- The pin configurations of the connectors are as viewed from the cable connector wiring section.
- Refer to (2) of this section for CN1 signal assignment.

(1) Signal arrangement

The servo amplifier front view shown is that of the MR-J3-20A or less. Refer to chapter 10 Outline Drawings for the appearances and connector layouts of the other servo amplifiers.



The 3M make connector is shown. When using any other connector, refer to section 12.1.2.

The frames of the CN1 connectors is connected to the PE (earth) terminal in the amplifier.

(2) CN1 signal assignment

The signal assignment of connector changes with the control mode as indicated below.

For the pins which are given parameter No.s in the related parameter column, their signals can be changed using those parameters.

Pin No.	(Note 1) I/O	(Note 2) I/O signals in control modes						Related parameter No.
		P	P/S	S	S/T	T	T/P	
1		P15R	P15R	P15R	P15R	P15R	P15R	
2	I		−/VC	VC	VC/VLA	VLA	VLA/−	
3		LG	LG	LG	LG	LG	LG	
4	O	LA	LA	LA	LA	LA	LA	
5	O	LAR	LAR	LAR	LAR	LAR	LAR	
6	O	LB	LB	LB	LB	LB	LB	
7	O	LBR	LBR	LBR	LBR	LBR	LBR	
8	O	LZ	LZ	LZ	LZ	LZ	LZ	
9	O	LZR	LZR	LZR	LZR	LZR	LZR	
10	I	PP	PP/−				−/PP	
11	I	PG	PG/−				−/PG	
12		OPC	OPC/−				−/OPC	
13								
14								
15	I	SON	SON	SON	SON	SON	SON	PD03
16	I		−/SP2	SP2	SP2/SP2	SP2	SP2/−	PD04
17	I	PC	PC/ST1	ST1	ST1/RS2	RS2	RS2/PC	PD05
18	I	TL	TL/ST2	ST2	ST2/RS1	RS1	RS1/TL	PD06
19	I	RES	RES	RES	RES	RES	RES	PD07
20		DICOM	DICOM	DICOM	DICOM	DICOM	DICOM	
21		DICOM	DICOM	DICOM	DICOM	DICOM	DICOM	
22	O	INP	INP/SA	SA	SA/−		−/INP	PD13
23	O	ZSP	ZSP	ZSP	ZSP	ZSP	ZSP	PD14
24	O	INP	INP/SA	SA	SA/−		−/INP	PD15
25	O	TLC	TLC	TLC	TLC/VLC	VLC	VLC/TLC	PD16
26								
27	I	TLA	(Note 3) TLA	(Note 3) TLA	(Note 3) TLA/TC	TC	TC/TLA	
28		LG	LG	LG	LG	LG	LG	
29								
30		LG	LG	LG	LG	LG	LG	
31								
32								
33	O	OP	OP	OP	OP	OP	OP	
34		LG	LG	LG	LG	LG	LG	
35	I	NP	NP/−				−/NP	
36	I	NG	NG/−				−/NG	
37								
38								
39								
40								
41	I	CR	CR/SP1	SP1	SP1/SP1	SP1	SP1/CR	PD08
42	I	EMG	EMG	EMG	EMG	EMG	EMG	
43	I	LSP	LSP	LSP	LSP/−		−/LSP	PD10
44	I	LSN	LSN	LSN	LSN/−		−/LSN	PD11
45	I	LOP	LOP	LOP	LOP	LOP	LOP	PD12

Pin No.	(Note 1) I/O	(Note 2) I/O signals in control modes						Related parameter No.
		P	P/S	S	S/T	T	T/P	
46		DOCOM	DOCOM	DOCOM	DOCOM	DOCOM	DOCOM	
47		DOCOM	DOCOM	DOCOM	DOCOM	DOCOM	DOCOM	
48	O	ALM	ALM	ALM	ALM	ALM	ALM	
49	O	RD	RD	RD	RD	RD	RD	PD18
50								

Note 1. I: Input signal, O: Output signal

2. P: Position control mode, S: Speed control mode, T: Torque control mode, P/S: Position/speed control changeover mode, S/T: Speed/torque control changeover mode, T/P: Torque/position control changeover mode

3. TLA can be used when TL is made usable by setting the parameter No.PD03 to PD08/PD10 to PD12.

(3) Explanation of abbreviations

Abbreviation	Signal name	Abbreviation	Signal name
SON	Servo-on	TLC	Limiting torque
LSP	Forward rotation stroke end	VLC	Limiting speed
LSN	Reverse rotation stroke end	RD	Ready
CR	Clear	ZSP	Zero speed detection
SP1	Speed selection 1	INP	In-position
SP2	Speed selection 2	SA	Speed reached
PC	Proportion control	ALM	Trouble
ST1	Forward rotation start	WNG	Warning
ST2	Reverse rotation start	BWNG	Battery warning
TL	External torque limit selection	OP	Encoder Z-phase pulse (open collector)
RES	Reset	MBR	Electromagnetic brake interlock
EMG	Emergency stop	LZ	Encoder Z-phase pulse (differential line driver)
LOP	Control selection	LZR	
VC	Analog speed command	LA	Encoder A-phase pulse (differential line driver)
VLA	Analog speed limit	LAR	
TLA	Analog torque limit	LB	Encoder B-phase pulse (differential line driver)
TC	Analog torque command	LBR	
RS1	Forward rotation selection	DICOM	Digital I/F power supply input
RS2	Reverse rotation selection	OPC	Open collector power input
PP	Forward/reverse rotation pulse train	DOCOM	Digital I/F common
NP		P15R	15VDC power supply
PG		LG	Control common
NG		SD	Shield

3.5 Signal explanations

For the I/O interfaces (symbols in I/O division column in the table), refer to section 3.8.2.
In the control mode field of the table
P : Position control mode, S: Speed control mode, T: Torque control mode
○ : Denotes that the signal may be used in the initial setting status.
△ : Denotes that the signal may be used by setting the corresponding parameter No.PD03 to PD08, PD10 to PD12, PD13 to PD16, PD18.
The pin No.s in the connector pin No. column are those in the initial status.

(1) I/O devices

(a) Input devices

<table>
<tr><th rowspan="2">Device</th><th rowspan="2">Symbol</th><th rowspan="2">Connector pin No.</th><th rowspan="2">Functions/Applications</th><th rowspan="2">I/O division</th><th colspan="3">Control mode</th></tr>
<tr><th>P</th><th>S</th><th>T</th></tr>
<tr><td>Servo-on</td><td>SON</td><td>CN1-15</td><td>Turn SON on to power on the base circuit and make the servo amplifier ready to operate (servo-on).
Turn it off to shut off the base circuit and coast the servo motor.
Set "□□□4" in parameter No.PD01 to switch this signal on (keep terminals connected) automatically in the servo amplifier.</td><td>DI-1</td><td>○</td><td>○</td><td>○</td></tr>
<tr><td>Reset</td><td>RES</td><td>CN1-19</td><td>Turn RES on for more than 50ms to reset the alarm.
Some alarms cannot be deactivated by the reset (RES). Refer to section 9.1.
Turning RES on in an alarm-free status shuts off the base circuit. The base circuit is not shut off when "□□1□" is set in parameter No.PD20.
This device is not designed to make a stop. Do not turn it ON during operation.</td><td>DI-1</td><td>○</td><td>○</td><td>○</td></tr>
<tr><td>Forward rotation stroke end</td><td>LSP</td><td>CN1-43</td><td rowspan="2">To start operation, turn LSP/LSN on. Turn it off to bring the motor to a sudden stop and make it servo-locked.
Set "□□□1" in parameter No.PD20 to make a slow stop.
(Refer to section 5.4.3.)
<table>
<tr><th colspan="2">(Note) Input device</th><th colspan="2">Operation</th></tr>
<tr><th>LSP</th><th>LSN</th><th>CCW direction</th><th>CW direction</th></tr>
<tr><td>1</td><td>1</td><td>○</td><td>○</td></tr>
<tr><td>0</td><td>1</td><td></td><td>○</td></tr>
<tr><td>1</td><td>0</td><td>○</td><td></td></tr>
<tr><td>0</td><td>0</td><td></td><td></td></tr>
</table>
Note. 0: off
1: on

Set parameter No.PD01 as indicated below to switch on the signals (keep terminals connected) automatically in the servo amplifier.
<table>
<tr><th rowspan="2">Parameter No.PD01</th><th colspan="2">Status</th></tr>
<tr><th>LSP</th><th>LSN</th></tr>
<tr><td>□4□□</td><td>Automatic ON</td><td></td></tr>
<tr><td>□8□□</td><td></td><td>Automatic ON</td></tr>
<tr><td>□C□□</td><td>Automatic ON</td><td>Automatic ON</td></tr>
</table>
When LSP or LSN turns OFF, an external stroke limit warning (AL. 99) occurs, and Warning (WNG) turns OFF. However, when using WNG, set the parameter No.PD13 to PD16/PD18 to make it usable.</td><td rowspan="2">DI-1</td><td rowspan="2">○</td><td rowspan="2">○</td><td rowspan="2"></td></tr>
<tr><td>Reverse rotation stroke end</td><td>LSN</td><td>CN1-44</td></tr>
</table>

<table>
<tr><th rowspan="2">Device</th><th rowspan="2">Symbol</th><th rowspan="2">Connec-tor pin No.</th><th rowspan="2">Functions/Applications</th><th rowspan="2">I/O division</th><th colspan="3">Control mode</th></tr>
<tr><th>P</th><th>S</th><th>T</th></tr>
<tr><td>External torque limit selection</td><td>TL</td><td>CN1-18</td><td>Turn TL off to make Forward torque limit (parameter No.PA11) and Reverse torque limit (parameter No.PA12) valid, or turn it on to make Analog torque limit (TLA) valid.
For details, refer to section 3.6.1 (5).</td><td>DI-1</td><td>○</td><td>△</td><td></td></tr>
<tr><td>Internal torque limit selection</td><td>TL1</td><td></td><td>When using this signal, make it usable by making the setting of parameter No.PD03 to PD08, PD10 to PD12.
For details, refer to section 3.6.1 (5).</td><td>DI-1</td><td>△</td><td>△</td><td>△</td></tr>
<tr><td>Forward rotation start</td><td>ST1</td><td>CN1-17</td><td rowspan="2">Used to start the servo motor in any of the following directions.
<table>
<tr><th colspan="2">(Note) Input device</th><th rowspan="2">Servo motor starting direction</th></tr>
<tr><th>ST2</th><th>ST1</th></tr>
<tr><td>0</td><td>0</td><td>Stop (servo lock)</td></tr>
<tr><td>0</td><td>1</td><td>CCW</td></tr>
<tr><td>1</td><td>0</td><td>CW</td></tr>
<tr><td>1</td><td>1</td><td>Stop (servo lock)</td></tr>
</table>
Note. 0: off
1: on

If both ST1 and ST2 are switched on or off during operation, the servo motor will be decelerated to a stop according to the parameter No.PC02 setting and servo-locked.
When "□□□1" is set in parameter No.PC23, the servo motor is not servo-locked after deceleration to a stop.</td><td rowspan="2">DI-1</td><td rowspan="2"></td><td rowspan="2">○</td><td rowspan="2"></td></tr>
<tr><td>Reverse rotation start</td><td>ST2</td><td>CN1-18</td></tr>
<tr><td>Forward rotation selection</td><td>RS1</td><td>CN1-18</td><td rowspan="2">Used to select any of the following servo motor torque generation directions.
<table>
<tr><th colspan="2">(Note) Input device</th><th rowspan="2">Torque generation direction</th></tr>
<tr><th>RS2</th><th>RS1</th></tr>
<tr><td>0</td><td>0</td><td>Torque is not generated.</td></tr>
<tr><td>0</td><td>1</td><td>Forward rotation in driving mode/ reverse rotation in regenerative mode</td></tr>
<tr><td>1</td><td>0</td><td>Reverse rotation in driving mode/ forward rotation in regenerative mode</td></tr>
<tr><td>1</td><td>1</td><td>Torque is not generated.</td></tr>
</table>
Note. 0: off
1: on</td><td rowspan="2">DI-1</td><td rowspan="2"></td><td rowspan="2"></td><td rowspan="2">○</td></tr>
<tr><td>Reverse rotation selection</td><td>RS2</td><td>CN1-17</td></tr>
</table>

<table>
<tr><th rowspan="2">Device</th><th rowspan="2">Symbol</th><th rowspan="2">Connector pin No.</th><th rowspan="2">Functions/Applications</th><th rowspan="2">I/O division</th><th colspan="3">Control mode</th></tr>
<tr><th>P</th><th>S</th><th>T</th></tr>
<tr><td>Speed selection 1</td><td>SP1</td><td>CN1-41</td><td rowspan="3"><Speed control mode>
Used to select the command speed for operation.
When using SP3, make it usable by making the setting of parameter No.PD03 to PD08, PD10 to PD12.
<table>
<tr><th colspan="3">(Note)
Input device</th><th rowspan="2">Speed command</th></tr>
<tr><th>SP3</th><th>SP2</th><th>SP1</th></tr>
<tr><td>0</td><td>0</td><td>0</td><td>Analog speed command (VC)</td></tr>
<tr><td>0</td><td>0</td><td>1</td><td>Internal speed command 1 (parameter No.PC05)</td></tr>
<tr><td>0</td><td>1</td><td>0</td><td>Internal speed command 2 (parameter No.PC06)</td></tr>
<tr><td>0</td><td>1</td><td>1</td><td>Internal speed command 3 (parameter No.PC07)</td></tr>
<tr><td>1</td><td>0</td><td>0</td><td>Internal speed command 4 (parameter No.PC08)</td></tr>
<tr><td>1</td><td>0</td><td>1</td><td>Internal speed command 5 (parameter No.PC09)</td></tr>
<tr><td>1</td><td>1</td><td>0</td><td>Internal speed command 6 (parameter No.PC10)</td></tr>
<tr><td>1</td><td>1</td><td>1</td><td>Internal speed command 7 (parameter No.PC11)</td></tr>
</table>
Note. 0: off
1: on

<Torque control mode>
Used to select the limit speed for operation.
When using SP3, make it usable by making the setting of parameter No.PD03 to PD08, PD10 to PD12.
<table>
<tr><th colspan="3">(Note)
Input device</th><th rowspan="2">Speed limit</th></tr>
<tr><th>SP3</th><th>SP2</th><th>SP1</th></tr>
<tr><td>0</td><td>0</td><td>0</td><td>Analog speed limit (VLA)</td></tr>
<tr><td>0</td><td>0</td><td>1</td><td>Internal speed limit 1 (parameter No.PC05)</td></tr>
<tr><td>0</td><td>1</td><td>0</td><td>Internal speed limit 2 (parameter No.PC06)</td></tr>
<tr><td>0</td><td>1</td><td>1</td><td>Internal speed limit 3 (parameter No.PC07)</td></tr>
<tr><td>1</td><td>0</td><td>0</td><td>Internal speed limit 4 (parameter No.PC08)</td></tr>
<tr><td>1</td><td>0</td><td>1</td><td>Internal speed limit 5 (parameter No.PC09)</td></tr>
<tr><td>1</td><td>1</td><td>0</td><td>Internal speed limit 6 (parameter No.PC10)</td></tr>
<tr><td>1</td><td>1</td><td>1</td><td>Internal speed limit 7 (parameter No.PC11)</td></tr>
</table>
Note. 0: off
1: on</td><td>DI-1</td><td></td><td>○</td><td>○</td></tr>
<tr><td>Speed selection 2</td><td>SP2</td><td>CN1-16</td><td>DI-1</td><td></td><td>○</td><td>○</td></tr>
<tr><td>Speed selection 3</td><td>SP3</td><td></td><td>DI-1</td><td></td><td>△</td><td>△</td></tr>
</table>

<table>
<tr><th rowspan="2">Device</th><th rowspan="2">Symbol</th><th rowspan="2">Connec-tor pin No.</th><th rowspan="2">Functions/Applications</th><th rowspan="2">I/O division</th><th colspan="3">Control mode</th></tr>
<tr><th>P</th><th>S</th><th>T</th></tr>
<tr><td>Proportion control</td><td>PC</td><td>CN1-17</td><td>Turn PC on to switch the speed amplifier from the proportional integral type to the proportional type.
If the servo motor at a stop is rotated even one pulse due to any external factor, it generates torque to compensate for a position shift. When the servo motor shaft is to be locked mechanically after positioning completion (stop), switching on the proportion control (PC) upon positioning completion will suppress the unnecessary torque generated to compensate for a position shift.
When the shaft is to be locked for a long time, switch on the proportion control (PC) and external torque limit selection (TL) at the same time to make the torque less than the rated by the analog torque limit (TLA).</td><td>DI-1</td><td>○</td><td>△</td><td></td></tr>
<tr><td>Emergency stop</td><td>EMG</td><td>CN1-42</td><td>Turn EMG off (open between commons) to bring the motor to an emergency stop state, in which the base circuit is shut off and the dynamic brake is operated. Turn EMG on (short between commons) in the emergency stop state to reset that state.</td><td>DI-1</td><td>○</td><td>○</td><td>○</td></tr>
<tr><td>Clear</td><td>CR</td><td>CN1-41</td><td>Turn CR on to clear the position control counter droop pulses on its leading edge. The pulse width should be 10ms or longer.
The delay amount set in parameter No.PB03 (position command acceleration/deceleration time constant) is also cleared. When the parameter No.PD22 setting is "□□□ 1 ", the pulses are always cleared while CR is on.</td><td>DI-1</td><td>○</td><td></td><td></td></tr>
<tr><td>Electronic gear selection 1</td><td>CM1</td><td></td><td rowspan="2">When using CM1 and CM2, make them usable by the setting of parameters No.PD03 to PD08, PD10 to PD12.
The combination of CM1 and CM2 gives you a choice of four different electronic gear numerators set in the parameters.
CM1 and CM2 cannot be used in the absolute position detection system.
<table>
<tr><th colspan="2">(Note) Input device</th><th rowspan="2">Electronic gear molecule</th></tr>
<tr><th>CM2</th><th>CM1</th></tr>
<tr><td>0</td><td>0</td><td>Parameter No.PA06</td></tr>
<tr><td>0</td><td>1</td><td>Parameter No.PC32</td></tr>
<tr><td>1</td><td>0</td><td>Parameter No.PC33</td></tr>
<tr><td>1</td><td>1</td><td>Parameter No.PC34</td></tr>
</table>
Note. 0: off
1: on</td><td>DI-1</td><td>△</td><td></td><td></td></tr>
<tr><td>Electronic gear selection 2</td><td>CM2</td><td></td><td>DI-1</td><td>△</td><td></td><td></td></tr>
<tr><td>Gain changing</td><td>CDP</td><td></td><td>When using this signal, make it usable by the setting of parameter No.PD03 to PD08, PD10 to PD12.
Turn CDP on to change the load inertia moment ratio and gain values into the parameter No.PB29 to PB34 values.</td><td>DI-1</td><td>△</td><td>△</td><td>△</td></tr>
</table>

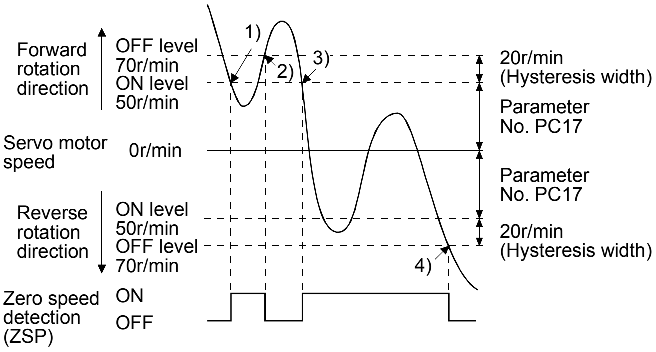
<table>
<tr><th rowspan="2">Device</th><th rowspan="2">Symbol</th><th rowspan="2">Connector pin No.</th><th rowspan="2">Functions/Applications</th><th rowspan="2">I/O division</th><th colspan="3">Control mode</th></tr>
<tr><th>P</th><th>S</th><th>T</th></tr>
<tr><td>Control change</td><td>LOP</td><td>CN1-45</td><td><Position/speed control change mode>
Used to select the control mode in the position/speed control change mode.
<table>
<tr><th>(Note) LOP</th><th>Control mode</th></tr>
<tr><td>0</td><td>Position</td></tr>
<tr><td>1</td><td>Speed</td></tr>
</table>
Note. 0: off
1: on

<Speed/torque control change mode>
Used to select the control mode in the speed/torque control change mode.
<table>
<tr><th>(Note) LOP</th><th>Control mode</th></tr>
<tr><td>0</td><td>Speed</td></tr>
<tr><td>1</td><td>Torque</td></tr>
</table>
Note. 0: off
1: on

<Torque/position control mode>
Used to select the control mode in the torque/position control change mode.
<table>
<tr><th>(Note) LOP</th><th>Control mode</th></tr>
<tr><td>0</td><td>Torque</td></tr>
<tr><td>1</td><td>Position</td></tr>
</table>
Note. 0: off
1: on</td><td>DI-1</td><td colspan="3">Refer to Functions/ Applications.</td></tr>
<tr><td>Second acceleration/deceleration selection</td><td>STAB2</td><td></td><td>When using this signal, set the parameter No.PD03 to PD08/PD10 to PD12 to make it usable.
This signal allows selection of the acceleration/deceleration time constant at servo motor rotation in the speed control mode or torque control mode. The S-pattern acceleration/deceleration time constant is always uniform.
<table>
<tr><th>(Note) STAB2</th><th>Acceleration/deceleration time constant</th></tr>
<tr><td>0</td><td>Acceleration time constant
(parameter No.PC01)
Deceleration time constant
(parameter No.PC02)</td></tr>
<tr><td>1</td><td>Acceleration time constant 2
(parameter No.PC30)
Deceleration time constant 2
(parameter No.PC31)</td></tr>
</table>
Note. 0: off
1: on</td><td>DI-1</td><td></td><td>△</td><td>△</td></tr>
<tr><td>ABS transfer mode</td><td>ABSM</td><td>CN1-17</td><td>ABS transfer mode request device.
The CN1-17 pin acts as ABSM only during absolute position data transfer. (Refer to chapter 14.)</td><td>DI-1</td><td>○</td><td></td><td></td></tr>
<tr><td>ABS request</td><td>ABSR</td><td>CN1-18</td><td>ABS request device.
The CN1-18 pin acts as ABSR only during absolute position data transfer. (Refer to chapter 14.)</td><td>DI-1</td><td>○</td><td></td><td></td></tr>
</table>

(b) Output devices

Device	Symbol	Connector pin No.	Functions/Applications	I/O division	Control mode		
					P	S	T
Trouble	ALM	CN1-48	ALM turns off when power is switched off or the protective circuit is activated to shut off the base circuit. Without alarm occurring, ALM turns on within 1s after power-on.	DO-1	○	○	○
Dynamic brake interlock	DB		When using the signal, make it usable by the setting of parameter No.PD13 to PD16 and PD18. DB turns off when the dynamic brake needs to operate. When using the external dynamic brake on the servo amplifier of 11 kW or more, this device is required. (Refer to section 12.6) For the servo amplifier of 7kW or less, it is not necessary to use this device.	DO-1	○	○	○
Ready	RD	CN1-49	RD turns on when the servo is switched on and the servo amplifier is ready to operate.	DO-1	○	○	○
In-position	INP	CN1-24	INP turns on when the number of droop pulses is in the preset in-position range. The in-position range can be changed using parameter No.PA10. When the in-position range is increased, may be kept connected during low-speed rotation. INP turns on when servo on turns on.	DO-1	○		
Speed reached	SA		SA turns on when the servo motor speed has nearly reached the preset speed. When the preset speed is 20r/min or less, SA always turns on. SA does not turn on even when the servo on (SON) is turned off or the servo motor speed by the external force reaches the preset speed while both the forward rotation start (ST1) and the reverse rotation start (ST2) are off.	DO-1		○	
Limiting speed	VLC	CN1-25	VLC turns on when speed reaches the value limited using any of the internal speed limits 1 to 7 (parameter No.PC05 to PC11) or the analog speed limit (VLA) in the torque control mode. VLC turns off when servo on (SON) turns off.	DO-1			○
Limiting torque	TLC		TLC turns on when the torque generated reaches the value set to the Forward torque limit (parameter No.PA11), Reverse torque limit (parameter No.PA12) or analog torque limit (TLA).	DO-1	○	○	

Device	Symbol	Connector pin No.	Functions/Applications	I/O division	Control mode		
					P	S	T
Zero speed detection	ZSP	CN1-23	ZSP turns on when the servo motor speed is zero speed (50r/min) or less. Zero speed can be changed using parameter No.PC17. Example Zero speed is 50r/min  ZSP turns on 1) when the servo motor is decelerated to 50r/min, and ZSP turns off 2) when the servo motor is accelerated to 70r/min again. ZSP turns on 3) when the servo motor is decelerated again to 50r/min, and turns off 4) when the servo motor speed has reached -70r/min. The range from the point when the servo motor speed has reached ON level, and ZSP turns on, to the point when it is accelerated again and has reached OFF level is called hysteresis width. Hysteresis width is 20r/min for the MR-J3-A servo amplifier.	DO-1	○	○	○
Electromagnetic brake interlock	MBR		Set the parameter No.PD13 to PD16/PD18 or parameter No.PA04 to make this signal usable. Note that ZSP will be unusable. MBR turns off when the servo is switched off or an alarm occurs.	DO-1	△	△	△
Warning	WNG		To use this signal, assign the connector pin for output using parameter No.PD13 to PD16, PD18. The old signal before assignment will be unusable. When warning has occurred, WNG turns on. When there is no warning, WNG turns off within about 1.5s after power-on.	DO-1	△	△	△
Battery warning	BWNG		To use this signal, assign the connector pin for output using parameter No.PD13 to PD16, PD18. The old signal before assignment will be unusable. BWNG turns on when battery cable disconnection warning (AL. 92) or battery warning (AL. 9F) has occurred. When there is no battery warning, BWNG turns off within about 1.5s after power-on.	DO-1	△	△	△

<table>
<tr><th rowspan="2">Signal</th><th rowspan="2">Symbol</th><th rowspan="2">Connector pin No.</th><th rowspan="2">Functions/Applications</th><th rowspan="2">I/O division</th><th colspan="3">Control mode</th></tr>
<tr><th>P</th><th>S</th><th>T</th></tr>
<tr><td>Alarm code</td><td>ACD 0
ACD 1
ACD 2</td><td>CN1-24
CN1-23
CN1-22</td><td>To use this signal, set "□□□1" in parameter No.PD24.
This signal is output when an alarm occurs. When there is no alarm, respective ordinary signals (RD, INP, SA, ZSP) are output.
Alarm codes and alarm names are listed below.
<table>
<tr><th colspan="3">(Note) Alarm code</th><th rowspan="2">Alarm display</th><th rowspan="2">Name</th></tr>
<tr><th>CN1-22</th><th>CN1-23</th><th>CN1-24</th></tr>
<tr><td>0</td><td>0</td><td>0</td><td>88888</td><td>Watchdog</td></tr>
<tr><td></td><td></td><td></td><td>AL.12</td><td>Memory error 1</td></tr>
<tr><td></td><td></td><td></td><td>AL.13</td><td>Clock error</td></tr>
<tr><td></td><td></td><td></td><td>AL.15</td><td>Memory error 2</td></tr>
<tr><td></td><td></td><td></td><td>AL.17</td><td>Board error</td></tr>
<tr><td></td><td></td><td></td><td>AL.19</td><td>Memory error 3</td></tr>
<tr><td></td><td></td><td></td><td>AL.37</td><td>Parameter error</td></tr>
<tr><td></td><td></td><td></td><td>AL.8A</td><td>Serial communication time-out error</td></tr>
<tr><td></td><td></td><td></td><td>AL.8E</td><td>Serial communication error</td></tr>
<tr><td>0</td><td>0</td><td>1</td><td>AL.30</td><td>Regenerative error</td></tr>
<tr><td></td><td></td><td></td><td>AL.33</td><td>Overvoltage</td></tr>
<tr><td>0</td><td>1</td><td>0</td><td>AL.10</td><td>Undervoltage</td></tr>
<tr><td>0</td><td>1</td><td>1</td><td>AL.45</td><td>Main circuit device overheat</td></tr>
<tr><td></td><td></td><td></td><td>AL.46</td><td>Servo motor overheat</td></tr>
<tr><td></td><td></td><td></td><td>AL.47</td><td>Cooling fan alarm</td></tr>
<tr><td></td><td></td><td></td><td>AL.50</td><td>Overload 1</td></tr>
<tr><td></td><td></td><td></td><td>AL.51</td><td>Overload 2</td></tr>
<tr><td>1</td><td>0</td><td>0</td><td>AL.24</td><td>Main circuit error</td></tr>
<tr><td></td><td></td><td></td><td>AL.32</td><td>Overcurrent</td></tr>
<tr><td>1</td><td>0</td><td>1</td><td>AL.31</td><td>Overspeed</td></tr>
<tr><td></td><td></td><td></td><td>AL.35</td><td>Command pulse frequency alarm</td></tr>
<tr><td></td><td></td><td></td><td>AL.52</td><td>Error excessive</td></tr>
<tr><td>1</td><td>1</td><td>0</td><td>AL.16</td><td>Encoder error 1</td></tr>
<tr><td></td><td></td><td></td><td>AL.1A</td><td>Monitor combination error</td></tr>
<tr><td></td><td></td><td></td><td>AL.20</td><td>Encoder error 2</td></tr>
<tr><td></td><td></td><td></td><td>AL.25</td><td>Absolute position erase</td></tr>
</table>
Note. 0: off
1: on</td><td>DO-1</td><td>△</td><td>△</td><td>△</td></tr>
<tr><td>Variable gain selection</td><td>CDPS</td><td></td><td>CDPS is on during gain changing.</td><td>DO-1</td><td>△</td><td>△</td><td>△</td></tr>
<tr><td>Absolute position erasing</td><td>ABSV</td><td></td><td>ABSV turns on when the absolute position is erased.</td><td>DO-1</td><td>△</td><td></td><td></td></tr>
<tr><td>ABS transmission data bit 0</td><td>ABSB0</td><td>CN1-22</td><td>Outputs ABS transmission data bit 0. CN1-22 acts as ABSB0 only during ABS transmission data transmission. (Refer to chapter 14.)</td><td>DO-1</td><td>○</td><td></td><td></td></tr>
<tr><td>ABS transmission data bit 1</td><td>ABSB1</td><td>CN1-23</td><td>Outputs ABS transmission data bit 1. CN1-23 acts as ABSB1 only during ABS transmission data transmission. (Refer to chapter 14.)</td><td>DO-1</td><td>○</td><td></td><td></td></tr>
<tr><td>ABS transmission data ready</td><td>ABST</td><td>CN1-25</td><td>Outputs ABS transmission data ready. CN1-25 acts as ABST only during ABS transmission data transmission. (Refer to chapter 14.)</td><td>DO-1</td><td>○</td><td></td><td></td></tr>
</table>

(2) Input signals

Signal	Symbol	Connector pin No.	Functions/Applications	I/O division	Control mode		
					P	S	T
Analog torque limit	TLA	CN1-27	To use this signal in the speed control mode, set any of parameters No.PD13 to PD16, PD18 to make external torque limit selection (TL) available. When the analog torque limit (TLA) is valid, torque is limited in the full servo motor output torque range. Apply 0 to +10VDC across TLA-LG. Connect the positive terminal of the power supply to TLA. Maximum torque is generated at +10V. (Refer to section 3.6.1 (5).) Resolution:10bit	Analog input	○	△	
Analog torque command	TC		Used to control torque in the full servo motor output torque range. Apply 0 to ±8VDC across TC-LG. Maximum torque is generated at ±8V. (Refer to section 3.6.3 (1).) The torque at ±8V input can be changed using parameter No.PC13.	Analog input			○
Analog speed command	VC	CN1-2	Apply 0 to ±10VDC across VC-LG. Speed set in parameter No.PC12 is provided at ±10V. (Refer to section 3.6.2 (1).) Resolution:14bit or equivalent	Analog input		○	
Analog speed limit	VLA		Apply 0 to ±10VDC across VLA-LG. Speed set in parameter No.PC12 is provided at +10V. (Refer to section 3.6.3 (3).)	Analog input			○
Forward rotation pulse train Reverse rotation pulse train	PP NP PG NG	CN1-10 CN1-35 CN1-11 CN1-36	Used to enter a command pulse train. ・In the open collector system (max. input frequency 200kpps) Forward rotation pulse train across PP-DOCOM Reverse rotation pulse train across NP-DOCOM ・In the differential receiver system (max. input frequency 1Mpps) Forward rotation pulse train across PG-PP Reverse rotation pulse train across NG-NP The command pulse train form can be changed using parameter No. PA13.	DI-2	○		

(3) Output signals

Signal	Symbol	Connector pin No.	Functions/Applications	I/O division	Control mode		
					P	S	T
Encoder Z-phase pulse (Open collector)	OP	CN1-33	Outputs the zero-point signal of the encoder. One pulse is output per servo motor revolution. OP turns on when the zero-point position is reached. (Negative logic) The minimum pulse width is about 400μs. For home position return using this pulse, set the creep speed to 100r/min. or less.	DO-2	○	○	○
Encoder A-phase pulse (Differential line driver)	LA LAR	CN1-4 CN1-5	Outputs pulses per servo motor revolution set in parameter No.PA15 in the differential line driver system. In CCW rotation of the servo motor, the encoder B-phase pulse lags the encoder A-phase pulse by a phase angle of π/2. The relationships between rotation direction and phase difference of the A- and B-phase pulses can be changed using parameter No. PC19.	DO-2	○	○	○
Encoder B-phase pulse (Differential line driver)	LB LBR	CN1-6 CN1-7					
Encoder Z-phase pulse (Differential line driver)	LZ LZR	CN1-8 CN1-9	The same signal as OP is output in the differential line driver system.	DO-2	○	○	○
Analog monitor 1	MO1	CN6-3	Used to output the data set in parameter No.PC14 to across MO1-LG in terms of voltage. Resolution: 10 bits or equivalent	Analog output	○	○	○
Analog monitor 2	MO2	CN6-2	Used to output the data set in parameter No.PC15 to across MO2-LG in terms of voltage. Resolution: 10 bits or equivalent	Analog output	○	○	○

(4) Communication

POINT

- Refer to chapter 13 for the communication function.

Signal	Symbol	Connector pin No.	Functions/Applications	I/O division	Control mode		
					P	S	T
RS-422 I/F	SDP SDN RDP RDN	CN3-5 CN3-4 CN3-3 CN3-6	Terminals for RS-422 communication. (Refer to chapter 13.)		○	○	○

(5) Power supply

Signal	Symbol	Connector pin No.	Functions/Applications	I/O division	Control mode		
					P	S	T
Digital I/F power supply input	DICOM	CN1-20 CN1-21	Used to input 24VDC (24VDC 10% 300mA) for I/O interface of the servo amplifier. The power supply capacity changes depending on the number of I/O interface points to be used. For sink interface, connect ⊕ of 24VDC external power supply. For source interface, connect ⊖ of 24VDC external power supply.		○	○	○
Open collector power input	OPC	CN1-12	When inputting a pulse train in the open collector system, supply this terminal with the positive (+) power of 24VDC.		○		
Digital I/F common	DOCOM	CN1-46 CN1-47	Common terminal for input device such as SON and EMG of the servo amplifier. Pins are connected internally. For sink interface, connect ⊖ of 24VDC external power supply. For source interface, connect ⊕ of 24VDC external power supply.		○	○	○
15VDC power supply	P15R	CN1-1	Outputs 15VDC to across P15R-LG. Available as power for TC, TLA, VC, VLA. Permissible current: 30mA		○	○	○
Control common	LG	CN1-3 CN1-28 CN1-30 CN1-34 CN3-1 CN3-7 CN6-1	Common terminal for TLA, TC, VC, VLA, FPA, FPB, OP ,MO1, MO2 and P15R. Pins are connected internally.		○	○	○
Shield	SD	Plate	Connect the external conductor of the shield cable.		○	○	○

3.6 Detailed description of the signals

3.6.1 Position control mode

(1) Pulse train input

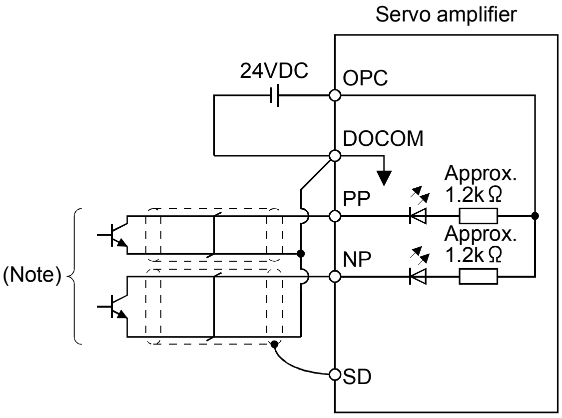
(a) Input pulse waveform selection

Command pulses may be input in any of three different forms, for which positive or negative logic can be chosen. Set the command pulse train form in parameter No.PA13. Refer to section 5.1.10 for details.

(b) Connections and waveforms

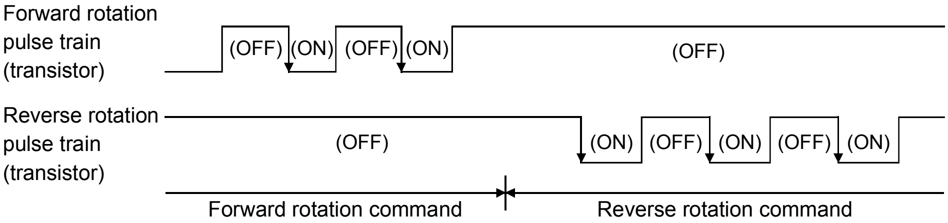
1) Open collector system

Connect as shown below.



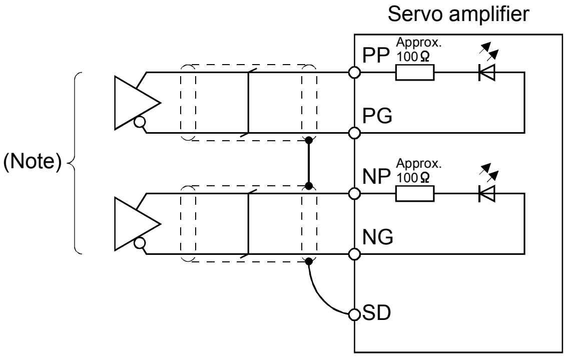
Note. Pulse train input interface is comprised of a photo coupler.
Therefore, it may be any malfunctions since the current is reduced when connect a resistance to a pulse train signal line.

The explanation assumes that the input waveform has been set to the negative logic and forward and reverse rotation pulse trains (parameter No.PA13 has been set to 0010). Their relationships with transistor ON/OFF are as follows.



2) Differential line driver system

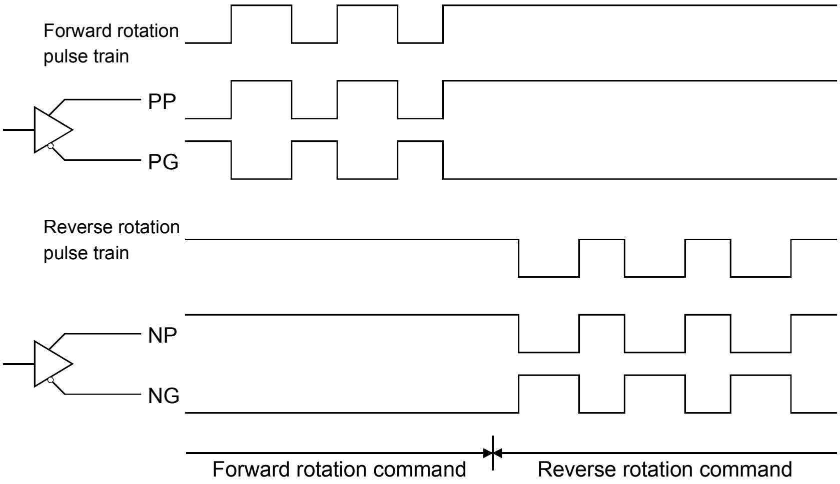
Connect as shown below.



Note. Pulse train input interface is comprised of a photo coupler.
Therefore, it may be any malfunctions since the current is reduced when connect a resistance to a pulse train signal line.

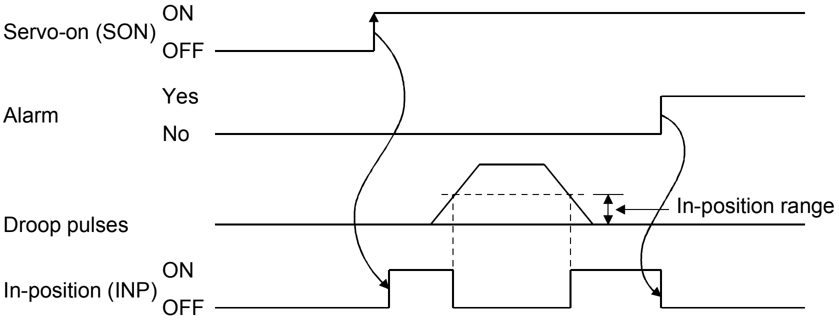
The explanation assumes that the input waveform has been set to the negative logic and forward and reverse rotation pulse trains (parameter No.PA13 has been set to 0010).

The waveforms of PP, PG, NP and NG are based on that of the ground of the differential line driver.

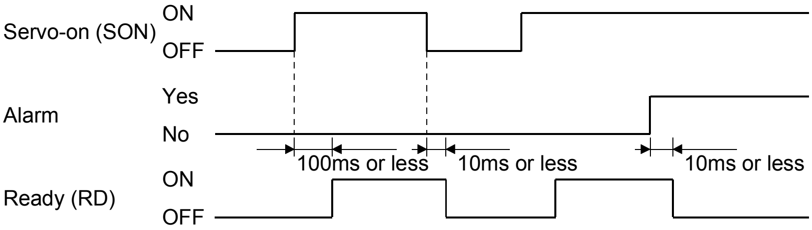


(2) In-position (INP)

INP turns on when the number of droop pulses in the deviation counter falls within the preset in-position range (parameter No.PA10). INP turns on when low-speed operation is performed with a large value set as the in-position range.



(3) Ready (RD)



(4) Electronic gear switching

The combination of CM1 and CM2 gives you a choice of four different electronic gear numerators set in the parameters.

As soon as CM1/CM2 is turned ON or OFF, the molecule of the electronic gear changes. Therefore, if any shock occurs at this change, use position smoothing (parameter No.PB03) to relieve shock.

(Note) Input device		Electronic gear molecule
CM2	CM1	
0	0	Parameter No.PA06
0	1	Parameter No.PC32
1	0	Parameter No.PC33
1	1	Parameter No.PC34

Note. 0: off
1: on

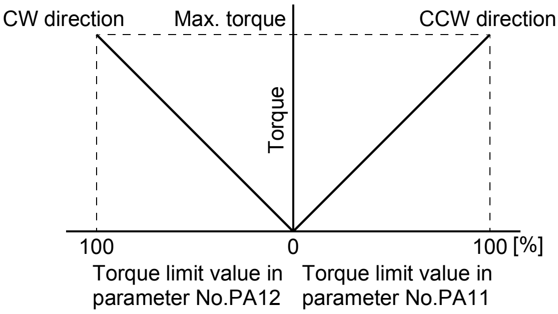
(5) Torque limit

⚠CAUTION

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

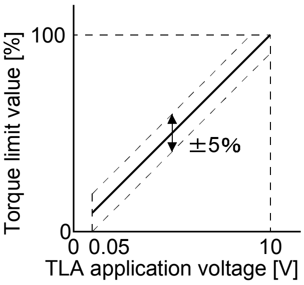
(a) Torque limit and torque

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

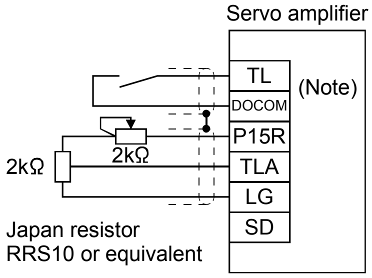


A relationship between the applied voltage of the analog torque limit (TLA) and the torque limit value of the servo motor is shown below. Torque limit values will vary about 5% relative to the voltage depending on products.

At the voltage of less than 0.05V, torque may vary as it may not be limited sufficiently. Therefore, use this function at the voltage of 0.05V or more.



TLA application voltage vs. torque limit value



Connection example

Note. For the sink I/O interface. For the source I/O interface, refer to section 3.8.3.

(b) Torque limit value selection

As shown below, the forward rotation torque limit (parameter No.PA11), or reverse rotation torque limit (parameter No. PA12) and the analog torque limit (TLA) can be chosen using the external torque limit selection (TL).

When internal torque limit selection (TL1) is made usable by parameter No.PD03 to PD08, PD10 to PD12, internal torque limit 2 (parameter No.PC35) can be selected. However, if the parameter No.PA11 and parameter No.PA12 value is less than the limit value selected by TL/TL1, the parameter No.PA11 and parameter No.PA12 value is made valid.

(Note) Input device		Limit value status			Validated torque limit values	
TL1	TL				CCW driving/CW regeneration	CW driving/CCW regeneration
0	0				Parameter No.PA11	Parameter No.PA12
0	1	TLA	>	Parameter No.PA11 Parameter No.PA12	Parameter No.PA11	Parameter No.PA12
		TLA	<	Parameter No.PA11 Parameter No.PA12	TLA	TLA
1	0	Parameter No.PC35	>	Parameter No.PA11 Parameter No.PA12	Parameter No.PA11	Parameter No.PA12
		Parameter No.PC35	<	Parameter No.PA11 Parameter No.PA12	Parameter No.PC35	Parameter No.PC35
1	1	TLA	>	Parameter No.PC35	Parameter No.PC35	Parameter No.PC35
		TLA	<	Parameter No.PC35	TLA	TLA

Note. 0: off
1: on

(c) Limiting torque (TLC)

TLC turns on when the servo motor torque reaches the torque limited using the forward rotation torque limit, reverse rotation torque limit or analog torque limit.

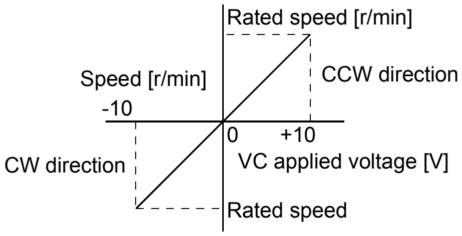
3.6.2 Speed control mode

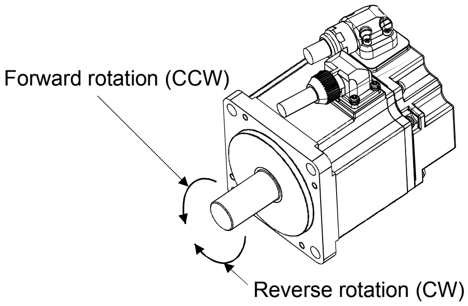
(1) Speed setting

(a) Speed command and speed

The servo motor is run at the speeds set in the parameters or at the speed set in the applied voltage of the analog speed command (VC). A relationship between the analog speed command (VC) applied voltage and the servo motor speed is shown below.

Rated speed is achieved at ±10V with initial setting. The speed at ±10V can be changed using parameter No.PC12.



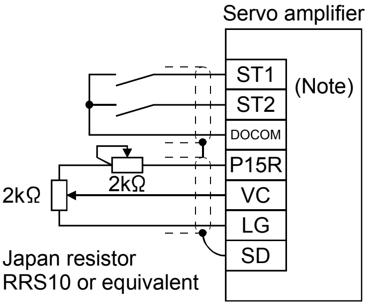


The following table indicates the rotation direction according to forward rotation start (ST1) and reverse rotation start (ST2) combination.

(Note 1) Input device		(Note 2) Rotation direction			
ST2	ST1	Analog speed command (VC)			Internal speed commands
		＋ Polarity	0V	－Polarity	
0	0	Stop (Servo lock)	Stop (Servo lock)	Stop (Servo lock)	Stop (Servo lock)
0	1	CCW	Stop (No servo lock)	CW	CCW
1	0	CW		CCW	CW
1	1	Stop (Servo lock)	Stop (Servo lock)	Stop (Servo lock)	Stop (Servo lock)

Note 1. 0: off
1: on
2. If the torque limit is canceled during servo lock, the servo motor may suddenly rotate according to position deviation in respect to the command position.

Generally, make connection as shown below.



Note. For the sink I/O interface. For the source I/O interface, refer to section 3.8.3.

(b) Speed selection 1 (SP1), speed selection 2 (SP2) and speed command value

Choose any of the speed settings made by the internal speed commands 1 to 3 using speed selection 1 (SP1) and speed selection 2 (SP2) or the speed setting made by the analog speed command (VC).

(Note) Input device		Speed command value
SP2	SP1	
0	0	Analog speed command (VC)
0	1	Internal speed command 1 (parameter No.PC05)
1	0	Internal speed command 2 (parameter No.PC06)
1	1	Internal speed command 3 (parameter No.PC07)

Note. 0: off
1: on

By making speed selection 3 (SP3) usable by setting of parameter No.PD03 to PD08/PD10 to PD12, you can choose the speed command values of analog speed command (VC) and internal speed commands 1 to 7.

(Note) Input device			Speed command value
SP3	SP2	SP1	
0	0	0	Analog speed command (VC)
0	0	1	Internal speed command 1 (parameter No.PC05)
0	1	0	Internal speed command 2 (parameter No.PC06)
0	1	1	Internal speed command 3 (parameter No.PC07)
1	0	0	Internal speed command 4 (parameter No.PC08)
1	0	1	Internal speed command 5 (parameter No.PC09)
1	1	0	Internal speed command 6 (parameter No.PC10)
1	1	1	Internal speed command 7 (parameter No.PC11)

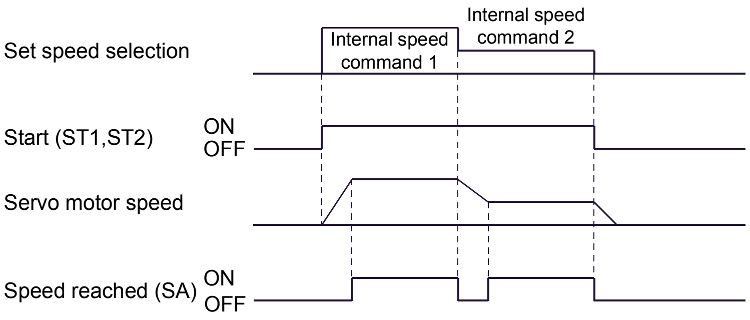
Note. 0: off
1: on

The speed may be changed during rotation. In this case, the values set in parameters No.PC01 and PC02 are used for acceleration/deceleration.

When the speed has been specified under any internal speed command, it does not vary due to the ambient temperature.

(2) Speed reached (SA)

SA turns on when the servo motor speed has nearly reached the speed set to the internal speed command or analog speed command.



(3) Torque limit

As in section 3.6.1 (5).

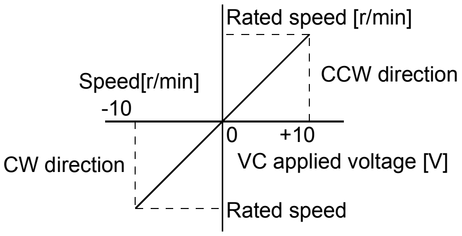
3.6.3 Torque control mode

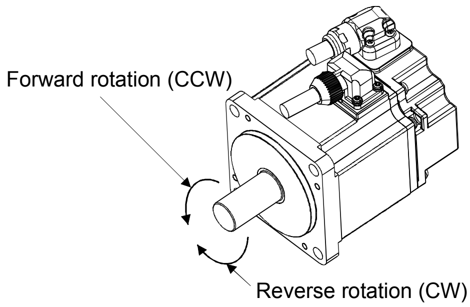
(1) Torque control

(a) Torque command and torque

A relationship between the applied voltage of the analog torque command (TC) and the torque by the servo motor is shown below.

The maximum torque is generated at ±8V. Note that the torque at ±8V input can be changed with parameter No.PC13.





Generated torque limit values will vary about 5% relative to the voltage depending on products.

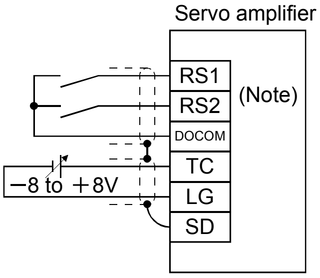
Also the torque may vary if the voltage is low (−0.05 to +0.05V) and the actual speed is close to the limit value. In such a case, increase the speed limit value.

The following table indicates the torque generation directions determined by the forward rotation selection (RS1) and reverse rotation selection (RS2) when the analog torque command (TC) is used.

(Note) Input device		Rotation direction		
RS2	RS1	Torque control command (TC)		
		+Polarity	0V	−Polarity
0	0	Torque is not generated.	Torque is not generated.	Torque is not generated.
0	1	CCW (reverse rotation in driving mode/forward rotation in regenerative mode)		CW (forward rotation in driving mode/reverse rotation in regenerative mode)
1	0	CW (forward rotation in driving mode/reverse rotation in regenerative mode)		CCW (reverse rotation in driving mode/forward rotation in regenerative mode)
1	1	Torque is not generated.		Torque is not generated.

Note. 0: off
1: on

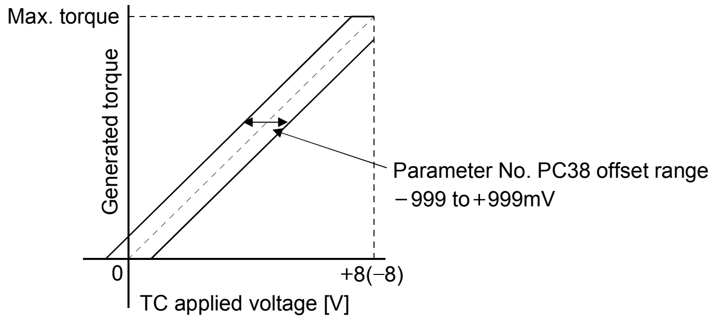
Generally, make connection as shown below.



Note. For the sink I/O interface. For the source I/O interface, refer to section 3.8.3.

(b) Analog torque command offset

Using parameter No.PC38, the offset voltage of −999 to ＋999mV can be added to the TC applied voltage as shown below.



(2) Torque limit

By setting parameter No.PA11 (forward rotation torque limit) or parameter No.PA12 (reverse rotation torque limit), torque is always limited to the maximum value during operation. A relationship between limit value and servo motor torque is as in section 3.6.1 (5). Note that the analog torque limit (TLA) is unavailable.

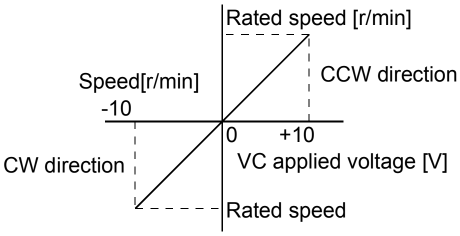
(3) Speed limit

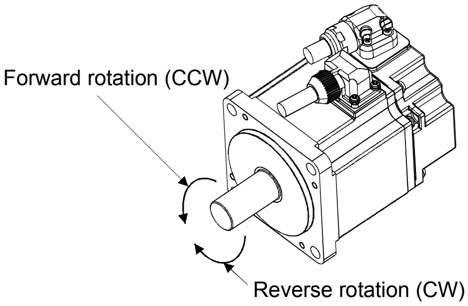
(a) Speed limit value and speed

The speed is limited to the values set in parameters No.PC05 to PC11 (internal speed limits 1 to 7) or the value set in the applied voltage of the analog speed limit (VLA).

A relationship between the analog speed limit (VLA) applied voltage and the servo motor speed is shown below.

When the servo motor speed reaches the speed limit value, torque control may become unstable. Make the set value more than 100r/min greater than the desired speed limit value.



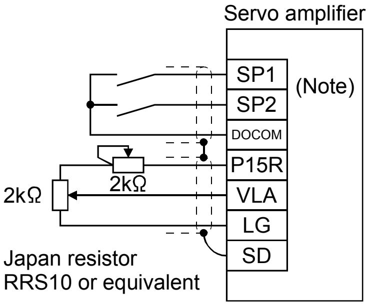


The following table indicates the limit direction according to forward rotation selection (RS1) and reverse rotation selection (RS2) combination.

(Note) Input device		Speed limit direction		
RS1	RS2	Analog speed limit (VLA)		Internal speed commands
		＋Polarity	－Polarity	
1	0	CCW	CW	CCW
0	1	CW	CCW	CW

Note. 0: off
1: on

Generally, make connection as shown below.



Note. For the sink I/O interface. For the source I/O interface, refer to section 3.8.3.

(b) Speed selection 1(SP1)/speed selection 2(SP2)/speed selection 3(SP3) and speed limit values

Choose any of the speed settings made by the internal speed limits 1 to 7 using speed selection 1(SP1), speed selection 2(SP2) and speed selection 3(SP3) or the speed setting made by the analog speed limit (VLA), as indicated below.

(Note) Input device			Speed limit value
SP3	SP2	SP1	
0	0	0	Analog speed limit (VLA)
0	0	1	Internal speed limit 1 (parameter No.PC05)
0	1	0	Internal speed limit 2 (parameter No.PC06)
0	1	1	Internal speed limit 3 (parameter No.PC07)
1	0	0	Internal speed limit 4 (parameter No.PC08)
1	0	1	Internal speed limit 5 (parameter No.PC09)
1	1	0	Internal speed limit 6 (parameter No.PC10)
1	1	1	Internal speed limit 7 (parameter No.PC11)

Note. 0: off
1: on

When the internal speed limits 1 to 7 are used to command the speed, the speed does not vary with the ambient temperature.

(c) Limiting speed (VLC)

VLC turns on when the servo motor speed reaches the speed limited using any of the internal speed limits 1 to 7 or the analog speed limit (VLA).

3.6.4 Position/speed control change mode

Set "□□□1" in parameter No.PA01 to switch to the position/speed control change mode. This function is not available in the absolute position detection system.

(1) Control change (LOP)

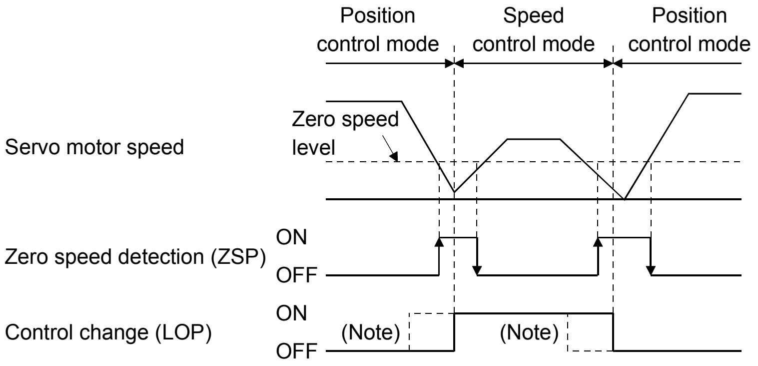
Use control change (LOP) to switch between the position control mode and the speed control mode from an external contact. Relationships between LOP and control modes are indicated below.

(Note) LOP	Servo control mode
0	Position control mode
1	Speed control mode

Note. 0: off
1: on

The control mode may be changed in the zero speed status. To ensure safety, change control after the servo motor has stopped. When position control mode is changed to speed control mode, droop pulses are reset.

If the LOP has been switched on-off at the speed higher than the zero speed and the speed is then reduced to the zero speed or less, the control mode cannot be changed. A change timing chart is shown below.



Note. When ZSP is not on, control cannot be changed if LOP is switched on-off.
If ZSP switches on after that, control cannot be changed.

(2) Torque limit in position control mode

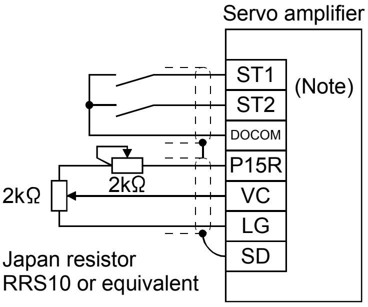
As in section 3.6.1 (5).

(3) Speed setting in speed control mode

(a) Speed command and speed

The servo motor is run at the speed set in parameter No.8 (internal speed command 1) or at the speed set in the applied voltage of the analog speed command (VC). A relationship between analog speed command (VC) applied voltage and servo motor speed and the rotation directions determined by the forward rotation start (ST1) and reverse rotation start (ST2) are as in (a), (1) in section 3.6.2.

Generally, make connection as shown below.



Note. For the sink I/O interface. For the source I/O interface, refer to section 3.8.3.

(b) Speed selection 1 (SP1), speed selection 2 (SP2) and speed command value

Choose any of the speed settings made by the internal speed commands 1 to 3 using speed selection 1 (SP1) and speed selection 2 (SP2) or the speed setting made by the analog speed command (VC).

(Note) Input device		Speed command value
SP2	SP1	
0	0	Analog speed command (VC)
0	1	Internal speed command 1 (parameter No.PC05)
1	0	Internal speed command 2 (parameter No.PC06)
1	1	Internal speed command 3 (parameter No.PC07)

Note. 0: off
1: on

By making speed selection 3 (SP3) usable by setting of parameter No.PD03 to PD08/PD10 to PD12, you can choose the speed command values of analog speed command (VC) and internal speed commands 1 to 7.

(Note) Input device			Speed command value
SP3	SP2	SP1	
0	0	0	Analog speed command (VC)
0	0	1	Internal speed command 1 (parameter No.PC05)
0	1	0	Internal speed command 2 (parameter No.PC06)
0	1	1	Internal speed command 3 (parameter No.PC07)
1	0	0	Internal speed command 4 (parameter No.PC08)
1	0	1	Internal speed command 5 (parameter No.PC09)
1	1	0	Internal speed command 6 (parameter No.PC10)
1	1	1	Internal speed command 7 (parameter No.PC11)

Note. 0: off
1: on

The speed may be changed during rotation. In this case, the values set in parameters No.PC01 and PC02 are used for acceleration/deceleration.
When the internal speed command 1 to 7 is used to command the speed, the speed does not vary with the ambient temperature.

(c) Speed reached (SA)
As in section 3.6.2 (2).

3.6.5 Speed/torque control change mode

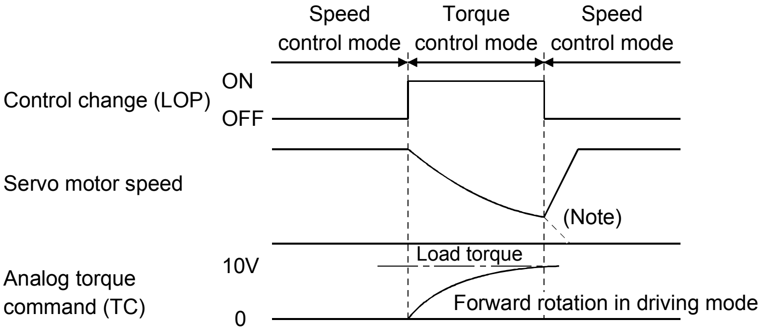
Set "□□□3" in parameter No.PA01 to switch to the speed/torque control change mode.

(1) Control change (LOP)
Use control change (LOP) to switch between the speed control mode and the torque control mode from an external contact. Relationships between LOP and control modes are indicated below.

(Note) LOP	Servo control mode
0	Speed control mode
1	Torque control mode

Note. 0: off
1: on

The control mode may be changed at any time. A change timing chart is shown below.



Note. When the start (ST1・ST2) is switched off as soon as the mode is changed to speed control, the servo motor comes to a stop according to the deceleration time constant.

(2) Speed setting in speed control mode
As in section 3.6.2 (1).

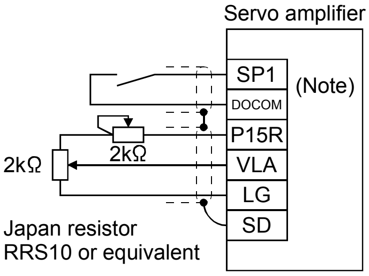
(3) Torque limit in speed control mode
As in section 3.6.1 (5).

(4) Speed limit in torque control mode

(a) Speed limit value and speed

The speed is limited to the limit value set in parameter No.8 (internal speed limit 1) or the value set in the applied voltage of the analog speed limit (VLA). A relationship between the analog speed limit (VLA) applied voltage and the servo motor speed is as in section 3.6.3 (3) (a).

Generally, make connection as shown below.



Note. For the sink I/O interface. For the source I/O interface, refer to section 3.8.3.

(b) Speed selection 1 (SP1) and speed limit value

Use speed selection 1 (SP1) to select between the speed set by the internal speed limit 1 and the speed set by the analog speed limit (VLA) as indicated in the following table.

(Note) Input device	Speed command value
SP1	
0	Analog speed limit (VLA)
1	Internal speed limit 1 (parameter No.PC05)

Note. 0: off

1: on

When the internal speed limit 1 is used to command the speed, the speed does not vary with the ambient temperature.

(c) Limiting speed (VLC)

As in section 3.6.3 (3) (c)

(5) Torque control in torque control mode

As in section 3.6.3 (1).

(6) Torque limit in torque control mode

As in section 3.6.3 (2).

3.6.6 Torque/position control change mode

Set "□□□5" in parameter No.PA01 to switch to the torque/position control change mode.

(1) Control change (LOP)

Use control change (LOP) to switch between the torque control mode and the position control mode from an external contact. Relationships between LOP and control modes are indicated below.

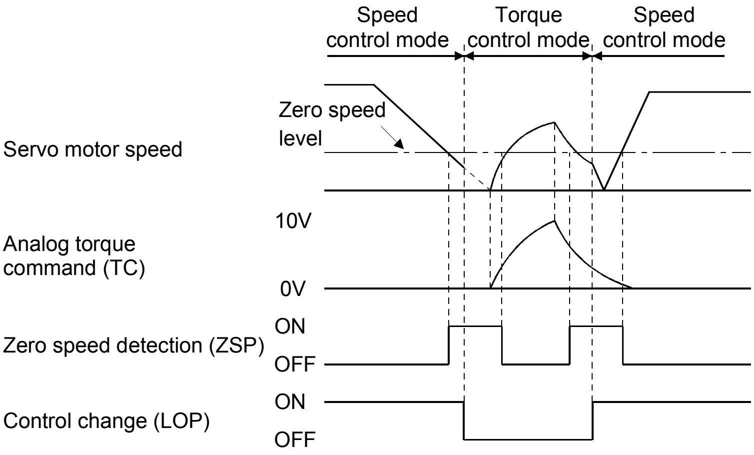
(Note) LOP	Servo control mode
0	Torque control mode
1	Position control mode

Note. 0: off
1: on

The control mode may be changed in the zero speed status.

To ensure safety, change control after the servo motor has stopped. When position control mode is changed to torque control mode, droop pulses are reset.

If the LOP has been switched on-off at the speed higher than the zero speed and the speed is then reduced to the zero speed or less, the control mode cannot be changed. A change timing chart is shown below.



(2) Speed limit in torque control mode

As in section 3.6.3 (3).

(3) Torque control in torque control mode

As in section 3.6.3 (1).

(4) Torque limit in torque control mode

As in section 3.6.3 (2).

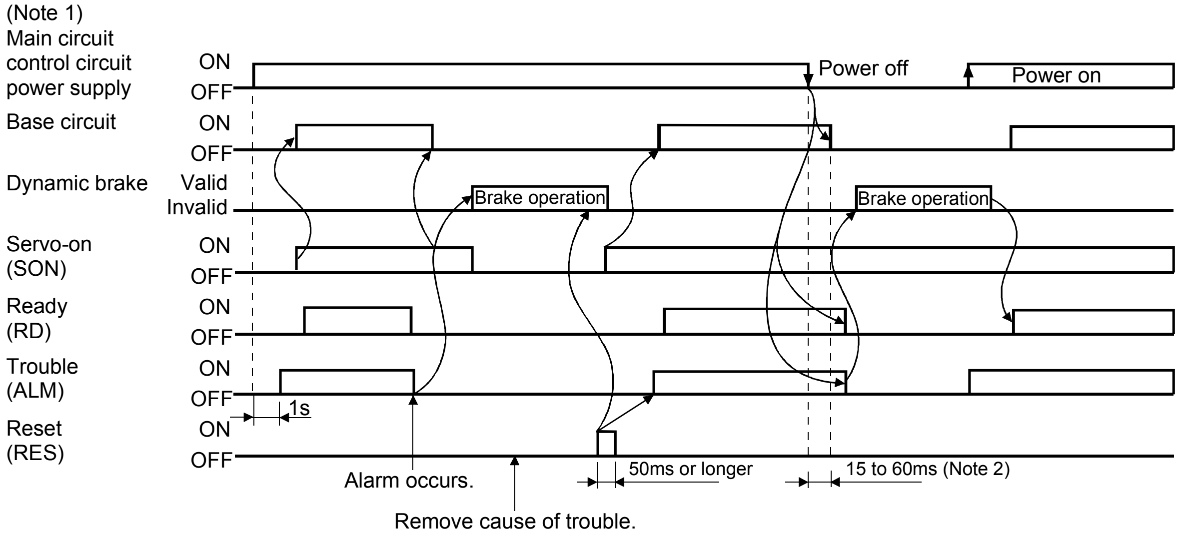
(5) Torque limit in position control mode

As in section 3.6.1 (5).

3.7 Alarm occurrence timing chart

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

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



Note 1. Shut off the main circuit power as soon as an alarm occurs.
2. Changes depending on the operating status.

(1) Overcurrent, overload 1 or overload 2

If operation is repeated by switching control circuit power off, then on to reset the overcurrent (AL.32), overload 1 (AL.50) or overload 2 (AL.51) alarm after its occurrence, without removing its cause, the servo amplifier and servo motor may become faulty due to temperature rise. Securely remove the cause of the alarm and also allow about 30 minutes for cooling before resuming operation.

(2) Regenerative alarm

If operation is repeated by switching control circuit power off, then on to reset the regenerative (AL.30) alarm after its occurrence, the external regenerative resistor will generate heat, resulting in an accident.

(3) Instantaneous power failure

Undervoltage (AL.10) occurs when the input power is in either of the following statuses.

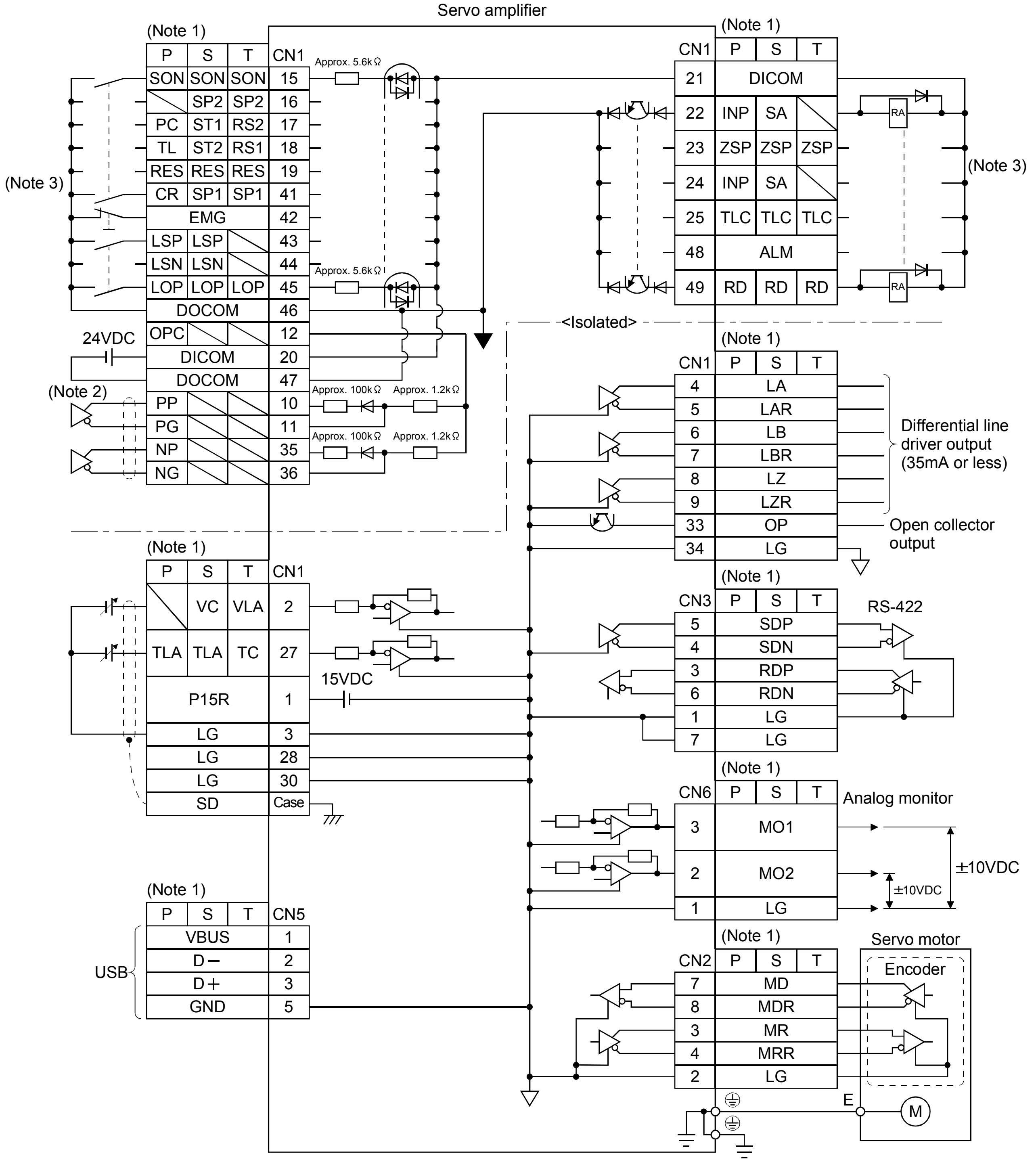
- A power failure of the control circuit power supply continues for 60ms or longer, then the power restores.
- During the servo-on status, the bus voltage dropped to 200VDC or less for MR-J3-□A, 158VDC or less for MR-J3-□A1, or 380VDC or less for MR-J3-□A4.

(4) In position control mode (incremental)

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

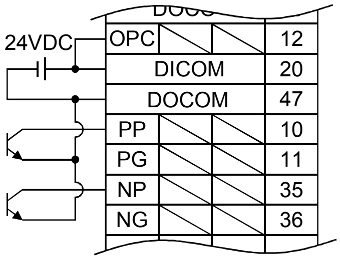
3.8 Interfaces

3.8.1 Internal connection diagram



Note 1. P: Position control mode S: Speed control mode T: Torque control mode

2. For the differential line driver pulse train input. For the open collector pulse train input, make the following connection.



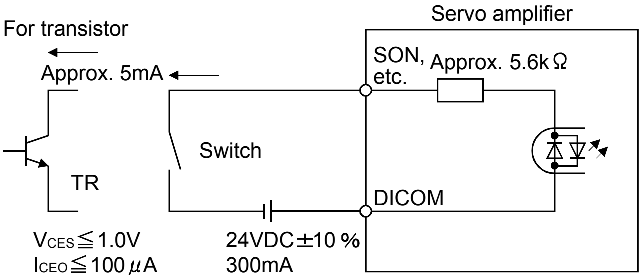
3. For the sink I/O interface. For the source I/O interface, refer to section 3.8.3.

3.8.2 Detailed description of interfaces

This section provides the details of the I/O signal interfaces (refer to the I/O division in the table) given in section 3.5. Refer to this section and make connection with the external equipment.

(1) Digital input interface DI-1

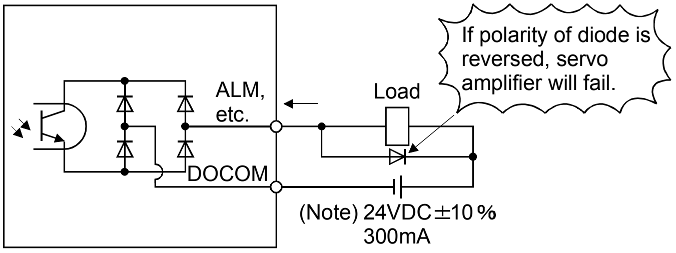
Give a signal with a relay or open collector transistor. Refer to section 3.8.3 for source input.



(2) Digital output interface DO-1

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

Refer to section 3.8.3 for the source output.



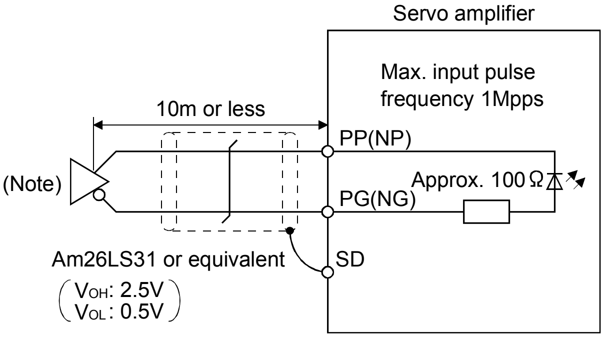
Note. If the voltage drop (maximum of 2.6V) interferes with the relay operation, apply high voltage (up to 26.4V) from external source.

(3) Pulse train input interface DI-2

Give a pulse train signal in the differential line driver system or open collector system.

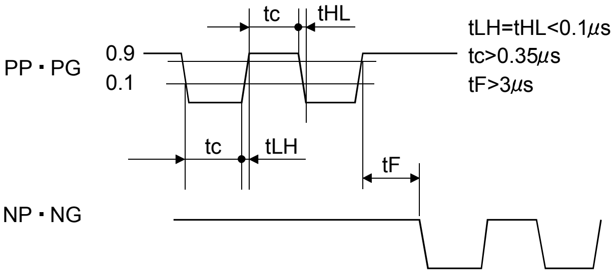
(a) Differential line driver system

1) Interface



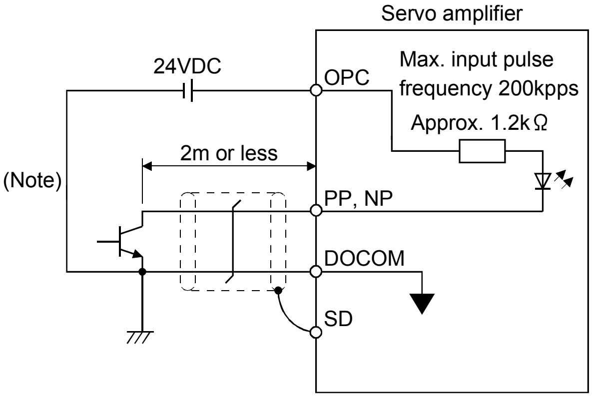
Note. Pulse train input interface is comprised of a photo coupler.
Therefore, it may be any malfunctions since the current is reduced when connect a resistance to a pulse train signal line.

2) Input pulse condition



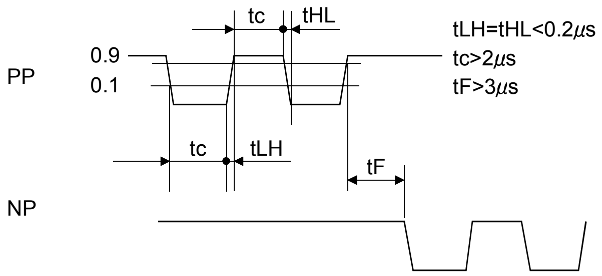
(b) Open collector system

1) Interface



Note. Pulse train input interface is comprised of a photo coupler.
Therefore, it may be any malfunctions since the current is reduced when connect a resistance to a pulse train signal line.

2) Input pulse condition

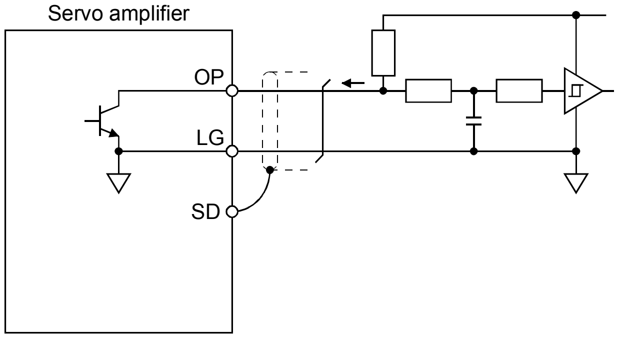


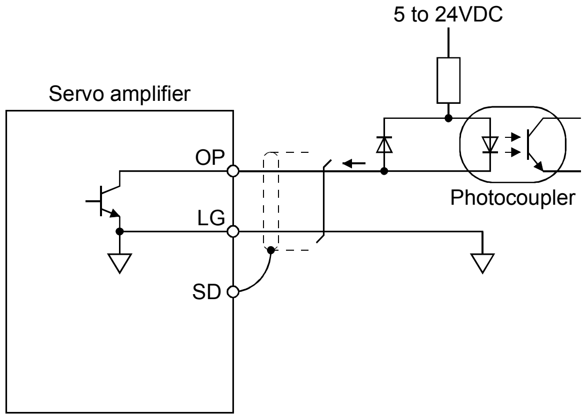
(4) Encoder output pulse DO-2

(a) Open collector system

Interface

Max. output current: 35mA

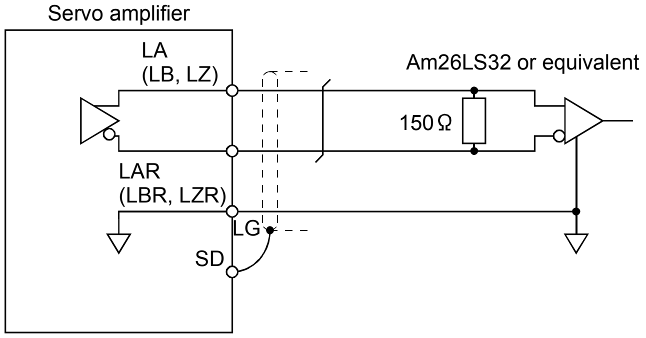


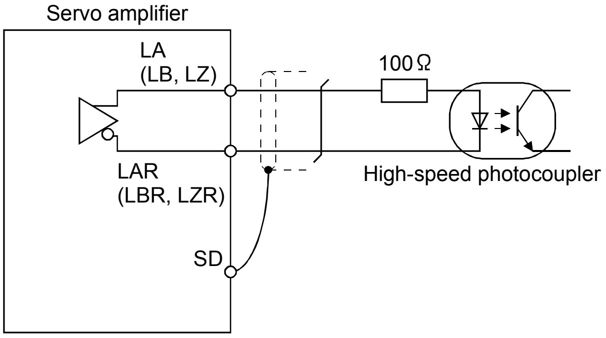


(b) Differential line driver system

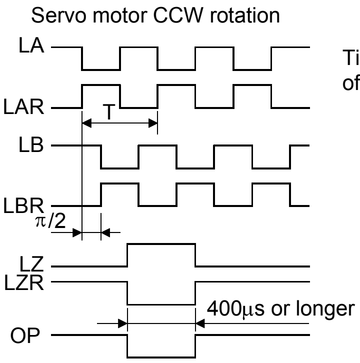
1) Interface

Max. output current: 35mA





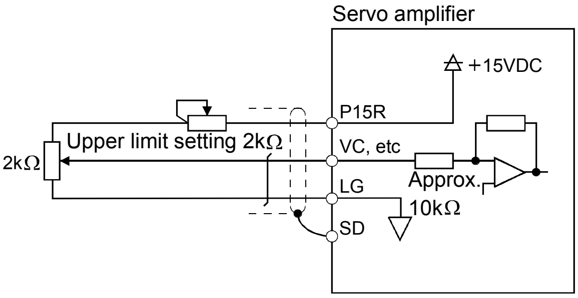
2) Output pulse



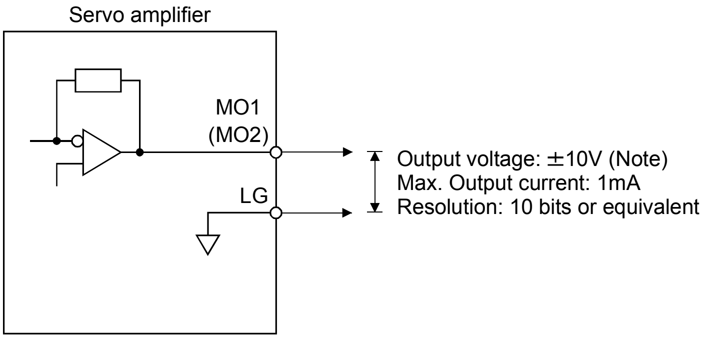
Time cycle (T) is determined by the settings of parameter No.PA15 and PC19.

(5) Analog input

Input impedance 10 to 12kΩ



(6) Analog output

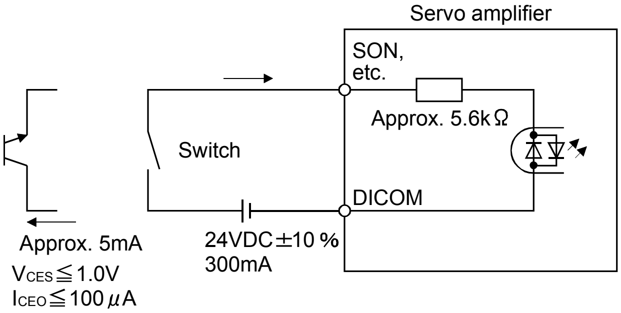


Note. Output voltage range varies depending on the monitored signal. (Refer to section 5.3.3.)
When connecting an analog output to an external device, use one whose withstand voltage is ±15VDC or more.

3.8.3 Source I/O interfaces

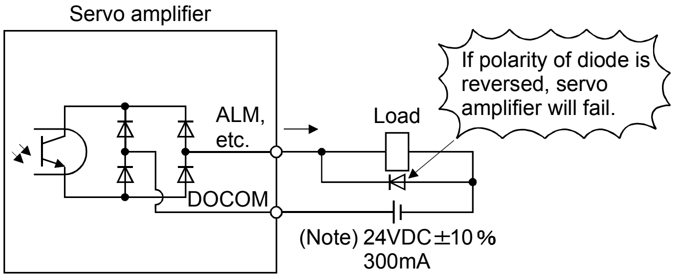
In this servo amplifier, source type I/O interfaces can be used. In this case, all DI-1 input signals and DO-1 output signals are of source type. Perform wiring according to the following interfaces.

(1) Digital input interface DI-1



(2) Digital output interface DO-1

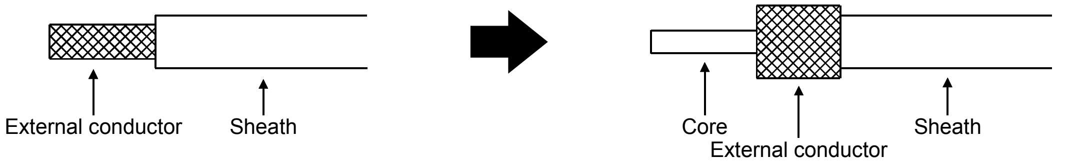
A maximum of 2.6V voltage drop occurs in the servo amplifier.



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

3.9 Treatment of cable shield external conductor

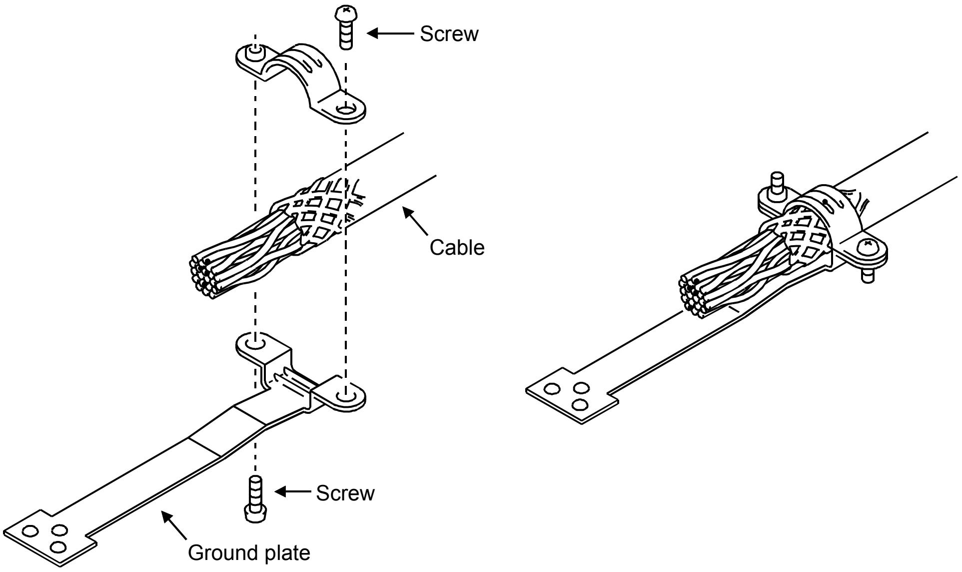
In the case of the CN1 and CN2 connectors, securely connect the shielded external conductor of the cable to the ground plate as shown in this section and fix it to the connector shell.



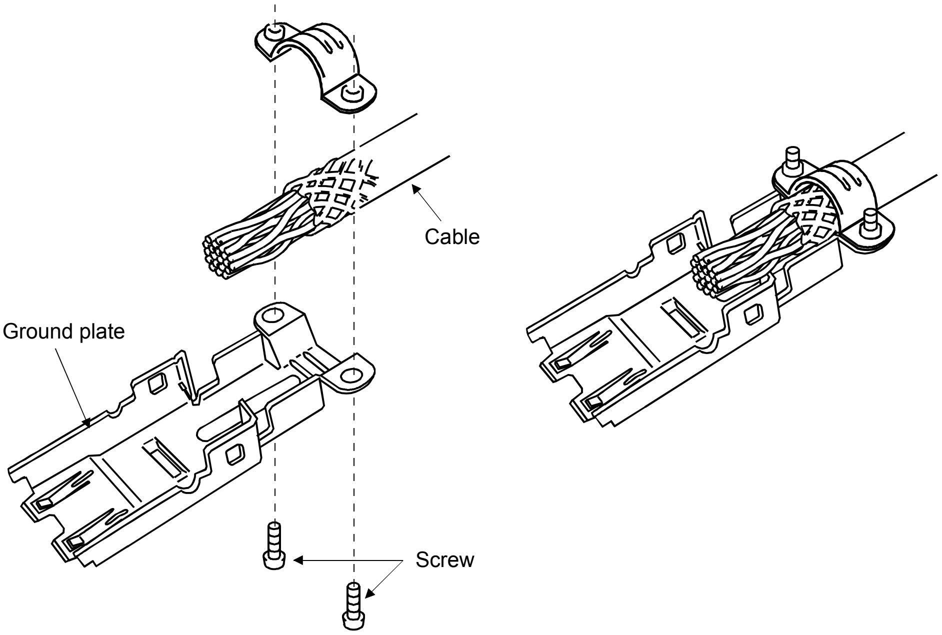
Strip the sheath.

Pull back the external conductor to cover the sheath.

(1) For CN1 connector (3M connector)



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



3.10 Connection of servo amplifier and servo motor

⚠WARNING	・During power-on, do not open or close the motor power line. Otherwise, a malfunction or faulty may occur.

3.10.1 Connection instructions

⚠WARNING	・Insulate the connections of the power supply terminals to prevent an electric shock.

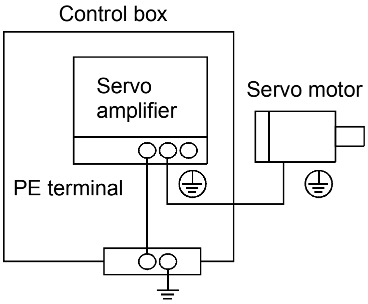
⚠CAUTION	・Connect the wires to the correct phase terminals (U, V, W) of the servo amplifier and servo motor. Not doing so may cause unexpected operation. ・Do not connect AC power supply directly to the servo motor. Otherwise, a fault may occur. ・Do not use the 24VDC interface power supply for the electromagnetic brake. Always use the power supply designed exclusively for the electromagnetic brake. Otherwise, a fault may occur.

POINT

- Refer to section 12.1 for the selection of the encoder cable.
- Refer to the Servo Motor Instruction Manual (Vol.2) for the selection of a surge absorber for the electromagnetic brake.

This section indicates the connection of the motor power supply (U, V, W). Use of the optional cable or connector set is recommended for connection between the servo amplifier and servo motor. Refer to section 12.1 for details of the options.

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

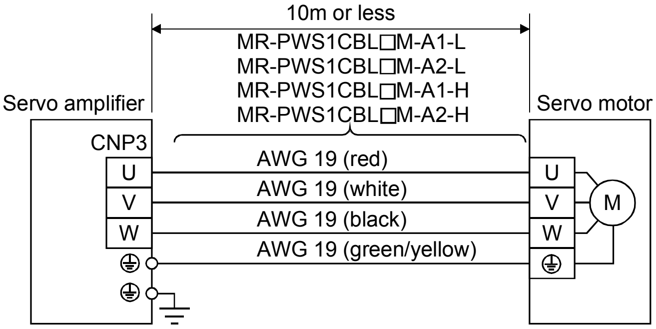


(2) Do not use the 24VDC interface power supply for the electromagnetic brake. Always use the power supply designed exclusively for the electromagnetic brake.

3.10.2 Power supply cable wiring diagrams

(1) HF-MP series · HF-KP series servo motor

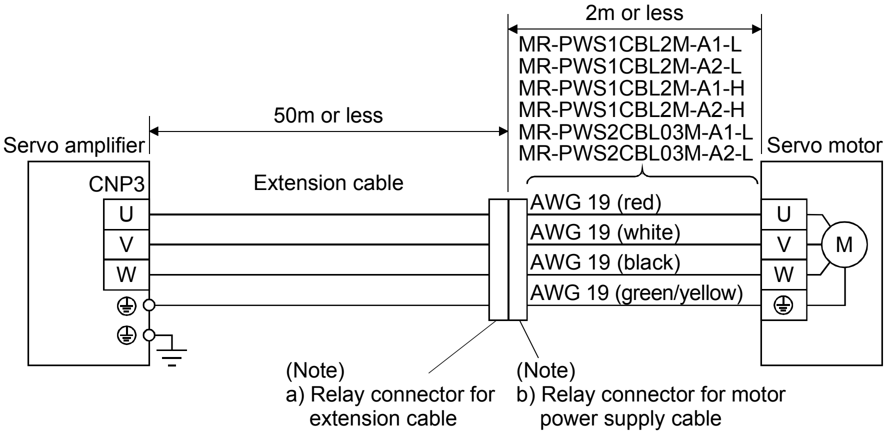
(a) When cable length is 10m or less



(b) When cable length exceeds 10m

When the cable length exceeds 10m, fabricate an extension cable as shown below. In this case, the motor power supply cable should be within 2m long.

Refer to section 12.11 for the wire used for the extension cable.



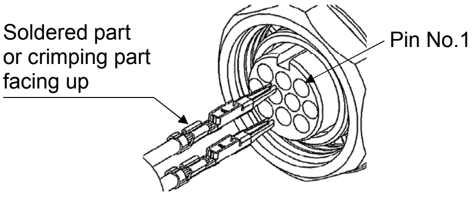
Note. Use of the following connectors is recommended when ingress protection (IP65) is necessary.

Relay connector	Description	IP rating
a) Relay connector for extension cable	Connector: RM15WTPZ-4P(71) Cord clamp: JR13WCC-5(72) (Hirose Electric) └ Numeral changes depending on the cable OD.	IP65
b) Relay connector for motor power supply cable	Connector: RM15WTJZ-4S(71) Cord clamp: JR13WCC-8(72) (Hirose Electric) └ Numeral changes depending on the cable OD.	IP65

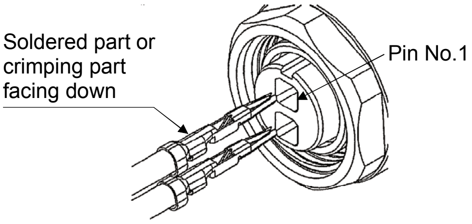
(2) HF-SP series · HC-RP series · HC-UP series · HC-LP series · HA-LP502 · HA-LP702 · HF-JP series servo motor

POINT

- Insert a contact in the direction shown in the figure. If inserted in the incorrect direction, the contact is damaged and falls off.



Model: CM10-SP10S-□(D6)
CM10-SP10S-VP-M
CM10-AP10S-□(D6)
CM10-AP10S-VP-M

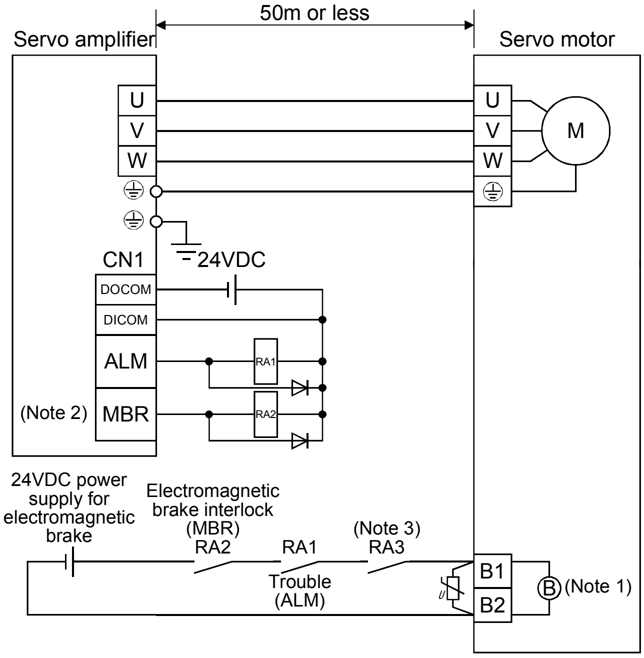


Model: CM10-SP2S-□(D6)
CM10-SP2S-VP-□
CM10-AP2S-□(D6)
CM10-AP2S-VP-□

(a) Wiring diagrams

Refer to section 12.11 for the cables used for wiring.

1) When the power supply connector and the electromagnetic brake connector are separately supplied.

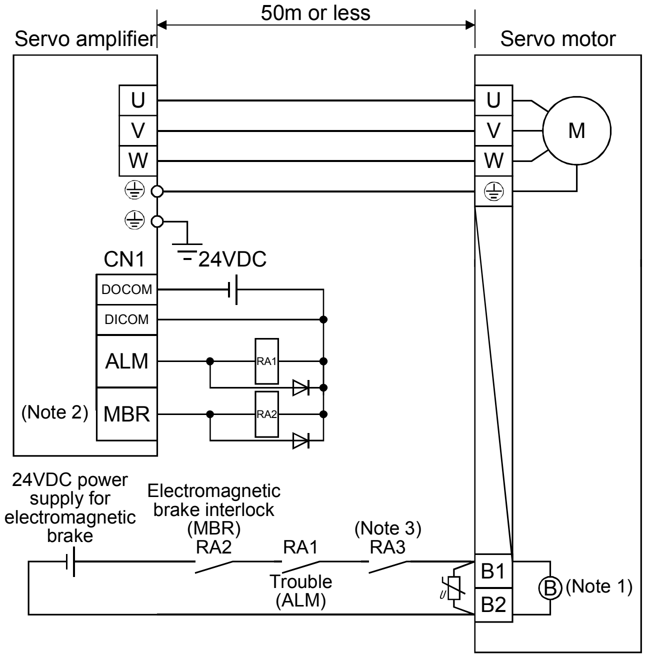


Note 1. There is no polarity in electromagnetic brake terminals B1 and B2.

2. When using a servo motor with an electromagnetic brake, assign the electromagnetic brake interlock (MBR) to external output signal in the parameters No.PA04, PD13 to PD16 and PD18.

3. Shut off the circuit by interlocking with the emergency stop switch.

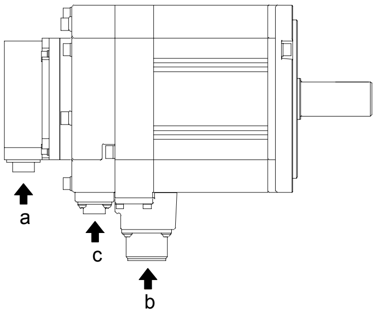
2) When the power supply connector and the electromagnetic brake connector are shared.



Note 1. There is no polarity in electromagnetic brake terminals B1 and B2.
2. When using a servo motor with an electromagnetic brake, assign the electromagnetic brake interlock (MBR) to external output signal in the parameters No.PA04, PD13 to PD16 and PD18.
3. Shut off the circuit by interlocking with the emergency stop switch.

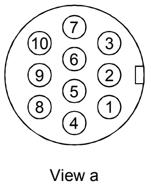
(b) Connector and signal allotment

The connector fitting the servo motor is prepared as optional equipment. Refer to section 12.1. For types other than those prepared as optional equipment, refer to chapter 3 in Servo Motor Instruction Manual (Vol. 2) to select.



Servo motor	Servo motor side connectors		
	Encoder	Power supply	Electromagnetic brake
HF-SP52(4) to 152(4)	CM10-R10P (DDK)	MS3102A18-10P	CM10-R2P (DDK)
HF-SP51 ・ 81			
HF-SP202(4) to 502(4)		MS3102A22-22P	
HF-SP121 to 301			
HF-SP421 ・ 702(4)		CE05-2A32-17PD-B	
HC-RP103 to 203		CE05-2A22-23PD-B	The connector for power is shared
HC-RP353 ・ 503		CE05-2A24-10PD-B	
HC-UP72 ・ 152		CE05-2A22-23PD-B	
HC-UP202 to 502		CE05-2A24-10PD-B	MS3102A10SL-4P
HC-LP52 to 152		CE05-2A22-23PD-B	The connector for power is shared
HC-LP202 ・ 302		CE05-2A24-10PD-B	MS3102A10SL-4P
HA-LP502		CE05-2A24-10PD-B	
HA-LP702		CE05-2A32-17PD-B	
HF-JP53(4) to 203(4) ・ 3534 ・ 5034		MS3102A18-10P	CM10-R2P (DDK)
HF-JP353 ・ 503		MS3102A22-22P	
HF-JP11K1M (4) ・ 15K1M (4)	MS3102A20-29P	MS3102A32-17P	MS3101A10SL-4P

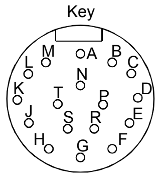
Encoder connector signal allotment
CM10-R10P



View a

Terminal No.	Signal
1	MR
2	MRR
3	
4	BAT
5	LG
6	
7	
8	P5
9	
10	SHD

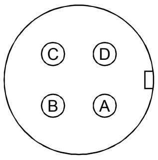
Encoder connector signal allotment
MS3102A20-29P



View a

Pin	Signal
A	MD
B	MDR
C	MR
D	MRR
E	
F	BAT
G	
H	
J	
K	
L	
M	CONT
N	SHD
P	
R	LG
S	P5
T	

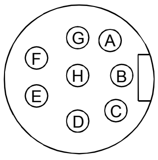
Power supply connector signal allotment
MS3102A18-10P
MS3102A22-22P
MS3102A32-17P
CE05-2A32-17PD-B



View b

Terminal No.	Signal
A	U
B	V
C	W
D	⏚ (earth)

Power supply connector signal allotment
CE05-2A22-23PD-B

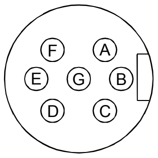


View b

Terminal No.	Signal
A	U
B	V
C	W
D	⏚ (earth)
E	
F	
G	B1 (Note)
H	B2 (Note)

Note. For the motor with an electromagnetic brake, supply electromagnetic brake power (24VDC). There is no polarity.

Power supply connector signal allotment
CE05-2A24-10PD-B

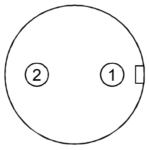


View b

Terminal No.	Signal
A	U
B	V
C	W
D	⏚ (earth)
E	B1 (Note)
F	B2 (Note)
G	

Note. For the motor with an electromagnetic brake, supply electromagnetic brake power (24VDC). There is no polarity.

Brake connector signal allotment
CM10-R2P

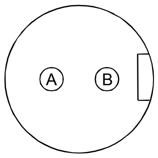


View c

Terminal No.	Signal
1	B1 (Note)
2	B2 (Note)

Note. For the motor with an electromagnetic brake, supply electromagnetic brake power (24VDC). There is no polarity.

Brake connector signal allotment
MS3102A10SL-4P



View c

Terminal No.	Signal
A	B1 (Note)
B	B2 (Note)

Note. For the motor with an electromagnetic brake, supply electromagnetic brake power (24VDC). There is no polarity.

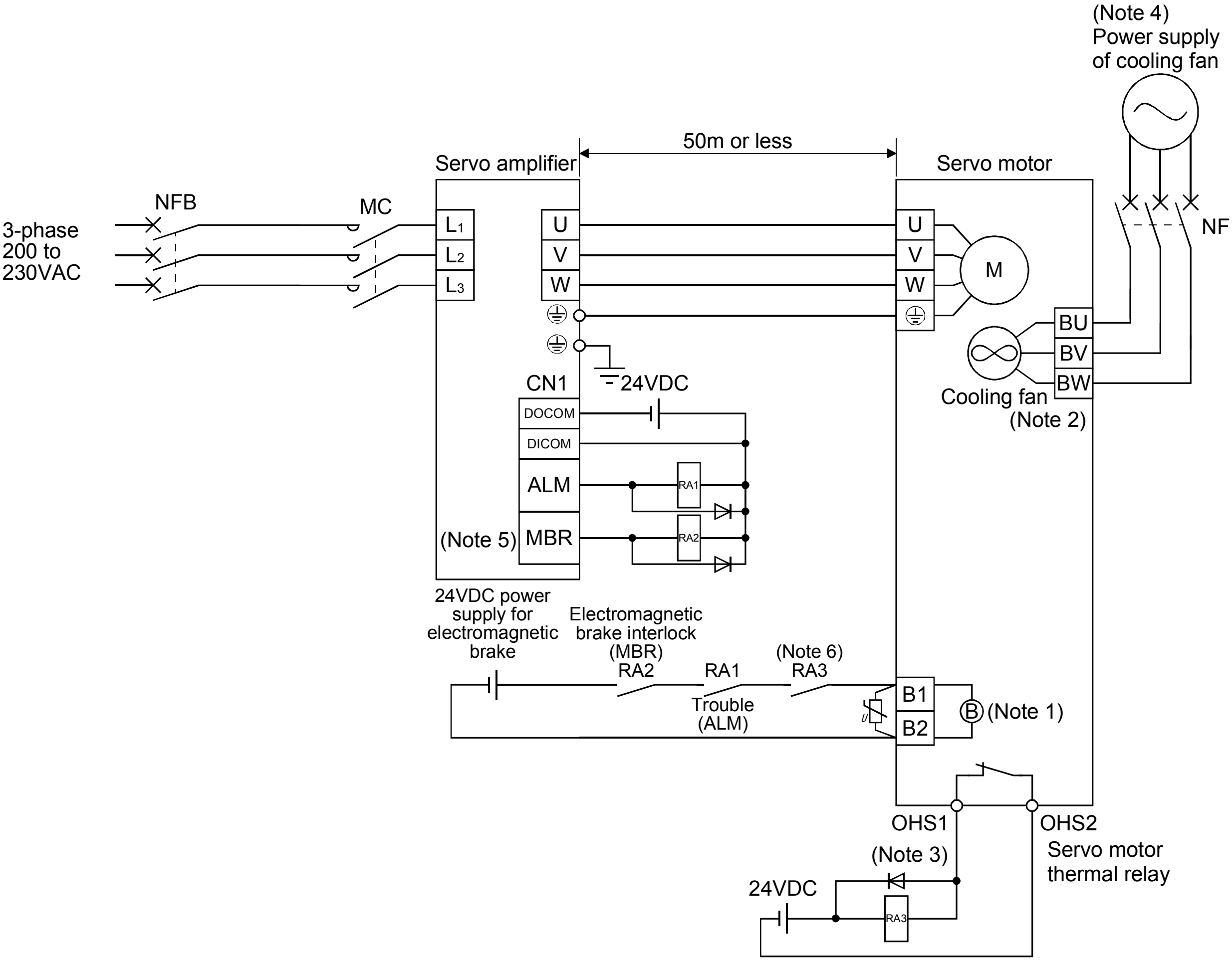
(3) HA-LP series servo motor

POINT
▪ Refer to (2) in this section for HA-LP502, 702.

(a) Wiring diagrams

Refer to section 12.11 for the cables used for wiring.

1) 200V class



Note 1. There is no polarity in electromagnetic brake terminals B1 and B2.

2. When the power supply for the cooling fan is 1-phase, BW does not exist.

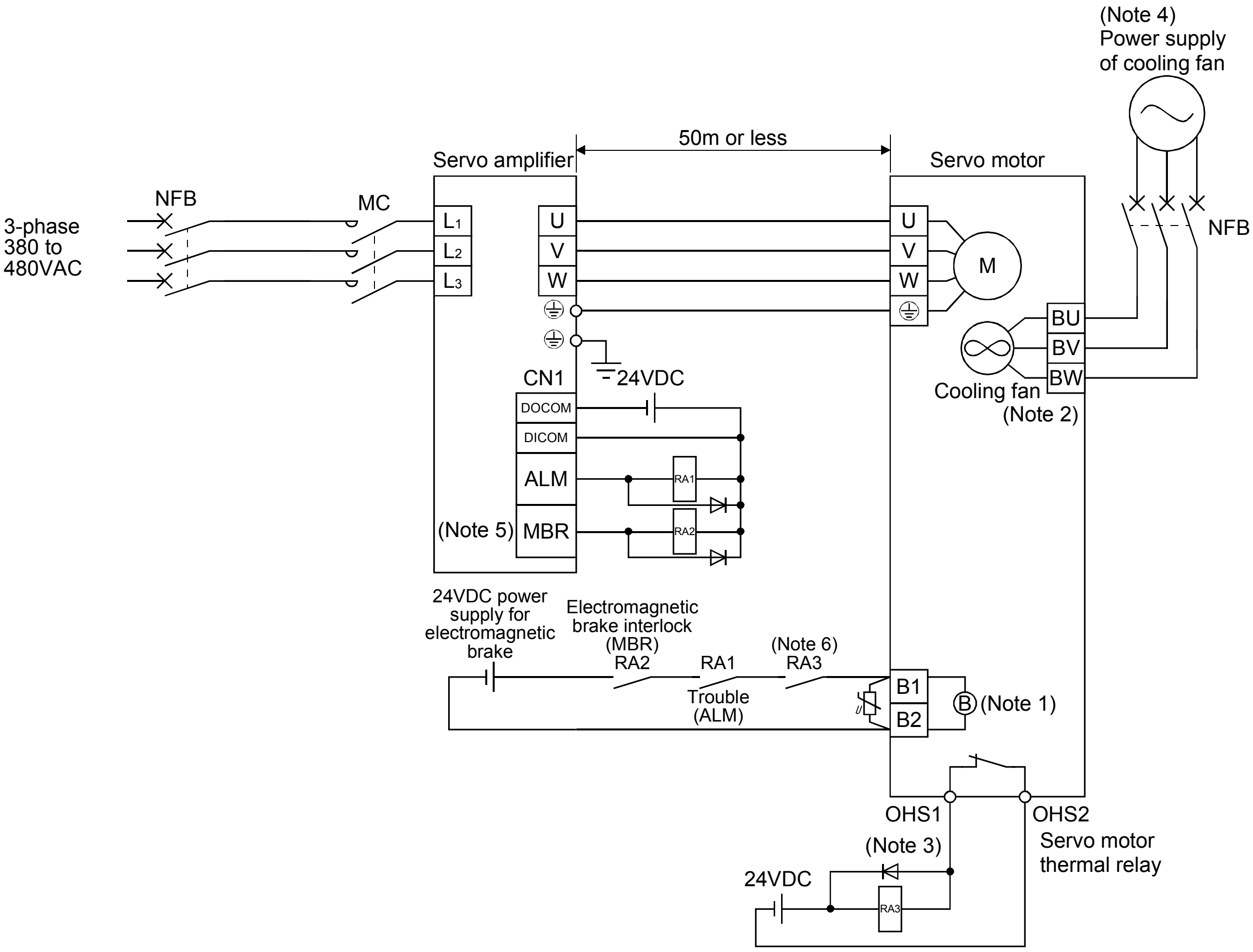
3. Configure the power supply circuit which turns off the magnetic contactor after detection of servo motor thermal.

4. For the cooling fan power supply, refer to section 3.10.2 (3) (b).

5. When using a servo motor with an electromagnetic brake, assign the electromagnetic brake interlock (MBR) to external output signal in the parameters No.PA04, PD13 to PD16 and PD18.

6. Shut off the circuit by interlocking with the emergency stop switch.

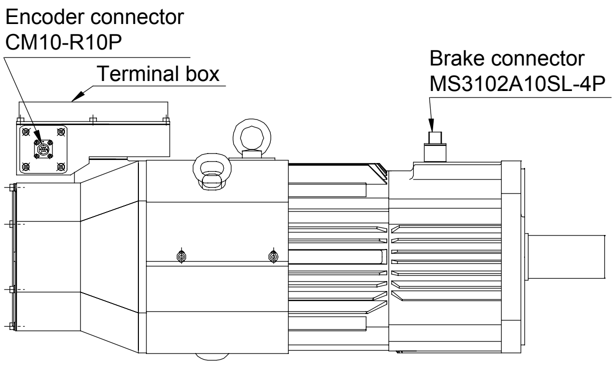
2) 400V class



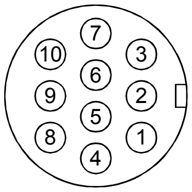
Note 1. There is no polarity in electromagnetic brake terminals B1 and B2.

2. There is no BW when the power supply of the cooling fan is a 1-phase.
3. Configure the power supply circuit which turns off the magnetic contactor after detection of servo motor thermal.
4. For the cooling fan power supply, refer to (3) (b) of this section.
5. When using a servo motor with an electromagnetic brake, assign the electromagnetic brake interlock (MBR) to external output signal in the parameters No.PA04, PD13 to PD16 and PD18.
6. Shut off the circuit by interlocking with the emergency stop switch.

(b) Servo motor terminals

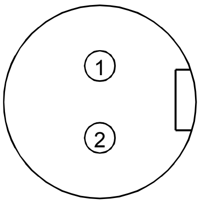


Encoder connector signal allotment
CM10-R10P



Terminal No.	Signal
1	MR
2	MRR
3	
4	BAT
5	LG
6	
7	
8	P5
9	
10	SHD

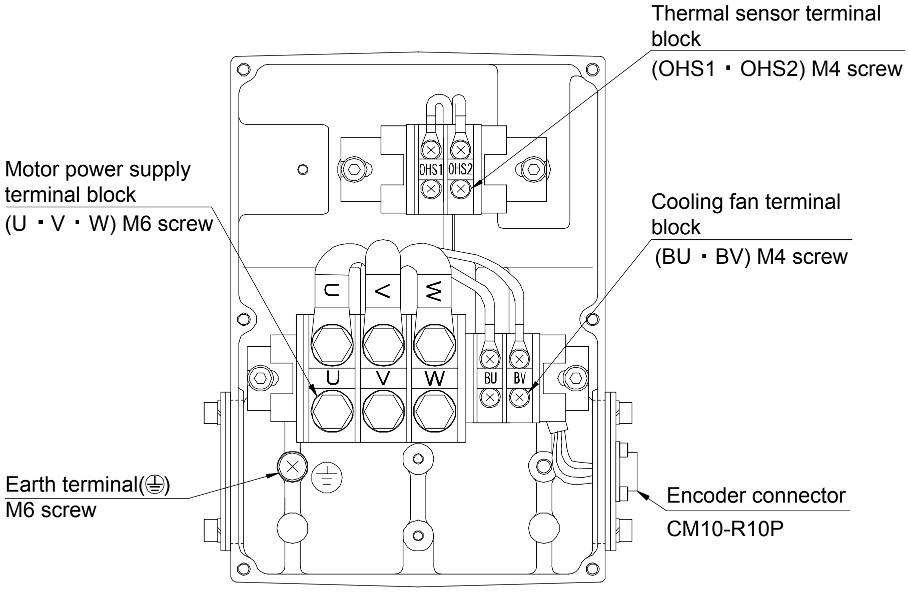
Brake connector signal allotment
MS3102A10SL-4P



Terminal No.	Signal
1	B1 (Note)
2	B2 (Note)

Note. For the motor with an electromagnetic brake, supply electromagnetic brake power (24VDC). There is no polarity.

Terminal box inside (HA-LP601(4) ・ 701M(4) ・ 11K2(4))

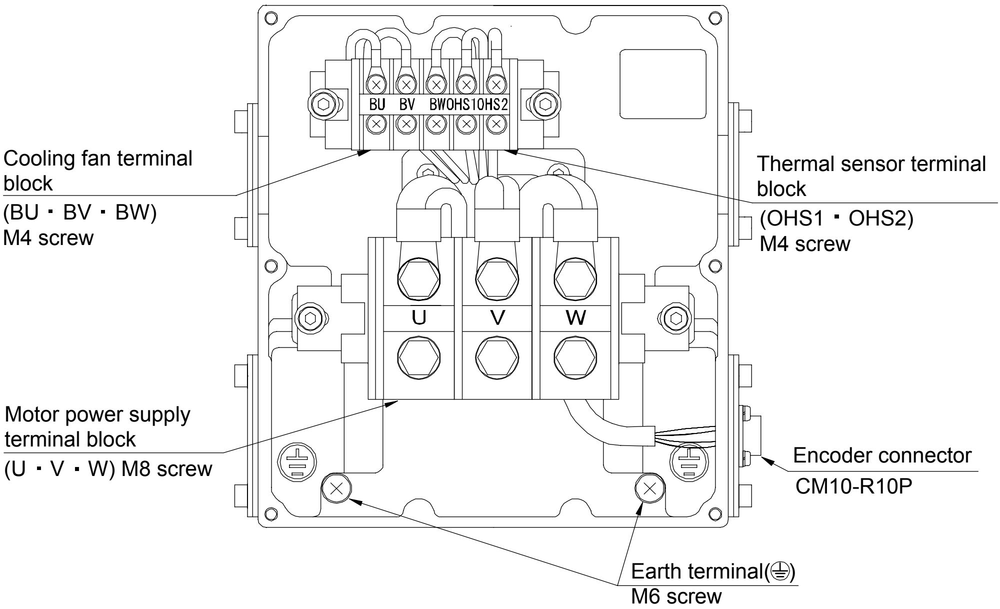


Terminal block signal arrangement

OHS1	OHS2

U	V	W	BU	BV

Terminal box inside (HA-LP801(4) ・ 12K1(4) ・ 11K1M(4) ・ 15K1M(4) ・ 15K2(4) ・ 22K2(4)

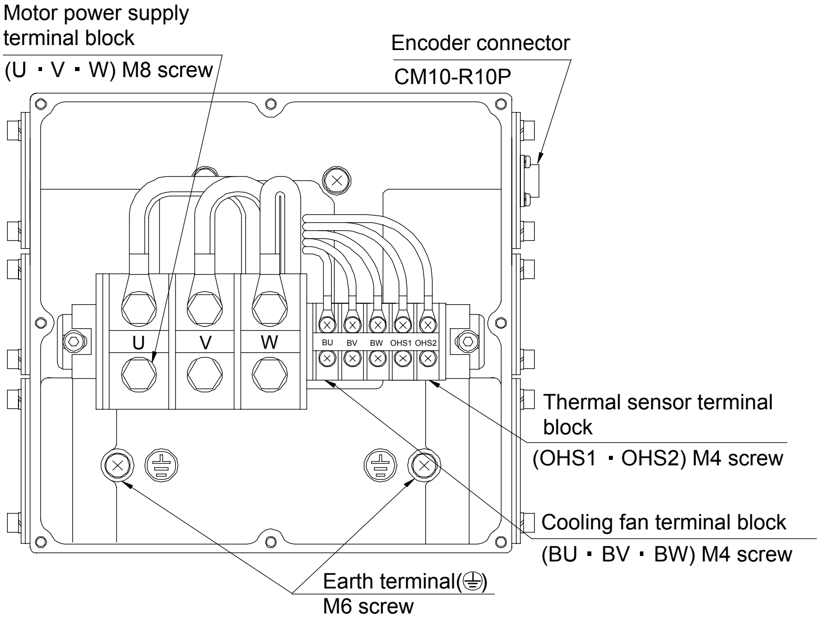


Terminal block signal arrangement

BU	BV	BW	OHS1	OHS2

U	V	W

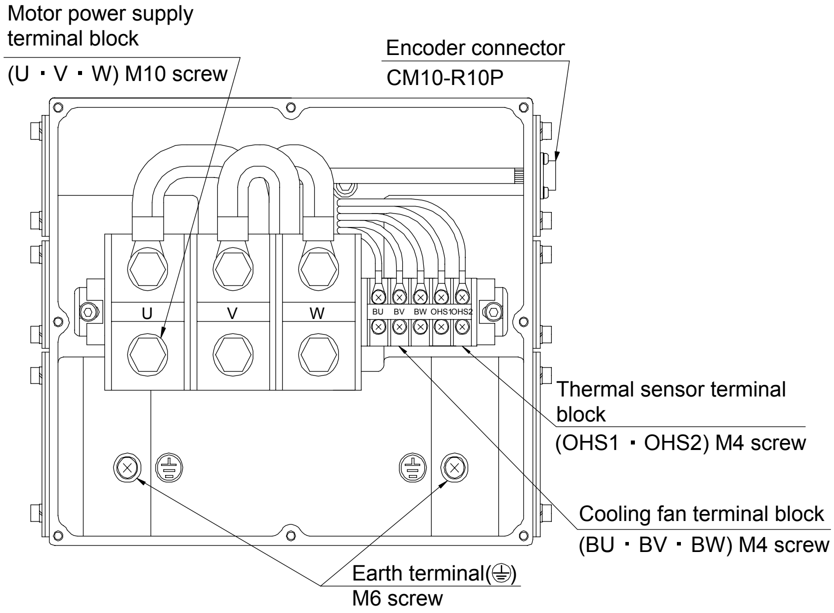
Terminal box inside (HA-LP15K1(4) ・ 20K1(4) ・ 22K1M(4))



Terminal block signal arrangement

U	V	W	BU	BV	BW	OHS1	OHS2

Terminal box inside (HA-LP25K1)



Terminal block signal arrangement

U	V	W	BU	BV	BW	OHS1	OHS2

<table>
<tr><th>Signal name</th><th>Abbreviation</th><th>Description</th></tr>
<tr><td>Power supply</td><td>U・V・W</td><td>Connect to the motor output terminals (U, V, W) of the servo amplifier. During power-on, do not open or close the motor power line. Otherwise, a malfunction or faulty may occur.</td></tr>
<tr><td>Cooling fan</td><td>(Note)
BU・BV・BW</td><td>Supply power which satisfies the following specifications.
<table>
<tr><th>Servo motor</th><th>Voltage division</th><th>Voltage, frequency</th><th>Power consumption [W]</th><th>Rated current [A]</th></tr>
<tr><td>HA-LP601, 701M, 11K2</td><td rowspan="4">200V class</td><td>1-phase 200 to 220VAC 50Hz
1-phase 200 to 230VAC 60Hz</td><td>42(50Hz)
54(60Hz)</td><td>0.21(50Hz)
0.25(60Hz)</td></tr>
<tr><td>HA-LP801, 12K1, 11K1M, 15K1M, 15K2, 22K2</td><td rowspan="3">3-phase 200 to 230VAC 50Hz/60Hz</td><td>62(50Hz)
76(60Hz)</td><td>0.18(50Hz)
0.17(60Hz)</td></tr>
<tr><td>HA-LP15K1, 20K1, 22K1M</td><td>65(50Hz)
85(60Hz)</td><td>0.20(50Hz)
0.22(60Hz)</td></tr>
<tr><td>HA-LP25K1</td><td>120(50Hz)
175(60Hz)</td><td>0.65(50Hz)
0.80(60Hz)</td></tr>
<tr><td>HA-LP6014, 701M4, 11K24</td><td rowspan="4">400V class</td><td>1-phase 200 to 220VAC 50Hz
1-phase 200 to 230VAC 60Hz</td><td>42(50Hz)
54(60Hz)</td><td>0.21(50Hz)
0.25(60Hz)</td></tr>
<tr><td>HA-LP8014, 12K14, 11K1M4, 15K1M4, 15K24, 22K24</td><td>3-phase 380 to 440VAC 50Hz
3-phase 380 to 480VAC 60Hz</td><td>62(50Hz)
76(60Hz)</td><td>0.14(50Hz)
0.11(60Hz)</td></tr>
<tr><td>HA-LP15K14, 20K14, 22K1M4</td><td rowspan="2">3-phase 380 to 460VAC 50Hz
3-phase 380 to 480VAC 60Hz</td><td>65(50Hz)
85(60Hz)</td><td>0.12(50Hz)
0.14(60Hz)</td></tr>
<tr><td>HA-LP25K14</td><td>110(50Hz)
150(60Hz)</td><td>0.20(50Hz)
0.22(60Hz)</td></tr>
</table>
</td></tr>
<tr><td>Motor thermal relay</td><td>OHS1・OHS2</td><td>OHS1—OHS2 are opened when heat is generated to an abnormal temperature.
Maximum rating: AC/DC 125V, or 250V, 2A
Minimum rating: AC/DC 6V, 0.15A</td></tr>
<tr><td>Earth terminal</td><td>⏚</td><td>For grounding, connect to the earth of the control box via the earth terminal of the servo amplifier.</td></tr>
</table>

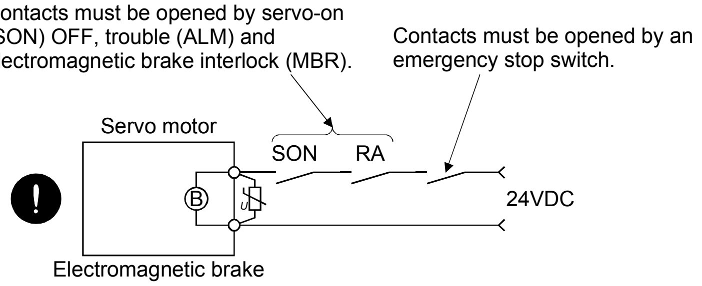
Note. The servo motor with cooling fan for 1-phase has no BW terminal.

3.11 Servo motor with an electromagnetic brake

3.11.1 Safety precautions

⚠ CAUTION

- Configure an electromagnetic brake circuit so that it is activated also by an external emergency stop switch.



- The electromagnetic brake is provided for holding purpose and must not be used for ordinary braking.
- Before performing the operation, be sure to confirm that the electromagnetic brake operates properly.
- Do not use the 24VDC interface power supply for the electromagnetic brake. Always use the power supply designed exclusively for the electromagnetic brake. Otherwise, a fault may occur.

POINT

- Refer to the Servo Motor Instruction Manual (Vol.2) for specifications such as the power supply capacity and operation delay time of the electromagnetic brake.
- Refer to the Servo Motor Instruction Manual (Vol.2) for the selection of a surge absorber for the electromagnetic brake.

Note the following when the servo motor with an electromagnetic brake is used.

1) Set "□□□1"in parameter No.PA04 to make the electromagnetic brake interlock (MBR) valid.

2) The brake will operate when the power (24VDC) switches off.

3) While the reset (RES) is on, the base circuit is shut off. When using the servo motor with a vertical shaft, use the electromagnetic brake interlock (MBR).

4) Switch off the servo-on (SON) after the servo motor has stopped.

3.11.2 Setting

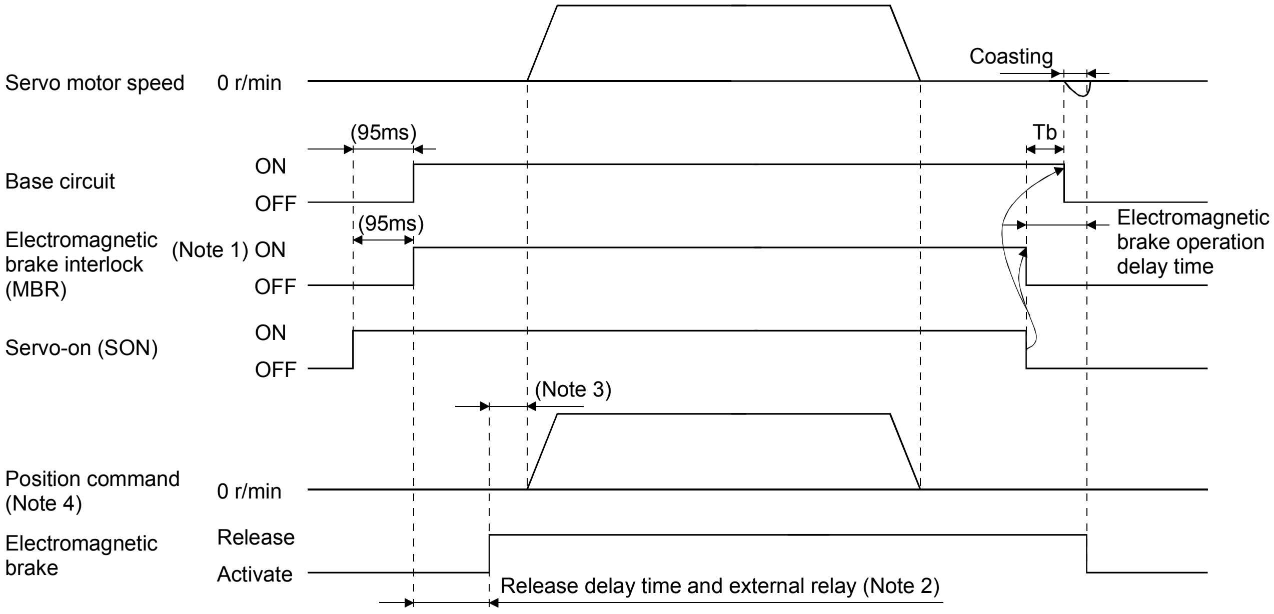
(1) Set "□□□1" in parameter No.PA04 to make the electromagnetic brake interlock (MBR) valid.

(2) Using parameter No.PC16 (electromagnetic brake sequence output), set a delay time (Tb) at servo-off from electromagnetic brake operation to base circuit shut-off as in the timing chart shown in section 3.11.3(1).

3.11.3 Timing charts

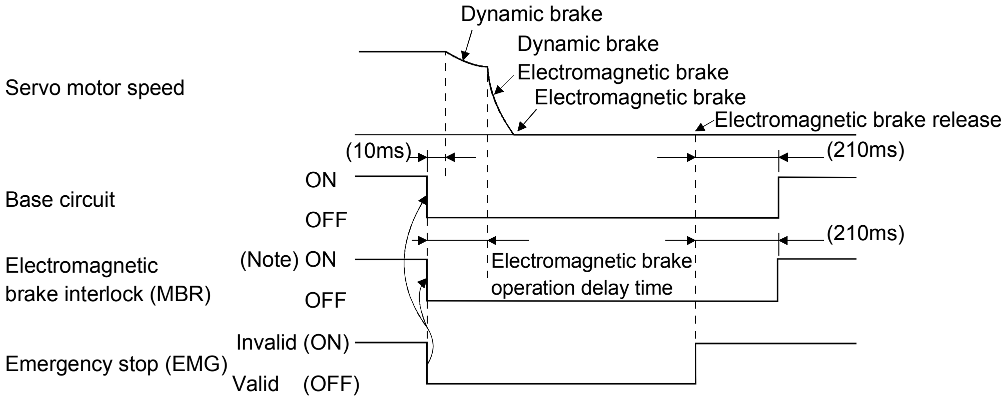
(1) Servo-on (SON) command (from controller) ON/OFF

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



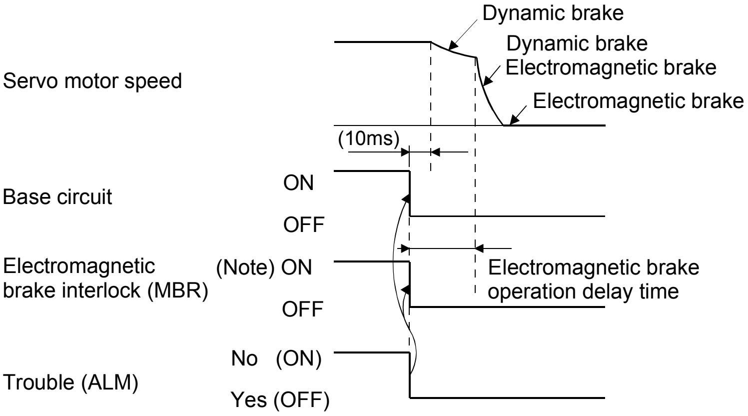
Note 1. ON: Electromagnetic brake is not activated.
OFF: Electromagnetic brake is activated.
2. Electromagnetic brake is released after delaying for the release delay time of electromagnetic brake and operation time of external circuit relay. For the release delay time of electromagnetic brake, refer to the Servo Motor Instruction Manual (Vol.2).
3. Give a position command after the electromagnetic brake is released.
4. For the position control mode.

(2) Emergency stop (EMG) ON/OFF



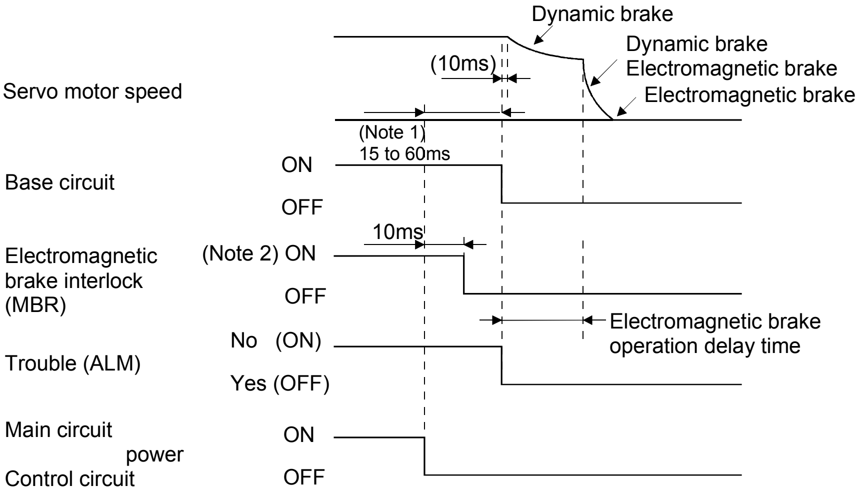
Note. ON: Electromagnetic brake is not activated.
OFF: Electromagnetic brake is activated.

(3) Alarm occurrence



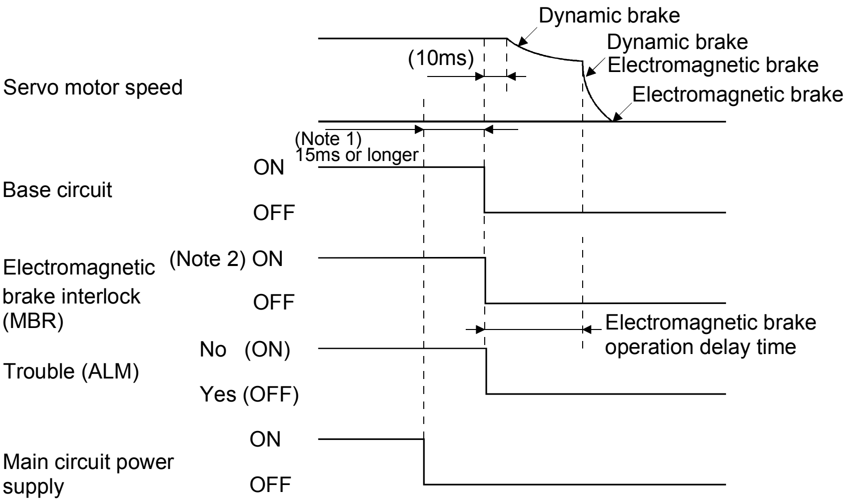
Note. ON: Electromagnetic brake is not activated.
OFF: Electromagnetic brake is activated.

(4) Both main and control circuit power supplies off



Note 1. Changes with the operating status.
2. ON: Electromagnetic brake is not activated.
OFF: Electromagnetic brake is activated.

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

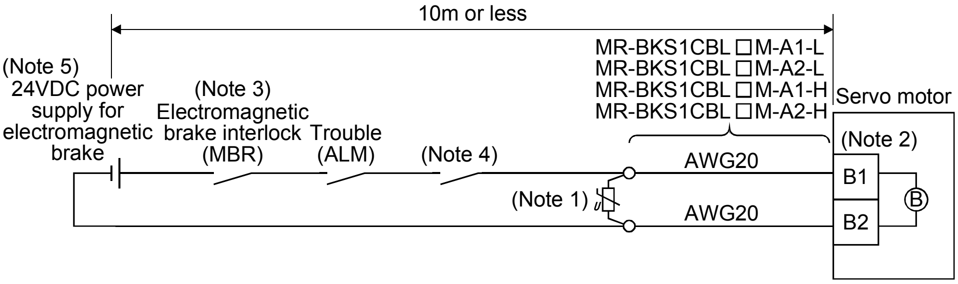


Note 1. Changes with the operating status.
2. ON: Electromagnetic brake is not activated.
OFF: Electromagnetic brake is activated.

3.11.4 Wiring diagrams (HF-MP series・HF-KP series servo motor)

POINT
・For HF-SP series・HC-RP series・HC-UP series・HC-LP series・HF-JP series servo motors, refer to section 3.10.2 (2).

(1) When cable length is 10m or less



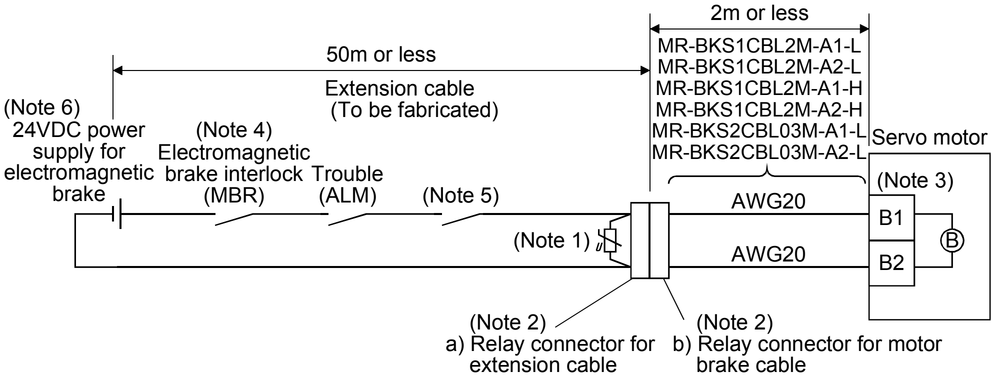
Note 1. Connect a surge absorber as close to the servo motor as possible.
2. There is no polarity in electromagnetic brake terminals (B1 and B2).
3. When using a servo motor with an electromagnetic brake, assign the electromagnetic brake interlock (MBR) to external output signal in the parameters No.PA04, PD13 to PD16 and PD18.
4. Shut off the circuit by interlocking with the emergency stop switch.
5. Do not use the 24VDC interface power supply for the electromagnetic brake.

When fabricating the motor brake cable MR-BKS1CBL□M-H, refer to section 12.1.4.

(2) When cable length exceeds 10m

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

Refer to section 12.11 for the wire used for the extension cable.



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

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

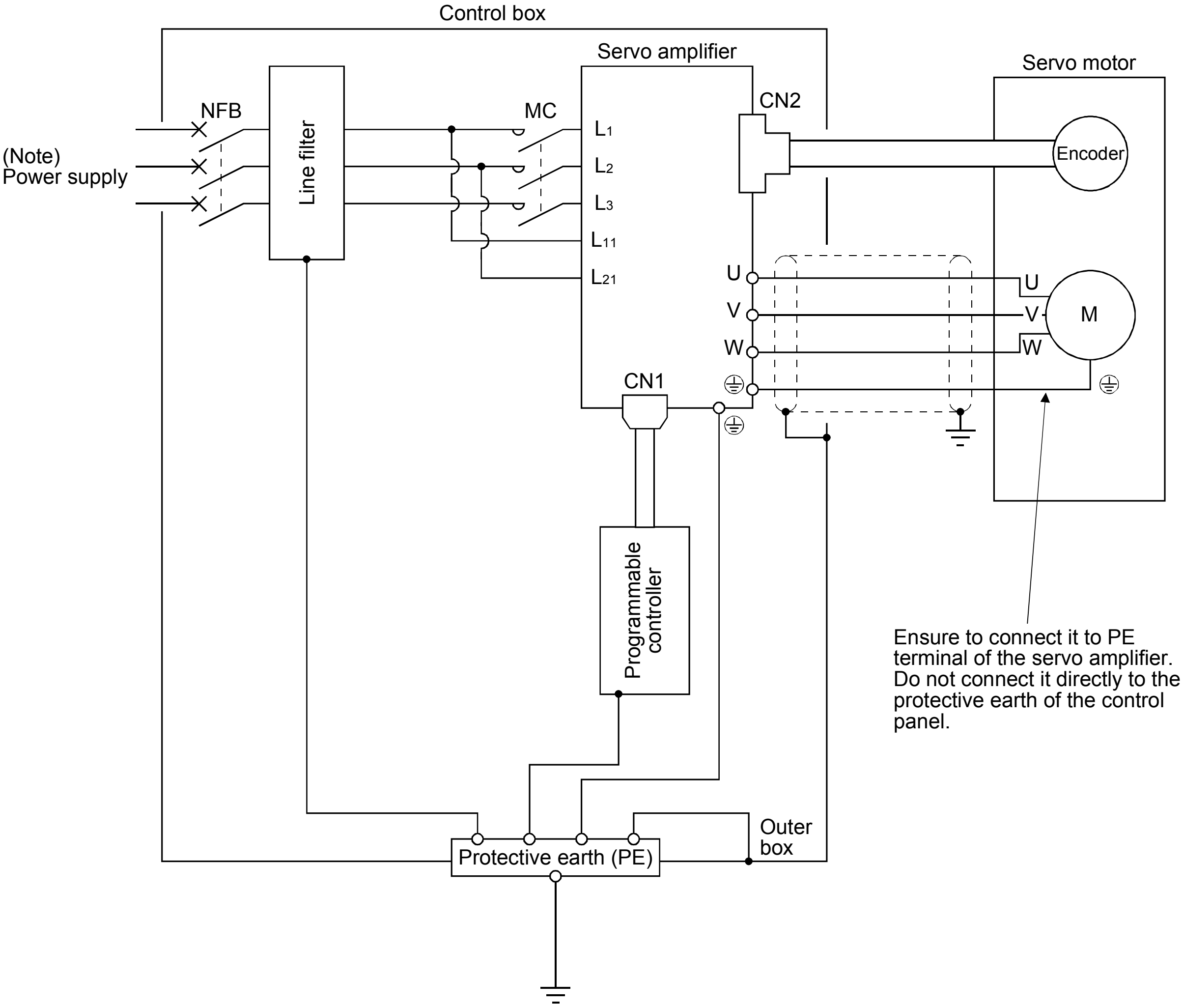
Relay connector	Description	IP rating
a) Relay connector for extension cable	CM10-CR2P-∗ (DDK) Wire size: S, M, L	IP65
b) Relay connector for motor brake cable	CM10-SP2S-∗ (D6) (DDK) Wire size: S, M, L	IP65

3. There is no polarity in electromagnetic brake terminals (B1 and B2).
4. When using a servo motor with an electromagnetic brake, assign the electromagnetic brake interlock (MBR) to external output signal in the parameters No.PA04, PD13 to PD16 and PD18.
5. Shut off the circuit by interlocking with the emergency stop switch.
6. Do not use the 24VDC interface power supply for the electromagnetic brake.

3.12 Grounding

⚠ WARNING	· Ground the servo amplifier and servo motor securely. · To prevent an electric shock, always connect the protective earth (PE) terminal (terminal marked ⏚) of the servo amplifier with the protective earth (PE) of the control box.

The servo amplifier switches the power transistor on-off to supply power to the servo motor. Depending on the wiring and ground cable routing, the servo amplifier may be affected by the switching noise (due to di/dt and dv/dt) of the transistor. To prevent such a fault, refer to the following diagram and always ground.
To conform to the EMC Directive, refer to the EMC Installation Guidelines (IB(NA)67310).



Ensure to connect it to PE terminal of the servo amplifier. Do not connect it directly to the protective earth of the control panel.

Note. For 1-phase 200 to 230VAC or 1-phase 100 to 120VAC, connect the power supply to L1 · L2 and leave L3 open.
There is no L3 for 1-phase 100 to 120VAC power supply. For the specification of power supply, refer to section 1.3.

4. STARTUP

⚠ WARNING

- Do not operate the switches with wet hands. You may get an electric shock.

⚠ CAUTION

- Before starting operation, check the parameters. Some machines may perform unexpected operation.
- Take safety measures, e.g. provide covers, to prevent accidental contact of hands and parts (cables, etc.) with the servo amplifier heat sink, regenerative resistor, servo motor, etc. since they may be hot while power is on or for some time after power-off. Their temperatures may be high and you may get burnt or a parts may damaged.
- During operation, never touch the rotating parts of the servo motor. Doing so can cause injury.

4.1 Switching power on for the first time

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

4.1.1 Startup procedure

Wiring check	Check whether the servo amplifier and servo motor are wired correctly using visual inspection, output signal (DO) forced output (section 6.8), etc. (Refer to section 4.1.2.)
↓	
Surrounding environment check	Check the surrounding environment of the servo amplifier and servo motor. (Refer to section 4.1.3.)
↓	
Parameter setting	Set the parameters as necessary, such as the used control mode and regenerative option selection. (Refer to chapter 5 and sections 4.2.4, 4.3.4 and 4.4.4.)
↓	
Test operation of servo motor alone in test operation mode	For the test operation, with the servo motor disconnected from the machine and operated at the speed as low as possible, check whether the servo motor rotates correctly. (Refer to sections 6.9, 4.2.3, 4.3.3 and 4.4.3.)
↓	
Test operation of servo motor alone by commands	For the test operation with the servo motor disconnected from the machine and operated at the speed as low as possible, give commands to the servo amplifier and check whether the servo motor rotates correctly.
↓	
Test operation with servo motor and machine connected	Connect the servo motor with the machine, give operation commands from the host command device, and check machine motions.
↓	
Gain adjustment	Make gain adjustment to optimize the machine motions. (Refer to chapter 7.)
↓	
Actual operation	
↓	
Stop	Stop giving commands and stop operation. The other conditions where the servo motor will come to a stop are indicated in sections 4.2.2, 4.3.2 and 4.4.2.

4.1.2 Wiring check

(1) Power supply system wiring

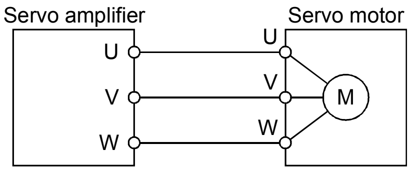
Before switching on the main circuit and control circuit power supplies, check the following items.

(a) Power supply system wiring

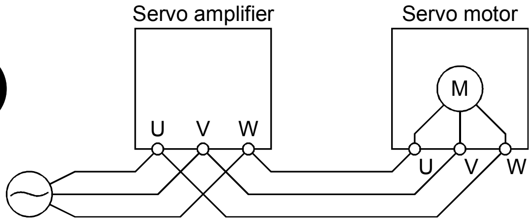
The power supplied to the power input terminals (L_1, L_2, L_3, L_{11}, L_{21}) of the servo amplifier should satisfy the defined specifications. (Refer to section 1.3.)

(b) Connection of servo amplifier and servo motor

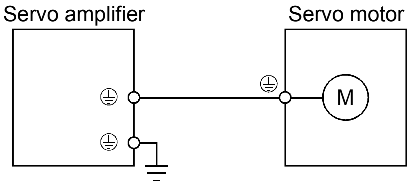
1) The servo motor power supply terminals (U, V, W) of the servo amplifier match in phase with the power input terminals (U, V, W) of the servo motor.



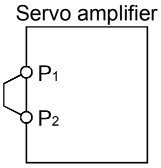
2) The power supplied to the servo amplifier should not be connected to the servo motor power supply terminals (U, V, W). To do so will fail the connected servo amplifier and servo motor.



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



4) P_1-P_2 (For 11k to 22kW, P_1-P) should be connected.



(c) When option and auxiliary equipment are used

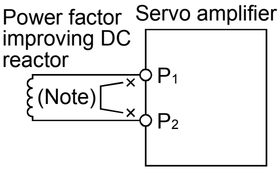
1) When regenerative option is used under 3.5kW for 200V class and 2kW for 400V class

- The lead between P terminal and D terminal of CNP2 connector should not be connected.
- The generative brake option should be connected to P terminal and C terminal.
- A twisted cable should be used. (Refer to section 12.2)

2) When regenerative option is used over 5kW for 200V class and 3.5kW for 400V class
   - The lead of built-in regenerative resistor connected to P terminal and C terminal of TE1 terminal block should not be connected.
   - The generative brake option should be connected to P terminal and C terminal.
   - A twisted cable should be used when wiring is over 5m and under 10m. (Refer to section 12.2)

3) When brake unit and power regenerative converter are used over 5kW
   - The lead of built-in regenerative resistor connected to P terminal and C terminal of TE1 terminal block should not be connected.
   - Brake unit, power regenerative converter or power regenerative common converter should be connected to P terminal and N terminal. (Refer to section 12.3 to 12.5)

4) The power factor improving DC reactor should be connected P_1 and P_2 (For 11k to 22kW, P_1 and P). (Refer to section 12.13.)



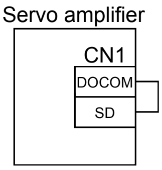
Note. Always disconnect P_1 and P_2 (For 11k to 22kW, P_1 and P).

(2) I/O signal wiring

(a) The I/O signals should be connected correctly.
Use DO forced output to forcibly turn on/off the pins of the CN1 connector. This function can be used to perform a wiring check. (Refer to section 6.8.) In this case, switch on the control circuit power supply only.

(b) 24VDC or higher voltage is not applied to the pins of connectors CN1.

(c) SD and DOCOM of connector CN1 is not shorted.



4.1.3 Surrounding environment

(1) Cable routing

(a) The wiring cables are free from excessive force.

(b) The encoder cable should not be used in excess of its flex life. (Refer to section 11.4.)

(c) The connector part of the servo motor should not be strained.

(2) Environment

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

4.2 Startup in position control mode

Make a startup in accordance with section 4.1. This section provides the methods specific to the position control mode.

4.2.1 Power on and off procedures

(1) Power-on

Switch power on in the following procedure. Always follow this procedure at power-on.

1) Switch off the servo-on (SON).

2) Make sure that a command pulse train is not input.

3) Switch on the main circuit power supply and control circuit power supply.
At power-on, "88888" appears instantaneously, but it is not an error.
When main circuit power/control circuit power is switched on, the display shows "C (Cumulative feedback pulses)", and in two second later, shows data.

In the absolute position detection system, first power-on results in the absolute position lost (AL.25) alarm and the servo system cannot be switched on.
The alarm can be deactivated then switching power off once and on again.
Also in the absolute position detection system, if power is switched on at the servo motor speed of 3000r/min or higher, position mismatch may occur due to external force or the like. Power must therefore be switched on when the servo motor is at a stop.

(2) Power-off

1) Make sure that a command pulse train is not input.

2) Switch off the Servo-on (SON).

3) Switch off the main circuit power supply and control circuit power supply.

4.2.2 Stop

In any of the following statuses, the servo amplifier interrupts and stops the operation of the servo motor.
Refer to section 3.11 for the servo motor with an electromagnetic brake.

(a) Servo-on (SON) OFF
The base circuit is shut off and the servo motor coasts.

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

(c) Emergency stop (EMG) OFF
The base circuit is shut off and the dynamic brake is operated to bring the servo motor to a sudden stop. Alarm AL.E6 occurs.

(d) Forward rotation stroke end (LSP), reverse rotation stroke end (LSN) OFF
The droop pulses are erased and the servo motor is stopped and servo-locked. It can be run in the opposite direction.

4.2.3 Test operation

Before starting actual operation, perform test operation to make sure that the machine operates normally.
Refer to section 4.2.1 for the power on and off methods of the servo amplifier.

Test operation of servo motor alone in JOG operation of test operation mode

In this step, confirm that the servo amplifier and servo motor operate normally.
With the servo motor disconnected from the machine, use the test operation mode and check whether the servo motor correctly rotates at the slowest speed. Refer to section 6.9 for the test operation mode.

Test operation of servo motor alone by commands

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

1) Switch on the Emergency stop (EMG) and Servo-on (SON). When the servo amplifier is put in a servo-on status, the Ready (RD) switches on.
2) Switch on the Forward rotation stroke end (LSP) or Reverse rotation stroke end (LSN).
3) When a pulse train is input from the command device, the servo motor starts rotating. Give a low speed command at first and check the rotation direction, etc. of the servo motor. If the servo motor does not operate in the intended direction, check the input signal.

Test operation with servo motor and machine connected

In this step, connect the servo motor with the machine and confirm that the machine operates normally under the commands from the command device.
Make sure that the servo motor rotates in the following procedure.

1) Switch on the Emergency stop (EMG) and Servo-on (SON). When the servo amplifier is put in a servo-on status, the Ready (RD) switches on.
2) Switch on the Forward rotation stroke end (LSP) or Reverse rotation stroke end (LSN).
3) When a pulse train is input from the command device, the servo motor starts rotating. Give a low speed command at first and check the operation direction, etc. of the machine. If the machine does not operate in the intended direction, check the input signal. In the status display or MR Configurator, check for any problems of the servo motor speed, command pulse frequency, load ratio, etc.
4) Then, check automatic operation with the program of the command device.

4.2.4 Parameter setting

POINT

- The encoder cable MR-EKCBL□M-L/H for the HF-MP series・HF-KP series servo motor or the encoder cable MR-ENECBL□M-H for HF-JP11K1M(4)・15K1M(4) servo motor requires the parameter No.PC22 setting to be changed depending on its length. Check whether the parameter is set correctly. If it is not set correctly, the encoder error 1 (At power on) (AL.16) will occur at power-on.

Servo motor	Encoder cable	Parameter No.PC22 setting
HF-MP series・HF-KP series	MR-EKCBL20M-L/H	0□□□(initial value)
	MR-EKCBL30M-L/H	1□□□
	MR-EKCBL40M-H	
	MR-EKCBL50M-H	
HF-JP11K1M(4)・15K1M(4)	MR-ENECBL2M-H	0□□□(initial value)
	MR-ENECBL5M-H	
	MR-ENECBL10M-H	
	MR-ENECBL20M-H	
	MR-ENECBL30M-H	1□□□
	MR-ENECBL40M-H	
	MR-ENECBL50M-H	

In the position control mode, the servo amplifier can be used by merely changing the basic setting parameters (No.PA□□) mainly.
As necessary, set the gain filter parameters (No.PB□□), extension setting parameters (No.PC□□) and I/O setting parameters (No.PD□□).

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

Note. The parameter No.PA19 setting must be changed when this parameter group is used.

4.2.5 Actual operation

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

4.2.6 Trouble at start-up

⚠ CAUTION

- Excessive adjustment or change of parameter setting must not be made as it will make operation instable.

POINT

- Using the optional MR Configurator, you can refer to unrotated servo motor reasons, etc.

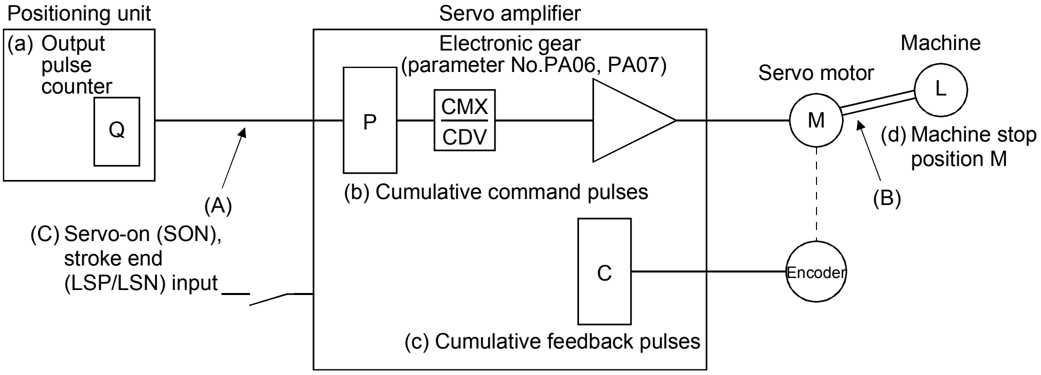
The following faults may occur at start-up. If any of such faults occurs, take the corresponding action.

(1) Troubleshooting

No.	Start-up sequence	Fault	Investigation	Possible cause	Reference
1	Power on	· LED is not lit. · LED flickers.	Not improved if connectors CN1, CN2 and CN3 are disconnected.	1. Power supply voltage fault 2. Servo amplifier is faulty.	
			Improved when connectors CN1 is disconnected.	Power supply of CN1 cabling is shorted.	
			Improved when connector CN2 is disconnected.	1. Power supply of encoder cabling is shorted. 2. Encoder is faulty.	
			Improved when connector CN3 is disconnected.	Power supply of CN3 cabling is shorted.	
		Alarm occurs.	Refer to section 9.2 and remove cause.		Section 9.2
2	Switch on servo-on (SON).	Alarm occurs.	Refer to section 9.2 and remove cause.		Section 9.2
		Servo motor shaft is not servo-locked (is free).	1. Check the display to see if the servo amplifier is ready to operate. 2. Check the external I/O signal indication (section 6.7) to see if the servo-on (SON) is ON.	1. Servo-on (SON) is not input. (Wiring mistake) 2. 24VDC power is not supplied to DICOM.	Section 6.7
3	Enter input command. (Test operation)	Servo motor does not rotate.	Check the cumulative command pulse on the status display or MR Configurator (section 6.3).	1. Wiring mistake (a) For open collector pulse train input, 24VDC power is not supplied to OPC. (b) LSP and LSN are not on. 2. Pulse train is not input from the controller. 3. Electromagnetic brake is operating.	Section 6.3
			Check if the Ready (RD) is ON.		
			Check the parameter No.PA13 (command pulse input form) setting.		
			Check if the Electromagnetic brake interlock (MBR) is ON.		
		Servo motor run in reverse direction.	Check the cumulative command pulse on the status display or MR Configurator.	1. Mistake in wiring to controller. 2. Mistake in setting of parameter No.PA14.	Chapter 5
			Check the parameter No.PA14 (rotation direction selection) setting.		

No.	Start-up sequence	Fault	Investigation	Possible cause	Reference
4	Gain adjustment	Rotation ripples (speed fluctuations) are large at low speed.	Make gain adjustment in the following procedure. 1. Increase the auto tuning response level. 2. Repeat acceleration and deceleration several times to complete auto tuning.	Gain adjustment fault	Chapter 7
		Large load inertia moment causes the servo motor shaft to oscillate side to side.	If the servo motor may be run with safety, repeat acceleration and deceleration several times to complete auto tuning.	Gain adjustment fault	Chapter 7
5	Cyclic operation	Position shift occurs	Confirm the cumulative command pulses, cumulative feedback pulses and actual servo motor position.	Pulse counting error, etc. due to noise.	(2) in this section

(2) How to find the cause of position shift



When a position shift occurs, check (a) output pulse counter, (b) cumulative command pulse display, (c) cumulative feedback pulse display, and (d) machine stop position in the above diagram.
(A), (B) and (C) indicate position shift causes. For example, (A) indicates that noise entered the wiring between positioning unit and servo amplifier, causing pulses to be miss-counted.

In a normal status without position shift, there are the following relationships.

1) Q = P (positioning unit's output counter = servo amplifier's cumulative command pulses)

2) When using the electronic gear

$$P \cdot \frac{\text{CMX (parameter No.PA06)}}{\text{CDV (parameter No.PA07)}}$$

= C (cumulative command pulses × electronic gear = cumulative feedback pulses)

3) When using parameter No.PA05 to set the number of pulses per servo motor one rotation.

$$P \cdot \frac{262144}{\text{FBP (parameter No.PA05)}} = C$$

4) $C \cdot \Delta \ell = M$ (cumulative feedback pulses × travel per pulse = machine position)

Check for a position shift in the following sequence.

1) When $Q \neq P$
Noise entered the pulse train signal wiring between positioning unit and servo amplifier, causing pulses to be miss-counted. (Cause A)
Make the following check or take the following measures.
- Check how the shielding is done.
- Change the open collector system to the differential line driver system.
- Run wiring away from the power circuit.
- Install a data line filter. (Refer to section 12.17 (2)(a).)

2) When $P \cdot \frac{CMX}{CDV} \neq C$

During operation, the servo-on (SON) or forward/reverse rotation stroke end was switched off or the clear (CR) and the reset (RES) switched on. (Cause C)
If a malfunction may occur due to much noise, increase the input filter setting (parameter No.PD19).

3) When $C \cdot \Delta \ell \neq M$
Mechanical slip occurred between the servo motor and machine. (Cause B)

4.3 Startup in speed control mode

Make a startup in accordance with section 4.1. This section provides the methods specific to the speed control mode.

4.3.1 Power on and off procedures

(1) Power-on
Switch power on in the following procedure. Always follow this procedure at power-on.

1) Switch off the servo-on (SON).

2) Make sure that the Forward rotation start (ST1) and Reverse rotation start (ST2) are off.

3) Switch on the main circuit power supply and control circuit power supply.
At power-on, "88888" appears instantaneously, but it is not an error.
When main circuit power/control circuit power is switched on, the display shows "r (servo motor speed)", and in two second later, shows data.

(2) Power-off
1) Switch off the Forward rotation start (ST1) or Reverse rotation start (ST2).

2) Switch off the Servo-on (SON).

3) Switch off the main circuit power supply and control circuit power supply.

4.3.2 Stop

In any of the following statuses, the servo amplifier interrupts and stops the operation of the servo motor. Refer to section 3.11 for the servo motor with an electromagnetic brake.

(a) Servo-on (SON) OFF
The base circuit is shut off and the servo motor coasts.

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

(c) Emergency stop (EMG) OFF
The base circuit is shut off and the dynamic brake is operated to bring the servo motor to a sudden stop. Alarm AL.E6 occurs.

(d) Stroke end (LSP/LSN) OFF
The servo motor is brought to a sudden stop and servo-locked. The motor may be run in the opposite direction.

(e) Simultaneous ON or simultaneous OFF of forward rotation start (ST1) and reverse rotation start (ST2)
The servo motor is decelerated to a stop.

POINT

- A sudden stop indicates deceleration to a stop at the deceleration time constant of zero.

4.3.3 Test operation

Before starting actual operation, perform test operation to make sure that the machine operates normally.
Refer to section 4.3.1 for the power on and off methods of the servo amplifier.

Test operation of servo motor alone in JOG operation of test operation mode

In this step, confirm that the servo amplifier and servo motor operate normally.
With the servo motor disconnected from the machine, use the test operation mode and check whether the servo motor correctly rotates at the slowest speed. Refer to section 6.9 for the test operation mode.

Test operation of servo motor alone by commands

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

1) Switch on the Emergency stop (EMG) and Servo-on (SON). When the servo amplifier is put in a servo-on status, the Ready (RD) switches on.

2) Switch on the Forward rotation stroke end (LSP) or Reverse rotation stroke end (LSN).

3) When the analog speed command (VC) is input from the command device and the Forward rotation start (ST1) or Reverse rotation start (ST2) is switched on, the servo motor starts rotating. Give a low speed command at first and check the rotation direction, etc. of the servo motor. If the servo motor does not operate in the intended direction, check the input signal.

Test operation with servo motor and machine connected

In this step, connect the servo motor with the machine and confirm that the machine operates normally under the commands from the command device.
Make sure that the servo motor rotates in the following procedure.

1) Switch on the Emergency stop (EMG) and Servo-on (SON). When the servo amplifier is put in a servo-on status, the Ready (RD) switches on.

2) Switch on the Forward rotation stroke end (LSP) or Reverse rotation stroke end (LSN).

3) When the analog speed command (VC) is input from the command device and the Forward rotation start (ST1) or Reverse rotation start (ST2) is switched on, the servo motor starts rotating. Give a low speed command at first and check the operation direction, etc. of the machine. If the machine does not operate in the intended direction, check the input signal. In the status display or MR Configurator, check for any problems of the servo motor speed, load ratio, etc.

4) Then, check automatic operation with the program of the command device.

4.3.4 Parameter setting

POINT

- The encoder cable MR-EKCBL□M-L/H for the HF-MP series・HF-KP series servo motor or the encoder cable MR-ENECBL□M-H for HF-JP11K1M(4)・15K1M(4) servo motor requires the parameter No.PC22 setting to be changed depending on its length. Check whether the parameter is set correctly. If it is not set correctly, the encoder error 1 (At power on) (AL.16) will occur at power-on.

Servo motor	Encoder cable	Parameter No.PC22 setting
HF-MP series・HF-KP series	MR-EKCBL20M-L/H	0□□□(initial value)
	MR-EKCBL30M-L/H	1□□□
	MR-EKCBL40M-H	
	MR-EKCBL50M-H	
HF-JP11K1M(4)・15K1M(4)	MR-ENECBL2M-H	0□□□(initial value)
	MR-ENECBL5M-H	
	MR-ENECBL10M-H	
	MR-ENECBL20M-H	
	MR-ENECBL30M-H	1□□□
	MR-ENECBL40M-H	
	MR-ENECBL50M-H	

When using this servo in the speed control mode, change the parameter No.PA01 setting to select the speed control mode. In the speed control mode, the servo can be used by merely changing the basic setting parameters (No.PA□□) and extension setting parameters (No.PC□□) mainly.
As necessary, set the gain filter parameters (No.PB□□) and I/O setting parameters (No.PD□□).

Parameter group	Main description
Basic setting parameter (No.PA□□)	Set the basic setting parameters first. In this parameter group, set the following items. Control mode selection (select the speed control mode) Regenerative option selection Auto tuning selection and adjustment Torque limit setting Encoder output pulse setting
Gain filter parameter (No.PB□□)	If satisfactory operation cannot be achieved by the gain adjustment made by auto tuning, execute in-depth gain adjustment using this parameter group. This parameter group must also be set when the gain changing function is used.
Extension setting parameter (No.PC□□)	In this parameter group, set the following items. Acceleration/deceleration time constant S-pattern acceleration/deceleration time constant Internal speed command Analog speed command maximum speed Analog speed command offset In addition, this parameter group must be set when analog monitor output, torque limit, etc. are used.
(Note) I/O setting parameter (No.PD□□)	Used when changing the I/O devices of the servo amplifier.

Note. The parameter No.PA19 setting must be changed when this parameter group is used.

4.3.5 Actual operation

Start actual operation after confirmation of normal operation by test operation and completion of the corresponding parameter settings.

4.3.6 Trouble at start-up

CAUTION

- Excessive adjustment or change of parameter setting must not be made as it will make operation instable.

POINT

- Using the MR Configurator, you can refer to unrotated servo motor reasons, etc.

The following faults may occur at start-up. If any of such faults occurs, take the corresponding action.

No.	Start-up sequence	Fault	Investigation	Possible cause	Reference
1	Power on	・LED is not lit. ・LED flickers.	Not improved if connectors CN1, CN2 and CN3 are disconnected.	1. Power supply voltage fault 2. Servo amplifier is faulty.	
			Improved when connectors CN1 is disconnected.	Power supply of CN1 cabling is shorted.	
			Improved when connector CN2 is disconnected.	1. Power supply of encoder cabling is shorted. 2. Encoder is faulty.	
			Improved when connector CN3 is disconnected.	Power supply of CN3 cabling is shorted.	
		Alarm occurs.	Refer to section 9.2 and remove cause.		Section 9.2
2	Switch on servo-on (SON).	Alarm occurs.	Refer to section 9.2 and remove cause.		Section 9.2
		Servo motor shaft is not servo-locked (is free).	1. Check the display to see if the servo amplifier is ready to operate. 2. Check the external I/O signal indication (section 6.7) to see if the servo-on (SON) is ON.	1. Servo-on (SON) is not input. (Wiring mistake) 2. 24VDC power is not supplied to DICOM.	Section 6.7
3	Switch on forward rotation start (ST1) or reverse rotation start (ST2).	Servo motor does not rotate.	Call the status display or MR Configurator and check the input voltage of the analog speed command (VC).	Analog speed command is 0V.	Section 6.3
			Call the external I/O signal display (section 6.7) and check the ON/OFF status of the input signal.	LSP, LSN, ST1 or ST2 is off.	Section 6.7
			Check the internal speed commands 1 to 7 (parameters No.PC05 to PC11).	Set value is 0.	Section 5.1.9
			Check the forward rotation torque limit (Parameter No.PA11) or reverse rotation torque limit (Parameter No.PA12)	Torque limit level is too low as compared to the load torque.	
			When the analog torque limit (TLA) is usable, check the input voltage on the status display or MR Configurator.	Torque limit level is too low as compared to the load torque.	

No.	Start-up sequence	Fault	Investigation	Possible cause	Reference
4	Gain adjustment	Rotation ripples (speed fluctuations) are large at low speed.	Make gain adjustment in the following procedure. Increase the auto tuning response level. Repeat acceleration and deceleration several times to complete auto tuning.	Gain adjustment fault	Chapter 7
		Large load inertia moment causes the servo motor shaft to oscillate side to side.	If the servo motor may be run with safety, repeat acceleration and deceleration several times to complete auto tuning.	Gain adjustment fault	Chapter 7

4.4 Startup in torque control mode

Make a startup in accordance with section 4.1. This section provides the methods specific to the torque control mode.

4.4.1 Power on and off procedures

(1) Power-on

Switch power on in the following procedure. Always follow this procedure at power-on.

1) Switch off the servo-on (SON).

2) Make sure that the Forward rotation selection (RS1) and Reverse rotation selection (RS2) are off.

3) Switch on the main circuit power supply and control circuit power supply.
At power-on, "88888" appears instantaneously, but it is not an error.
When main circuit power/control circuit power is switched on, the display shows "U (torque command voltage)", and in two second later, shows data.

(2) Power-off

1) Switch off the Forward rotation selection (RS1) or Reverse rotation selection (RS2).

2) Switch off the Servo-on (SON).

3) Switch off the main circuit power supply and control circuit power supply.

4.4.2 Stop

In any of the following statuses, the servo amplifier interrupts and stops the operation of the servo motor. Refer to section 3.11 for the servo motor with an electromagnetic brake.

(a) Servo-on (SON) OFF
The base circuit is shut off and the servo motor coasts.

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

(c) Emergency stop (EMG) OFF
The base circuit is shut off and the dynamic brake is operated to bring the servo motor to a sudden stop. Alarm AL.E6 occurs.

(d) Simultaneous ON or simultaneous OFF of forward rotation selection (RS1) and reverse rotation selection (RS2)
The servo motor coasts.

POINT

- A sudden stop indicates deceleration to a stop at the deceleration time constant of zero.

4.4.3 Test operation

Before starting actual operation, perform test operation to make sure that the machine operates normally.
Refer to section 4.4.1 for the power on and off methods of the servo amplifier.

Test operation of servo motor alone in JOG operation of test operation mode

In this step, confirm that the servo amplifier and servo motor operate normally.
With the servo motor disconnected from the machine, use the test operation mode and check whether the servo motor correctly rotates at the slowest speed. Refer to section 6.9 for the test operation.

Test operation of servo motor alone by commands

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

1) Switch on the Servo-on (SON). When the servo amplifier is put in a servo-on status, the Ready (RD) switches on.

2) When the analog speed command (TC) is input from the command device and the Forward rotation start (RS1) or Reverse rotation start (RS2) is switched on, the servo motor starts rotating. Give a low speed command at first and check the rotation direction, etc. of the servo motor. If the servo motor does not operate in the intended direction, check the input signal.

Test operation with servo motor and machine connected

In this step, connect the servo motor with the machine and confirm that the machine operates normally under the commands from the command device.
Make sure that the servo motor rotates in the following procedure.

1) Switch on the Servo-on (SON). When the servo amplifier is put in a servo-on status, the Ready (RD) switches on.

2) When the analog speed command (TC) is input from the command device and the Forward rotation start (RS1) or Reverse rotation start (RS2) is switched on, the servo motor starts rotating. Give a low speed command at first and check the operation direction, etc. of the machine. If the machine does not operate in the intended direction, check the input signal. In the status display or MR Configurator, check for any problems of the servo motor speed, load ratio, etc.

3) Then, check automatic operation with the program of the command device.

4.4.4 Parameter setting

POINT

- The encoder cable MR-EKCBL□M-L/H for the HF-MP series・HF-KP series servo motor or the encoder cable MR-ENECBL□M-H for HF-JP11K1M(4)・15K1M(4) servo motor requires the parameter No.PC22 setting to be changed depending on its length. Check whether the parameter is set correctly. If it is not set correctly, the encoder error 1 (At power on) (AL.16) will occur at power-on.

Servo motor	Encoder cable	Parameter No.PC22 setting
HF-MP series・HF-KP series	MR-EKCBL20M-L/H	0□□□(initial value)
	MR-EKCBL30M-L/H	1□□□
	MR-EKCBL40M-H	
	MR-EKCBL50M-H	
HF-JP11K1M(4)・15K1M(4)	MR-ENECBL2M-H	0□□□(initial value)
	MR-ENECBL5M-H	
	MR-ENECBL10M-H	
	MR-ENECBL20M-H	
	MR-ENECBL30M-H	1□□□
	MR-ENECBL40M-H	
	MR-ENECBL50M-H	

When using this servo in the torque control mode, change the parameter No.PA01 setting to select the torque control mode. In the torque control mode, the servo can be used by merely changing the basic setting parameters (No.PA□□) and extension setting parameters (No.PC□□) mainly.
As necessary, set the I/O setting parameters (No.PD□□).

Parameter group	Main description
Basic setting parameter (No.PA□□)	Set the basic setting parameters first. In this parameter group, set the following items. Control mode selection (select the torque control mode) Regenerative option selection Torque limit setting Encoder output pulse setting
Gain filter parameter (No.PB□□)	If satisfactory operation cannot be achieved by the gain adjustment made by auto tuning, execute in-depth gain adjustment using this parameter group. This parameter group must also be set when the gain changing function is used.
Extension setting parameter (No.PC□□)	In this parameter group, set the following items. Acceleration/deceleration time constant S-pattern acceleration/deceleration time constant Internal torque command Analog torque command maximum speed Analog torque command offset In addition, this parameter group must be set when analog monitor output, speed limit, etc. are used.
(Note) I/O setting parameter (No.PD□□)	Used when changing the I/O devices of the servo amplifier.

Note. The parameter No.PA19 setting must be changed when this parameter group is used.

4.4.5 Actual operation

Start actual operation after confirmation of normal operation by test operation and completion of the corresponding parameter settings.

4.4.6 Trouble at start-up

⚠CAUTION

- Excessive adjustment or change of parameter setting must not be made as it will make operation instable.

POINT

- Using the MR Configurator, you can refer to unrotated servo motor reasons, etc.

The following faults may occur at start-up. If any of such faults occurs, take the corresponding action.

No.	Start-up sequence	Fault	Investigation	Possible cause	Reference
1	Power on	・LED is not lit. ・LED flickers.	Not improved if connectors CN1, CN2 and CN3 are disconnected.	1. Power supply voltage fault 2. Servo amplifier is faulty.	
			Improved when connectors CN1 is disconnected.	Power supply of CN1 cabling is shorted.	
			Improved when connector CN2 is disconnected.	1. Power supply of encoder cabling is shorted. 2. Encoder is faulty.	
			Improved when connector CN3 is disconnected.	Power supply of CN3 cabling is shorted.	
		Alarm occurs.	Refer to chapter 9 and remove cause.		Chapter 9
2	Switch on servo-on (SON).	Alarm occurs.	Refer to chapter 9 and remove cause.		Chapter 9
		Servo motor shaft is free.	Call the external I/O signal display (section 6.7) and check the ON/OFF status of the input signal.	1. Servo-on (SON) is not input. (Wiring mistake) 2. 24VDC power is not supplied to DICOM.	Section 6.7
3	Switch on forward rotation start (RS1) or reverse rotation start (RS2).	Servo motor does not rotate.	Call the status display or MR Configurator (section 6.3) and check the analog torque command (TC).	Analog torque command is 0V.	Section 6.3
			Call the external I/O signal display (section 6.7) and check the ON/OFF status of the input signal.	RS1 or RS2 is off.	Section 6.7
			Check the internal speed limits 1 to 7 (parameters No.PC05 to PC11).	Set value is 0.	Section 5.3
			Check the analog torque command maximum output (parameter No.26) value.	Torque command level is too low as compared to the load torque.	
			Check the internal torque limit 1 (parameter No.PC13).	Set value is 0.	Section 5.1.11

5. PARAMETERS

⚠ **CAUTION**

- Never adjust or change the parameter values extremely as it will make operation instable.
- When a fixed number is indicated in each digit of a parameter, do not change the value by any means.

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

Parameter group	Main description
Basic setting parameters (No.PA□□)	When using this servo amplifier in the position control mode, make basic setting with these parameters.
Gain/filter parameters (No.PB□□)	Use these parameters when making gain adjustment manually.
Extension setting parameters (No.PC□□)	When using this servo amplifier in the speed control mode or torque control mode, mainly use these parameters.
I/O setting parameters (No.PD□□)	Use these parameters when changing the I/O signals of the servo amplifier.

When using this servo in the position control mode, mainly setting the basic setting parameters (No.PA□□) allows the setting of the basic parameters at the time of introduction.

5.1 Basic setting parameters (No.PA□□)

POINT

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

5.1.1 Parameter list

No.	Symbol	Name	Initial value	Unit	Control mode		
					Position	Speed	Torque
PA01	*STY	Control mode	0000h		○	○	○
PA02	*REG	Regenerative option	0000h		○	○	○
PA03	*ABS	Absolute position detection system	0000h		○		
PA04	*AOP1	Function selection A-1	0000h		○	○	○
PA05	*FBP	Number of command input pulses per revolution	0		○		
PA06	CMX	Electronic gear numerator (Command pulse multiplying factor numerator)	1		○		
PA07	CDV	Electronic gear denominator (Command pulse multiplying factor denominator)	1		○		
PA08	ATU	Auto tuning mode	0001h		○	○	
PA09	RSP	Auto tuning response	12		○	○	
PA10	INP	In-position range	100	pulse	○		
PA11	TLP	Forward rotation torque limit	100.0	%	○	○	○
PA12	TLN	Reverse rotation torque limit	100.0	%	○	○	○
PA13	*PLSS	Command pulse input form	0000h		○		
PA14	*POL	Rotation direction selection	0		○		
PA15	*ENR	Encoder output pulses	4000	pulse/rev	○	○	○

No.	Symbol	Name	Initial value	Unit	Control mode		
					Position	Speed	Torque
PA16		For manufacturer setting	0000h				
PA17			0000h				
PA18			0000h				
PA19	*BLK	Parameter write inhibit	000Bh		○	○	○

5.1.2 Parameter write inhibit

Parameter			Initial value	Unit	Setting range	Control mode		
No.	Symbol	Name				Position	Speed	Torque
PA19	*BLK	Parameter write inhibit	000Bh		Refer to the text.	○	○	○

POINT

- Turn off the power and then on again after setting the parameter to validate the parameter value.

In the factory setting, this servo amplifier allows changes to the basic setting parameter, gain/filter parameter and extension setting parameter settings. With the setting of parameter No.PA19, writing can be disabled to prevent accidental changes.
The following table indicates the parameters which are enabled for reference and writing by the setting of parameter No.PA19. Operation can be performed for the parameters marked ○.

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

5.1.3 Selection of control mode

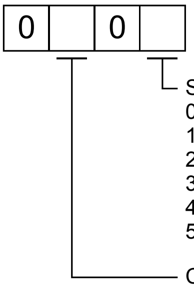
Parameter			Initial value	Unit	Setting range	Control mode		
No.	Symbol	Name				Position	Speed	Torque
PA01	*STY	Control mode	0000h		Refer to the text.	○	○	○

POINT

- Turn off the power and then on again after setting the parameter to validate the parameter value.
- This parameter is supported by a combination of a servo amplifier, whose software version is C6 or later (manufactured in January 2010 or later), and a HF-KP servo motor (manufactured in June 2009 or later). Check the software version using status display or MR Configurator.
- Review the following parameter settings if the 350% maximum torque setting of the HF-KP servo motor has been set valid because these parameter settings are set based on the maximum torque setting.
  - Parameter No.PA11 (forward rotation torque limit)
  - Parameter No.PA12 (reverse rotation torque limit)
  - Parameter No.PC13 (analog torque command maximum output)
  - Parameter No.PC35 (internal torque limit 2)
- A HF-KP servo motor with a decelerator and servo motors except the HF-KP series do not support the 350% maximum torque setting. Making the 350% maximum torque setting valid when using these servo motors causes the parameter error (AL.37).

Set the control mode and control loop composition of the servo amplifier, and the maximum torque of the HF-KP series servo motor.
By making the high-response control valid in the control loop composition, response of the servo can be increased compared to the response under the standard control (factory setting).Moreover, the track ability for a command and the settling time in machines with high rigidity can be decreased. To further shorten the settling time using the auto tuning results of the high-response control, increase the setting of model loop gain (parameter No.PB07) in the manual mode. (Refer to section 7.3.)
By making the 350% maximum torque setting valid, the maximum torque of the HF-KP servo motor can be increased from 300 to 350%. To operate at the maximum torque of 350%, operate within the range of overload protection characteristic. If operated beyond the overload protection characteristic range, servo motor overheat (AL.46), overload 1 (AL.50), and overload 2 (AL.51) may occur.

Parameter No.PA01



Selection of control mode
0: Position control mode
1: Position control mode and speed control mode
2: Speed control mode
3: Speed control mode and torque control mode
4: Torque control mode
5: Torque control mode and position control mode

Control type selection

Setting	Control loop composition	350% maximum torque setting of HF-KP servo motor
0	Standard control	Invalid
3	Standard control	Valid
4	High-response control valid	Invalid
5	High-response control valid	Valid

5.1.4 Selection of regenerative option

Parameter			Initial value	Unit	Setting range	Control mode		
No.	Symbol	Name				Position	Speed	Torque
PA02	*REG	Regenerative option	0000h		Refer to the text.	○	○	○

POINT

- Turn off the power and then on again after setting the parameter to validate the parameter value.
- Incorrect setting may cause the regenerative option to burn.
- If the regenerative option selected is not for use with the servo amplifier, parameter error (AL.37) occurs.
- For a drive unit of 30kW or more, always set the parameter to "□□00" since selecting regenerative option is carried out by the converter unit.

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

Parameter No.PA02

0	0		

Selection of regenerative option
00: Regenerative option is not used
- For servo amplifier of 100W, regenerative resistor is not used.
- For servo amplifier of 200 to 7kW, built-in regenerative resistor is used.
- Supplied regenerative resistors or regenerative option is used with the servo amplifier of 11k to 22kW.
- For a drive unit of 30kW or more, select regenerative option by the converter unit.

01: FR-BU2-(H)･FR-RC-(H)･FR-CV-(H)
02: MR-RB032
03: MR-RB12
04: MR-RB32
05: MR-RB30
06: MR-RB50(Cooling fan is required)
08: MR-RB31
09: MR-RB51(Cooling fan is required)
80: MR-RB1H-4
81: MR-RB3M-4(Cooling fan is required)
82: MR-RB3G-4(Cooling fan is required)
83: MR-RB5G-4(Cooling fanis required)
84: MR-RB34-4(Cooling fanis required)
85: MR-RB54-4(Cooling fanis required)
FA: When the supplied regenerative resistor is cooled by the cooling fan to increase the ability with the servo amplifier of 11k to 22kW.

5.1.5 Using absolute position detection system

Parameter			Initial value	Unit	Setting range	Control mode		
No.	Symbol	Name				Position	Speed	Torque
PA03	*ABS	Absolute position detection system	0000h		Refer to the text.	○		

POINT

- Turn off the power and then on again after setting the parameter to validate the parameter value.

Set this parameter when using the absolute position detection system in the position control mode.

Parameter No.PA03

0	0	0	

Selection of absolute position detection system (Refer to chapter 14)
0: Used in incremental system
1: Used in absolute position detection system
ABS transfer by DI0
2: Used in absolute position detection system
ABS transfer by communication

5.1.6 Using electromagnetic brake interlock (MBR)

Parameter			Initial value	Unit	Setting range	Control mode		
No.	Symbol	Name				Position	Speed	Torque
PA04	*AOP1	Function selection A-1	0000h		Refer to the text.	○	○	○

POINT

- Turn off the power and then on again after setting the parameter to validate the parameter value.

Set this parameter when assigning the electromagnetic brake to the CN1-23 pin.

Parameter No.PA04

0	0	0	

CN1-23 pin function selection
0: Output device assigned with parameter No.PD14
1: Electromagnetic brake interlock (MBR)

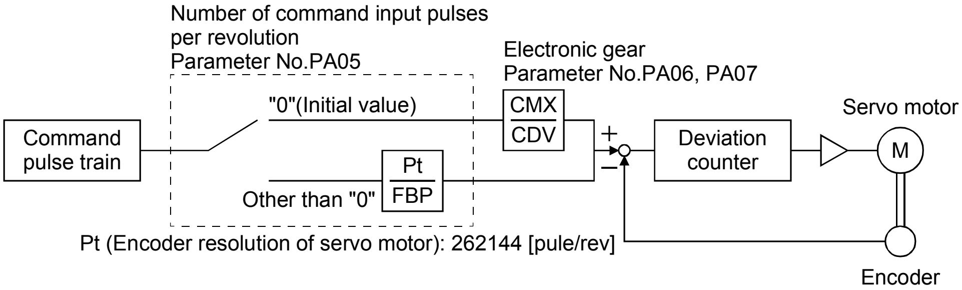
5.1.7 Number of command input pulses per servo motor revolution

Parameter			Initial value	Unit	Setting range	Control mode		
No.	Symbol	Name				Position	Speed	Torque
PA05	*FBP	Number of command input pulses per revolution	0		0 ・ 1000 to 50000	○		

POINT

- Turn off the power and then on again after setting the parameter to validate the parameter value.

When "0" (initial value) is set in parameter No.PA05, the electronic gear (parameter No.PA06, PA07) is made valid. When the setting is other than "0", that value is used as the command input pulses necessary to rotate the servo motor one turn. At this time, the electronic gear is made invalid.



Parameter No.PA05 setting	Description
0	Electronic gear (parameter No.PA06, PA07) is made valid.
1000 to 50000	Number of command input pulses necessary to rotate the servo motor one turn [pulse]

5.1.8 Electronic gear

Parameter			Initial value	Unit	Setting range	Control mode		
No.	Symbol	Name				Position	Speed	Torque
PA06	CMX	Electronic gear numerator (command pulse multiplying factor numerator)	1		1 to 1048576	○		
PA07	CDV	Electronic gear denominator (command pulse multiplying factor denominator)	1		1 to 1048576	○		

⚠CAUTION ▪ Incorrect setting can lead to unexpected fast rotation, causing injury.

POINT

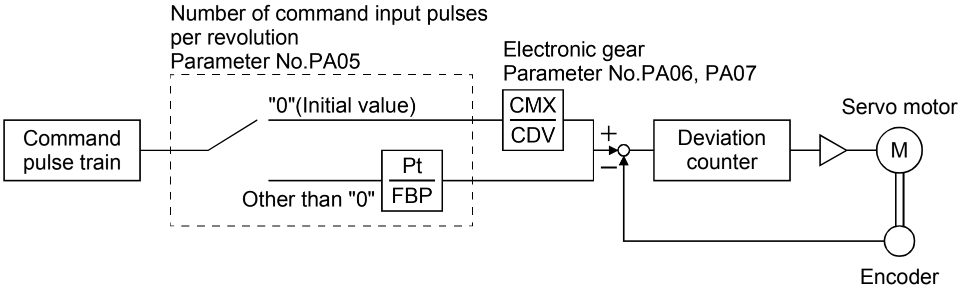
▪ The electronic gear setting range is $\frac{1}{10} < \frac{\text{CMX}}{\text{CDV}} < 2000$.

If the set value is outside this range, noise may be generated during acceleration/ deceleration or operation may not be performed at the preset speed and/or acceleration/deceleration time constants.

▪ Always set the electronic gear with servo off state to prevent unexpected operation due to improper setting.

(1) Concept of electronic gear

The machine can be moved at any multiplication factor to input pulses.



$$\frac{\text{CMX}}{\text{CDV}} = \frac{\text{Parameter No.PA06}}{\text{Parameter No.PA07}}$$

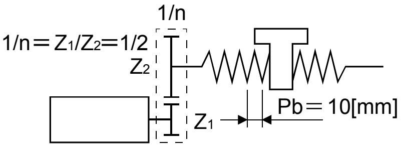
The following setting examples are used to explain how to calculate the electronic gear.

POINT

▪ The following specification symbols are required to calculate the electronic gear

Pb : Ball screw lead [mm]
1/n : Reduction ratio
Pt : Encoder resolution of servo motor [pulses/rev]
$\Delta \ell 0$: Travel per command pulse [mm/pulse]
ΔS : Travel per servo motor revolution [mm/rev]
$\Delta\theta^{\circ}$: Angle per pulse [° /pulse]
$\Delta\theta$: Angle per revolution [° /rev]

(a) For motion in increments of 10μm per pulse



Encoder resolution of servo motor
262144[pulse/rev]

Machine specifications

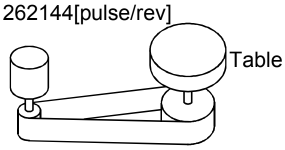
Ball screw lead Pb =10 [mm]
Reduction ratio: 1/n = Z_1/Z_2 = 1/2
Z_1: Number of gear teeth at the servo motor side
Z_2: Number of gear teeth at the load side
Encoder resolution of servo motor: Pt = 262144 [pulse/rev]

$$\frac{CMX}{CDV} = \Delta\ell_0 \cdot \frac{Pt}{\Delta S} = \Delta\ell_0 \cdot \frac{Pt}{n \cdot Pb} = 10 \times 10^{-3} \cdot \frac{262144}{1/2 \cdot 10} = \frac{524288}{1000} = \frac{65536}{125}$$

Hence, set 65538 to CMX and 125 to CDV.

(b) Conveyor setting example
For rotation in increments of 0.01° per pulse

Encoder resolution of servo motor
262144[pulse/rev]



Timing belt: 625/12544

Machine specifications

Table : 360° /rev
Reduction ratio: 1/n = P_1/P_2 = 625/12544
P_1: Pulley diameter at the servo motor side
P_2: Pulley diameter at the load side
Encoder resolution of servo motor: Pt = 262144 [pulse/rev]

$$\frac{CMX}{CDV} = \Delta\theta^{\circ} \cdot \frac{Pt}{\Delta\theta} = 0.01 \cdot \frac{262144}{625/12544 \cdot 360} = \frac{102760448}{703125} \quad \text{(5.1)}$$

Since CMX is not within the setting range in this status, it must be reduced to the lowest term.
When CMX has been reduced to a value within the setting range, round off the value to the nearest unit.

$$\frac{CMX}{CDV} = \frac{102760448}{703125} = \frac{822083.6}{5625} \cong \frac{822084}{5625}$$

Hence, set 822084 to CMX and 5625 to CDV.

POINT

- For unlimited one-way rotation, e.g. an index table, indexing positions will be missed due to cumulative error produced by rounding off.
- For example, entering a command of 36000 pulses in the above example causes the table to rotate only.

$$36000 \cdot \frac{822084}{5625} \cdot \frac{1}{262144} \cdot \frac{625}{12544} \cdot 360^{\circ} = 360.00018^{\circ}$$

- Therefore, indexing cannot be done in the same position on the table.

(2) Instructions for reduction

The calculated value before reduction must be as near as possible to the calculated value after reduction. In the case of (1), (b) in this section, an error will be smaller if reduction is made to provide no fraction for CDV. The fraction of Expression (5.1) before reduction is calculated as follows.

$$\frac{\mathrm{CMX}}{\mathrm{CDV}}=\frac{102760448}{703125}=146.1481927 \quad \cdots\cdots (5.2)$$

The result of reduction to provide no fraction for CMX is as follows.

$$\frac{\mathrm{CMX}}{\mathrm{CDV}}=\frac{102760448}{703125}=\frac{917504}{6277.9}\fallingdotseq\frac{917504}{6278}=146.1459063 \quad \cdots\cdots (5.3)$$

The result of reduction to provide no fraction for CDV is as follows.

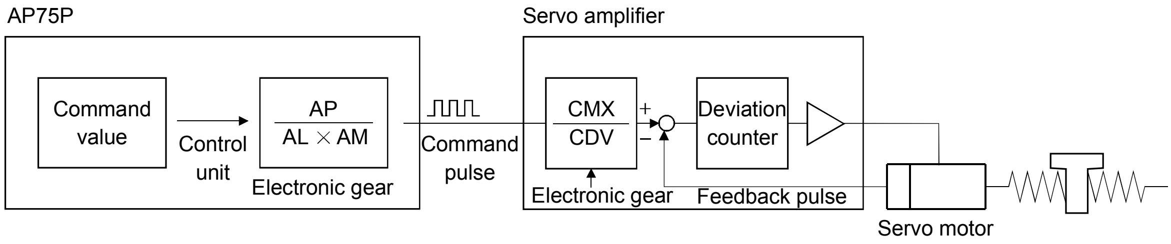
$$\frac{\mathrm{CMX}}{\mathrm{CDV}}=\frac{102760448}{703125}=\frac{822083.6}{5625}\fallingdotseq\frac{822084}{5625}=146.1482667 \quad \cdots\cdots (5.4)$$

As a result, it is understood that the value nearer to the calculation result of Expression (5.2) is the result of Expression (5.4). Accordingly, the set values of (1), (b) in this section are CMX=822084, CDV=5625.

(3) Setting for use of QD75

The QD75 also has the following electronic gear parameters. Normally, the servo amplifier side electronic gear must also be set due to the restriction on the command pulse frequency (differential 1Mpulse/s, open collector 200kpulse/s).

AP: Number of pulses per servo motor revolution
AL: Moving distance per servo motor revolution
AM: Unit scale factor



The encoder resolution of the servo motor is 262144 pulses/rev. For example, the pulse command required to rotate the servo motor is as follows.

Servo motor speed [r/min]	Required pulse command
2000	262144 × 2000/60=8738133 [pulse/s]
3000	262144 × 3000/60=13107200 [pulse/s]

Use the electronic gear of the servo amplifier to rotate the servo motor under the maximum output pulse command of the QD75.

To rotate the servo motor at 3000r/min in the open collector system (200kpulse/s), set the electronic gear as follows.

$$f \cdot \frac{CMX}{CDV} = \frac{N_0}{60} \cdot Pt$$

f : Input pulses frequency [pulse/s]
N_0 : Servo motor speed [r/min]
Pt : Encoder resolution of servo motor [pulse/rev]

$$200 \cdot 10^3 \cdot \frac{CMX}{CDV} = \frac{3000}{60} \cdot 262144$$

$$\frac{CMX}{CDV} = \frac{3000}{60} \cdot \frac{262144}{200 \cdot 10^3} = \frac{3000 \cdot 262144}{60 \cdot 200000} = \frac{8192}{125}$$

The following table indicates the electronic gear setting example (ball screw lead = 10mm) when the QD75 is used in this way.

Rated servo motor speed				3000r/min		2000r/min	
Servo amplifier	Input system			Open collector	Differential line driver	Open collector	Differential line driver
	Max. input pulse frequency [pulse/s]			200k	1M	200k	1M
	Feedback pulse/revolution [pulse/rev]			262144		262144	
	Electronic gear (CMX/CDV)			8192/125	8192/625	16384/375	16384/1875
QD75	Command pulse frequency [kpulse/s] (Note)			200k	1M	200k	1M
	Number of pulses per servo motor revolution as viewed from QD75[pulse/rev]			4000	20000	6000	30000
	Electronic gear	Minimum command unit 1pulse	AP	1	1	1	1
			AL	1	1	1	1
			AM	1	1	1	1
		Minimum command unit 0.1μm	AP	4000	20000	6000	30000
			AL	100.0[μm]	100.0[μm]	100.0[μm]	100.0[μm]
			AM	10	10	10	10

Note. Command pulse frequency at rated speed

POINT

- In addition to the setting method using the electronic gear given here, the number of pulses per servo motor revolution can also be set directly using parameter No.PA05. In this case, parameter No.PA05 is the "Number of pulses per servo motor revolution as viewed from QD75".

5.1.9 Auto tuning

Parameter			Initial value	Unit	Setting range	Control mode		
No.	Symbol	Name				Position	Speed	Torque
PA08	ATU	Auto tuning mode	0001h		Refer to the text.	○	○	
PA09	RSP	Auto tuning response	12		1 to 32	○	○	

Make gain adjustment using auto tuning. Refer to section 7.2 for details.

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

Select the gain adjustment mode.

Parameter No.PA08

0 0 0 ☐

Gain adjustment mode setting

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

Note. The parameters have the following names.

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

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

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

Setting	Response	Guideline for machine resonance frequency [Hz]
1	Low response	10.0
2		11.3
3		12.7
4		14.3
5		16.1
6		18.1
7		20.4
8		23.0
9		25.9
10		29.2
11		32.9
12		37.0
13		41.7
14		47.0
15		52.9
16	Middle response	59.6

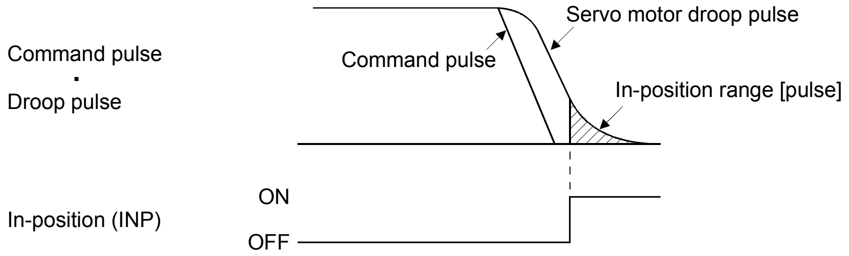
Setting	Response	Guideline for machine resonance frequency [Hz]
17	Middle response	67.1
18		75.6
19		85.2
20		95.9
21		108.0
22		121.7
23		137.1
24		154.4
25		173.9
26		195.9
27		220.6
28		248.5
29		279.9
30		315.3
31		355.1
32	High response	400.0

5.1.10 In-position range

Parameter			Initial value	Unit	Setting range	Control mode		
No.	Symbol	Name				Position	Speed	Torque
PA10	INP	In-position range	100	pulse	0 to 65535 (Note)	○		

Note. For the software version C0 or older servo amplifiers, the setting range is 0 to 10,000.

Set the range, where In-position (INP) is output, in the command pulse unit before calculation of the electronic gear. With the setting of parameter No.PC24, the range can be changed to the encoder output pulse unit.



5.1.11 Torque limit

Parameter			Initial value	Unit	Setting range	Control mode		
No.	Symbol	Name				Position	Speed	Torque
PA11	TLP	Forward rotation torque limit	100.0	%	0 to 100.0	○	○	○
PA12	TLN	Reverse rotation torque limit	100.0	%	0 to 100.0	○	○	○

The torque generated by the servo motor can be limited. Refer to section 3.6.1 (5) and use these parameters. When torque is output with the analog monitor output, the smaller torque of the values in the parameter No.PA11 (forward rotation torque limit) and parameter No.PA12 (reverse rotation torque limit) is the maximum output voltage (8V).

(1) Forward rotation torque limit (parameter No.PA11)
Set this parameter on the assumption that the maximum torque is 100 [%]. Set this parameter when limiting the torque of the servo motor in the CCW driving mode or CW regeneration mode. Set this parameter to "0.0" to generate no torque.

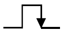
(2) Reverse rotation torque limit (parameter No.PA12)
Set this parameter on the assumption that the maximum torque is 100 [%]. Set this parameter when limiting the torque of the servo motor in the CW driving mode or CCW regeneration mode. Set this parameter to "0.0" to generate no torque.

5.1.12 Selection of command pulse input form

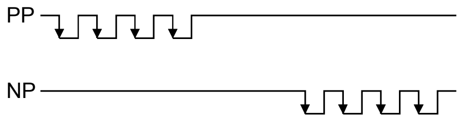
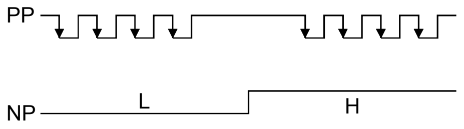
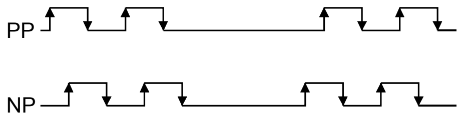
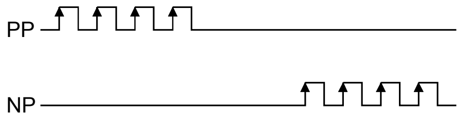
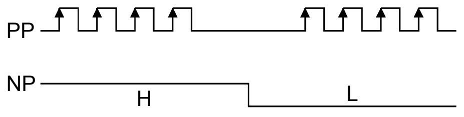
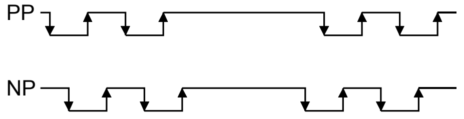
Parameter			Initial value	Unit	Setting range	Control mode		
No.	Symbol	Name				Position	Speed	Torque
PA13	*PLSS	Command pulse input form	0000h		Refer to the text.	○		

POINT

- Turn off the power and then on again after setting the parameter to validate the parameter value.

Select the input form of the pulse train input signal. Command pulses may be input in any of three different forms, for which positive or negative logic can be chosen.
Arrow  or  in the table indicates the timing of importing a pulse train.
A- and B-phase pulse trains are imported after they have been multiplied by 4.

Selection of command pulse input form

Setting	Pulse train form		Forward rotation command	Reverse rotation command
0010h	Negative logic	Forward rotation pulse train Reverse rotation pulse train		
0011h		Signed pulse train		
0012h		A-phase pulse train B-phase pulse train		
0000h	Positive logic	Forward rotation pulse train Reverse rotation pulse train		
0001h		Signed pulse train		
0002h		A-phase pulse train B-phase pulse train		

5.1.13 Selection of servo motor rotation direction

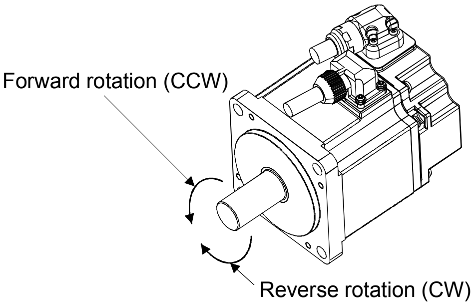
Parameter			Initial value	Unit	Setting range	Control mode		
No.	Symbol	Name				Position	Speed	Torque
PA14	*POL	Rotation direction selection	0		0・1	○		

POINT

- Turn off the power and then on again after setting the parameter to validate the parameter value.

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

Parameter No.PA14 setting	Servo motor rotation direction	
	When forward rotation pulse is input	When reverse rotation pulse is input
0	CCW	CW
1	CW	CCW



5.1.14 Encoder output pulse

Parameter			Initial value	Unit	Setting range	Control mode		
No.	Symbol	Name				Position	Speed	Torque
PA15	*ENR	Encoder output pulse	4000	pulse/rev	1 to 100000	○	○	○

POINT

- Turn off the power and then on again after setting the parameter to validate the parameter value.

Used to set the encoder pulses (A-phase, B-phase) output by the servo amplifier.
Set the value 4 times greater than the A-phase or B-phase pulses.
You can use parameter No.PC19 to choose the output pulse setting or output division ratio setting.
The number of A/B-phase pulses actually output is 1/4 times greater than the preset number of pulses.
The maximum output frequency is 4.6Mpps (after multiplication by 4). Use this parameter within this range.

(1) For output pulse designation

Set "☐☐0☐" (initial value) in parameter No.PC19.

Set the number of pulses per servo motor revolution.

Output pulse = set value [pulses/rev]

For instance, set "5600" to parameter No.PA15, the actually output A/B-phase pulses are as indicated below.

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

(2) For output division ratio setting

Set "☐☐1☐" in parameter No.PC19.

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

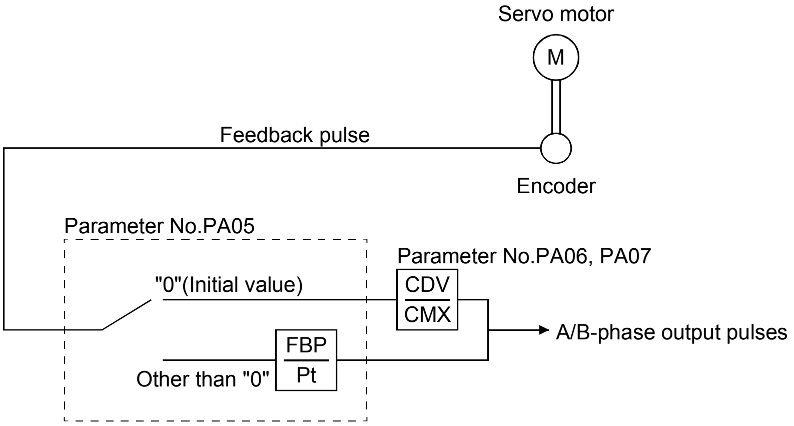
$$\text{Output pulse} = \frac{\text{Resolution per servo motor revolution}}{\text{Set value}} \text{ [pulses/rev]}$$

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

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

(3) When outputting pulse train similar to command pulses

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



5.2 Gain/filter parameters (No.PB□□)

POINT

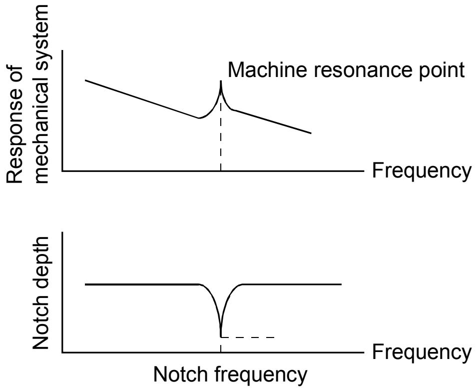
- For any parameter whose symbol is preceded by *, set the parameter value and switch power off once, then switch it on again to make that parameter setting valid.

5.2.1 Parameter list

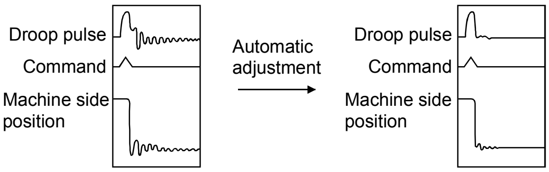
No.	Symbol	Name	Initial value	Unit	Control mode		
					Position	Speed	Torque
PB01	FILT	Adaptive tuning mode (Adaptive filter Ⅱ)	0000h		○	○	
PB02	VRFT	Vibration suppression control tuning mode (Advanced vibration suppression control)	0000h		○		
PB03	PST	Position command acceleration/deceleration time constant (Position smoothing)	0	ms	○		
PB04	FFC	Feed forward gain	0	%	○		
PB05		For manufacturer setting	500				
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment	7.0	Multiplier (×1)	○	○	
PB07	PG1	Model loop gain	24	rad/s	○	○	
PB08	PG2	Position loop gain	37	rad/s	○		
PB09	VG2	Speed loop gain	823	rad/s	○	○	
PB10	VIC	Speed integral compensation	33.7	ms	○	○	
PB11	VDC	Speed differential compensation	980		○	○	
PB12	OVA	Overshoot amount compensation	0	%	○		
PB13	NH1	Machine resonance suppression filter 1	4500	Hz	○	○	
PB14	NHQ1	Notch shape selection 1	0000h		○	○	
PB15	NH2	Machine resonance suppression filter 2	4500	Hz	○	○	
PB16	NHQ2	Notch shape selection 2	0000h		○	○	
PB17		Automatic setting parameter					
PB18	LPF	Low-pass filter setting	3141	rad/s	○	○	
PB19	VRF1	Vibration suppression control vibration frequency setting	100.0	Hz	○		
PB20	VRF2	Vibration suppression control resonance frequency setting	100.0	Hz	○		
PB21		For manufacturer setting	0.00				
PB22			0.00				
PB23	VFBF	Low-pass filter selection	0000h		○	○	
PB24	*MVS	Slight vibration suppression control selection	0000h		○		
PB25	*BOP1	Function selection B-1	0000h		○		
PB26	*CDP	Gain changing selection	0000h		○	○	
PB27	CDL	Gain changing condition	10		○	○	
PB28	CDT	Gain changing time constant	1	ms	○	○	
PB29	GD2B	Gain changing ratio of load inertia moment to servo motor inertia moment	7.0	Multiplier (×1)	○	○	
PB30	PG2B	Gain changing position loop gain	37	rad/s	○		
PB31	VG2B	Gain changing speed loop gain	823	rad/s	○	○	
PB32	VICB	Gain changing speed integral compensation	33.7	ms	○	○	
PB33	VRF1B	Gain changing vibration suppression control vibration frequency setting	100.0	Hz	○		
PB34	VRF2B	Gain changing vibration suppression control resonance frequency setting	100.0	Hz	○		

No.	Symbol	Name	Initial value	Unit	Control mode		
					Position	Speed	Torque
PB35		For manufacturer setting	0.00				
PB36			0.00				
PB37			100				
PB38			0.0				
PB39			0.0				
PB40			0.0				
PB41			1125				
PB42			1125				
PB43			0004h				
PB44			0000h				
PB45	CNHF	Vibration suppression control filter 2	0000h		○		

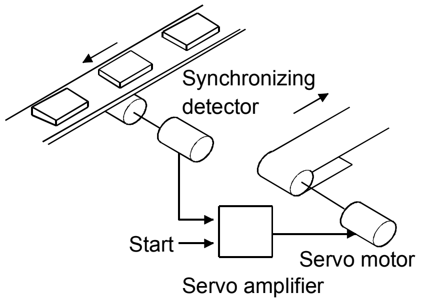
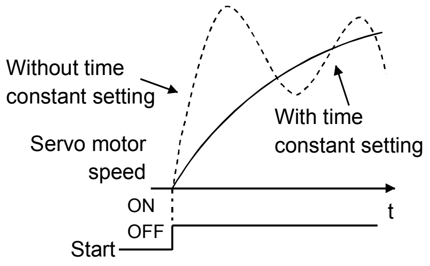
5.2.2 Detail list

<table>
<tr><th rowspan="2">No.</th><th rowspan="2">Symbol</th><th rowspan="2">Name and function</th><th rowspan="2">Initial value</th><th rowspan="2">Unit</th><th rowspan="2">Setting range</th><th colspan="3">Control mode</th></tr>
<tr><th>Position</th><th>Speed</th><th>Torque</th></tr>
<tr><td>PB01</td><td>FILT</td><td>Adaptive tuning mode (adaptive filter Ⅱ)
Select the setting method for filter tuning. Setting this parameter to "□□□1" (filter tuning mode) automatically changes the machine resonance suppression filter 1 (parameter No.PB13) and notch shape selection 1 (parameter No.PB14).

0 0 0 □
Adaptive tuning mode selection
<table><tr><th>Setting</th><th>Adaptive tuning mode</th><th>Automatically set parameter</th></tr><tr><td>0</td><td>Filter OFF</td><td>(Note)</td></tr><tr><td>1</td><td>Filter tuning mode</td><td>Parameter No.PB13
Parameter No.PB14</td></tr><tr><td>2</td><td>Manual mode</td><td></td></tr></table>Note. Parameter No.PB13 and PB14 are fixed to the initial values.

When this parameter is set to "□□□1", the tuning is completed after positioning operation is done the predetermined number or times for the predetermined period of time, and the setting changes to "□□□2". When the adaptive tuning is not necessary, the setting changes to "□□□0". When this parameter is set to "□□□0", the initial values are set to the machine resonance suppression filter 1 and notch shape selection 1. However, this does not occur when the servo off.</td><td>0000h</td><td></td><td>Refer to name and function column.</td><td>○</td><td>○</td><td></td></tr>
</table>

<table>
<tr><th rowspan="2">No.</th><th rowspan="2">Symbol</th><th rowspan="2">Name and function</th><th rowspan="2">Initial value</th><th rowspan="2">Unit</th><th rowspan="2">Setting range</th><th colspan="3">Control mode</th></tr>
<tr><th>Position</th><th>Speed</th><th>Torque</th></tr>
<tr><td>PB02</td><td>VRFT</td><td>
Vibration suppression control tuning mode (advanced vibration suppression control)
The vibration suppression is valid when the parameter No.PA08 (auto tuning mode) setting is "□□□2" or "□□□3". When PA08 is "□□□1", vibration suppression is always invalid.
Select the setting method for vibration suppression control tuning. Setting this parameter to "□□□1" (vibration suppression control tuning mode) automatically changes the vibration suppression control - vibration frequency (parameter No.PB19) and vibration suppression control - resonance frequency (parameter No.PB20) after positioning is done the predetermined number of times.


0 0 0 □
Vibration suppression control tuning mode
<table>
<tr><th>Setting</th><th>Vibration suppression control tuning mode</th><th>Automatically set parameter</th></tr>
<tr><td>0</td><td>Vibration suppression control OFF</td><td>(Note)</td></tr>
<tr><td>1</td><td>Vibration suppression control tuning mode (Advanced vibration suppression control)</td><td>Parameter No.PB19
Parameter No.PB20</td></tr>
<tr><td>2</td><td>Manual mode</td><td></td></tr>
</table>
Note. Parameter No.PB19 and PB20 are fixed to the initial values.
When this parameter is set to "□□□1", the tuning is completed after positioning operation is done the predetermined number or times for the predetermined period of time, and the setting changes to "□□□2". When the vibration suppression control tuning is not necessary, the setting changes to "□□□0". When this parameter is set to "□□□0", the initial values are set to the vibration suppression control - vibration frequency and vibration suppression control - resonance frequency. However, this does not occur when the servo off.
</td><td>0000h</td><td></td><td>Refer to name and function column.</td><td>○</td><td></td><td></td></tr>
</table>

No.	Symbol	Name and function	Initial value	Unit	Setting range	Control mode		
						Position	Speed	Torque
PB03	PST	Position command acceleration/deceleration time constant (position smoothing) Used to set the time constant of a low-pass filter in response to the position command. You can use parameter No.PB25 to choose the primary delay or linear acceleration/deceleration control system. When you choose linear acceleration/deceleration, the setting range is 0 to 10ms. Setting of longer than 10ms is recognized as 10ms. **POINT** ・When you have chosen linear acceleration/deceleration, do not select control selection (parameter No.PA01) and restart after instantaneous power failure (parameter No.PC22). Doing so will cause the servo motor to make a sudden stop at the time of position control switching or restart. (Example) When a command is given from a synchronizing detector, synchronous operation can be started smoothly if started during line operation.   	0	ms	0 to 20000	○		
PB04	FFC	Feed forward gain Set the feed forward gain. When the setting is 100%, the droop pulses during operation at constant speed are nearly zero. However, sudden acceleration/deceleration will increase the overshoot. As a guideline, when the feed forward gain setting is 100%, set 1s or longer as the acceleration time constant up to the rated speed.	0	%	0 to 100	○		

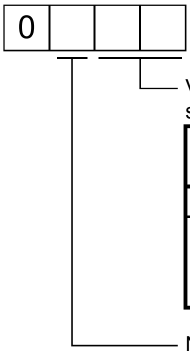
No.	Symbol	Name and function	Initial value	Unit	Setting range	Control mode		
						Position	Speed	Torque
PB05		For manufacturer setting Do not change this value by any means.	500					
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment Used to set the ratio of the load inertia moment to the servo motor shaft inertia moment. When auto tuning mode 1 and interpolation mode is selected, the result of auto tuning is automatically used. (Refer to section 7.1.1) In this case, it varies between 0 and 100.0.	7.0	Multiplier (×1)	0 to 300.0	○	○	
PB07	PG1	Model loop gain Set the response gain up to the target position. Increase the gain to improve track ability in response to the command. When auto turning mode 1・2 is selected, the result of auto turning is automatically used.	24	rad/s	1 to 2000	○	○	
PB08	PG2	Position loop gain Used to set the gain of the position loop. Set this parameter to increase the position response to level load disturbance. Higher setting increases the response level but is liable to generate vibration and/or noise. When auto tuning mode 1・2 and interpolation mode is selected, the result of auto tuning is automatically used.	37	rad/s	1 to 1000	○		
PB09	VG2	Speed loop gain Used to set the gain of the speed loop. Set this parameter when vibration occurs on machines of low rigidity or large backlash. Higher setting increases the response level but is liable to generate vibration and/or noise. When auto tuning mode 1・2, manual mode and interpolation mode is selected, the result of auto tuning is automatically used. Note. The setting range of 50000 applies to the servo amplifier whose software version is A3 or later. The setting range of the servo amplifier whose software version is older than A3 is 20 to 20000. When the software version of MR Configurator is A3 or earlier, 20001 or more cannot be set. Use the display/operation section of the servo amplifier to set 20001 or more.	823	rad/s	20 to 50000 (Note)	○	○	
PB10	VIC	Speed integral compensation Used to set the integral time constant of the speed loop. Lower setting increases the response level but is liable to generate vibration and/or noise. When auto tuning mode 1・2 and interpolation mode is selected, the result of auto tuning is automatically used.	33.7	ms	0.1 to 1000.0	○	○	
PB11	VDC	Speed differential compensation Used to set the differential compensation. Made valid when the proportion control (PC) is switched on.	980		0 to 1000	○	○	

<table>
<tr><th rowspan="2">No.</th><th rowspan="2">Symbol</th><th rowspan="2">Name and function</th><th rowspan="2">Initial value</th><th rowspan="2">Unit</th><th rowspan="2">Setting range</th><th colspan="3">Control mode</th></tr>
<tr><th>Position</th><th>Speed</th><th>Torque</th></tr>
<tr><td>PB12</td><td>OVA
(Note)</td><td>Overshoot amount compensation
Used to suppress overshoot in position control.
Overshoot can be suppressed in machines with high friction.
Set a control ratio against the friction torque in percentage unit.
Overshoot amount compensation can be set as shown in the following table in parameter No.PA01 (control mode).
<table>
<tr><th>Parameter No.PA01</th><th>Overshoot amount compensation</th></tr>
<tr><td>0</td><td rowspan="2">Set value of parameter No.PB12</td></tr>
<tr><td>3</td></tr>
<tr><td>4</td><td rowspan="2">Automatically set (5%) when "0" is set in parameter No.PB12
Set value of parameter No.PB12 when a value other than "0" is set in parameter No.PB12</td></tr>
<tr><td>5</td></tr>
</table>
Note. This parameter is supported by the servo amplifiers whose software versions are C6 or later.
Check the software version using status display or MR Configurator.</td><td>0</td><td>%</td><td>0
to
100</td><td>○</td><td></td><td></td></tr>
<tr><td>PB13</td><td>NH1</td><td>Machine resonance suppression filter 1
Set the notch frequency of the machine resonance suppression filter 1.
Setting parameter No.PB01 (Adaptive tuning mode (Adaptive filter Ⅱ)) to "□□□1" automatically changes this parameter.
When the parameter No.PB01 setting is "□□□0", the setting of this parameter is ignored.</td><td>4500</td><td>Hz</td><td>100
to
4500</td><td>○</td><td>○</td><td></td></tr>
<tr><td>PB14</td><td>NHQ1</td><td>Notch shape selection 1
Used to selection the machine resonance suppression filter 1.
0 □ □ 0
Notch depth selection
<table>
<tr><th>Setting value</th><th>Depth</th><th>Gain</th></tr>
<tr><td>0</td><td>Deep</td><td>−40dB</td></tr>
<tr><td>1</td><td rowspan="2">to</td><td>−14dB</td></tr>
<tr><td>2</td><td>−8dB</td></tr>
<tr><td>3</td><td>Shallow</td><td>−4dB</td></tr>
</table>
Notch width selection
<table>
<tr><th>Setting value</th><th>Width</th><th>α</th></tr>
<tr><td>0</td><td>Standard</td><td>2</td></tr>
<tr><td>1</td><td rowspan="2">to</td><td>3</td></tr>
<tr><td>2</td><td>4</td></tr>
<tr><td>3</td><td>Wide</td><td>5</td></tr>
</table>
Setting parameter No.PB01 (Adaptive tuning mode (Adaptive filter Ⅱ)) to "□□□1" automatically changes this parameter.
When the parameter No.PB01 setting is "□□□0", the setting of this parameter is ignored.</td><td>0000h</td><td></td><td>Refer to name and function column.</td><td>○</td><td>○</td><td></td></tr>
</table>

<table>
<tr><th rowspan="2">No.</th><th rowspan="2">Symbol</th><th rowspan="2">Name and function</th><th rowspan="2">Initial value</th><th rowspan="2">Unit</th><th rowspan="2">Setting range</th><th colspan="3">Control mode</th></tr>
<tr><th>Position</th><th>Speed</th><th>Torque</th></tr>
<tr><td>PB15</td><td>NH2</td><td>Machine resonance suppression filter 2
Set the notch frequency of the machine resonance suppression filter 2.
Set parameter No.PB16 (notch shape selection 2) to "□□□1" to make this parameter valid.</td><td>4500</td><td>Hz</td><td>100
to
4500</td><td>○</td><td>○</td><td></td></tr>
<tr><td>PB16</td><td>NHQ2</td><td>Notch shape selection 2
Select the shape of the machine resonance suppression filter 2.
0 □ □ □
Machine resonance suppression filter 2 selection
0: Invalid
1: Valid
Notch depth selection
<table>
<tr><th>Setting value</th><th>Depth</th><th>Gain</th></tr>
<tr><td>0</td><td>Deep</td><td>−40dB</td></tr>
<tr><td>1</td><td rowspan="2">to</td><td>−14dB</td></tr>
<tr><td>2</td><td>−8dB</td></tr>
<tr><td>3</td><td>Shallow</td><td>−4dB</td></tr>
</table>
Notch width selection
<table>
<tr><th>Setting value</th><th>Width</th><th>α</th></tr>
<tr><td>0</td><td>Standard</td><td>2</td></tr>
<tr><td>1</td><td rowspan="2">to</td><td>3</td></tr>
<tr><td>2</td><td>4</td></tr>
<tr><td>3</td><td>Wide</td><td>5</td></tr>
</table>
</td><td>0000h</td><td></td><td>Refer to name and function column.</td><td>○</td><td>○</td><td></td></tr>
<tr><td>PB17</td><td></td><td>Automatic setting parameter
The value of this parameter is set according to a set value of parameter No.PB06 (Ratio of load inertia moment to servo motor inertia moment).</td><td></td><td></td><td></td><td></td><td></td><td></td></tr>
<tr><td>PB18</td><td>LPF</td><td>Low-pass filter setting
Set the low-pass filter.
Setting parameter No.PB23 (low-pass filter selection) to "□□0□" automatically changes this parameter.
When parameter No.PB23 is set to "□□1□", this parameter can be set manually.</td><td>3141</td><td>rad/s</td><td>100
to
18000</td><td>○</td><td>○</td><td></td></tr>
<tr><td>PB19</td><td>VRF1</td><td>Vibration suppression control vibration frequency setting
Set the vibration frequency for vibration suppression control to suppress low-frequency machine vibration, such as enclosure vibration.
Setting parameter No.PB02 (vibration suppression control tuning mode) to "□□□1" automatically changes this parameter. When parameter No.PB02 is set to "□□□2", this parameter can be set manually.</td><td>100.0</td><td>Hz</td><td>0.1
to
100.0</td><td>○</td><td></td><td></td></tr>
<tr><td>PB20</td><td>VRF2</td><td>Vibration suppression control resonance frequency setting
Set the resonance frequency for vibration suppression control to suppress low-frequency machine vibration, such as enclosure vibration.
Setting parameter No.PB02 (vibration suppression control tuning mode) to "□□□1" automatically changes this parameter. When parameter No.PB02 is set to "□□□2", this parameter can be set manually.</td><td>100.0</td><td>Hz</td><td>0.1
to
100.0</td><td>○</td><td></td><td></td></tr>
<tr><td>PB21</td><td rowspan="2"></td><td>For manufacturer setting</td><td>0.00</td><td rowspan="2"></td><td rowspan="2"></td><td rowspan="2"></td><td rowspan="2"></td><td rowspan="2"></td></tr>
<tr><td>PB22</td><td>Do not change this value by any means.</td><td>0.00</td></tr>
</table>

No.	Symbol	Name and function	Initial value	Unit	Setting range	Control mode		
						Position	Speed	Torque
PB23	VFBF	Low-pass filter selection Select the low-pass filter. 0 0 □ 0 Low-pass filter selection 0: Automatic setting 1: Manual setting (parameter No.PB18 setting) When automatic setting has been selected, select the filter that has the band width close to the one calculated with $\frac{VG2 \cdot 10}{1 + GD2}$ [rad/s]	0000h		Refer to name and function column.	○	○	
PB24	*MVS	Slight vibration suppression control selection Select the slight vibration suppression control. When parameter No.PA08 (auto tuning mode) is set to "□□□3", the slight vibration suppression control is made valid. 0 0 0 □ Slight vibration suppression control selection 0: Invalid 1: Valid	0000h		Refer to name and function column.	○		
PB25	*BOP1	Function selection B-1 Select the control systems for position command acceleration/deceleration time constant (parameter No.PB03). 0 0 □ 0 Control of position command acceleration/deceleration time constant 0: Primary delay 1: Linear acceleration/deceleration When linear acceleration/deceleration is selected, do not execute control switching after instantaneous power failure. The servo motor will make a sudden stop during the control switching or automatic restart.	0000h		Refer to name and function column.	○		
PB26	*CDP	Gain changing selection Select the gain changing condition. (Refer to section 8.6.) 0 0 □ □ Gain changing selection Under any of the following conditions, the gains change on the basis of the parameter No.PB29 to PB34 settings. 0: Invalid 1: Input device (Gain changing (CDP)) 2: Command frequency (Parameter No.PB27 setting) 3: Droop pulse (Parameter No.PB27 setting) 4: Servo motor speed (Parameter No.PB27 setting) Gain changing condition 0: Valid when the input device (gain changing (CDP)) is ON, or valid when the value is equal to or larger than the value set in parameter No.PB27 1: Valid when the input device (gain changing (CDP)) is OFF, or valid when the value is equal to or smaller than the value set in parameter No.PB27	0000h		Refer to name and function column.	○	○	

No.	Symbol	Name and function	Initial value	Unit	Setting range	Control mode		
						Position	Speed	Torque
PB27	CDL	Gain changing condition Used to set the value of gain changing condition (command frequency, droop pulses, servo motor speed) selected in parameter No.PB26.The set value unit changes with the changing condition item. (Refer to section 8.6.)	10	kpps pulse r/min	0 to 9999	○	○	
PB28	CDT	Gain changing time constant Used to set the time constant at which the gains will change in response to the conditions set in parameters No.PB26 and PB27. (Refer to section 8.6.)	1	ms	0 to 100	○	○	
PB29	GD2B	Gain changing ratio of load inertia moment to servo motor inertia moment Used to set the ratio of load inertia moment to servo motor inertia moment when gain changing is valid. This parameter is made valid when the auto tuning is invalid (parameter No.PA08: □□□3).	7.0	Multi-plier (×1)	0 to 300.0	○	○	
PB30	PG2B	Gain changing position loop gain Set the position loop gain when the gain changing is valid. This parameter is made valid when the auto tuning is invalid (parameter No.PA08: □□□3).	37	rad/s	1 to 2000	○		
PB31	VG2B	Gain changing speed loop gain Set the speed loop gain when the gain changing is valid. This parameter is made valid when the auto tuning is invalid (parameter No.PA08: □□□3). Note. The setting range of 50000 applies to the servo amplifier whose software version is A3 or later. The setting range of the servo amplifier whose software version is older than A3 is 20 to 20000. When the software version of MR Configurator is A3 or earlier, 20001 or more cannot be set. Use the display/operation section of the servo amplifier to set 20001 or more.	823	rad/s	20 to 20000	○	○	
PB32	VICB	Gain changing speed integral compensation Set the speed integral compensation when the gain changing is valid. This parameter is made valid when the auto tuning is invalid (parameter No.PA08: □□□3).	33.7	ms	0.1 to 5000.0	○	○	
PB33	VRF1B	Gain changing vibration suppression control - vibration frequency setting Set the vibration frequency for vibration suppression control when the gain changing is valid. This parameter is made valid when the parameter No.PB02 setting is "□□□2" and the parameter No.PB26 setting is "□□□1". When using the vibration suppression control gain changing, always execute the changing after the servo motor has stopped.	100.0	Hz	0.1 to 100.0	○		
PB34	VRF2B	Gain changing vibration suppression control - resonance frequency setting Set the resonance frequency for vibration suppression control when the gain changing is valid. This parameter is made valid when the parameter No.PB02 setting is "□□□2" and the parameter No.PB26 setting is "□□□1". When using the vibration suppression control gain changing, always execute the changing after the servo motor has stopped.	100.0	Hz	0.1 to 100.0	○		

<table>
<tr><th rowspan="2">No.</th><th rowspan="2">Symbol</th><th rowspan="2">Name and function</th><th rowspan="2">Initial value</th><th rowspan="2">Unit</th><th rowspan="2">Setting range</th><th colspan="3">Control mode</th></tr>
<tr><th>Position</th><th>Speed</th><th>Torque</th></tr>
<tr><td>PB35</td><td rowspan="10"></td><td rowspan="10">For manufacturer setting
Do not change this value by any means.</td><td>0.00</td><td rowspan="10"></td><td rowspan="10"></td><td rowspan="10"></td><td rowspan="10"></td><td rowspan="10"></td></tr>
<tr><td>PB36</td><td>0.00</td></tr>
<tr><td>PB37</td><td>100</td></tr>
<tr><td>PB38</td><td>0.0</td></tr>
<tr><td>PB39</td><td>0.0</td></tr>
<tr><td>PB40</td><td>0.0</td></tr>
<tr><td>PB41</td><td>1125</td></tr>
<tr><td>PB42</td><td>1125</td></tr>
<tr><td>PB43</td><td>0004h</td></tr>
<tr><td>PB44</td><td>0000h</td></tr>
<tr><td>PB45</td><td>CNHF
(Note 1)</td><td>Vibration suppression control filter 2
Used to set the vibration suppression control filter 2.
By setting this parameter, machine side vibration, such as workpiece end vibration and base shake, can be suppressed.


Vibration suppression control filter 2 setting frequency selection (Note 2)
<table>
<tr><th>Setting value</th><th>Frequency [Hz]</th></tr>
<tr><td>0</td><td>Invalid</td></tr>
<tr><td>1
to
5F</td><td>2250
to
4.5</td></tr>
</table>
Notch depth selection (Note 2)
<table>
<tr><th>Setting value</th><th>Depth</th></tr>
<tr><td>0
to
F</td><td>−40.0dB
to
−0.6dB</td></tr>
</table>
Note 1. This parameter is supported by the servo amplifiers whose software versions are C6 or later. Check the software version using status display or MR Configurator.
2. Refer to section 8.7 for the setting details.</td><td>0000h</td><td></td><td>Refer to name and function column.</td><td>○</td><td></td><td></td></tr>
</table>

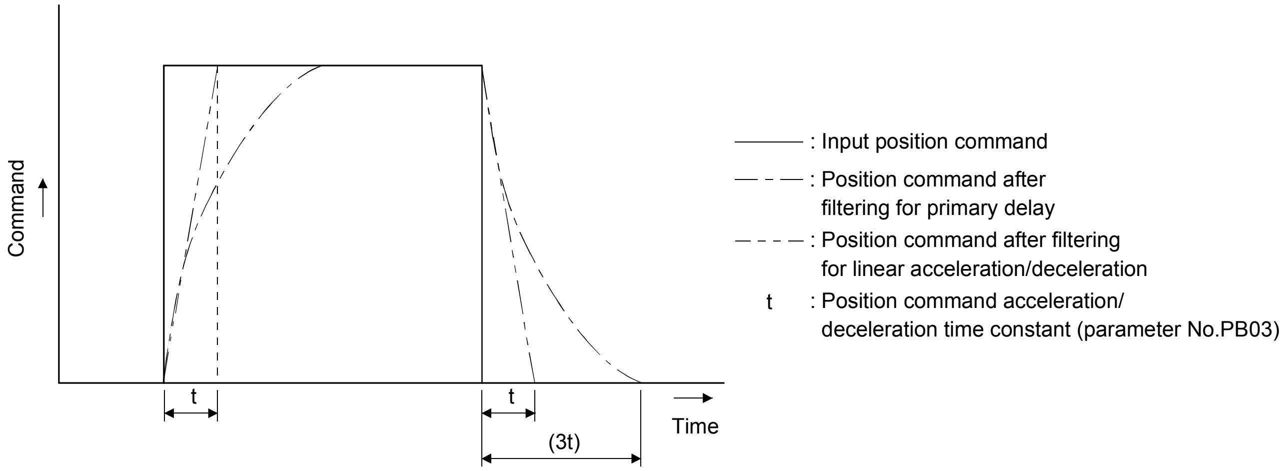
5.2.3 Position smoothing

By setting the position command acceleration/deceleration time constant (parameter No.PB03), you can run the servo motor smoothly in response to a sudden position command.

The following diagrams show the operation patterns of the servo motor in response to a position command when you have set the position command acceleration/deceleration time constant.

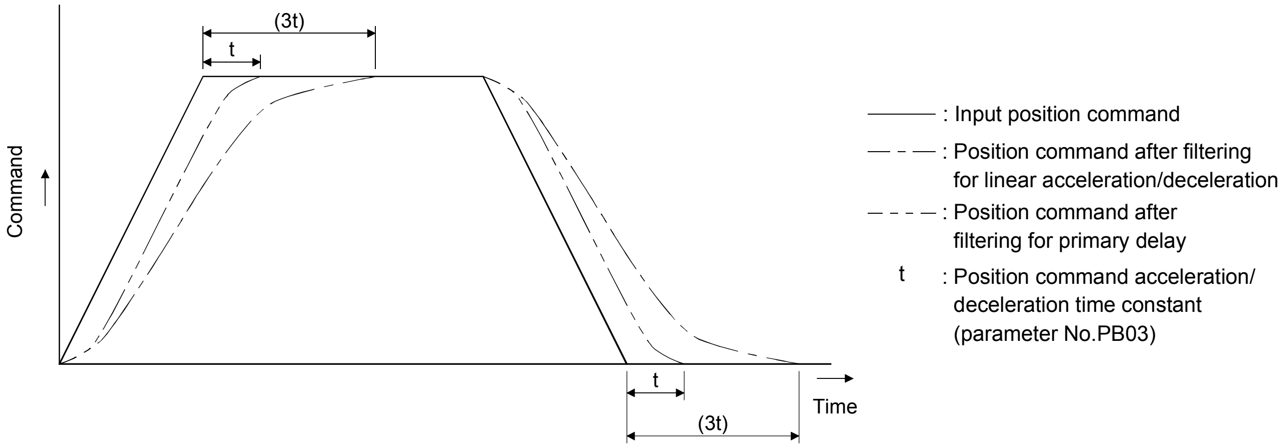
Choose the primary delay or linear acceleration/deceleration in parameter No.PB25 according to the machine used.

(1) For step input



(2) For trapezoidal input

For trapezoidal input (linear acceleration/deceleration), the setting range is 0 to 10ms.



5.3 Extension setting parameters (No.PC□□)

POINT

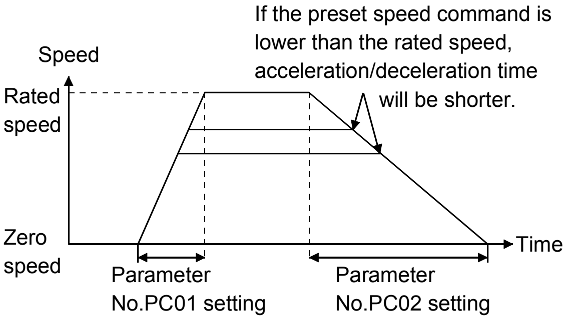
- For any parameter whose symbol is preceded by *, set the parameter value and switch power off once, then switch it on again to make that parameter setting valid.

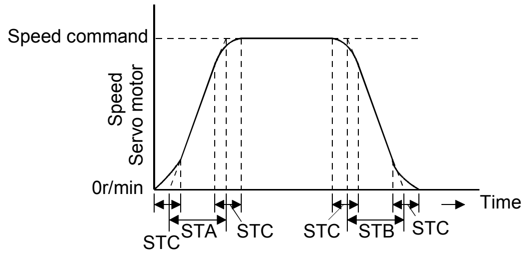
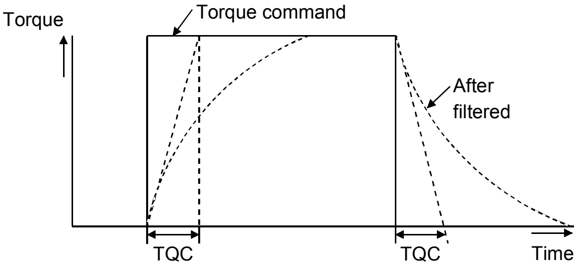
5.3.1 Parameter list

No.	Symbol	Name	Initial value	Unit	Control mode		
					Position	Speed	Torque
PC01	STA	Acceleration time constant	0	ms		○	○
PC02	STB	Deceleration time constant	0	ms		○	○
PC03	STC	S-pattern acceleration/deceleration time constant	0	ms		○	○
PC04	TQC	Torque command time constant	0	ms			○
PC05	SC1	Internal speed command 1	100	r/min		○	
		Internal speed limit 1					○
PC06	SC2	Internal speed command 2	500	r/min		○	
		Internal speed limit 2					○
PC07	SC3	Internal speed command 3	1000	r/min		○	
		Internal speed limit 3					○
PC08	SC4	Internal speed command 4	200	r/min		○	
		Internal speed limit 4					○
PC09	SC5	Internal speed command 5	300	r/min		○	
		Internal speed limit 5					○
PC10	SC6	Internal speed command 6	500	r/min		○	
		Internal speed limit 6					○
PC11	SC7	Internal speed command 7	800	r/min		○	
		Internal speed limit 7					○
PC12	VCM	Analog speed command maximum speed	0	r/min		○	
		Analog speed limit maximum speed					○
PC13	TLC	Analog torque command maximum output	100.0	%			○
PC14	MOD1	Analog monitor 1 output	0000h		○	○	○
PC15	MOD2	Analog monitor 2 output	0001h		○	○	○
PC16	MBR	Electromagnetic brake sequence output	100	ms	○	○	○
PC17	ZSP	Zero speed	50	r/min	○	○	○
PC18	*BPS	Alarm history clear	0000h		○	○	○
PC19	*ENRS	Encoder output pulses selection	0000h		○	○	○
PC20	*SNO	Station number setting	0	station	○	○	○
PC21	*SOP	Communication function selection	0000h		○	○	○
PC22	*COP1	Function selection C-1	0000h		○	○	○
PC23	*COP2	Function selection C-2	0000h			○	○
PC24	*COP3	Function selection C-3	0000h		○		
PC25		For manufacturer setting	0000h				
PC26	*COP5	Function selection C-5	0000h		○	○	
PC27	*COP6	Function selection C-6	0000h		○	○	○
PC28		For manufacturer setting	0000h				
PC29			0000h				
PC30	STA2	Acceleration time constant 2	0	ms		○	○
PC31	STB2	Deceleration time constant 2	0	ms		○	○
PC32	CMX2	Command pulse multiplying factor numerator 2	1		○		
PC33	CMX3	Command pulse multiplying factor numerator 3	1		○		

No.	Symbol	Name	Initial value	Unit	Control mode		
					Position	Speed	Torque
PC34	CMX4	Command pulse multiplying factor numerator 4	1		○		
PC35	TL2	Internal torque limit 2	100.0	%	○	○	○
PC36	*DMD	Status display selection	0000h		○	○	○
PC37	VCO	Analog speed command offset	0	mV		○	
		Analog speed limit offset					○
PC38	TPO	Analog torque command offset	0	mV			○
		Analog torque limit offset				○	
PC39	MO1	Analog monitor 1 offset	0	mV	○	○	○
PC40	MO2	Analog monitor 2 offset	0	mV	○	○	○
PC41		For manufacturer setting	0				
PC42			0				
PC43			0000h				
PC44			0000h				
PC45			0000h				
PC46			0000h				
PC47			0000h				
PC48			0000h				
PC49			0000h				
PC50			0000h				

5.3.2 List of details

No.	Symbol	Name and function	Initial value	Unit	Setting range	Control mode		
						Position	Speed	Torque
PC01	STA	Acceleration time constant Used to set the acceleration time required to reach the rated speed from 0r/min in response to the analog speed command and internal speed commands 1 to 7.  For example for the servo motor of 3000r/min rated speed, set 3000 (3s) to increase speed from 0r/min to 1000r/min in 1 second.	0	ms	0 to 50000		○	○
PC02	STB	Deceleration time constant Used to set the deceleration time required to reach 0r/min from the rated speed in response to the analog speed command and internal speed commands 1 to 7.	0	ms	0 to 50000		○	○

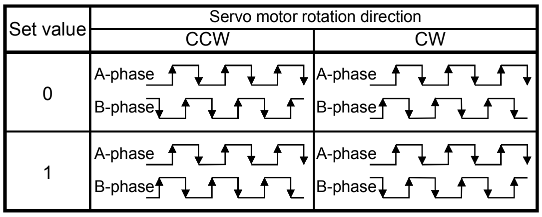
No.	Symbol	Name and function	Initial value	Unit	Setting range	Control mode		
						Position	Speed	Torque
PC03	STC	S-pattern acceleration/deceleration time constant Used to smooth start/stop of the servo motor. Set the time of the arc part for S-pattern acceleration/ deceleration.  STA: Acceleration time constant (parameter No.PC01) STB: Deceleration time constant (parameter No.PC02) STC: S-pattern acceleration/deceleration time constant (parameter No.PC03) Long setting of STA (acceleration time constant) or STB (deceleration time constant) may produce an error in the time of the arc part for the setting of the S-pattern acceleration/deceleration time constant. The upper limit value of the actual arc part time is limited by $\frac{2000000}{\mathrm{STA}}$ for acceleration or by $\frac{2000000}{\mathrm{STB}}$ for deceleration. (Example) At the setting of STA=20000, STB=5000 and STC=200, the actual arc part times are as follows. During acceleration: 100[ms] $\left(\text{Limited to 100[ms] since } \frac{2000000}{20000} = 100[\text{ms}] < 200[\text{ms}]. \right)$ During deceleration: 200[ms] $\left(\text{200[ms] as set since } \frac{2000000}{5000} = 400[\text{ms}] > 200[\text{ms}]. \right)$	0	ms	0 to 1000		○	○
PC04	TQC	Torque command time constant Used to set the constant of a low-pass filter in response to the torque command.  TQC: Torque command time constant	0	ms	0 to 20000			○
PC05	SC1	Internal speed command 1 Used to set speed 1 of internal speed commands.	100	r/min	0 to instan-taneous permi-ssible speed		○	
		Internal speed limit 1 Used to set speed 1 of internal speed limits.						○

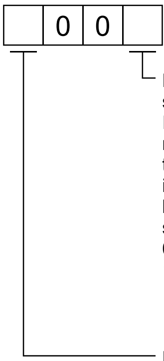
<table>
<tr><th rowspan="2">No.</th><th rowspan="2">Symbol</th><th rowspan="2">Name and function</th><th rowspan="2">Initial value</th><th rowspan="2">Unit</th><th rowspan="2">Setting range</th><th colspan="3">Control mode</th></tr>
<tr><th>Position</th><th>Speed</th><th>Torque</th></tr>
<tr><td rowspan="2">PC06</td><td rowspan="2">SC2</td><td>Internal speed command 2
Used to set speed 2 of internal speed commands.</td><td rowspan="2">500</td><td rowspan="2">r/min</td><td rowspan="2">0 to instantaneous permissible speed</td><td></td><td>○</td><td></td></tr>
<tr><td>Internal speed limit 2
Used to set speed 2 of internal speed limits.</td><td></td><td></td><td>○</td></tr>
<tr><td rowspan="2">PC07</td><td rowspan="2">SC3</td><td>Internal speed command 3
Used to set speed 3 of internal speed commands.</td><td rowspan="2">1000</td><td rowspan="2">r/min</td><td rowspan="2">0 to instantaneous permissible speed</td><td></td><td>○</td><td></td></tr>
<tr><td>Internal speed limit 3
Used to set speed 3 of internal speed limits.</td><td></td><td></td><td>○</td></tr>
<tr><td rowspan="2">PC08</td><td rowspan="2">SC4</td><td>Internal speed command 4
Used to set speed 4 of internal speed commands.</td><td rowspan="2">200</td><td rowspan="2">r/min</td><td rowspan="2">0 to instantaneous permissible speed</td><td></td><td>○</td><td></td></tr>
<tr><td>Internal speed limit 4
Used to set speed 4 of internal speed limits.</td><td></td><td></td><td>○</td></tr>
<tr><td rowspan="2">PC09</td><td rowspan="2">SC5</td><td>Internal speed command 5
Used to set speed 5 of internal speed commands.</td><td rowspan="2">300</td><td rowspan="2">r/min</td><td rowspan="2">0 to instantaneous permissible speed</td><td></td><td>○</td><td></td></tr>
<tr><td>Internal speed limit 5
Used to set speed 5 of internal speed limits.</td><td></td><td></td><td>○</td></tr>
<tr><td rowspan="2">PC10</td><td rowspan="2">SC6</td><td>Internal speed command 6
Used to set speed 6 of internal speed commands.</td><td rowspan="2">500</td><td rowspan="2">r/min</td><td rowspan="2">0 to instantaneous permissible speed</td><td></td><td>○</td><td></td></tr>
<tr><td>Internal speed limit 6
Used to set speed 6 of internal speed limits.</td><td></td><td></td><td>○</td></tr>
<tr><td rowspan="2">PC11</td><td rowspan="2">SC7</td><td>Internal speed command 7
Used to set speed 7 of internal speed commands.</td><td rowspan="2">800</td><td rowspan="2">r/min</td><td rowspan="2">0 to instantaneous permissible speed</td><td></td><td>○</td><td></td></tr>
<tr><td>Internal speed limit 7
Used to set speed 7 of internal speed limits.</td><td></td><td></td><td>○</td></tr>
<tr><td rowspan="2">PC12</td><td rowspan="2">VCM</td><td>Analog speed command maximum speed
Used to set the speed at the maximum input voltage (10V) of the analog speed command (VC).
When "0" is set, the analog speed command maximum speed would be the rated speed of the servo motor connected.
The speed is as indicated below for motorless operation of test operation.
<table>
<tr><th colspan="2">Servo amplifier capacity [W]</th><th>Servo motor speed [r/min]</th></tr>
<tr><td>100V class</td><td>100 to 400</td><td rowspan="2">3000</td></tr>
<tr><td rowspan="2">200V class</td><td>100 to 750</td></tr>
<tr><td>1k to 37k</td><td rowspan="2">2000</td></tr>
<tr><td>400V class</td><td>600 to 55k</td></tr>
</table></td><td>0</td><td>
r/min</td><td>0
1 to 50000</td><td></td><td>○</td><td></td></tr>
<tr><td>Analog speed limit maximum speed
Used to set the speed at the maximum input voltage (10V) of the analog speed limit (VLA).
Set "0" to select the rated speed of the servo motor connected.</td><td>0</td><td>
r/min</td><td>0
1 to 50000</td><td></td><td></td><td>○</td></tr>
</table>

<table>
<tr><th rowspan="2">No.</th><th rowspan="2">Symbol</th><th rowspan="2">Name and function</th><th rowspan="2">Initial value</th><th rowspan="2">Unit</th><th rowspan="2">Setting range</th><th colspan="3">Control mode</th></tr>
<tr><th>Position</th><th>Speed</th><th>Torque</th></tr>
<tr><td>PC13</td><td>TLC</td><td>Analog torque command maximum output
Used to set the output torque at the analog torque command voltage (TC = ±8V) of +8V on the assumption that the maximum torque is 100[%]. For example, set 50 to output (maximum torque × 50/100) at the TC of +8V.</td><td>100.0</td><td>%</td><td>0
to
1000.0</td><td></td><td></td><td>○</td></tr>
<tr><td>PC14</td><td>MOD1</td><td>Analog monitor 1 output
Used to selection the signal provided to the analog monitor 1 (MO1) output. (Refer to section 5.3.3.)

0 0 0 □
Analog monitor 1 (MO1) output selection
<table>
<tr><th>Setting</th><th>Item</th></tr>
<tr><td>0</td><td>Servo motor speed (±8V/max. speed)</td></tr>
<tr><td>1</td><td>Torque (±8V/max. torque) (Note 2)</td></tr>
<tr><td>2</td><td>Servo motor speed (+8V/max. speed)</td></tr>
<tr><td>3</td><td>Torque (+8V/max. torque) (Note 2)</td></tr>
<tr><td>4</td><td>Current command (±8V/max. current command)</td></tr>
<tr><td>5</td><td>Command pulse frequency (±10V/1Mpps)</td></tr>
<tr><td>6</td><td>Droop pulses (±10V/100 pulses) (Note 1)</td></tr>
<tr><td>7</td><td>Droop pulses (±10V/1000 pulses) (Note 1)</td></tr>
<tr><td>8</td><td>Droop pulses (±10V/10000 pulses) (Note 1)</td></tr>
<tr><td>9</td><td>Droop pulses (±10V/100000 pulses) (Note 1)</td></tr>
<tr><td>A</td><td>Feedback position (±10V/1 Mpulses) (Note 1)</td></tr>
<tr><td>B</td><td>Feedback position (±10V/10 Mpulses) (Note 1)</td></tr>
<tr><td>C</td><td>Feedback position (±10V/100 Mpulses) (Note 1)</td></tr>
<tr><td>D</td><td>Bus voltage (±8V/400V) (Note 3)</td></tr>
</table>
Note1. Encoder pulse unit.
2. 8V is outputted at the maximum torque. However, when parameter No.PA11・PA12 are set to limit torque, 8V is outputted at the torque highly limited.
3. For 400V class servo amplifier, the bus voltage becomes +8V/800V.</td><td>0000h</td><td></td><td>Refer to name and function column.</td><td>○</td><td>○</td><td>○</td></tr>
<tr><td>PC15</td><td>MOD2</td><td>Analog monitor 2 output
Used to selection the signal provided to the analog monitor 2 (MO2) output. (Refer to section 5.3.3.)

0 0 0 □
Select the analog monitor 2 (MO2) output
The settings are the same as those of parameter No.PC14.</td><td>0001h</td><td></td><td>Refer to name and function column.</td><td>○</td><td>○</td><td>○</td></tr>
<tr><td>PC16</td><td>MBR</td><td>Electromagnetic brake sequence output
Used to set the delay time (Tb) between electronic brake interlock (MBR) and the base drive circuit is shut-off.</td><td>100</td><td>ms</td><td>0
to
1000</td><td>○</td><td>○</td><td>○</td></tr>
<tr><td>PC17</td><td>ZSP</td><td>Zero speed
Used to set the output range of the zero speed detection (ZSP).
Zero speed detection (ZSP) has hysteresis width of 20r/min (refer to section 3.5 (1) (b)).</td><td>50</td><td>r/min</td><td>0
to
10000</td><td>○</td><td>○</td><td>○</td></tr>
</table>

No.	Symbol	Name and function	Initial value	Unit	Setting range	Control mode		
						Position	Speed	Torque
PC18	*BPS	Alarm history clear Used to clear the alarm history. 0 0 0 ☐ Alarm history clear 0: Invalid 1: Valid When alarm history clear is made valid, the alarm history is cleared at next power-on. After the alarm history is cleared, the setting is automatically made invalid (reset to 0).	0000h		Refer to name and function column.	○	○	○
PC19	*ENRS	Encoder output pulses selection Use to select the, encoder output pulses direction and encoder output pulses setting. 0 0 ☐ ☐ Encoder output pulses phase changing Changes the phases of A/B-phase encoder output pulses.  Encoder output pulses setting selection (refer to parameter No.PA15) 0: Output pulses setting 1: Division ratio setting 2: Ratio is automatically set to command pulse unit Setting "2" makes the parameter No.PA15 (encoder output pulses) setting invalid.	0000h		Refer to name and function column.	○	○	○
PC20	*SNO	Station number setting Used to specify the station number for serial communication. Always set one station to one axis of servo amplifier. If one station number is set to two or more stations, normal communication cannot be made.	0	station	0 to 31	○	○	○
PC21	*SOP	Communication function selection Select the communication I/F and select the RS-422 communication conditions. 0 ☐ ☐ 0 RS-422 communication baud rate selection 0: 9600 [bps] 1: 19200 [bps] 2: 38400 [bps] 3: 57600 [bps] 4: 115200[bps] RS-422 communication response delay time 0: Invalid 1: Valid, reply sent after delay time of 800 μs or longer	0000h		Refer to name and function column.	○	○	○

No.	Symbol	Name and function	Initial value	Unit	Setting range	Control mode		
						Position	Speed	Torque
PC22	*COP1	Function selection C-1 Select the execution of automatic restart after instantaneous power failure selection, and encoder cable communication system selection.  Restart after instantaneous power failure selection If the power supply voltage has returned to normal after an undervoltage status caused by the reduction of the input power supply voltage in the speed control mode, the servo motor can be restarted by merely turning on the start signal without resetting the alarm. 0: Invalid (Undervoltage alarm (AL.10) occurs.) 1: Valid (If this function is enabled for the drive unit of 30kW or more, the parameter error (AL.37) occurs.) Encoder cable communication system selection 0: Two-wire type 1: Four-wire type Incorrect setting will result in an encoder error 1 (At power ON) (AL.16). Refer to section 12.1.2 for the communication method of the encoder cable.	0000h		Refer to name and function column.	 ○	○ ○	 ○

No.	Symbol	Name and function	Initial value	Unit	Setting range	Control mode		
						Position	Speed	Torque
PC23	*COP2	Function selection C-2 Select the servo lock at speed control mode stop, the VC-VLA voltage averaging, and the speed limit in torque control mode. □ □ 0 □ Selection of servo lock at stop In the speed control mode, the servo motor shaft can be locked to prevent the shaft from being moved by the external force. 0: Valid (Servo-locked) The operation to maintain the stop position is performed. 1: Invalid (Not servo-locked) The stop position is not maintained. The control to make the speed 0r/min is performed.	0000h		Refer to name and function column.		○	
		VC/VLA voltage averaging Used to set the filtering time when the analog speed command (VC) voltage or analog speed limit (VLA) is imported. Set 0 to vary the speed to voltage fluctuation in real time. Increase the set value to vary the speed slower to voltage fluctuation. Set value: Filtering time [ms] 0: 0 1: 0.444 2: 0.888 3: 1.777 4: 3.555 5: 7.111					○	○
		Selection of speed limit for torque control 0: Valid 1: Invalid Do not use this function except when configuring a speed loop externally. If the speed limit is invalid, the following parameters can be used. Parameter No.PB01 (Adaptive tuning mode (Adaptive filter Ⅱ)) Parameter No.PB13 (machine resonance suppression filter 1) Parameter No.PB14 (notch shape selection 1) Parameter No.PB15 (machine resonance suppression filter 2) Parameter No.PB16 (notch shape selection 2)						○
PC24	*COP3	Function selection C-3 Select the unit of the in-position range. 0 0 0 □ In-position range unit selection 0: Command input pulse unit 1: Servo motor encoder pulse unit	0000h		Refer to name and function column.	○		
PC25		For manufacturer setting Do not change this value by any means.	0000h					

No.	Symbol	Name and function	Initial value	Unit	Setting range	Control mode		
						Position	Speed	Torque
PC26	*COP5	Function selection C-5 Select the stroke limit warning (AL. 99). 0 0 0 □ Stroke limit warning (AL. 99) selection 0: Valid 1: Invalid When this parameter is set to "1", AL. 99 will not occur if the forward rotation stroke end (LSP) or reverse rotation stroke end (LSN) turns OFF.	0000h		Refer to name and function column.	○	○	
PC27	*COP6	Function selection C-6 Set this function if undervoltage alarm occurs because of distorted power supply voltage waveform when using power regenerative converter or power regenerative common converter. 0 0 0 □ Setting when undervoltage alarm occurs 0: Initial value (Waveform of power supply voltage is not distorted) 1: Set "1" if undervoltage alarm occurs because of distorted power supply voltage waveform when using power regenerative converter or power regenerative common converter.	0000h		Refer to name and function column.	○	○	○
PC28		For manufacturer setting	0000h					
PC29		Do not change this value by any means.	0000h					
PC30	STA2	Acceleration time constant 2 This parameter is made valid when the acceleration/deceleration selection (STAB2) is turned ON. Used to set the acceleration time required to reach the rated speed from Or/min in response to the analog speed command and internal speed commands 1 to 7.	0	ms	0 to 50000		○	○
PC31	STB2	Deceleration time constant 2 This parameter is made valid when the acceleration/deceleration selection (STAB2) is turned ON. Used to set the deceleration time required to reach Or/min from the rated speed in response to the analog speed command and internal speed commands 1 to 7.	0	ms	0 to 50000		○	○
PC32	CMX2	Command pulse multiplying factor numerator 2 Available when the parameter No.PA05 is set to "0".	1		1 to 65535	○		
PC33	CMX3	Command pulse multiplying factor numerator 3 Available when the parameter No.PA05 is set to "0".	1		1 to 65535	○		
PC34	CMX4	Command pulse multiplying factor numerator 4 Available when the parameter No.PA05 is set to "0".	1		1 to 65535	○		

<table>
<tr><th rowspan="2">No.</th><th rowspan="2">Symbol</th><th rowspan="2">Name and function</th><th rowspan="2">Initial value</th><th rowspan="2">Unit</th><th rowspan="2">Setting range</th><th colspan="3">Control mode</th></tr>
<tr><th>Position</th><th>Speed</th><th>Torque</th></tr>
<tr><td>PC35</td><td>TL2</td><td>Internal torque limit 2
Set this parameter to limit servo motor torque on the assumption that the maximum torque is 100[%].
When 0 is set, torque is not produced.
When torque is output in analog monitor output, this set value is the maximum output voltage (8V). (Refer to section 3.6.1 (5)).</td><td>100.0</td><td>%</td><td>0
to
100.0</td><td>○</td><td>○</td><td>○</td></tr>
<tr><td>PC36</td><td>*DMD</td><td>Status display selection
Select the status display to be provided at power-on.
0 □ □ □
Selection of status display at power-on
0: Cumulative feedback pulse
1: Servo motor speed
2: Droop pulse
3: Cumulative command pulses
4: Command pulse frequency
5: Analog speed command voltage (Note 1)
6: Analog torque command voltage (Note 2)
7: Regenerative load ratio
8: Effective load ratio
9: Peak load ratio
A: Instantaneous torque
B: Within one-revolution position (1 pulse unit)
C: Within one-revolution position (100 pulse unit)
D: ABS counter
E: Load inertia moment ratio
F: Bus voltage
Note 1. In speed control mode. Analog speed limit voltage in torque control mode.
2. In torque control mode. Analog torque limit voltage in speed or position control mode.
Status display at power-on in corresponding control mode
0: Depends on the control mode.
<table>
<tr><th>Control mode</th><th>Status display at power-on</th></tr>
<tr><td>Position</td><td>Cumulative feedback pulses</td></tr>
<tr><td>Position/speed</td><td>Cumulative feedback pulses/servo motor speed</td></tr>
<tr><td>Speed</td><td>Servo motor speed</td></tr>
<tr><td>Speed/torque</td><td>Servo motor speed/analog torque command voltage</td></tr>
<tr><td>Torque</td><td>Analog torque command voltage</td></tr>
<tr><td>Torque/position</td><td>Analog torque command voltage/cumulative feedback pulses</td></tr>
</table>
1: Depends on the first digit setting of this parameter.</td><td>0000h</td><td></td><td>Refer to name and function column.</td><td>○</td><td>○</td><td>○</td></tr>
</table>

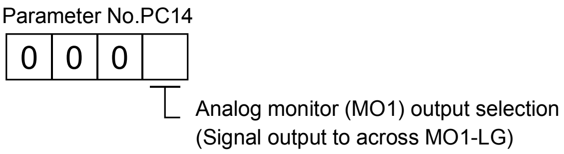
No.	Symbol	Name and function	Initial value	Unit	Setting range	Control mode		
						Position	Speed	Torque
PC37	VCO	Analog speed command offset Used to set the offset voltage of the analog speed command (VC). For example, if CCW rotation is provided by switching on forward rotation start (ST1) with 0V applied to VC, set a negative value. When automatic VC offset is used, the automatically offset value is set to this parameter. (Refer to section 6.4.) The initial value is the value provided by the automatic VC offset function before shipment at the VC-LG voltage of 0V.	Depending on servo amplifier	mV	−999 to 999		○	
		Analog speed limit offset Used to set the offset voltage of the analog speed limit (VLA). For example, if CCW rotation is provided by switching on forward rotation selection (RS1) with 0V applied to VLA, set a negative value. When automatic VC offset is used, the automatically offset value is set to this parameter. (Refer to section 6.4.) The initial value is the value provided by the automatic VC offset function before shipment at the VLA-LG voltage of 0V.						○
PC38	TPO	Analog torque command offset Used to set the offset voltage of the analog torque command (TC).	0	mV	−999 to 999			○
		Analog torque limit offset Used to set the offset voltage of the analog torque limit (TLA).					○	
PC39	MO1	Analog monitor 1 offset Used to set the offset voltage of the analog monitor (MO1).	0	mV	−999 to 999	○	○	○
PC40	MO2	Analog monitor 2 offset Used to set the offset voltage of the analog monitor (MO2).	0	mV	−999 to 999	○	○	○
PC41		For manufacturer setting Do not change this value by any means.	0					
PC42			0					
PC43			0000h					
PC44			0000h					
PC45			0000h					
PC46			0000h					
PC47			0000h					
PC48			0000h					
PC49			0000h					
PC50			0000h					

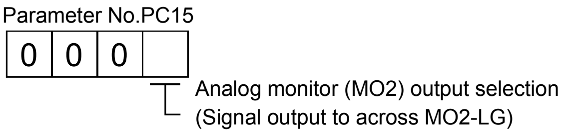
5.3.3 Analog monitor

The servo status can be output to two channels in terms of voltage.

(1) Setting

Change the following digits of parameter No.PC14, PC15.





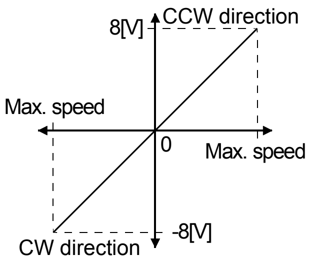
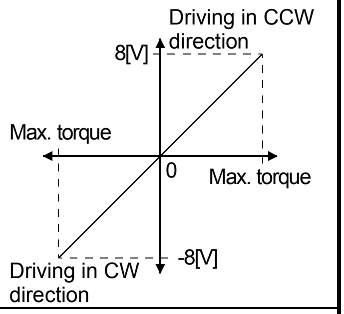
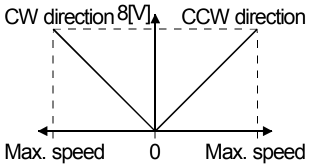
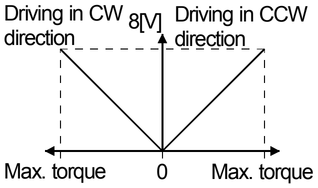
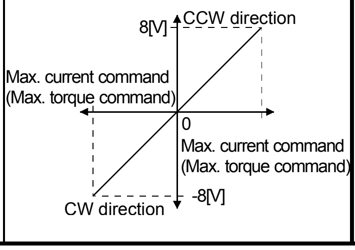
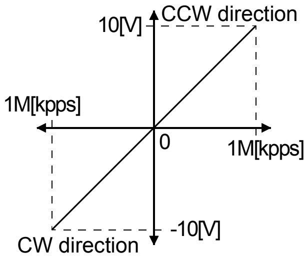
Parameters No.PC39 and PC40 can be used to set the offset voltages to the analog output voltages. The setting range is between −999 and 999mV.

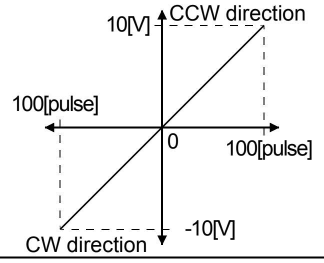
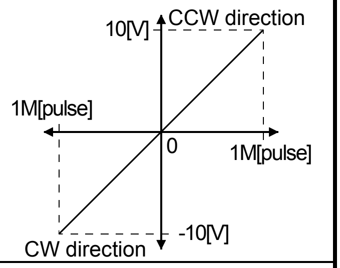
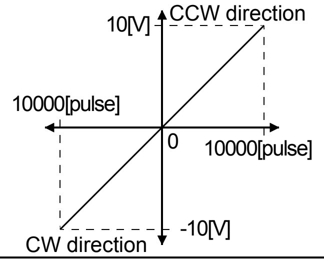
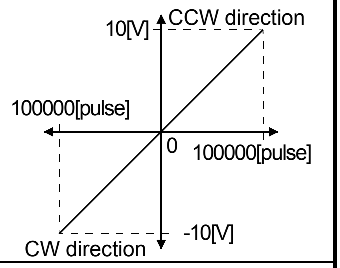
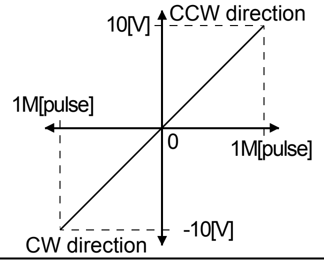
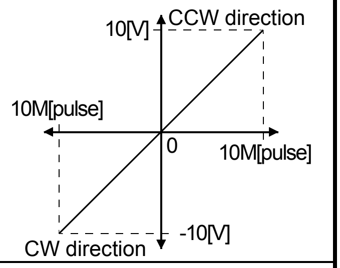
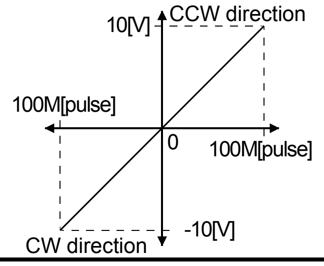
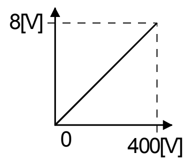
Parameter No.	Description	Setting range [mV]
PC39	Used to set the offset voltage for the analog monitor 1 (MO1).	−999 to 999
PC40	Used to set the offset voltage for the analog monitor 2 (MO2).	

(2) Set content

The servo amplifier is factory-set to output the servo motor speed to analog monitor 1 (MO1) and the torque to analog monitor (MO2). The setting can be changed as listed below by changing the parameter No.PC14 and PC15 value.

Refer to (3) for the measurement point.

Setting	Output item	Description	Setting	Output item	Description
0	Servo motor speed		1	Torque (Note 3)	
2	Servo motor speed		3	Torque (Note 3)	
4	Current command		5	Command pulse frequency	

Setting	Output item	Description	Setting	Output item	Description
6	Droop pulses (Note) (±10V/100 pulses)		7	Droop pulses (Note) (±10V/1000 pulses)	
8	Droop pulses (Note 1) (±10V/10000 pulses)		9	Droop pulses (Note 1) (±10V/100000 pulses)	
A	Feedback position (Note 1,2) (±10V/1 Mpulses)		B	Feedback position (Note 1,2) (±10V/10 Mpulses)	
C	Feedback position (Note 1,2) (±10V/100 Mpulses)		D	Bus voltage (Note 4)	

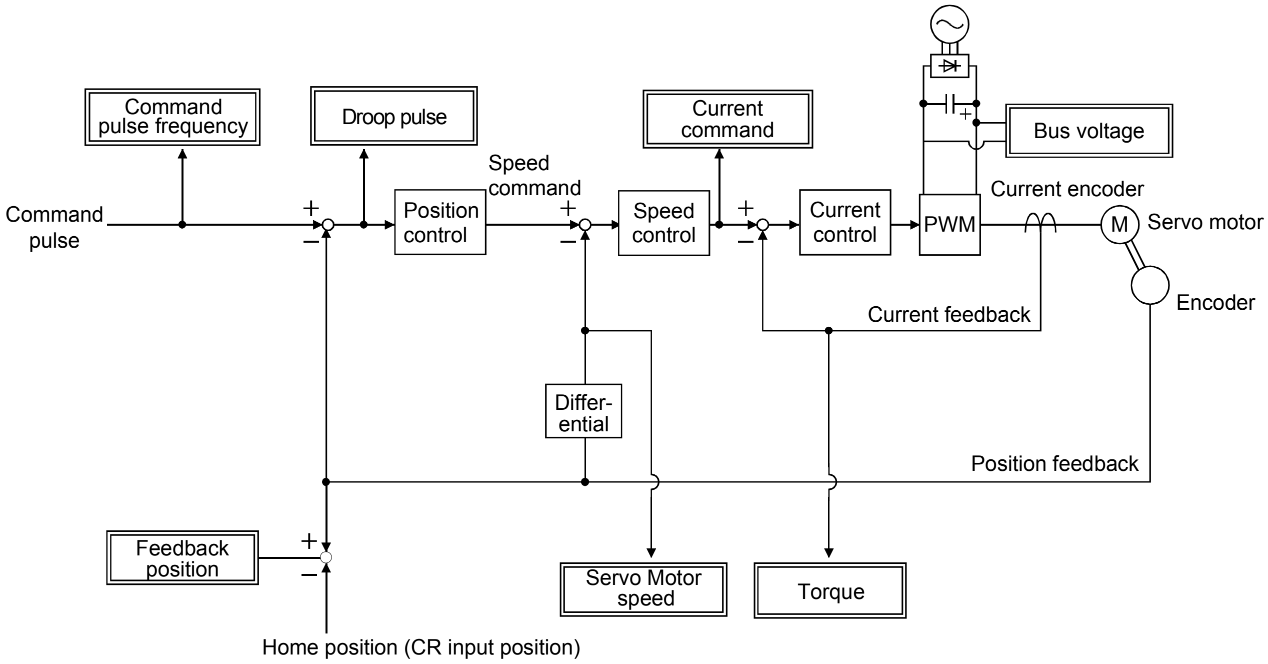
Note 1. Encoder pulse unit.

2. Available in position control mode

3. 8V is outputted at the maximum torque.
However, when parameter No.PA11 ・ PA12 are set to limit torque, 8V is outputted at the torque highly limited.

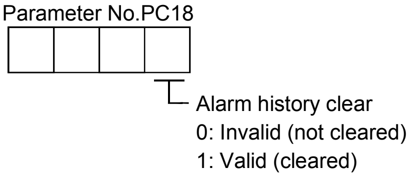
4. For 400V class servo amplifier, the busvoltage becomes +8V/800V.

(3) Analog monitor block diagram



5.3.4 Alarm history clear

The servo amplifier stores past six alarms since the power is switched on for the first time. To control alarms which will occur during the operation, clear the alarm history using parameter No.PC18 before starting the operation.
Turn off the power and then on again after setting the parameter to validate the parameter value.
Clearing the alarm history automatically returns to "□□□0".
After setting, this parameter is made valid by switch power from OFF to ON.



5.4 I/O setting parameters (No.PD□□)

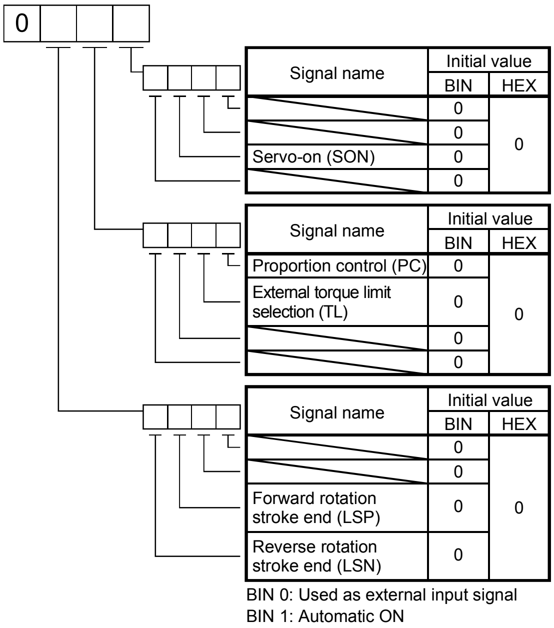
POINT

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

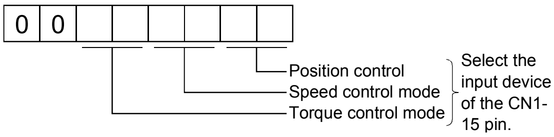
5.4.1 Parameter list

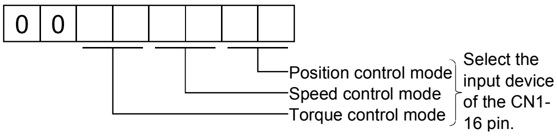
No.	Symbol	Name	Initial value	Unit	Control mode		
					Position	Speed	Torque
PD01	*DIA1	Input signal automatic ON selection 1	0000h		○	○	○
PD02		For manufacturer setting	0000h				
PD03	*DI1	Input signal device selection 1 (CN1-15)	00020202h		○	○	○
PD04	*DI2	Input signal device selection 2 (CN1-16)	00212100h		○	○	○
PD05	*DI3	Input signal device selection 3 (CN1-17)	00070704h		○	○	○
PD06	*DI4	Input signal device selection 4 (CN1-18)	00080805h		○	○	○
PD07	*DI5	Input signal device selection 5 (CN1-19)	00030303h		○	○	○
PD08	*DI6	Input signal device selection 6 (CN1-41)	00202006h		○	○	○
PD09		For manufacturer setting	00000000h				
PD10	*DI8	Input signal device selection 8 (CN1-43)	00000A0Ah		○	○	○
PD11	*DI9	Input signal device selection 9 (CN1-44)	00000B0Bh		○	○	○
PD12	*DI10	Input signal device selection 10 (CN1-45)	00232323h		○	○	○
PD13	*DO1	Output signal device selection 1 (CN1-22)	0004h		○	○	○
PD14	*DO2	Output signal device selection 2 (CN1-23)	000Ch		○	○	○
PD15	*DO3	Output signal device selection 3 (CN1-24)	0004h		○	○	○
PD16	*DO4	Output signal device selection 4 (CN1-25)	0007h		○	○	○
PD17		For manufacturer setting	0003h				
PD18	*DO6	Output signal device selection 6 (CN1-49)	0002h		○	○	○
PD19	*DIF	Input filter setting	0002h		○	○	○
PD20	*DOP1	Function selection D-1	0000h		○	○	○
PD21		For manufacturer setting	0000h				
PD22	*DOP3	Function selection D-3	0000h		○		
PD23		For manufacturer setting	0000h				
PD24	*DOP5	Function selection D-5	0000h		○	○	○
PD25		For manufacturer setting	0000h				
PD26			0000h				
PD27			0000h				
PD28			0000h				
PD29			0000h				
PD30			0000h				

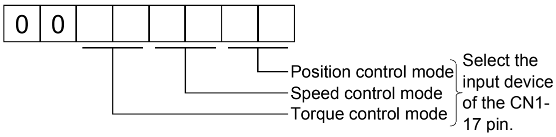
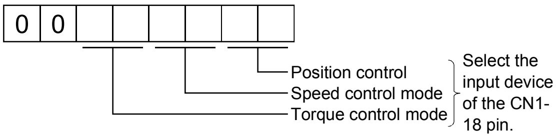
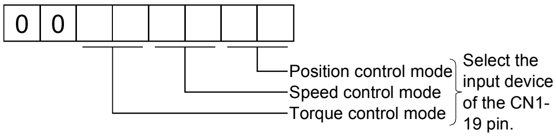
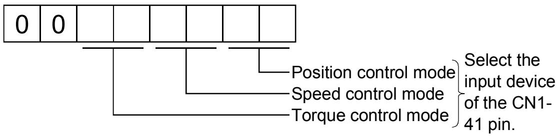
5.4.2 List of details

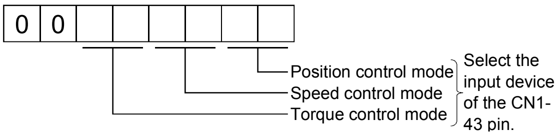
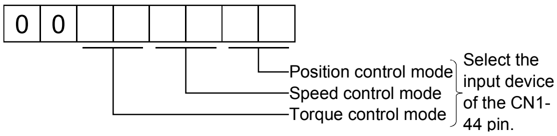
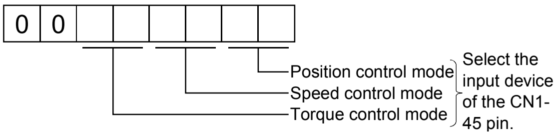
<table>
<tr><th rowspan="2">No.</th><th rowspan="2">Symbol</th><th rowspan="2">Name and function</th><th rowspan="2">Initial value</th><th rowspan="2">Unit</th><th rowspan="2">Setting range</th><th colspan="3">Control mode</th></tr>
<tr><th>Position</th><th>Speed</th><th>Torque</th></tr>
<tr><td>PD01</td><td>*DIA1</td><td>Input signal automatic ON selection 1
Select the input devices to be automatically turned ON.

<table>
<tr><th rowspan="2">Signal name</th><th colspan="2">Initial value</th></tr>
<tr><th>BIN</th><th>HEX</th></tr>
<tr><td></td><td>0</td><td rowspan="4">0</td></tr>
<tr><td></td><td>0</td></tr>
<tr><td>Servo-on (SON)</td><td>0</td></tr>
<tr><td></td><td>0</td></tr>
</table>
<table>
<tr><th rowspan="2">Signal name</th><th colspan="2">Initial value</th></tr>
<tr><th>BIN</th><th>HEX</th></tr>
<tr><td>Proportion control (PC)</td><td>0</td><td rowspan="4">0</td></tr>
<tr><td>External torque limit selection (TL)</td><td>0</td></tr>
<tr><td></td><td>0</td></tr>
<tr><td></td><td>0</td></tr>
</table>
<table>
<tr><th rowspan="2">Signal name</th><th colspan="2">Initial value</th></tr>
<tr><th>BIN</th><th>HEX</th></tr>
<tr><td></td><td>0</td><td rowspan="4">0</td></tr>
<tr><td></td><td>0</td></tr>
<tr><td>Forward rotation stroke end (LSP)</td><td>0</td></tr>
<tr><td>Reverse rotation stroke end (LSN)</td><td>0</td></tr>
</table>
BIN 0: Used as external input signal
BIN 1: Automatic ON

For example, to turn ON SON, the setting is "□□□4".</td><td>0000h</td><td></td><td>Refer to name and function column.</td><td>○</td><td>○</td><td>○</td></tr>
<tr><td>PD02</td><td></td><td>For manufacturer setting
Do not change this value by any means.</td><td>0000h</td><td></td><td>Refer to name and function column.</td><td></td><td></td><td></td></tr>
</table>

<table>
<tr><th rowspan="2">No.</th><th rowspan="2">Symbol</th><th rowspan="2">Name and function</th><th rowspan="2">Initial value</th><th rowspan="2">Unit</th><th rowspan="2">Setting range</th><th colspan="3">Control mode</th></tr>
<tr><th>Position</th><th>Speed</th><th>Torque</th></tr>
<tr><td>PD03</td><td>*DI1</td><td>Input signal device selection 1 (CN1-15)
Any input signal can be assigned to the CN1-15 pin.
Note that the setting digits and the signal that can be assigned change depending on the control mode.


The devices that can be assigned in each control mode are those that have the symbols indicated in the following table.
If any other device is set, it is invalid.
<table>
<tr><th rowspan="2">Setting</th><th colspan="3">Control modes (Note 1)</th></tr>
<tr><th>P</th><th>S</th><th>T</th></tr>
<tr><td>00</td><td></td><td></td><td></td></tr>
<tr><td>01</td><td colspan="3">For manufacturer setting (Note 2)</td></tr>
<tr><td>02</td><td>SON</td><td>SON</td><td>SON</td></tr>
<tr><td>03</td><td>RES</td><td>RES</td><td>RES</td></tr>
<tr><td>04</td><td>PC</td><td>PC</td><td></td></tr>
<tr><td>05</td><td>TL</td><td>TL</td><td></td></tr>
<tr><td>06</td><td>CR</td><td></td><td></td></tr>
<tr><td>07</td><td></td><td>ST1</td><td>RS2</td></tr>
<tr><td>08</td><td></td><td>ST2</td><td>RS1</td></tr>
<tr><td>09</td><td>TL1</td><td>TL1</td><td></td></tr>
<tr><td>0A</td><td>LSP</td><td>LSP</td><td></td></tr>
<tr><td>0B</td><td>LSN</td><td>LSN</td><td></td></tr>
<tr><td>0C</td><td colspan="3">For manufacturer setting (Note 2)</td></tr>
<tr><td>0D</td><td>CDP</td><td>CDP</td><td></td></tr>
<tr><td>0E to 1F</td><td colspan="3">For manufacturer setting (Note 2)</td></tr>
<tr><td>20</td><td></td><td>SP1</td><td>SP1</td></tr>
<tr><td>21</td><td></td><td>SP2</td><td>SP2</td></tr>
<tr><td>22</td><td></td><td>SP3</td><td>SP3</td></tr>
<tr><td>23</td><td>LOP</td><td>LOP</td><td>LOP</td></tr>
<tr><td>24</td><td>CM1</td><td></td><td></td></tr>
<tr><td>25</td><td>CM2</td><td></td><td></td></tr>
<tr><td>26</td><td></td><td>STAB2</td><td>STAB2</td></tr>
<tr><td>27 to 3F</td><td colspan="3">For manufacturer setting (Note 2)</td></tr>
</table>
Note 1. P: Position control mode
S: Speed control mode
T: Torque control mode
2. For manufacturer setting. Never set this value.</td><td>0002
0202h</td><td></td><td>Refer to name and function column.</td><td>○</td><td>○</td><td>○</td></tr>
<tr><td>PD04</td><td>*DI2</td><td>Input signal device selection 2 (CN1-16)
Any input signal can be assigned to the CN1-16 pin.
The devices that can be assigned and the setting method are the same as in parameter No.PD03.

</td><td>0021
2100h</td><td></td><td>Refer to name and function column.</td><td>○</td><td>○</td><td>○</td></tr>
</table>

No.	Symbol	Name and function	Initial value	Unit	Setting range	Control mode		
						Position	Speed	Torque
PD05	*DI3	Input signal device selection 3 (CN1-17) Any input signal can be assigned to the CN1-17 pin. The devices that can be assigned and the setting method are the same as in parameter No.PD03.  When "Valid (ABS transfer by DI0)" has been selected for the absolute position detection system in parameter No.PA03, the CN1-17 pin is set to the ABS transfer mode (ABSM). (Refer to section 14.7.)	0007 0704h		Refer to name and function column.	○	○	○
PD06	*DI4	Input signal device selection 4 (CN1-18) Any input signal can be assigned to the CN1-18 pin. The devices that can be assigned and the setting method are the same as in parameter No.PD03.  When "Valid (ABS transfer by DI0)" has been selected for the absolute position detection system in parameter No.PA03, the CN1-18 pin is set to the ABS transfer request (ABSR). (Refer to section 14.7.)	0008 0805h		Refer to name and function column.	○	○	○
PD07	*DI5	Input signal device selection 5 (CN1-19) Any input signal can be assigned to the CN1-19 pin. The devices that can be assigned and the setting method are the same as in parameter No.PD03. 	0003 0303h		Refer to name and function column.	○	○	○
PD08	*DI6	Input signal device selection 6 (CN1-41) Any input signal can be assigned to the CN1-41 pin. The devices that can be assigned and the setting method are the same as in parameter No.PD03. 	0020 2006h		Refer to name and function column.	○	○	○
PD09		For manufacturer setting Do not change this value by any means.	0000 0000h					

No.	Symbol	Name and function	Initial value	Unit	Setting range	Control mode		
						Position	Speed	Torque
PD10	*DI8	Input signal device selection 8 (CN1-43) Any input signal can be assigned to the CN1-43 pin. The devices that can be assigned and the setting method are the same as in parameter No.PD03. 	0000 0A0Ah		Refer to name and function column.	○	○	○
PD11	*DI9	Input signal device selection 9 (CN1-44) Any input signal can be assigned to the CN1-44 pin. The devices that can be assigned and the setting method are the same as in parameter No.PD03. 	0000 0B0Bh		Refer to name and function column.	○	○	○
PD12	*DI10	Input signal device selection 10 (CN1-45) Any input signal can be assigned to the CN1-45 pin. The devices that can be assigned and the setting method are the same as in parameter No.PD03. 	0023 2323h		Refer to name and function column.	○	○	○

<table>
<tr><th rowspan="2">No.</th><th rowspan="2">Symbol</th><th rowspan="2">Name and function</th><th rowspan="2">Initial value</th><th rowspan="2">Unit</th><th rowspan="2">Setting range</th><th colspan="3">Control mode</th></tr>
<tr><th>Position</th><th>Speed</th><th>Torque</th></tr>
<tr><td>PD13</td><td>*DO1</td><td>Output signal device selection 1 (CN1-22)
Any output signal can be assigned to the CN1-22 pin.
In the initial setting, INP is assigned in the position control mode, and SA is assigned in the speed control mode.
Note that the device that can be assigned changes depending on the control mode.

0 0 ☐ ☐
Select the output device of the CN1-22 pin.

The devices that can be assigned in each control mode are those that have the symbols indicated in the following table. If any other device is set, it is invalid.
<table>
<tr><th rowspan="2">Setting</th><th colspan="3">Control modes (Note 1)</th></tr>
<tr><th>P</th><th>S</th><th>T</th></tr>
<tr><td>00</td><td>Always OFF</td><td>Always OFF</td><td>Always OFF</td></tr>
<tr><td>01</td><td colspan="3">For manufacturer setting (Note 2)</td></tr>
<tr><td>02</td><td>RD</td><td>RD</td><td>RD</td></tr>
<tr><td>03</td><td>ALM</td><td>ALM</td><td>ALM</td></tr>
<tr><td>04</td><td>INP</td><td>SA</td><td>Always OFF</td></tr>
<tr><td>05</td><td>MBR</td><td>MBR</td><td>MBR</td></tr>
<tr><td>06</td><td>DB</td><td>DB</td><td>DB</td></tr>
<tr><td>07</td><td>TLC</td><td>TLC</td><td>VLC</td></tr>
<tr><td>08</td><td>WNG</td><td>WNG</td><td>WNG</td></tr>
<tr><td>09</td><td>BWNG</td><td>BWNG</td><td>BWNG</td></tr>
<tr><td>0A</td><td>Always OFF</td><td>SA</td><td>SA</td></tr>
<tr><td>0B</td><td>Always OFF</td><td>Always OFF</td><td>VLC</td></tr>
<tr><td>0C</td><td>ZSP</td><td>ZSP</td><td>ZSP</td></tr>
<tr><td>0D</td><td colspan="3">For manufacturer setting (Note 2)</td></tr>
<tr><td>0E</td><td colspan="3">For manufacturer setting (Note 2)</td></tr>
<tr><td>0F</td><td>CDPS</td><td>Always OFF</td><td>Always OFF</td></tr>
<tr><td>10</td><td colspan="3">For manufacturer setting (Note 2)</td></tr>
<tr><td>11</td><td>ABSV</td><td>Always OFF</td><td>Always OFF</td></tr>
<tr><td>12 to 3F</td><td colspan="3">For manufacturer setting (Note 2)</td></tr>
</table>
Note 1. P: Position control mode
S: Speed control mode
T: Torque control mode
2. For manufacturer setting. Never set this value.

When "Valid (ABS transfer by DI0)" has been selected for the absolute position detection system in parameter No.PA03, the CN1-22 pin is set to the ABS transmission data bit 0 (ABSB0) in the ABS transfer mode only. (Refer to section 14.7.)</td><td>0004h</td><td></td><td>Refer to name and function column.</td><td>○</td><td>○</td><td>○</td></tr>
</table>

No.	Symbol	Name and function	Initial value	Unit	Setting range	Control mode		
						Position	Speed	Torque
PD14	*DO2	Output signal device selection 2 (CN1-23) Any output signal can be assigned to the CN1-23 pin. In the initial setting, ZSP is assigned to the pin. The devices that can be assigned and the setting method are the same as in parameter No.PD13. 0 0 □ □ Select the output device of the CN1-23 pin. When "Valid (ABS transfer by DI0)" has been selected for the absolute position detection system in parameter No.PA03, the CN1-23 pin is set to the ABS transmission data bit 1 (ABSB1) in the ABS transfer mode only. (Refer to section 14.7.)	000Ch		Refer to name and function column.	○	○	○
PD15	*DO3	Output signal device selection 3 (CN1-24) Any output signal can be assigned to the CN1-24 pin. In the initial setting, INP is assigned in the position control mode, and SA is assigned in the speed control mode. The devices that can be assigned and the setting method are the same as in parameter No.PD13. 0 0 □ □ Select the output device of the CN1-24 pin.	0004h		Refer to name and function column.	○	○	○
PD16	*DO4	Output signal device selection 4 (CN1-25) Any output signal can be assigned to the CN1-25 pin. In the initial setting, TLC is assigned in the position control and speed control modes, and VLC is assigned in the torque control mode. The devices that can be assigned and the setting method are the same as in parameter No.PD13. 0 0 □ □ Select the output device of the CN1-25 pin. When "Valid (ABS transfer by DI0)" has been selected for the absolute position detection system in parameter No.PA03, the CN1-25 pin is set to the ABS transmission data ready (ABST) in the ABS transfer mode only. (Refer to section 14.7.)	0007h		Refer to name and function column.	○	○	○
PD17		For manufacturer setting Do not change this value by any means.	0003h					
PD18	*DO6	Output signal device selection 6 (CN1-49) Any output signal can be assigned to the CN1-49 pin. In the initial setting, RD is assigned to the pin. The devices that can be assigned and the setting method are the same as in parameter No.PD13. 0 0 □ □ Select the output device of the CN1-49 pin.	0002h		Refer to name and function column.	○	○	○

No.	Symbol	Name and function	Initial value	Unit	Setting range	Control mode		
						Position	Speed	Torque
PD19	*DIF	Input filter setting Select the input filter. 0 0 0 □ Input signal filter If external input signal causes chattering due to noise, etc., input filter is used to suppress it. 0: None 1: 1.777[ms] 2: 3.555[ms] 3: 5.333[ms]	0002h		Refer to name and function column.	○	○	○
PD20	*DOP1	Function selection D-1 Select the stop processing at forward rotation stroke end (LSP)/reverse rotation stroke end (LSN) OFF and the base circuit status at reset (RES) ON. 0 0 □ □ How to make a stop when forward rotation stroke end (LSP) • reverse rotation stroke end (LSN) is valid. (Refer to Section 5.4.3.) 0: Sudden stop 1: Slow stop Selection of base circuit status at reset (RES) ON 0: Base circuit switched off 1: Base circuit not switched off	0000h		Refer to name and function column.	 ○ ○	 ○ ○	 ○
PD21		For manufacturer setting Do not change this value by any means.	0000h					
PD22	*DOP3	Function selection D-3 Set the clear (CR). 0 0 0 □ Clear (CR) selection 0: Droop pulses are cleared on the leading edge. 1: While on, droop pulses are always cleared.	0000h		Refer to name and function column.	○		
PD23		For manufacturer setting Do not change this value by any means.	0000h					

No.	Symbol	Name and function	Initial value	Unit	Setting range	Control mode		
						Position	Speed	Torque
PD24	*DOP5	Function selection D-5 Select the alarm code and warning (WNG) outputs.	0000h		Refer to name and function column.	○	○	○

0 0 □ □

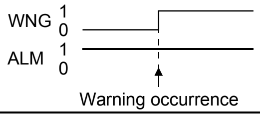
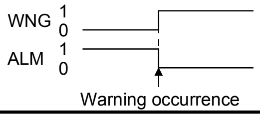
Setting of alarm code output

Set value	Connector pins of CN1		
	22	23	24
0	Alarm code is not output.		
1	Alarm code is output at alarm occurrence.		

(Note) Alarm code			Alarm display	Name
CN1 pin 22	CN1 pin 23	CN1 pin 24		
0	0	0	88888	Watchdog
			AL.12	Memory error 1
			AL.13	Clock error
			AL.15	Memory error 2
			AL.17	Board error 2
			AL.19	Memory error 3
			AL.37	Parameter error
			AL.8A	Serial communication time-out error
			AL.8E	Serial communication error
0	0	1	AL.30	Regenerative error
			AL.33	Overvoltage
0	1	0	AL.10	Undervoltage
0	1	1	AL.45	Main circuit device overheat
			AL.46	Servo motor overheat
			AL.47	Cooling fan alarm
			AL.50	Overload 1
			AL.51	Overload 2
1	0	0	AL.24	Main circuit
			AL.32	Overcurrent
1	0	1	AL.31	Overspeed
			AL.35	Command pulse frequency error
			AL.52	Error excessive
1	1	0	AL.16	Encoder error 1
			AL.1A	Motor combination error
			AL.20	Encoder error 2
			AL.25	Absolute position erase

Note. 0: off
1: on
A parameter alarm (AL. 37) occurs if the alarm code output is selected with parameter No. PA03 set to "□□□1" and the DI0-based absolute position detection system selected.

Selection of output device at warning occurrence
Select the warning (WNG) and trouble (ALM) output status at warning occurrence.

Setting	(Note) Device status
0	
1	

Note. 0: off
1: on

No.	Symbol	Name and function	Initial value	Unit	Setting range	Control mode		
						Position	Speed	Torque
PD25		For manufacturer setting Do not change this value by any means.	0000h					
PD26			0000h					
PD27			0000h					
PD28			0000h					
PD29			0000h					
PD30			0000h					

5.4.3 Using forward/reverse rotation stroke end to change the stopping pattern

The stopping pattern is factory-set to make a sudden stop when the forward/reverse rotation stroke end is made valid. A slow stop can be made by changing the parameter No.PD20 value.

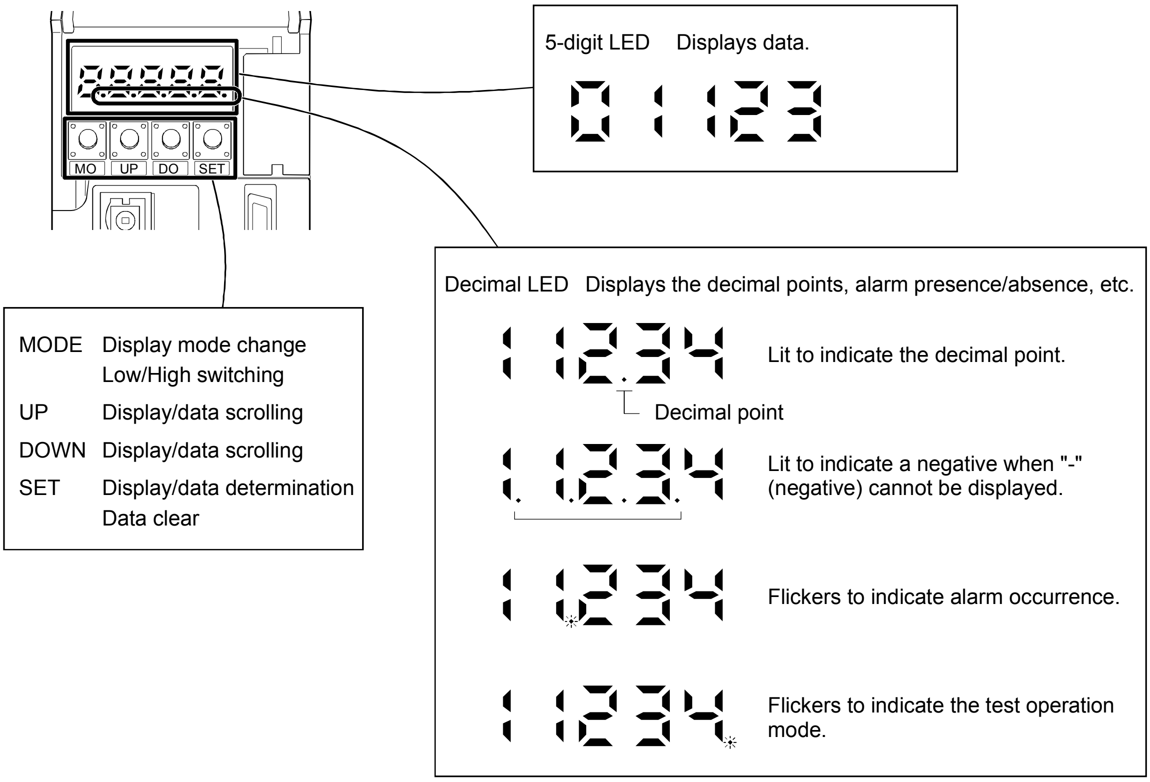
Parameter No.PD20 setting	Stopping method
□□□0 (initial value)	Sudden stop Position control mode : Motor stops with droop pulses cleared. Speed control mode : Motor stops at deceleration time constant of zero.
□□□1	Slow stop Position control mode : The motor is decelerated to a stop in accordance with the parameter No.PB03 value. Speed control mode : The motor is decelerated to a stop in accordance with the parameter No.PC02 value.

MEMO

6. DISPLAY AND OPERATION SECTIONS

6.1 Overview

The MR-J3-A servo amplifier has the display section (5-digit, 7-segment LED) and operation section (4 pushbuttons) for servo amplifier status display, alarm display, parameter setting, etc.
The operation section and display data are described below.



5-digit LED Displays data.

Decimal LED Displays the decimal points, alarm presence/absence, etc.

MODE	Display mode change Low/High switching
UP	Display/data scrolling
DOWN	Display/data scrolling
SET	Display/data determination Data clear

Lit to indicate the decimal point.

Decimal point

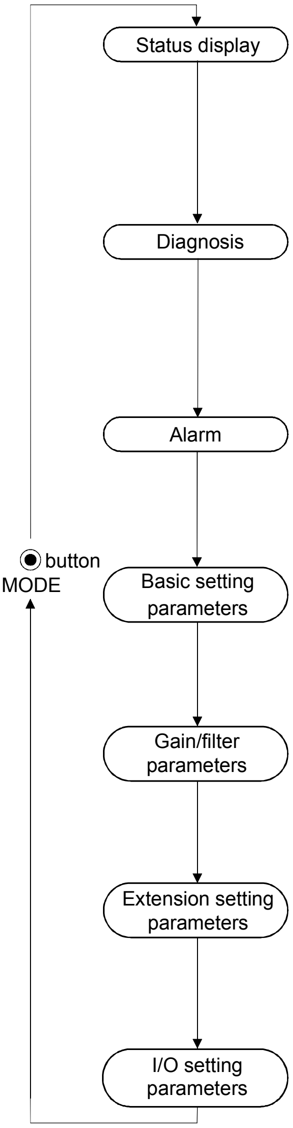
Lit to indicate a negative when "-" (negative) cannot be displayed.

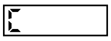
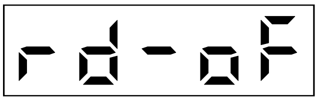
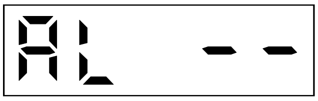
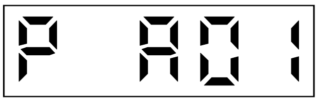
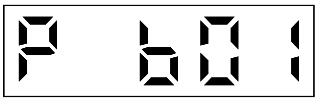
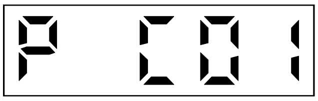
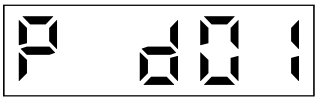
Flickers to indicate alarm occurrence.

Flickers to indicate the test operation mode.

6.2 Display sequence

Press the "MODE" button once to shift to the next display mode. Refer to section 6.3 and later for the description of the corresponding display mode.
To refer to or set the gain filter parameters, extension setting parameters and I/O setting parameters, make them valid with parameter No.PA19 (parameter write disable).



Display mode transition	Initial screen	Function	Reference
Status display		Servo status display.  appears at power-on. (Note)	Section 6.3
Diagnosis		Sequence display, external signal display, forced output signal (DO), test operation, software version display, VC automatic offset, servo motor series ID display, servo motor type ID display, servo motor encoder ID display, parameter write inhibit, next deactivation display.	Section 6.4
Alarm		Current alarm display, alarm history display, parameter error No. display, point table error No. display.	Section 6.5
Basic setting parameters		Display and setting of basic setting parameters.	Section 6.6
Gain/filter parameters		Display and setting of gain filter parameters.	
Extension setting parameters		Display and setting of extension setting parameters.	
I/O setting parameters		Display and setting of I/O setting parameters.	

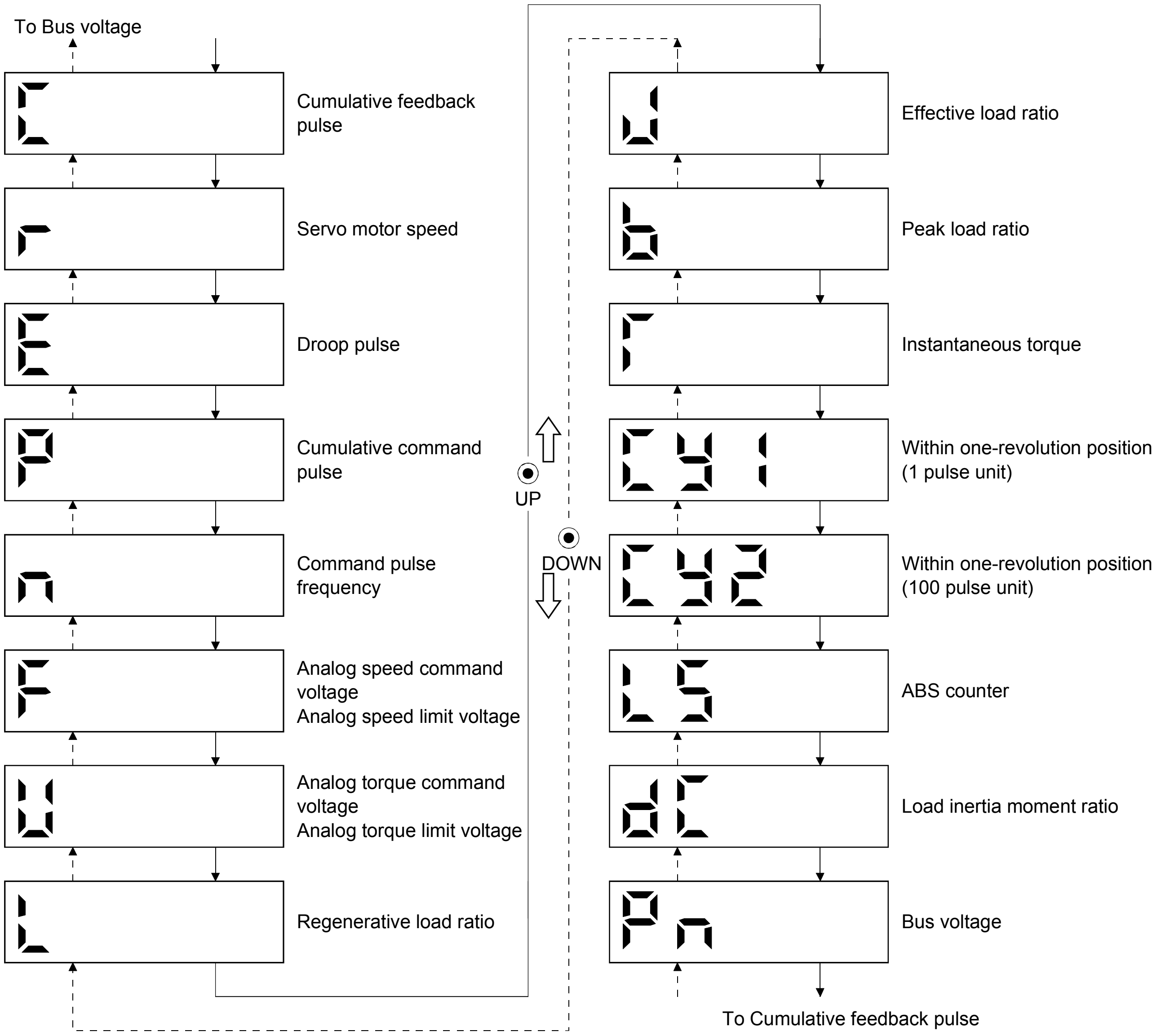
Note. When the axis name is set to the servo amplifier using MR Configurator, the axis name is displayed and the servo status is then displayed.

6.3 Status display

The servo status during operation is shown on the 5-digit, 7-segment LED display. Press the "UP" or "DOWN" button to change display data as desired. When the required data is selected, the corresponding symbol appears. Press the "SET" button to display its data. At only power-on, however, data appears after the symbol of the status display selected in parameter No.PC36 has been shown for 2[s].
The servo amplifier display shows the lower five digits of 16 data items such as the motor speed.

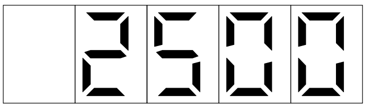
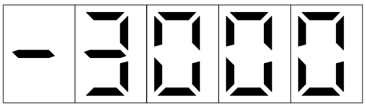
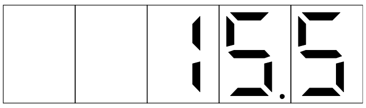
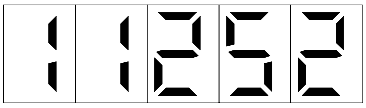
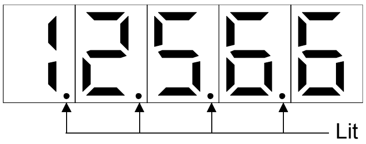
6.3.1 Display transition

After choosing the status display mode with the "MODE" button, pressing the "UP" or "DOWN" button changes the display as shown below.



6.3.2 Display examples

The following table lists display examples.

Item	Status	Displayed data
		Servo amplifier display
Servo motor speed	Forward rotation at 2500r/min	
	Reverse rotation at 3000r/min	 Reverse rotation is indicated by "−".
Load inertia moment	15.5 Multiplier (×1)	
ABS counter	11252rev	
	−12566rev	 Negative value is indicated by the lit decimal points in the upper four digits.

6.3.3 Status display list

POINT

- Refer to appendix 3 for the measurement point.

The following table lists the servo statuses that may be shown.

Name	Symbol	Unit	Description	Display range
Cumulative feedback pulses	C	pulse	Feedback pulses from the servo motor encoder are counted and displayed. The values in excess of ±99999 can be counted. However, the counter shows only the lower five digits of the actual value since the servo amplifier display is five digits. Press the "SET" button to reset the display value to zero. The value of minus is indicated by the lit decimal points in the upper four digits.	−99999 to 99999
Servo motor speed	r	r/min	The servo motor speed is displayed. The value rounded off is displayed in ×0.1r/min.	−7200 to 7200
Droop pulses	E	pulse	The number of droop pulses in the deviation counter is displayed. When the servo motor is rotating in the reverse direction, the decimal points in the upper four digits are lit. The values in excess of ±99999 can be counted. However, the counter shows only the lower five digits of the actual value since the servo amplifier display is five digits. The number of pulses displayed is in the encoder pulse unit.	−99999 to 99999
Cumulative command pulses	P	pulse	The position command input pulses are counted and displayed. As the value displayed is not yet multiplied by the electronic gear (CMX/CDV), it may not match the indication of the cumulative feedback pulses. The values in excess of ±99999 can be counted. However, the counter shows only the lower five digits of the actual value since the servo amplifier display is five digits. Press the "SET" button to reset the display value to zero. When the servo motor is rotating in the reverse direction, the decimal points in the upper four digits are lit.	−99999 to 99999
Command pulse frequency	n	kpps	The frequency of the position command input pulses is displayed. The value displayed is not multiplied by the electronic gear (CMX/CDV).	−1500 to 1500
Analog speed command voltage Analog speed limit voltage	F	V	(1) Torque control mode Analog speed limit (VLA) voltage is displayed.	−10.00 to 10.00
			(2) Speed control mode Analog speed command (VC) voltage is displayed.	
Analog torque command voltage Analog torque limit voltage	U	V	(1) Position control mode, speed control mode Analog torque limit (TLA) voltage is displayed.	0 to 10.00
			(2) Torque control mode Analog torque command (TLA) voltage is displayed.	−8.00 to +8.00
Regenerative load ratio	L	%	The ratio of regenerative power to permissible regenerative power is displayed in %.	0 to 100
Effective load ratio	J	%	The continuous effective load current is displayed. The effective value in the past 15 seconds is displayed relative to the rated current of 100%.	0 to 300

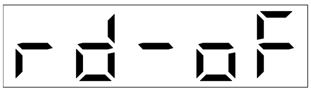
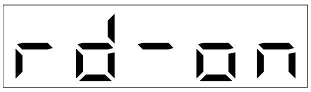
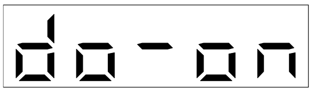
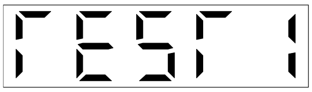
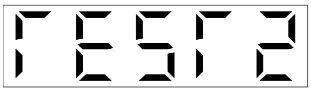
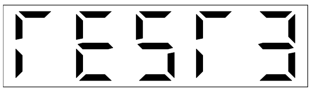
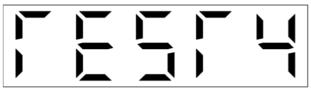
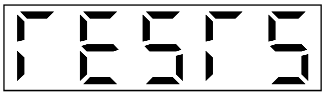
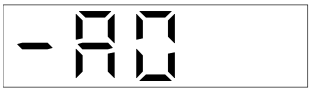
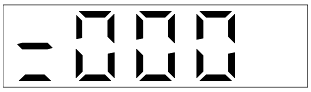
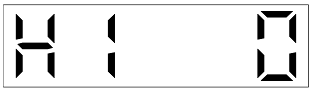
Name	Symbol	Unit	Description	Display range
Peak load ratio	b	%	The maximum current is displayed. The highest value in the past 15 seconds is displayed relative to the rated current of 100%.	0 to 400
Instantaneous torque	T	%	Torque that occurred instantaneously is displayed. The value of the torque that occurred is displayed in real time relative to the rate torque of 100%.	0 to 400
Within one-revolution position low	Cy1	pulse	Position within one revolution is displayed in encoder pulses. The value returns to 0 when it exceeds the maximum number of pulses. However, the counter shows only the lower five digits of the actual value since the servo amplifier display is five digits. The value is incremented in the CCW direction of rotation.	0 to 99999
Within one-revolution position high	Cy2	100 pulse	The within one-revolution position is displayed in 100 pulse increments of the encoder. The value returns to 0 when it exceeds the maximum number of pulses. The value is incremented in the CCW direction of rotation.	0 to 2621
ABS counter	LS	rev	Travel value from the home position in the absolute position detection systems is displayed in terms of the absolute position detectors counter value.	－32768 to 32767
Load inertia moment ratio	dC	Multiplier (×10^{-1})	The estimated ratio of the load inertia moment to the servo motor shaft inertia moment is displayed.	0.0 to 300.0
Bus voltage	Pn	V	The voltage (across P＋-N－) of the main circuit converter is displayed.	0 to 900

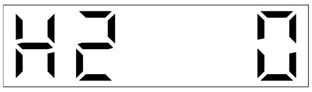
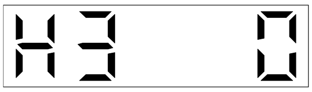
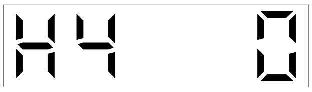
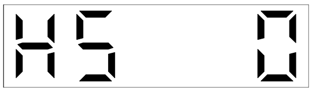
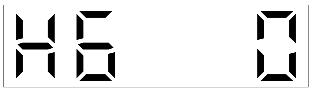
6.3.4 Changing the status display screen

The status display item of the servo amplifier display shown at power-on can be changed by changing the parameter No.PC36 settings.
The item displayed in the initial status changes with the control mode as follows.

Control mode	Status display at power-on
Position	Cumulative feedback pulses
Position/speed	Cumulative feedback pulses/servo motor speed
Speed	Servo motor speed
Speed/torque	Servo motor speed/analog torque command voltage
Torque	Analog torque command voltage
Torque/position	Analog torque command voltage/cumulative feedback pulses

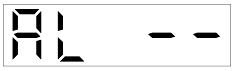
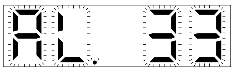
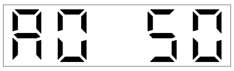
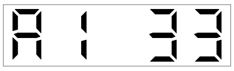
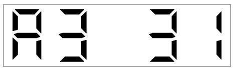
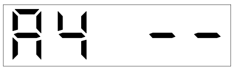
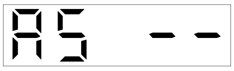
6.4 Diagnostic mode

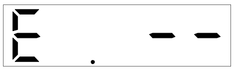
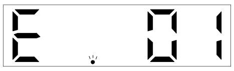
Name		Display	Description
Sequence			Not ready. Indicates that the servo amplifier is being initialized or an alarm has occurred.
			Ready. Indicates that the servo was switched on after completion of initialization and the servo amplifier is ready to operate.
External I/O signal display		Refer to section 6.7.	Indicates the ON-OFF states of the external I/O signals. The upper segments correspond to the input signals and the lower segments to the output signals. Lit: ON Extinguished: OFF
Output signal (DO) forced output			The digital output signal can be forced on/off. For more information, refer to section 6.8.
Test operation mode	JOG operation		JOG operation can be performed when there is no command from the external command device. For details, refer to section 6.9.2.
	Positioning operation		Positioning operation can be performed when there is no command from the external command device. The MR Configurator is required for positioning operation. For details, refer to section 6.9.3.
	Motorless operation		Without connection of the servo motor, the servo amplifier provides output signals and displays the status as if the servo motor is running actually in response to the input device. For details, refer to section 6.9.4.
	Machine analyzer operation		Merely connecting the servo amplifier allows the resonance point of the mechanical system to be measured. The MR Configurator is required for machine analyzer operation. For details, refer to section 12.8.
	Amplifier diagnosis		Simple diagnosis as to correct function of the input/output interface of the servo amplifier can be made. To diagnose the amplifier, the diagnosis cable (MR-J3ACHECK) and MR Configurator are necessary. For details, refer to section 12.8.
Software version low			Indicates the version of the software.
Software version high			Indicates the system number of the software.
Automatic VC offset			If offset voltages in the analog circuits inside and outside the servo amplifier cause the servo motor to rotate slowly at the analog speed command (VC) or analog speed limit (VLA) of 0V, this function automatically makes zero-adjustment of offset voltages. When using this function, make it valid in the following procedure. Making it valid causes the parameter No.PC37 value to be the automatically adjusted offset voltage. 1) Press "SET" once. 2) Set the number in the first digit to 1 with "UP"/"DOWN". 3) Press "SET". This function cannot be used if the input voltage of VC or VLA is －0.4V or less, or ＋0.4V or more.

Name	Display	Description
Servo motor series ID		Press the "SET" button to show the series ID of the servo motor currently connected. For indication details, refer to the Servo Motor Instruction Manual (Vol.2).
Servo motor type ID		Press the "SET" button to show the type ID of the servo motor currently connected. For indication details, refer to the Servo Motor Instruction Manual (Vol.2).
Servo motor encoder ID		Press the "SET" button to show the encoder ID of the servo motor currently connected. For indication details, refer to the Servo Motor Instruction Manual (Vol.2).
For manufacturer setting		For manufacturer setting
For manufacturer setting		For manufacturer setting

6.5 Alarm mode

The current alarm, past alarm history and parameter error are displayed. The lower 2 digits on the display indicate the alarm number that has occurred or the parameter number in error. Display examples are shown below.

Name	Display	Description
Current alarm		Indicates no occurrence of an alarm.
		Indicates the occurrence of overvoltage (AL.33). Flickers at occurrence of the alarm.
Alarm history		Indicates that the last alarm is overload 1 (AL.50).
		Indicates that the second alarm in the past is overvoltage (AL.33).
		Indicates that the third alarm in the past is undervoltage (AL.10).
		Indicates that the fourth alarm in the past is overspeed (AL.31).
		Indicates that there is no fifth alarm in the past.
		Indicates that there is no sixth alarm in the past.

Name	Display	Description
Parameter error No.		Indicates no occurrence of parameter error (AL.37).
		Indicates that the data of parameter No.PA12 is faulty.

Functions at occurrence of an alarm

(1) Any mode screen displays the current alarm.

(2) Even during alarm occurrence, the other screen can be viewed by pressing the button in the operation area. At this time, the decimal point in the fourth digit remains flickering.

(3) For any alarm, remove its cause and clear it in any of the following methods (for clearable alarms, refer to section 9.1).

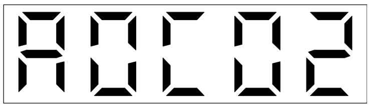
   (a) Switch power OFF, then ON.

   (b) Press the "SET" button on the current alarm screen.

   (c) Turn on the alarm reset (RES).

(4) Use parameter No.PC18 to clear the alarm history.

(5) Pressing "SET" on the alarm history display screen for 2s or longer shows the following detailed information display screen. Note that this is provided for maintenance by the manufacturer.



(6) Press "UP" or "DOWN" to move to the next history.

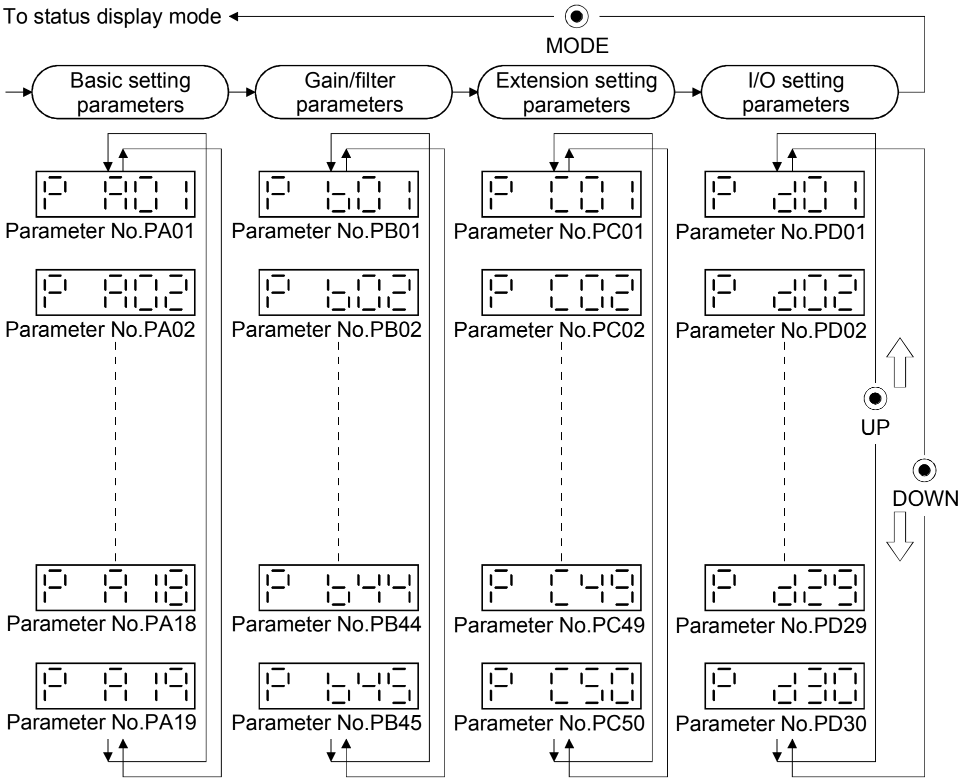
6.6 Parameter mode

POINT

- To use the I/O setting parameters, change the parameter No.PA19 (parameter write inhibit value. (Refer to section 5.1.1)
- The I/O signal settings can be changed using the I/O setting parameter No.PD03 to PD08, PD10 to PD16, PD18.

6.6.1 Parameter mode transition

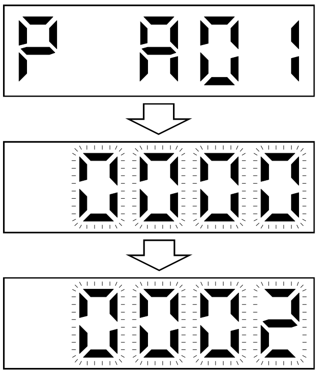
After choosing the corresponding parameter mode with the "MODE" button, pressing the "UP" or "DOWN" button changes the display as shown below.



6.6.2 Operation example

(1) Parameters of 5 or less digits

The following example shows the operation procedure performed after power-on to change the control mode (Parameter No.PA01) into the speed control mode. Press "MODE" to switch to the basic setting parameter screen.



Press MODE four times. Select parameter No.8 with UP or DOWN.

······The parameter number is displayed.

Press UP or DOWN to change the number.

Press SET twice.

······The set value of the specified parameter number flickers.

Press UP twice.

······During flickering, the set value can be changed.

Use UP or DOWN .
(□□□2: Speed control mode)

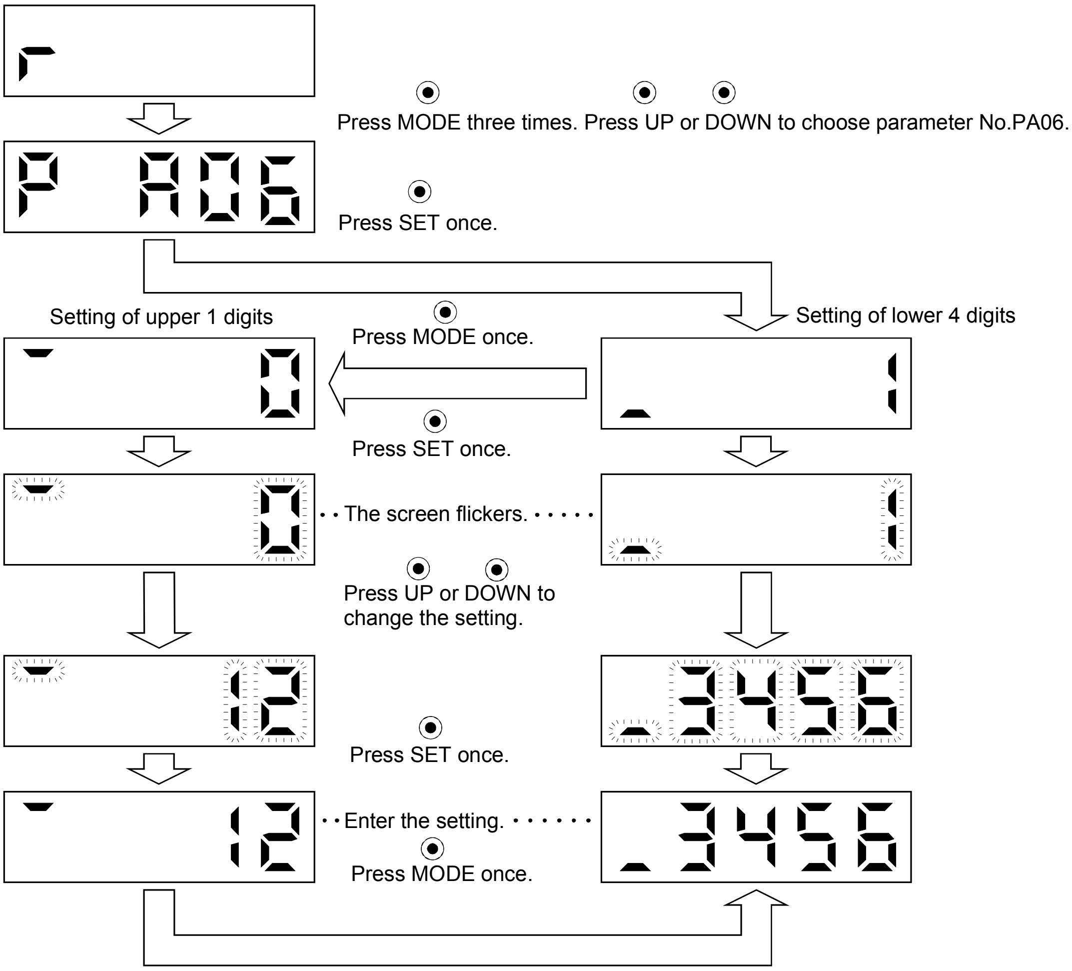
Press SET to enter.

To shift to the next parameter, press the "UP" or "DOWN" button.
When changing the parameter No.PA01 setting, change its set value, then switch power off once and switch it on again to make the new value valid.

(2) Parameters of 6 or more digits

The following example gives the operation procedure to change the electronic gear numerator (parameter No.PA06) to "123456".

(Note)



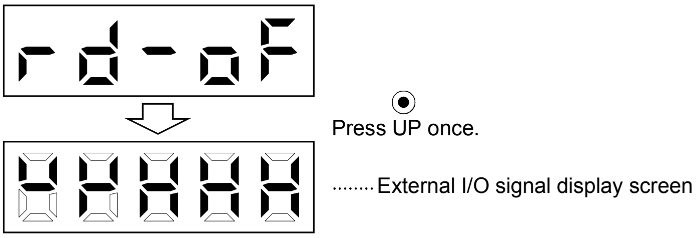
Note. The example assumes that the status display screen that appears at power-on has been set to the servo motor speed in parameter No.PC36.

6.7 External I/O signal display

The ON/OFF states of the digital I/O signals connected to the servo amplifier can be confirmed.

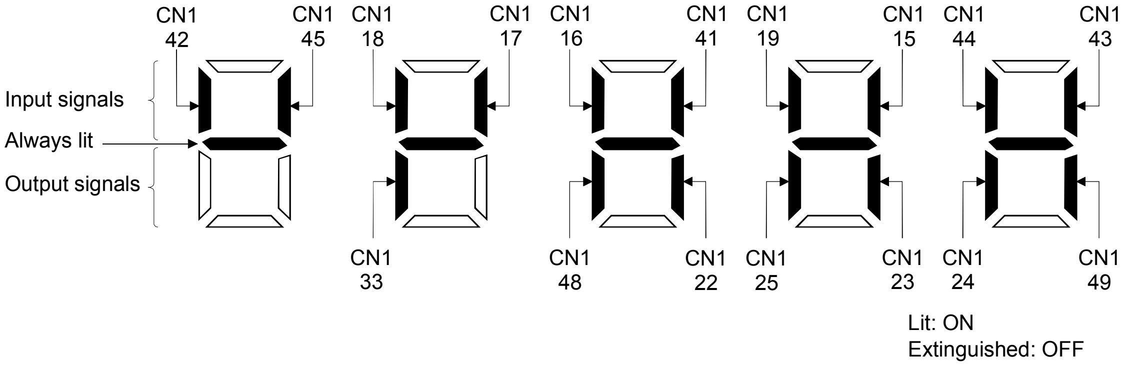
(1) Operation

After power-on, change the display mode to the diagnostic mode using the "MODE" button.



(2) Display definition

The 7-segment LED segments and CN1 connector pins correspond as shown below.



The LED segment corresponding to the pin is lit to indicate ON, and is extinguished to indicate OFF. The signals corresponding to the pins in the respective control modes are indicated below.

(a) Control modes and I/O signals

Connector	Pin No.	Signal input/output (Note 1) I/O	(Note 2) Symbols of I/O signals in control modes						Related parameter
			P	P/S	S	S/T	T	T/P	
CN1	15	I	SON	SON	SON	SON	SON	SON	No.PD03
	16	I		－/SP2	SP2	SP2/SP2	SP2	SP2/－	No.PD04
	17	I	PC	PC/ST1	ST1	ST1/RS2	RS2	RS2/PC	No.PD05
	18	I	TL	TL/ST2	ST2	ST2/RS1	RS1	RS1/TL	No.PD06
	19	I	RES	RES	RES	RES	RES	RES	No.PD07
	22	O	INP	INP/SA	SA	SA/－		－/INP	No.PD13
	23	O	ZSP	ZSP	ZSP	ZSP	ZSP	ZSP	No.PD14
	24	O	INP	INP/SA	SA	SA/－		－/INP	No.PD15
	25	O	TLC	TLC	TLC	TLC/VLC	VLC	VLC/TLC	No.PD16
	33	O	OP	OP	OP	OP	OP	OP	
	41	I	CR	CR/SP1	SP1	SP1/SP1	SP1	SP1/CR	No.PD08
	42	I	EMG	EMG	EMG	EMG	EMG	EMG	
	43	I	LSP	LSP	LSP	LSP/－		－/LSP	No.PD10
	44	I	LSN	LSN	LSN	LSN/－		－/LSN	No.PD11
	45	I	LOP	LOP	LOP	LOP	LOP	LOP	No.PD12
	48	O	ALM	ALM	ALM	ALM	ALM	ALM	
	49	O	RD	RD	RD	RD	RD	RD	No.PD18

Note 1. I: Input signal, O: Output signal

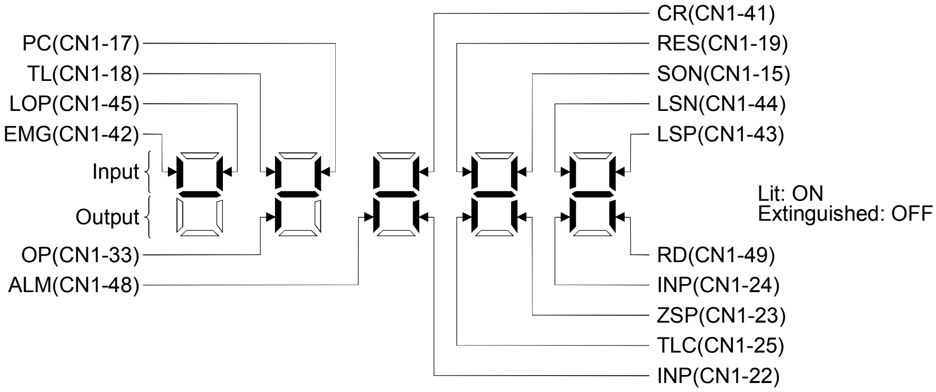
2. P: Position control mode, S: Speed control mode, T: Torque control mode, P/S: Position/speed control change mode, S/T: Speed/torque control change mode, T/P: Torque/position control change mode

(b) Symbol and signal names

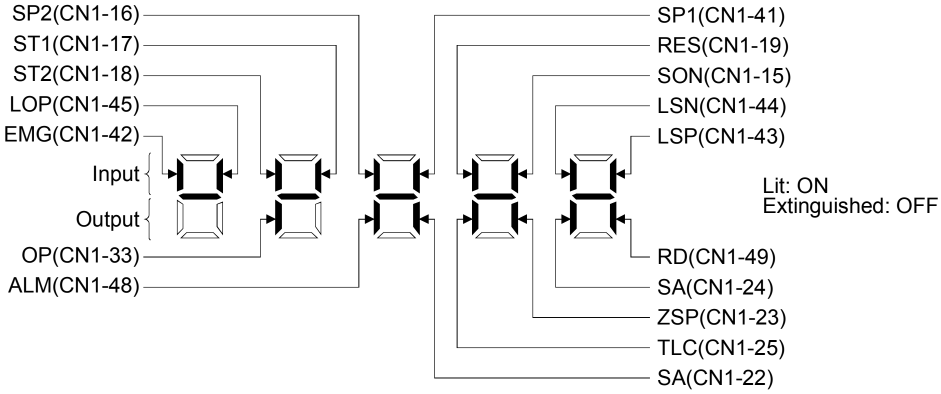
Symbol	Signal name	Symbol	Signal name
SON	Servo-on	RES	Reset
LSP	Forward rotation stroke end	EMG	Emergency stop
LSN	Reverse rotation stroke end	LOP	Control change
CR	Clear	TLC	Limiting torque
SP1	Speed selection 1	VLC	Limiting speed
SP2	Speed selection 2	RD	Ready
PC	Proportion control	ZSP	Zero speed detection
ST1	Forward rotation start	INP	In-position
ST2	Reverse rotation start	SA	Speed reached
RS1	Forward rotation selection	ALM	Trouble
RS2	Reverse rotation selection	OP	Encoder Z-phase pulse (open collector)
TL	External torque limit selection		

(3) Display data at initial values

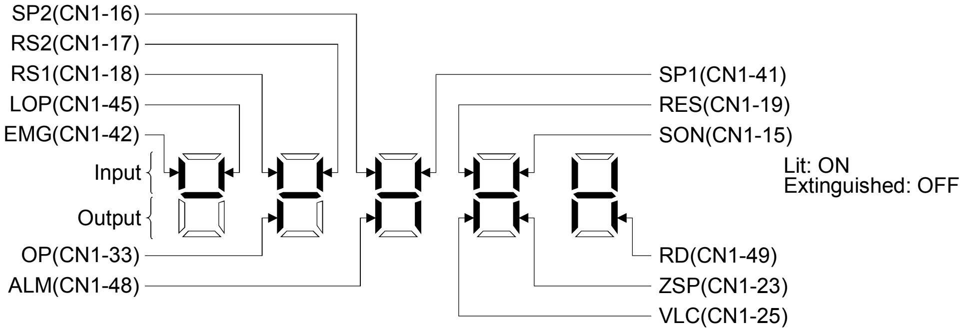
(a) Position control mode



(b) Speed control mode



(c) Torque control mode



6.8 Output signal (DO) forced output

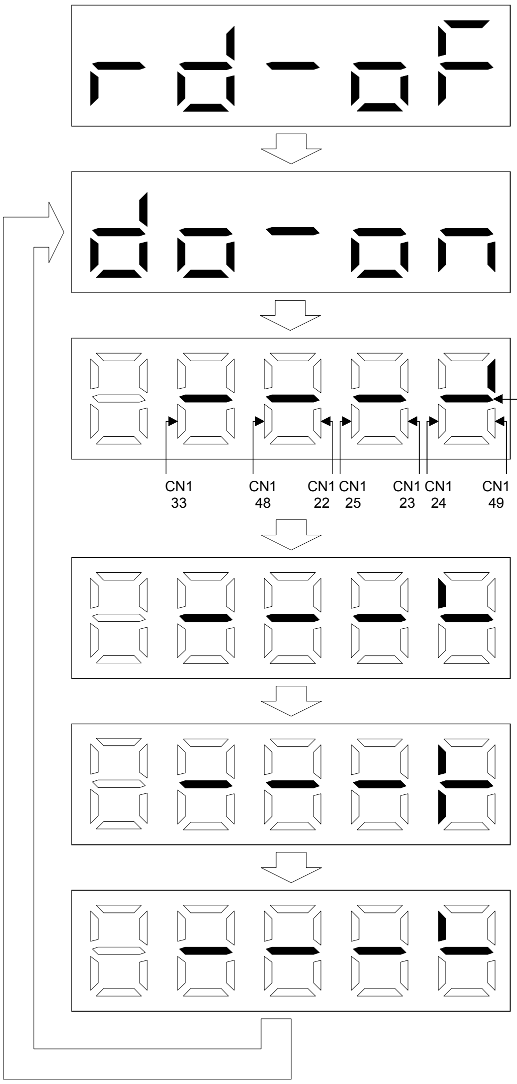
POINT

- When the servo system is used in a vertical lift application, turning on the electromagnetic brake interlock (MBR) by the DO forced output after assigning it to connector CN1 will release the electromagnetic brake, causing a drop. Take drop preventive measures on the machine side.

The output signal can be forced on/off independently of the servo status. This function is used for output signal wiring check, etc. This operation must be performed in the servo off state by turning off the servo-on (SON).

Operation

After power-on, change the display mode to the diagnostic mode using the "MODE" button.



Press UP twice.

Press SET for longer than 2 seconds.

······ Switch on/off the signal below the lit segment.

Always lit

······ Indicates the ON/OFF of the output signal. The correspondences between segments and signals are as in the output signals of the external I/O signal display. (Lit: ON, extinguished: OFF)

Press MODE once.

······ The segment above CN1-pin 24 is lit.

Press UP once.

······ CN1-pin 24 is switched on. (CN1-pin 24-DOCOM conduct.)

Press DOWN once.

······ CN1-pin 24 is switched off.

Press SET for longer than 2 seconds.

6.9 Test operation mode

⚠ CAUTION

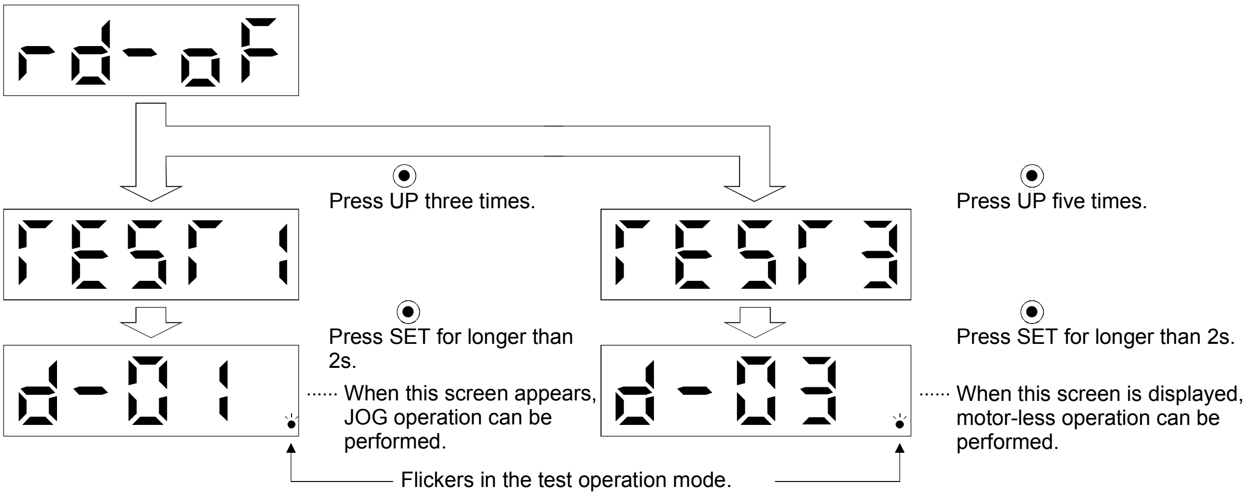
- The test operation mode is designed to confirm servo operation. Do not use it for actual operation.
- If any operational fault has occurred, stop operation using the emergency stop (EMG) signal.

POINT

- The test operation mode cannot be used in the absolute position detection system by DIO (parameter No.PA03: □□□1).
- The MR Configurator is required to perform positioning operation.
- Test operation cannot be performed if the servo-on (SON) is not turned OFF.

6.9.1 Mode change

After power-on, change the display mode to the diagnostic mode using the "MODE" button. Choose JOG operation/motor-less operation in the following procedure.



6.9.2 JOG operation

POINT

- When performing JOG operation, turn ON EMG, LSP and LSN. LSP and LSN can be set to automatic ON by setting parameter No.PD01 to "□C□□".

JOG operation can be performed when there is no command from the external command device.

(1) Operation

The servo motor rotates while holding down the "UP" or the "DOWN" button. The servo motor stops rotating by releasing the button. The operation condition can be changed using the MR Configurator. The initial conditions and setting ranges for operation are listed below.

Item	Initial setting	Setting range
Speed [r/min]	200	0 to instantaneous permissible speed
Acceleration/deceleration time constant [ms]	1000	0 to 50000

How to use the buttons is explained below.

Button	Description
"UP"	Press to start CCW rotation. Release to stop.
"DOWN"	Press to start CW rotation. Release to stop.

If the communication cable is disconnected during JOG operation using the MR Configurator, the servo motor decelerates to a stop.

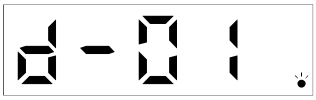
(2) Status display

Call the status display screen by pressing the "MODE" button in the JOG operation stand-by status. When the JOG operation is performed using the “UP” or the “DOWN” button, the servo status appears on the display.

The status display screen shifts to the next screen every time the "MODE" button is pressed. For details of the status display, refer to section 5.3. The status display screen returns to the JOG operation stand-by screen after one screen cycle. Note that the status display screen cannot be changed by the "UP" or the "DOWN" button in the JOG operation mode.

(3) Termination of JOG operation

To end the JOG operation, turn the power off once or press the "MODE" button to switch to the next screen, and then hold down the "SET" button for 2[s] or longer.

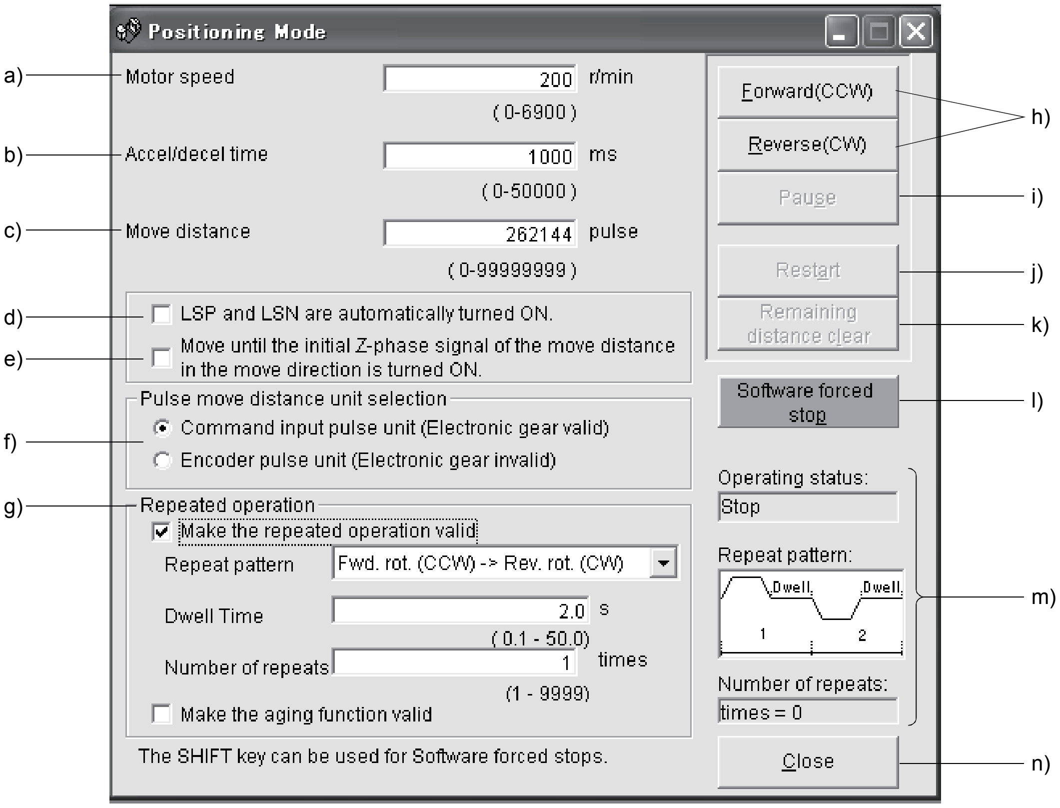


6.9.3 Positioning operation

POINT
- MR Configurator is required to perform positioning operation.
- Turn ON EMG when performing positioning operation.

With no command given from the external command device, positioning operation can be executed.

(1) Operation



Motor speed 200 r/min (0-6900)

Accel/decel time 1000 ms (0-50000)

Move distance 262144 pulse (0-99999999)

☐ LSP and LSN are automatically turned ON.

☐ Move until the initial Z-phase signal of the move distance in the move direction is turned ON.

Pulse move distance unit selection

● Command input pulse unit (Electronic gear valid)

○ Encoder pulse unit (Electronic gear invalid)

Repeated operation

☑ Make the repeated operation valid

Repeat pattern Fwd. rot. (CCW) -> Rev. rot. (CW)

Dwell Time 2.0 s (0.1 - 50.0)

Number of repeats 1 times (1 - 9999)

☐ Make the aging function valid

The SHIFT key can be used for Software forced stops.

Operating status: Stop

Repeat pattern:

Number of repeats: times = 0

a) Motor speed [r/min]
Enter the servo motor speed into the "Motor speed" input field.

b) Accel/decel time [ms]
Enter the acceleration/deceleration time constant into the "Accel/decel time" input field.

c) Move distance [pulse]
Enter the moving distance into the "Move distance" input field.

d) LSP and LSN are automatically turned ON
When setting the external stroke signal to automatic ON, click the check box to make it valid. When it is not checked, turn ON LSP and LSN externally.

e) Move until the initial Z-phase signal of the move distance in the move direction is turned ON.
Movement is made until the moving distance is reached and the first Z-phase signal in the moving direction turns ON.

f) Pulse move distance unit selection

Select with the option buttons whether the moving distance set in c) is in the command pulse unit or in the encoder pulse unit.

When the command input pulse unit is selected, the value, which is the set moving distance multiplied by the electronic gear ($\frac{CMX}{CDV}$), will be the command value. When the encoder pulse unit is selected, the moving distance is not multiplied by the electronic gear.

g) Repeat operation

To perform the repeated operation, click the check box of "Make the repeated operation valid". The next table shows the initial setting and the setting range of the repeated operation.

Item	Initial setting	Setting range
Repeat pattern	Fwd. rot.(CCW)→Rev. rot. (CW)	Fwd. rot.(CCW)→Rev. rot. (CW) Fwd. rot.(CCW)→Fwd. rot.(CCW) Rev. rot. (CW)→Fwd. rot.(CCW) Rev. rot. (CW)→Rev. rot. (CW)
Dwell time [s]	2.0	0.1 to 50.0
Number of repeats [times]	1	1 to 9999

To perform continuous operation with the repeat pattern and dwell time settings, which are set by referring to the above table, click the check box of "Make the aging function valid".

h) Forward/Reverse

Click the "Forward" button to rotate the servo motor in the forward rotation direction.

Click the "Reverse" button to rotate the servo motor in the reverse rotation direction.

i) Pause

Click the "Pause" button during servo motor rotation to temporarily stop the servo motor.

This button is valid during servo motor rotation.

j) Restart

Click the "Restart" button during a temporary stop to restart the servo motor rotation.

This button is valid during a temporary stop of the servo motor.

k) Remaining distance clear

Click the "Remaining distance clear" button during a temporary stop to erase the remaining distance.

This button is valid during a temporary stop of the servo motor.

l) Software forced stop

Click the "Software forced stop" button during servo motor rotation to make a hard stop.

This button is valid during servo motor rotation.

m) Repeat operation status

Display the operation status, the repeat pattern, and the number of repeats during the repeated operation.

n) Close

Click the "Close" button to cancel the positioning operation mode and close the window.

(2) Status display

The status display can be monitored during positioning operation.

6.9.4 Motor-less operation

Without connecting the servo motor, you can provide output signals or monitor the status display as if the servo motor is running in response to input device. This operation can be used to check the sequence of a host programmable controller or the like.

(1) Operation

Turn SON off, and then select motor-less operation. After that, perform external operation as in ordinary operation.

(2) Status display

Change the display to the status display screen by pressing the "MODE" button. (Refer to section 6.2.)
The status screen can be changed by pressing the "UP" or the "DOWN" button. (Refer to section 6.3.)

(3) Termination of motor-less operation

To terminate the motor-less operation, switch power off.

MEMO

7. GENERAL GAIN ADJUSTMENT

POINT

- Consider individual machine differences, and do not adjust gain too strictly. It is recommended to keep the servo motor torque to 90% or less of the maximum torque of the servo motor during the operation.
- For use in the torque control mode, you need not make gain adjustment.

7.1 Different adjustment methods

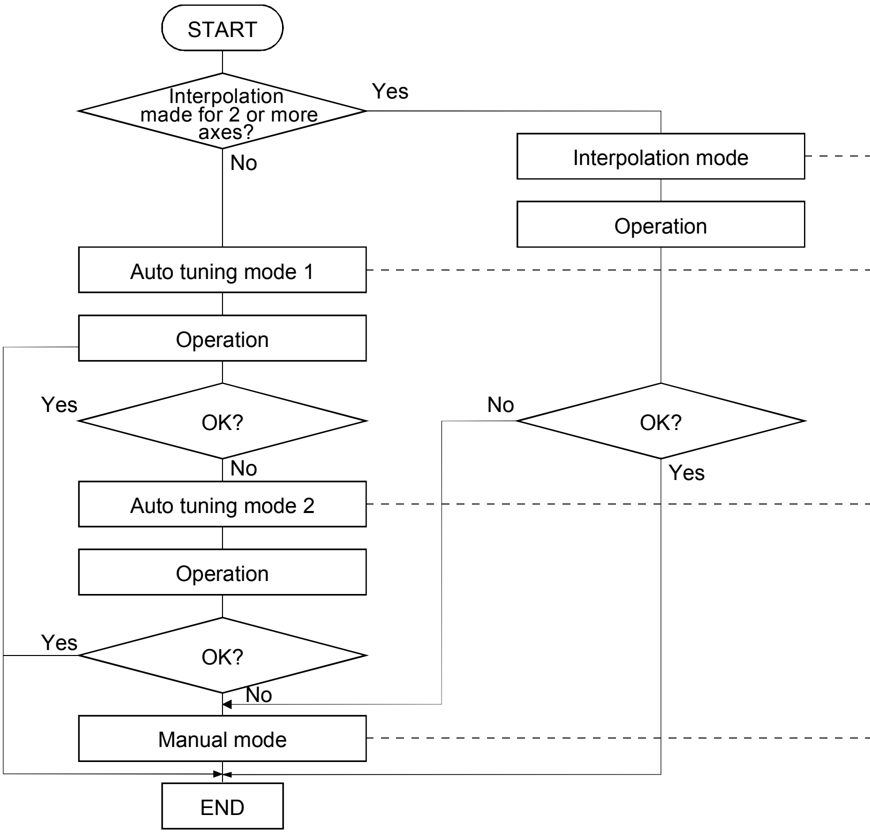
7.1.1 Adjustment on a single servo amplifier

The gain adjustment in this section can be made on a single servo amplifier. For gain adjustment, first execute auto tuning mode 1. If you are not satisfied with the results, execute auto tuning mode 2 and manual mode in this order.

(1) Gain adjustment mode explanation

Gain adjustment mode	Parameter No. PA08 setting	Estimation of load inertia moment ratio	Automatically set parameters	Manually set parameters
Auto tuning mode 1 (initial value)	0001	Always estimated	GD2 (parameter No.PB06) PG1 (parameter No.PB07) PG2 (parameter No.PB08) VG2 (parameter No.PB09) VIC (parameter No.PB10)	RSP (parameter No.PA09)
Auto tuning mode 2	0002	Fixed to parameter No. PB06 value	PG1 (parameter No.PB07) PG2 (parameter No.PB08) VG2 (parameter No.PB09) VIC (parameter No.PB10)	GD2 (parameter No.PB06) RSP (parameter No.PA09)
Manual mode	0003			GD2 (parameter No.PB06) PG1 (parameter No.PB07) PG2 (parameter No.PB08) VG2 (parameter No.PB09) VIC (parameter No.PB10)
Interpolation mode	0000	Always estimated	GD2 (parameter No.PB06) PG2 (parameter No.PB08) VG2 (parameter No.PB09) VIC (parameter No.PB10)	PG1 (parameter No.PB07) RSP (parameter No.PA09)

(2) Adjustment sequence and mode usage



Usage
Used when you want to match the position gain (PG1) between 2 or more axes. Normally not used for other purposes.
Allows adjustment by merely changing the response level setting. First use this mode to make adjustment.
Used when the conditions of auto tuning mode 1 are not met and the load inertia moment ratio could not be estimated properly, for example.
You can adjust all gains manually when you want to do fast settling or the like.

7.1.2 Adjustment using MR Configurator

This section gives the functions and adjustment that may be performed by using the servo amplifier with the MR Configurator which operates on a personal computer.

Function	Description	Adjustment
Machine analyzer	With the machine and servo motor coupled, the characteristic of the mechanical system can be measured by giving a random vibration command from the personal computer to the servo and measuring the machine response.	· You can grasp the machine resonance frequency and determine the notch frequency of the machine resonance suppression filter. · You can automatically set the optimum gains in response to the machine characteristic. This simple adjustment is suitable for a machine which has large machine resonance and does not require much settling time.
Gain search	Executing gain search under to-and-fro positioning command measures settling characteristic while simultaneously changing gains, and automatically searches for gains which make settling time shortest.	· You can automatically set gains which make positioning settling time shortest.
Machine simulation	Response at positioning settling of a machine can be simulated from machine analyzer results on personal computer.	· You can optimize gain adjustment and command pattern on personal computer.

7.2 Auto tuning

7.2.1 Auto tuning mode

The servo amplifier has a real-time auto tuning function which estimates the machine characteristic (load inertia moment ratio) in real time and automatically sets the optimum gains according to that value. This function permits ease of gain adjustment of the servo amplifier.

(1) Auto tuning mode 1

The servo amplifier is factory-set to the auto tuning mode 1.

In this mode, the load inertia moment ratio of a machine is always estimated to set the optimum gains automatically.

The following parameters are automatically adjusted in the auto tuning mode 1.

Parameter No.	Abbreviation	Name
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment
PB07	PG1	Model loop gain
PB08	PG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

POINT

- The auto tuning mode 1 may not be performed properly if the following conditions are not satisfied.
  - Time to reach 2000r/min is the acceleration/deceleration time constant of 5s or less.
  - Speed is 150r/min or higher.
  - The ratio of load inertia moment to servo motor inertia moment is 100 times or less.
- The acceleration/deceleration torque is 10% or more of the rated torque.
- Under operating conditions which will impose sudden disturbance torque during acceleration/deceleration or on a machine which is extremely loose, auto tuning may not function properly, either. In such cases, use the auto tuning mode 2 or manual mode to make gain adjustment.

(2) Auto tuning mode 2

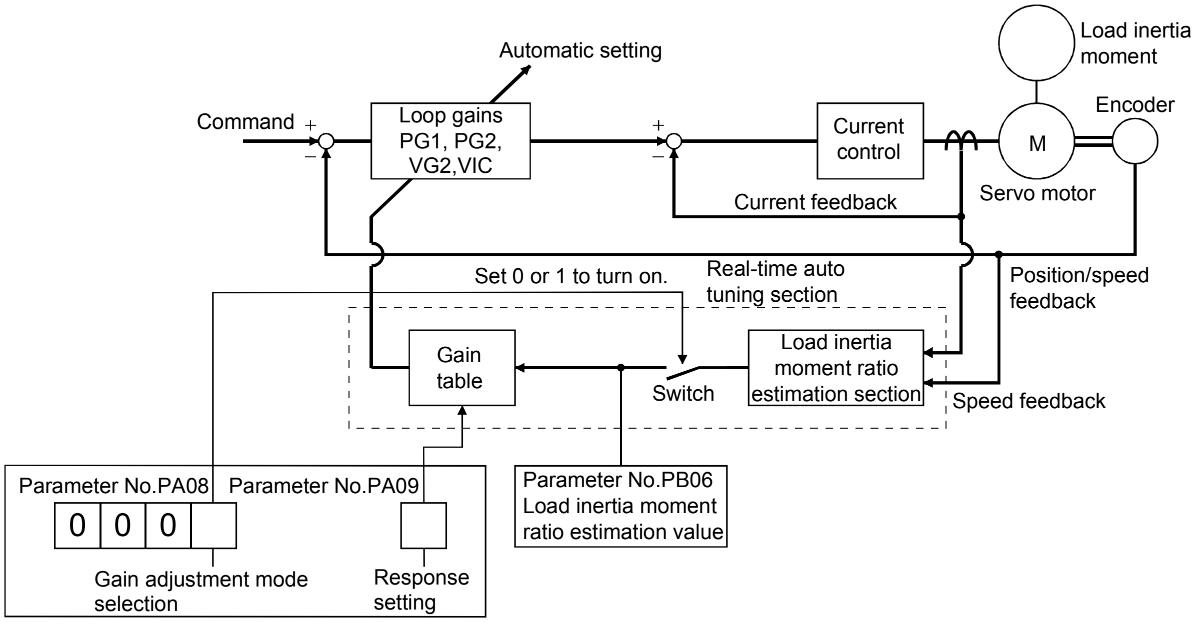
Use the auto tuning mode 2 when proper gain adjustment cannot be made by auto tuning mode 1. Since the load inertia moment ratio is not estimated in this mode, set the value of a correct load inertia moment ratio (parameter No.PB06).

The following parameters are automatically adjusted in the auto tuning mode 2.

Parameter No.	Abbreviation	Name
PB07	PG1	Model loop gain
PB08	PG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

7.2.2 Auto tuning mode basis

The block diagram of real-time auto tuning is shown below.



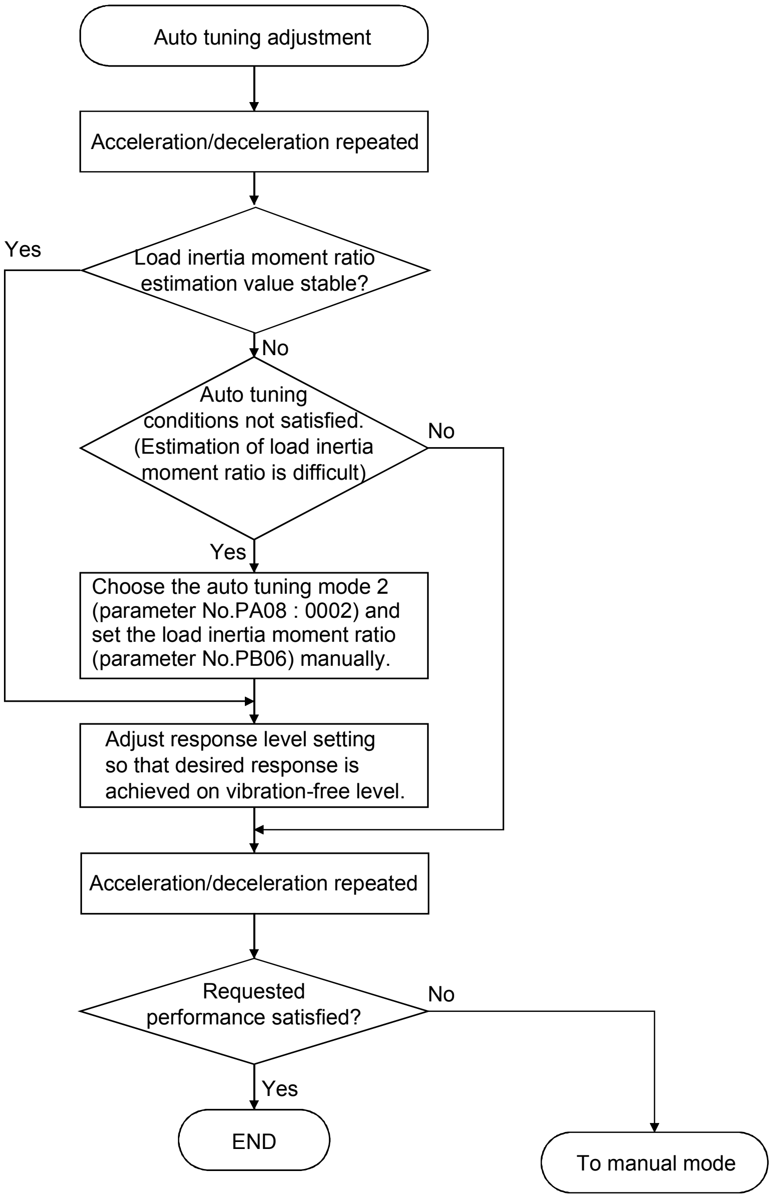
When a servo motor is accelerated/decelerated, the load inertia moment ratio estimation section always estimates the load inertia moment ratio from the current and speed of the servo motor. The results of estimation are written to parameter No.PB06 (the ratio of load inertia moment to servo motor). These results can be confirmed on the status display screen of the MR Configurator section.
If the value of the load inertia moment ratio is already known or if estimation cannot be made properly, chose the "auto tuning mode 2" (parameter No.PA08: 0002) to stop the estimation of the load inertia moment ratio (Switch in above diagram turned off), and set the load inertia moment ratio (parameter No.PB06) manually.
From the preset load inertia moment ratio (parameter No.PB06) value and response level (parameter No. PA09), the optimum loop gains are automatically set on the basis of the internal gain tale.
The auto tuning results are saved in the EEP-ROM of the servo amplifier every 60 minutes since power-on. At power-on, auto tuning is performed with the value of each loop gain saved in the EEP-ROM being used as an initial value.

POINT

- If sudden disturbance torque is imposed during operation, the estimation of the inertia moment ratio may malfunction temporarily. In such a case, choose the "auto tuning mode 2" (parameter No.PA08: 0002) and set the correct load inertia moment ratio in parameter No.PB06.
- When any of the auto tuning mode 1 and auto tuning mode settings is changed to the manual mode 2 setting, the current loop gains and load inertia moment ratio estimation value are saved in the EEP-ROM.

7.2.3 Adjustment procedure by auto tuning

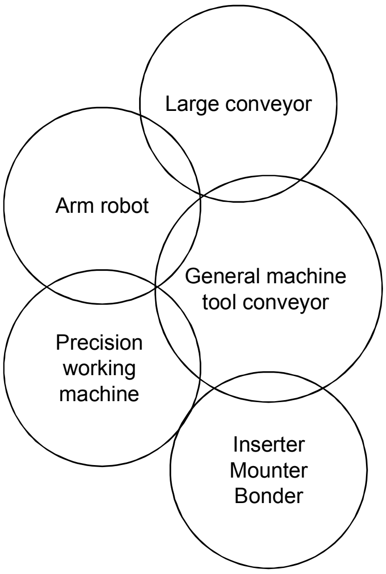
Since auto tuning is made valid before shipment from the factory, simply running the servo motor automatically sets the optimum gains that match the machine. Merely changing the response level setting value as required completes the adjustment. The adjustment procedure is as follows.



7.2.4 Response level setting in auto tuning mode

Set the response (The first digit of parameter No.PA09) of the whole servo system. As the response level setting is increased, the track ability and settling time for a command decreases, but a too high response level will generate vibration. Hence, make setting until desired response is obtained within the vibration-free range. If the response level setting cannot be increased up to the desired response because of machine resonance beyond 100Hz, adaptive tuning mode (parameter No.PB01) or machine resonance suppression filter (parameter No.PB13 to PB16) may be used to suppress machine resonance. Suppressing machine resonance may allow the response level setting to increase. Refer to section 8.2, 8.3 for adaptive tuning mode and machine resonance suppression filter.

Setting of parameter No.PA09

Response level setting	Machine characteristic		
	Machine rigidity	Machine resonance frequency guideline	Guideline of corresponding machine
1	Low	10.0	
2		11.3	
3		12.7	
4		14.3	
5		16.1	
6		18.1	
7		20.4	
8		23.0	
9		25.9	
10		29.2	
11		32.9	
12		37.0	
13		41.7	
14		47.0	
15		52.9	
16	Middle	59.6	
17		67.1	
18		75.6	
19		85.2	
20		95.9	
21		108.0	
22		121.7	
23		137.1	
24		154.4	
25		173.9	
26		195.9	
27		220.6	
28		248.5	
29		279.9	
30		315.3	
31		355.1	
32	High	400.0	

7.3 Manual mode 1 (simple manual adjustment)

If you are not satisfied with the adjustment of auto tuning, you can make simple manual adjustment with three parameters.

> **POINT**
>
> - If machine resonance occurs, adaptive tuning mode (parameter No.PB01) or machine resonance suppression filter (parameter No.PB13 to PB16) may be used to suppress machine resonance. (Refer to section 8.3.)

(1) For speed control

(a) Parameters

The following parameters are used for gain adjustment.

Parameter No.	Abbreviation	Name
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment
PB07	PG1	Model loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

(b) Adjustment procedure

Step	Operation	Description
1	Brief-adjust with auto tuning. Refer to section 7.2.3.	
2	Change the setting of auto tuning to the manual mode (Parameter No.PA08: 0003).	
3	Set an estimated value to the ratio of load inertia moment to servo motor inertia moment. (If the estimate value with auto tuning is correct, setting change is not required.)	
4	Set a slightly smaller value to the model loop gain. Set a slightly larger value to the speed integral compensation.	
5	Increase the speed loop gain within the vibration- and unusual noise-free range, and return slightly if vibration takes place.	Increase the speed loop gain.
6	Decrease the speed integral compensation within the vibration-free range, and return slightly if vibration takes place.	Decrease the time constant of the speed integral compensation.
7	Increase the model loop gain, and return slightly if overshooting takes place.	Increase the model loop gain.
8	If the gains cannot be increased due to mechanical system resonance or the like and the desired response cannot be achieved, response may be increased by suppressing resonance with adaptive tuning mode or machine resonance suppression filter and then executing steps 3 to 7.	Suppression of machine resonance. Refer to section 8.2, 8.3.
9	While checking the rotational status, fine-adjust each gain.	Fine adjustment

(c) Adjustment description

1) Speed loop gain (parameter No.PB09)

This parameter determines the response level of the speed control loop. Increasing this value enhances response but a too high value will make the mechanical system liable to vibrate. The actual response frequency of the speed loop is as indicated in the following expression.

$$\text{Speed loop response frequency(Hz)} = \frac{\text{Speed loop gain setting}}{(1+\text{ratio of load inertia moment to servo motor inertia moment})\times 2\pi}$$

2) Speed integral compensation (VIC: parameter No.PB10)

To eliminate stationary deviation against a command, the speed control loop is under proportional integral control. For the speed integral compensation, set the time constant of this integral control. Increasing the setting lowers the response level. However, if the load inertia moment ratio is large or the mechanical system has any vibratory element, the mechanical system is liable to vibrate unless the setting is increased to some degree. The guideline is as indicated in the following expression.

$$\text{Speed integral compensation setting(ms)} \geq \frac{2000 \text{ to } 3000}{\text{Speed loop gain setting}/\,(1+\text{ratio of load inertia moment to servo motor inertia moment setting})}$$

(2) For position control

(a) Parameters

The following parameters are used for gain adjustment.

Parameter No.	Abbreviation	Name
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment
PB07	PG1	Model loop gain
PB08	PG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

(b) Adjustment procedure

Step	Operation	Description
1	Brief-adjust with auto tuning. Refer to section 7.2.3.	
2	Change the setting of auto tuning to the manual mode (Parameter No.PA08: 0003).	
3	Set an estimated value to the ratio of load inertia moment to servo motor inertia moment. (If the estimate value with auto tuning is correct, setting change is not required.)	
4	Set a slightly smaller value to the model loop gain and the position loop gain. Set a slightly larger value to the speed integral compensation.	
5	Increase the speed loop gain within the vibration- and unusual noise-free range, and return slightly if vibration takes place.	Increase the speed loop gain.
6	Decrease the speed integral compensation within the vibration-free range, and return slightly if vibration takes place.	Decrease the time constant of the speed integral compensation.
7	Increase the position loop gain, and return slightly if vibration takes place.	Increase the position loop gain.
8	Increase the model loop gain, and return slightly if overshooting takes place.	Increase the position loop gain.
9	If the gains cannot be increased due to mechanical system resonance or the like and the desired response cannot be achieved, response may be increased by suppressing resonance with adaptive tuning mode or machine resonance suppression filter and then executing steps 3 to 8.	Suppression of machine resonance. Refer to section 8.2・8.3.
10	While checking the settling characteristic and rotational status, fine-adjust each gain.	Fine adjustment

(c) Adjustment description

1) Model loop gain (parameter No.PB07)

This parameter determines the response level of the model loop. Increasing position loop gain 1 improves track ability to a position command but a too high value will make overshooting liable to occur at the time of settling.

$$\text{Model loop gain guideline} \leq \frac{\text{Speed loop gain setting}}{(1+\text{ratio of load inertia moment to servo motor inertia moment})} \times \left(\frac{1}{4}\text{ to }\frac{1}{8}\right)$$

2) Speed loop gain (VG2: parameter No.PB09)

This parameter determines the response level of the speed control loop. Increasing this value enhances response but a too high value will make the mechanical system liable to vibrate. The actual response frequency of the speed loop is as indicated in the following expression.

$$\text{Speed loop response frequency (Hz)} = \frac{\text{Speed loop gain setting}}{(1+\text{ratio of load inertia moment to servo motor inertia moment}) \times 2\pi}$$

3) Speed integral compensation (parameter No.PB10)

To eliminate stationary deviation against a command, the speed control loop is under proportional integral control. For the speed integral compensation, set the time constant of this integral control. Increasing the setting lowers the response level. However, if the load inertia moment ratio is large or the mechanical system has any vibratory element, the mechanical system is liable to vibrate unless the setting is increased to some degree. The guideline is as indicated in the following expression.

$$\text{Speed integral compensation setting (ms)} \geq \frac{\text{2000 to 3000}}{\text{Speed loop gain setting}/(1+\text{ratio of load inertia moment to servo motor inertia moment 2 setting})}$$

7.4 Interpolation mode

The interpolation mode is used to match the position loop gains of the axes when performing the interpolation operation of servo motors of two or more axes for an X-Y table or the like. In this mode, manually set the model loop gain that determines command track ability. Other parameters for gain adjustment are set automatically.

(1) Parameter

(a) Automatically adjusted parameters

The following parameters are automatically adjusted by auto tuning.

Parameter No.	Abbreviation	Name
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment
PB08	PG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

(b) Manually adjusted parameters

The following parameters are adjustable manually.

Parameter No.	Abbreviation	Name
PB07	PG1	Model loop gain

(2) Adjustment procedure

Step	Operation	Description
1	Set to the auto tuning mode.	Select the auto tuning mode 1.
2	During operation, increase the response level setting (parameter No.PA09), and return the setting if vibration occurs.	Adjustment in auto tuning mode 1.
3	Check the values of model loop gain.	Check the upper setting limits.
4	Set the interpolation mode (parameter No.PA08: 0000).	Select the interpolation mode.
5	Set the model loop gain of all the axes to be interpolated to the same value. At that time, adjust to the setting value of the axis, which has the smallest model loop gain.	Set model loop gain.
6	Looking at the interpolation characteristic and rotation status, fine-adjust the gains and response level setting.	Fine adjustment.

(3) Adjustment description

(a) Model loop gain (parameter No.PB07)

This parameter determines the response level of the position control loop. Increasing model loop gain improves track ability to a position command but a too high value will make overshooting liable to occur at the time of settling. The droop pulses are determined by the following expression.

$$\text{Droop pulses (pulse)} = \frac{\frac{\text{Rotation speed (r/min)}}{60} \times 262144\text{(pulse)}}{\text{Model loop gain setting}}$$

7.5 Differences between MELSERVO-J2-Super and MELSERVO-J3 in auto tuning

To meet higher response demands, the MELSERVO-J3 series has been changed in response level setting range from the MELSERVO-J2-Super series. The following table lists comparison of the response level setting.

MELSERVO-J2-Super		MELSERVO-J3	
Parameter No.2 setting	Guideline for machine resonance frequency [Hz]	Parameter No.PA09 setting	Guideline for machine resonance frequency [Hz]
		1	10.0
		2	11.3
		3	12.7
□□□1	15	4	14.3
		5	16.1
		6	18.1
□□□2	20	7	20.4
		8	23.0
□□□3	25	9	25.9
□□□4	30	10	29.2
		11	32.9
□□□5	35	12	37.0
		13	41.7
□□□6	45	14	47.0
□□□7	55	15	52.9
		16	59.6
□□□8	70	17	67.1
		18	75.6
□□□9	85	19	85.2
		20	95.9
□□□A	105	21	108.0
		22	121.7
□□□B	130	23	137.1
□□□C	160	24	154.4
		25	173.9
□□□D	200	26	195.9
		27	220.6
□□□E	240	28	248.5
		29	279.9
□□□F	300	30	315.3
		31	355.1
		32	400.0

Note that because of a slight difference in gain adjustment pattern, response may not be the same if the resonance frequency is set to the same value.

MEMO

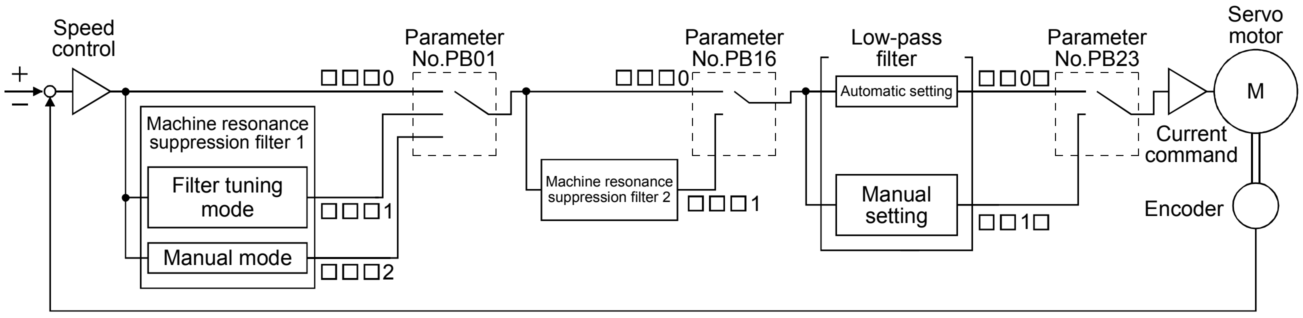
8. SPECIAL ADJUSTMENT FUNCTIONS

POINT

- The functions given in this chapter need not be used generally. Use them if you are not satisfied with the machine status after making adjustment in the methods in chapter 7.

If a mechanical system has a natural resonance point, increasing the servo system response level may cause the mechanical system to produce resonance (vibration or unusual noise) at that resonance frequency.
Using the machine resonance suppression filter and adaptive tuning can suppress the resonance of the mechanical system.

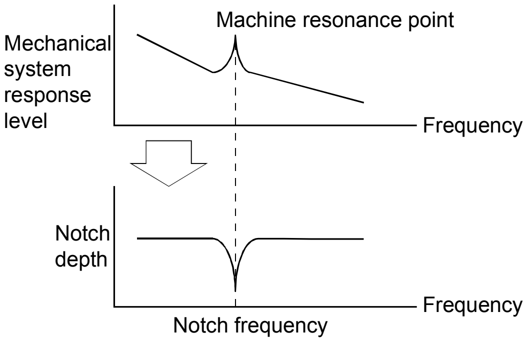
8.1 Function block diagram



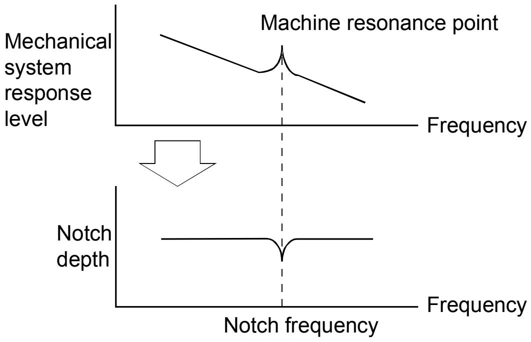
8.2 Adaptive filter Ⅱ

(1) Function

Adaptive filter Ⅱ (adaptive tuning) is a function in which the servo amplifier detects machine vibration for a predetermined period of time and sets the filter characteristics automatically to suppress mechanical system vibration. Since the filter characteristics (frequency, depth) are set automatically, you need not be conscious of the resonance frequency of a mechanical system.



When machine resonance is large and frequency is low



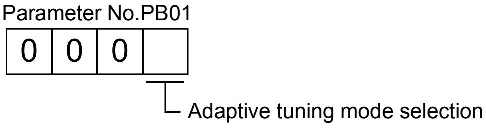
When machine resonance is small and frequency is high

POINT

- The machine resonance frequency which adaptive filter Ⅱ (adaptive tuning) can respond to is about 100 to 2.25kHz. Adaptive vibration suppression control has no effect on the resonance frequency outside this range.
- Adaptive vibration suppression control may provide no effect on a mechanical system which has complex resonance characteristics.

(2) Parameters

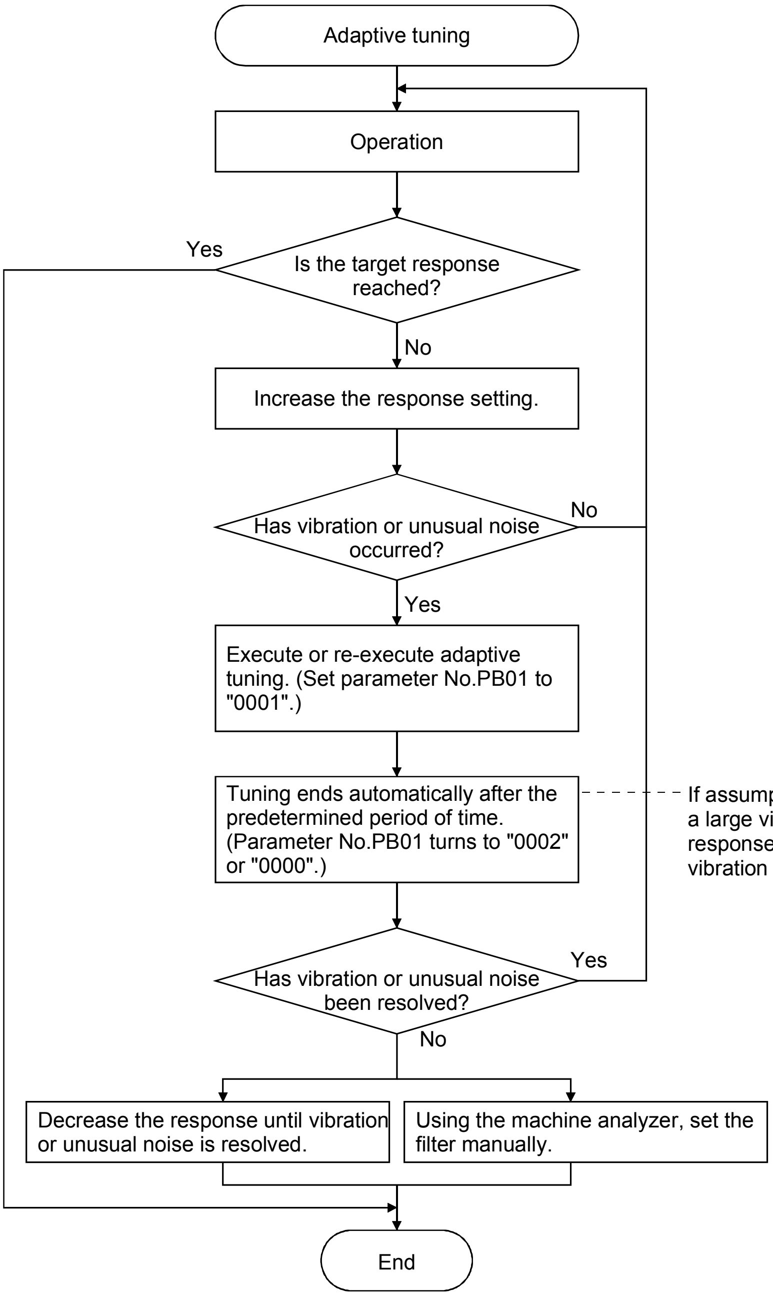
The adjustment mode of adaptive tuning mode (parameter No.PB01).



Setting	Adaptive tuning mode	Automatically set parameter
0	Filter OFF	(Note)
1	Filter tuning mode	Parameter No.PB13 Parameter No.PB14
2	Manual mode	

Note. Parameter No.PB13 and PB14 are fixed to the initial values.

(3) Adaptive tuning procedure



If assumption fails after tuning is executed at a large vibration or oscillation, decrease the response setting temporarily down to the vibration level and execute again.

Factor
- The response has increased to the machine limit.
- The machine is too complicated to provide the optimum filter.

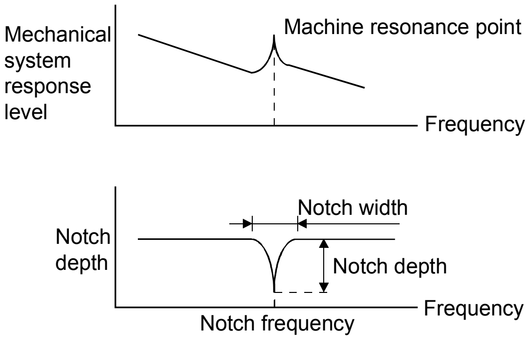
POINT

- "Filter OFF" enables a return to the initial value.
- When adaptive tuning is executed, vibration sound increases as an excitation signal is forcibly applied for several seconds.
- When adaptive tuning is executed, machine resonance is detected for a maximum of 10 seconds and a filter is generated. After filter generation, the adaptive tuning mode automatically shifts to the manual mode.
- Adaptive tuning generates the optimum filter with the currently set control gains. If vibration occurs when the response setting is increased, execute adaptive tuning again.
- During adaptive tuning, a filter having the best notch depth at the set control gain is generated. To allow a filter margin against machine resonance, increase the notch depth in the manual mode.

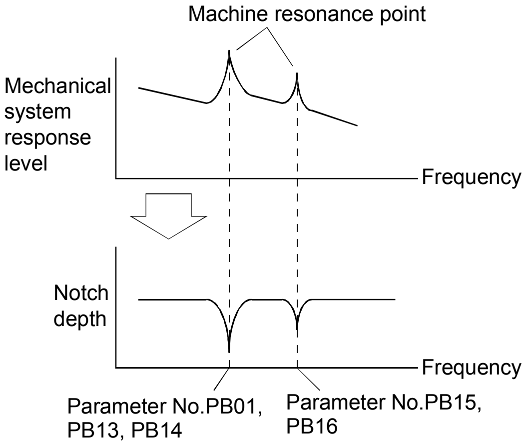
8.3 Machine resonance suppression filter

(1) Function

The machine resonance suppression filter is a filter function (notch filter) which decreases the gain of the specific frequency to suppress the resonance of the mechanical system. You can set the gain decreasing frequency (notch frequency), gain decreasing depth and width.



You can use the machine resonance suppression filter 1 (parameter No.PB13, PB14) and machine resonance suppression filter 2 (parameter No.PB15, PB16) to suppress the vibration of two resonance frequencies. Execution of adaptive tuning in the filter tuning mode automatically adjusts the machine resonance suppression filter. When filter tuning mode is ON, the filter tuning mode shifts to the manual mode after the predetermined period of time. The manual mode enables manual setting using the machine resonance suppression filter 1.



(2) Parameters

(a) Machine resonance suppression filter 1 (parameter No.PB13, PB14)

Set the notch frequency, notch depth and notch width of the machine resonance suppression filter 1 (parameter No.PB13, PB14)

When the "manual mode" is selected in the adaptive tuning mode (parameter No.PB01), the settings of the machine resonance suppression filter 1 are valid.

(b) Machine resonance suppression filter 2 (parameter No.PB15, PB16)

Setting method for the machine resonance suppression filter 2 (parameter No.PB15, PB16) is same as for the machine resonance suppression filter 1 (parameter No.PB13, PB14). However, the machine resonance suppression filter 2 can be set whether the filter tuning mode is valid or not.

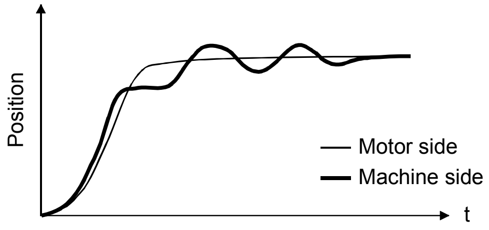
POINT

- The machine resonance suppression filter is a delay factor for the servo system. Hence, vibration may increase if you set a wrong resonance frequency or a too deep notch.
- If the frequency of machine resonance is unknown, decrease the notch frequency from higher to lower ones in order. The optimum notch frequency is set at the point where vibration is minimal.
- A deeper notch has a higher effect on machine resonance suppression but increases a phase delay and may increase vibration.
- A wider notch has a higher effect on machine resonance suppression but increases a phase delay and may increase vibration.
- The machine characteristic can be grasped beforehand by the machine analyzer on the MR Configurator. This allows the required notch frequency and depth to be determined.

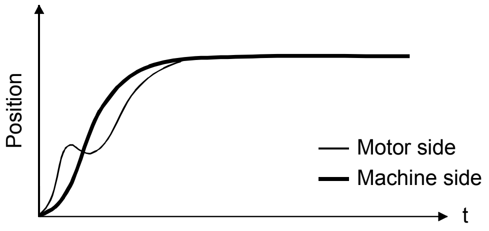
8.4 Advanced vibration suppression control

(1) Operation

Vibration suppression control is used to further suppress machine side vibration, such as workpiece end vibration and base shake. The motor side operation is adjusted for positioning so that the machine does not shake.



Vibration suppression control OFF
(Nomal control)



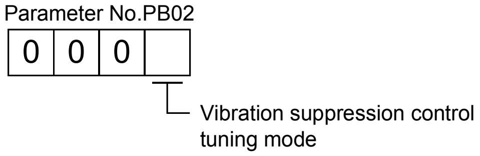
Vibration suppression control ON

When the advanced vibration suppression control (vibration suppression control tuning mode (parameter No.PB02)) is executed, the vibration frequency at machine side can automatically be estimated to suppress machine side vibration.

In the vibration suppression control tuning mode, this mode shifts to the manual mode after positioning operation is performed the predetermined number of times. The manual mode enables manual setting using the vibration suppression control vibration frequency setting (parameter No.PB19) and vibration suppression control resonance frequency setting (parameter No.PB20).

(2) Parameter

Select the adjustment mode of the vibration suppression control tuning mode (parameter No.PB02).



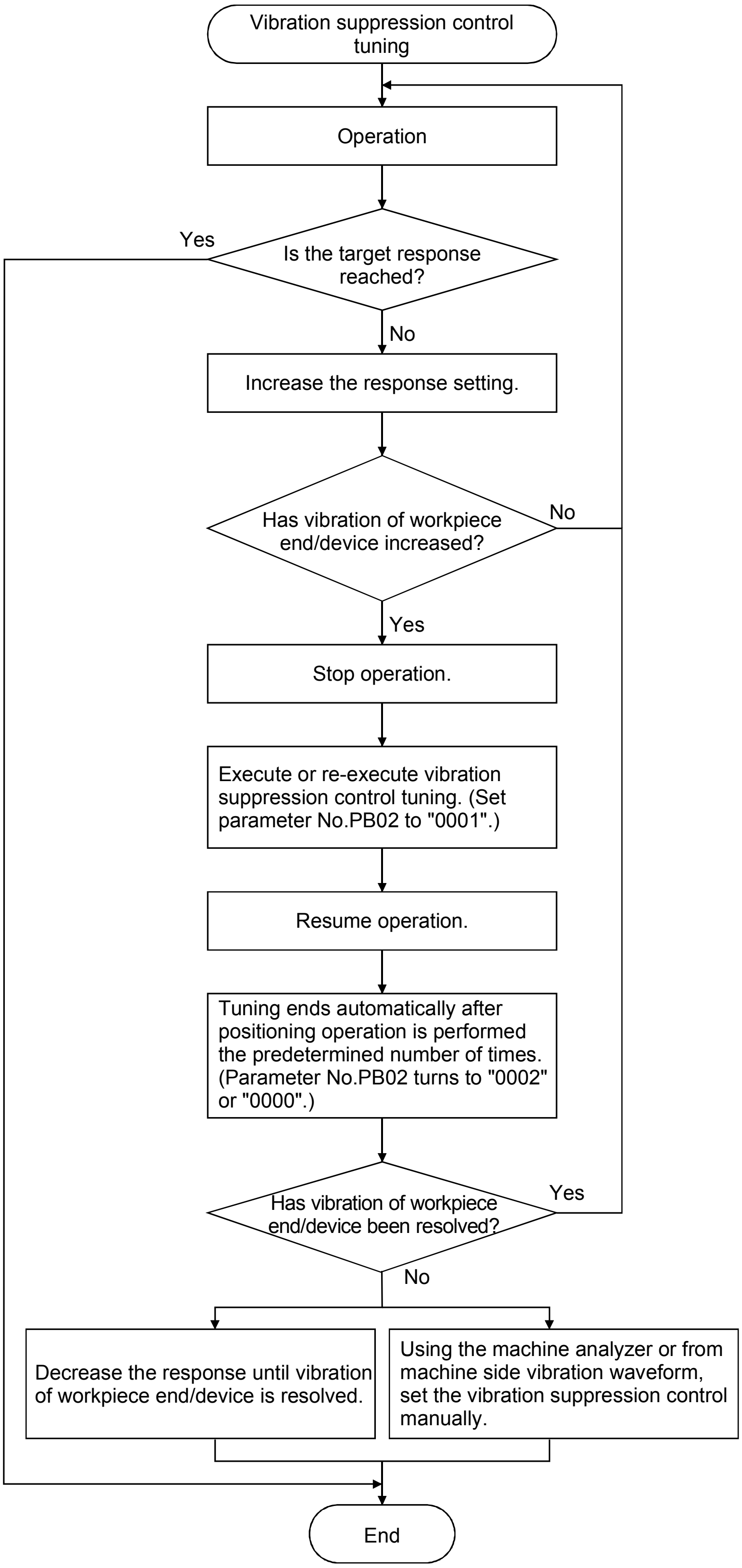
Setting	Vibration suppression control tuning mode	Automatically set parameter
0	Vibration suppression control OFF	(Note)
1	Vibration suppression control tuning mode (Advanced vibration suppression control)	Parameter No.PB19 Parameter No.PB20
2	Manual mode	

Note. Parameter No.PB19 and PB20 are fixed to the initial values.

POINT

- The function is made valid when the auto tuning mode (parameter No.PA08) is the auto tuning mode 2 ("0002") or manual mode ("0003").
- The machine resonance frequency supported in the vibration suppression control tuning mode is 1.0 to 100.0Hz. The function is not effective for vibration outside this range.
- Stop the motor before changing the vibration suppression control-related parameters (parameter No.PB02, PB19, PB20, PB33, PB34). A failure to do so will cause a shock.
- For positioning operation during execution of vibration suppression control tuning, provide a stop time to ensure a stop after full vibration damping.
- Vibration suppression control tuning may not make normal estimation if the residual vibration at the motor side is small.
- Vibration suppression control tuning sets the optimum parameter with the currently set control gains. When the response setting is increased, set vibration suppression control tuning again.

(3) Vibration suppression control tuning procedure

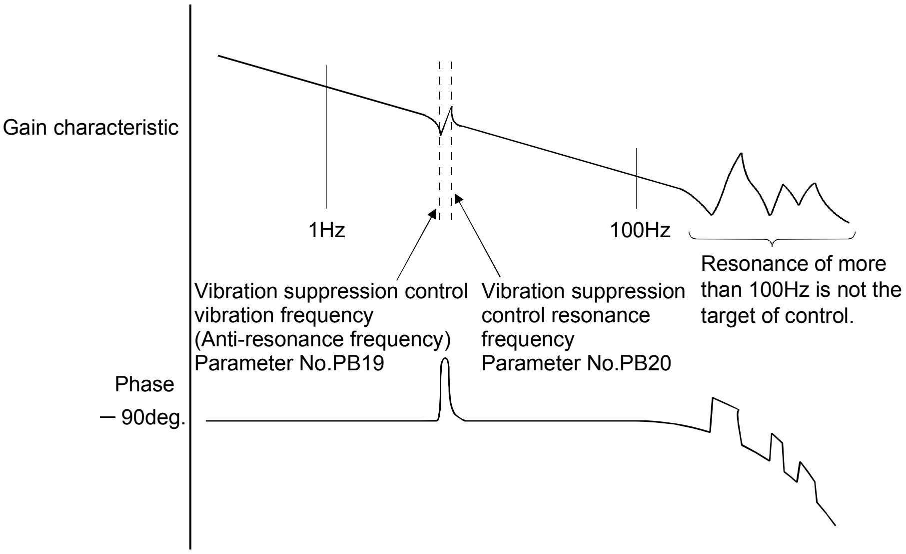


Factor
- Estimation cannot be made as machine side vibration has not been transmitted to the motor side.
- The response of the model loop gain has increased to the machine side vibration frequency (vibration suppression control limit).

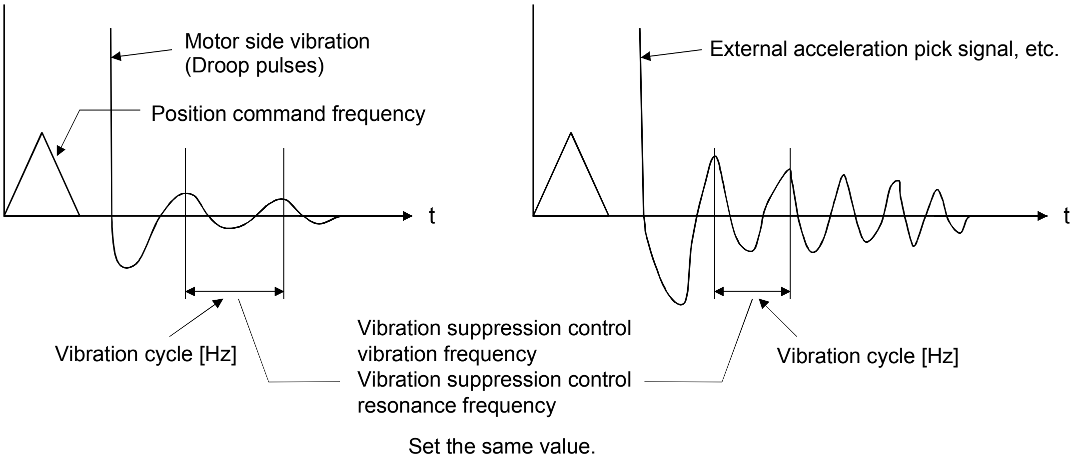
(4) Vibration suppression control manual mode

Measure work side vibration and device shake with the machine analyzer or external measuring instrument, and set the vibration suppression control vibration frequency (parameter No.PB19) and vibration suppression control resonance frequency (parameter No.PB20) to set vibration suppression control manually.

(a) When a vibration peak can be confirmed using machine analyzer by MR Configurator or external measuring instrument



(b) When vibration can be confirmed using monitor signal or external sensor



POINT

- When machine side vibration does not show up in motor side vibration, the setting of the motor side vibration frequency does not produce an effect.
- When the anti-resonance frequency and resonance frequency can be confirmed using the machine analyzer or external measuring instrument, do not set the same value but set different values to improve the vibration suppression performance.
- A vibration suppression control effect is not produced if the relationship between the model loop gain (parameter No.PB07) value and vibration frequency is as indicated below. Make setting after decreasing model loop gain (PG1), e.g. reduce the response setting.

$$\frac{1}{2\pi}(1.5\times \mathrm{PG1}) > \text{vibration frequency}$$

8.5 Low-pass filter

(1) Function

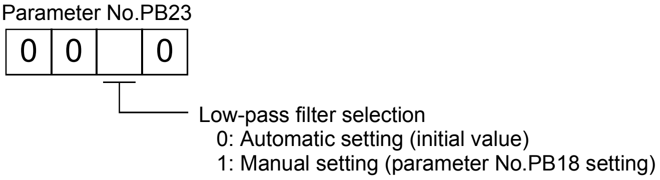
When a ball screw or the like is used, resonance of high frequency may occur as the response level of the servo system is increased. To prevent this, the low-pass filter is initial setting to be valid for a torque command. The filter frequency of this low-pass filter is automatically adjusted to the value in the following expression.

$$\text{Filter frequency(rad/s)} = \frac{\mathrm{VG2}}{1 + \mathrm{GD2}} \times 10$$

When parameter No.PB23 is set to "□□1□", manual setting can be made with parameter No.PB18.

(2) Parameter

Set the low-pass filter selection (parameter No.PB23.)



8.6 Gain changing function

This function can change the gains. You can change between gains during rotation and gains during stop or can use an input device to change gains during operation.

8.6.1 Applications

This function is used when.

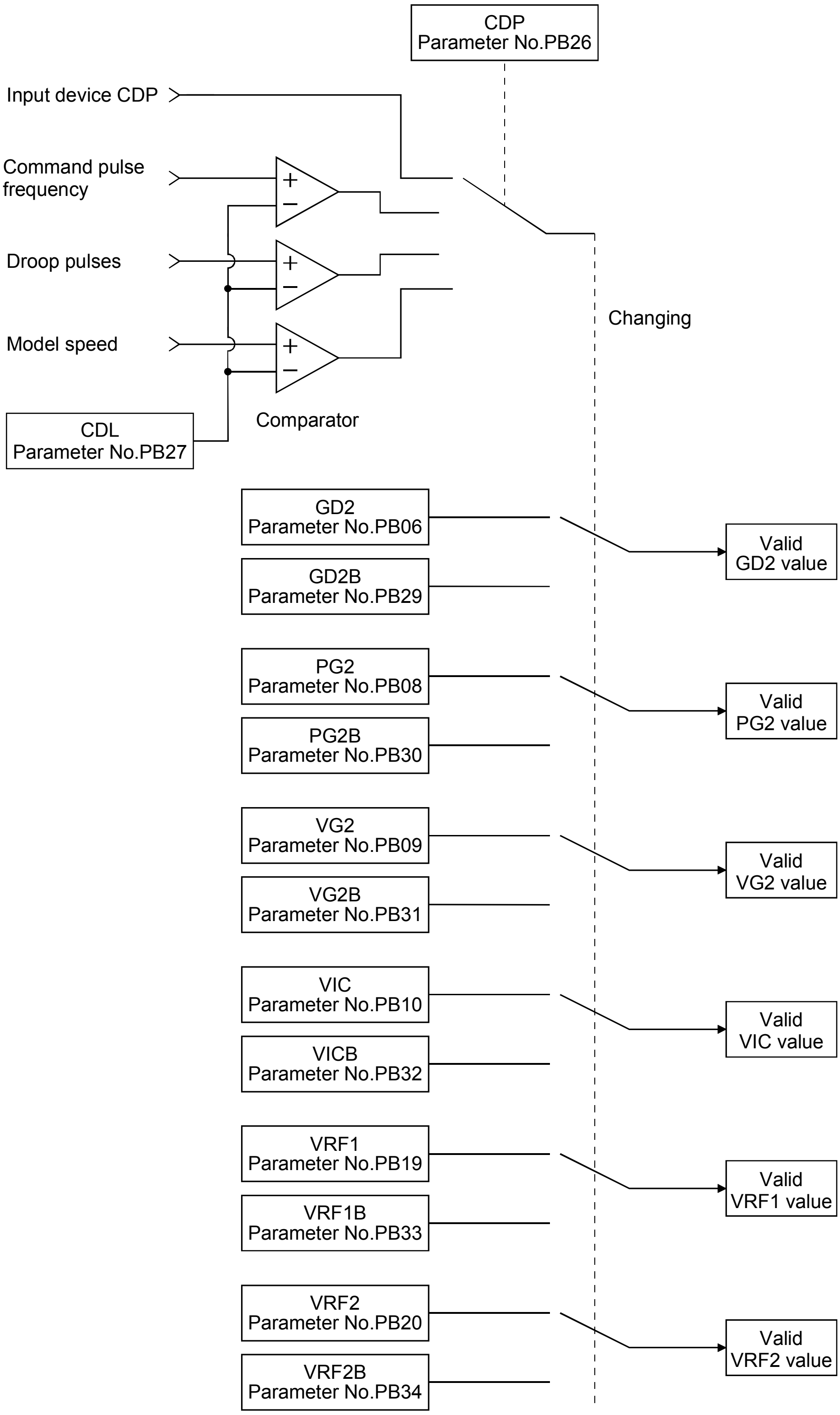
(1) You want to increase the gains during servo lock but decrease the gains to reduce noise during rotation.

(2) You want to increase the gains during settling to shorten the stop settling time.

(3) You want to change the gains using an input device to ensure stability of the servo system since the load inertia moment ratio varies greatly during a stop (e.g. a large load is mounted on a carrier).

8.6.2 Function block diagram

The valid loop gains PG2, VG2, VIC, GD2, VRF1 and VRF2 of the actual loop are changed according to the conditions selected by gain changing selection CDP (parameter No.PB26) and gain changing condition CDL (parameter No.PB27).



8.6.3 Parameters

When using the gain changing function, always set parameter No.PA08 to "□□□3" (auto tuning mode) to select the manual mode in the auto tuning modes. The gain changing function cannot be used in the auto tuning mode.

Parameter No.	Abbrevi-ation	Name	Unit	Description
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment	Multiplier (×1)	Control parameters before changing
PB07	PG1	Model loop gain	rad/s	Position and speed gains of a model used to set the response level to a command. Always valid.
PB08	PG2	Position loop gain	rad/s	
PB09	VG2	Speed loop gain	rad/s	
PB10	VIC	Speed integral compensation	ms	
PB29	GD2B	Gain changing ratio of load inertia moment to servo motor inertia moment	Multiplier (×1)	Used to set the ratio of load inertia moment to servo motor inertia moment after changing.
PB30	PG2B	Gain changing position loop gain	rad/s	Used to set the value of the after-changing position loop gain.
PB31	VG2B	Gain changing speed loop gain	rad/s	Used to set the value of the after-changing speed loop gain.
PB32	VICB	Gain changing speed integral compensation	ms	Used to set the value of the after-changing speed integral compensation.
PB26	CDP	Gain changing selection		Used to select the changing condition.
PB27	CDL	Gain changing condition	kpps pulse r/min	Used to set the changing condition values.
PB28	CDT	Gain changing time constant	ms	You can set the filter time constant for a gain change at changing.
PB33	VRF1B	Gain changing vibration suppression control vibration frequency setting	Hz	Used to set the value of the after-changing vibration suppression control vibration frequency setting.
PB34	VRF2B	Gain changing vibration suppression control resonance frequency setting	Hz	Used to set the value of the after-changing vibration suppression control resonance frequency setting.

(1) Parameters No.PB06 to PB10

These parameters are the same as in ordinary manual adjustment. Gain changing allows the values of ratio of load to motor inertia moment ratio, the position loop gain, the speed loop gain and the speed integral compensation to be changed.

(2) Gain changing ratio of load inertia moment to servo motor inertia moment (GD2B: parameter No.PB29)

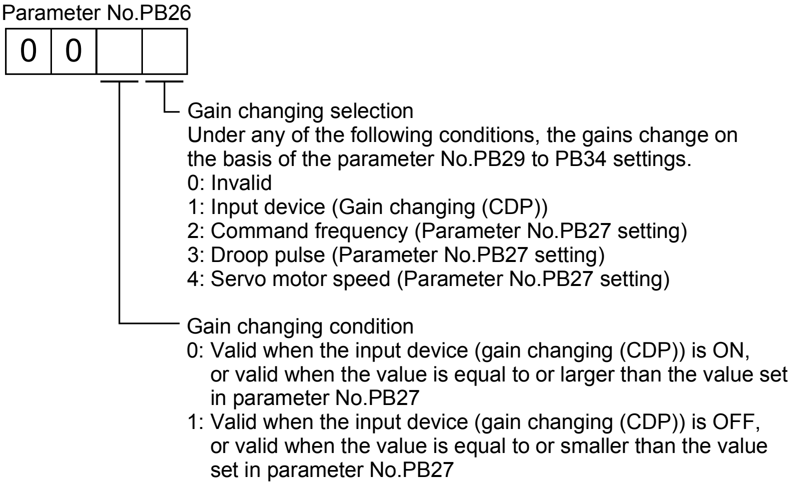
Set the load to servo motor inertia moment ratio after changing the gain. If the load to servo inertia moment ratio does not change, set the parameter to the same value as the load to servo motor inertia moment ratio (parameter No.PB06).

(3) Gain changing position loop gain (parameter No.PB30), Gain changing speed loop gain (parameter No. PB31), Gain changing speed integral compensation (parameter No.PB32)

Set the values of after-changing position loop gain, speed loop gain and speed integral compensation.

(4) Gain changing selection (parameter No.PB26)

Used to set the gain changing condition. Choose the changing condition in the first digit and second digit. If "1" is set in the first digit, the gain can be changed by the gain changing (CDP) input device. The gain changing (CDP) can be assigned to the pins using parameters No.PD03 to PD08 and PD10 to PD12.



Gain changing selection
Under any of the following conditions, the gains change on the basis of the parameter No.PB29 to PB34 settings.
- 0: Invalid
- 1: Input device (Gain changing (CDP))
- 2: Command frequency (Parameter No.PB27 setting)
- 3: Droop pulse (Parameter No.PB27 setting)
- 4: Servo motor speed (Parameter No.PB27 setting)

Gain changing condition
- 0: Valid when the input device (gain changing (CDP)) is ON, or valid when the value is equal to or larger than the value set in parameter No.PB27
- 1: Valid when the input device (gain changing (CDP)) is OFF, or valid when the value is equal to or smaller than the value set in parameter No.PB27

(5) Gain changing condition (parameter No.PB27)

Used to set the gain changing level when "command frequency", "droop pulse" or "servo motor speed" is set in the gain changing selection (parameter No.PB26).

The setting unit is as follows:

Gain changing condition	Unit
Command frequency	kpps
Droop pulses	pulse
Servo motor speed	r/min

(6) Gain changing time constant (parameter No.PB28)

You can set the primary delay filter to each gain at gain changing. This parameter is used to suppress shock given to the machine if the gain difference is large at gain changing, for example.

(7) Gain changing vibration suppression control

Gain changing vibration suppression control is only available when changing the valid parameters with ON/OFF of the input device.

8.6.4 Gain changing procedure

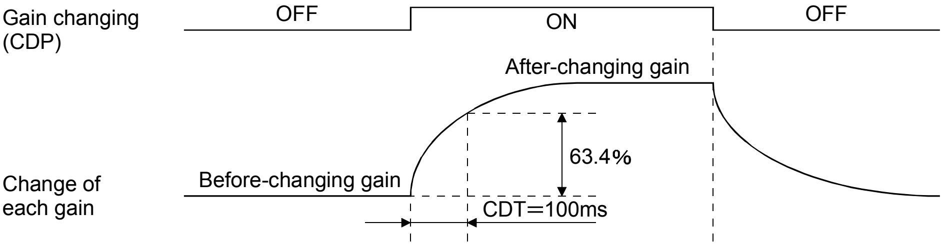
This operation will be described by way of setting examples.

(1) When you choose changing by input device (CDP)

(a) Setting

Parameter No.	Abbreviation	Name	Setting	Unit
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment	4.0	Multiplier (×1)
PB07	PG1	Model loop gain	100	rad/s
PB08	PG2	Position loop gain	120	rad/s
PB09	VG2	Speed loop gain	3000	rad/s
PB10	VIC	Speed integral compensation	20	ms
PB19	VRF1	Vibration suppression control vibration frequency setting	50	Hz
PB20	VRF2	Vibration suppression control resonance frequency setting	50	Hz
PB29	GD2B	Gain changing ratio of load inertia moment to servo motor inertia moment	10.0	Multiplier (×1)
PB30	PG2B	Gain changing position loop gain	84	rad/s
PB31	VG2B	Gain changing speed loop gain	4000	rad/s
PB32	VICB	Gain changing speed integral compensation	50	ms
PB26	CDP	Gain changing selection	0001 (Changed by ON/OFF of Input device (CDP))	
PB28	CDT	Gain changing time constant	100	ms
PB33	VRF1B	Gain changing vibration suppression control vibration frequency setting	60	Hz
PB34	VRF2B	Gain changing vibration suppression control resonance frequency setting	60	Hz

(b) Changing timing chart



Model loop gain			100		
Ratio of load inertia moment to servo motor inertia moment	4.0	→	10.0	→	4.0
Position loop gain	120	→	84	→	120
Speed loop gain	3000	→	4000	→	3000
Speed integral compensation	20	→	50	→	20
Vibration suppression control vibration frequency setting	50	→	60	→	50
Vibration suppression control resonance frequency setting	50	→	60	→	50

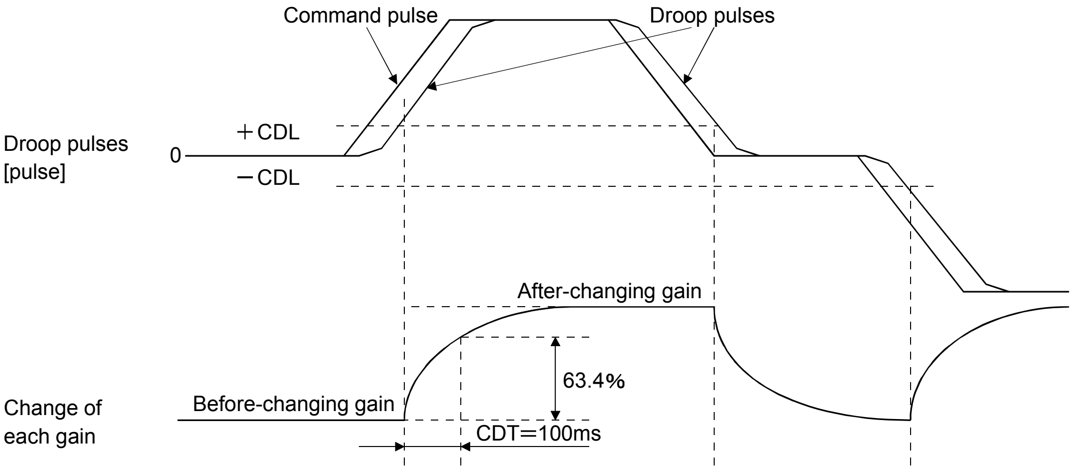
(2) When you choose changing by droop pulses

In this case, gain changing vibration suppression control cannot be used.

(a) Setting

Parameter No.	Abbreviation	Name	Setting	Unit
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment	4.0	Multiplier (×1)
PB07	PG1	Model loop gain	100	rad/s
PB08	PG2	Position loop gain	120	rad/s
PB09	VG2	Speed loop gain	3000	rad/s
PB10	VIC	Speed integral compensation	20	ms
PB29	GD2B	Gain changing ratio of load inertia moment to servo motor inertia moment	10.0	Multiplier (×1)
PB30	PG2B	Gain changing position loop gain	84	rad/s
PB31	VG2B	Gain changing speed loop gain	4000	rad/s
PB32	VICB	Gain changing speed integral compensation	50	ms
PB26	CDP	Gain changing selection	0003 (Changed by droop pulses)	
PB27	CDS	Gain changing condition	50	pulse
PB28	CDT	Gain changing time constant	100	ms

(b) Changing timing chart



Model loop gain	100						
Ratio of load inertia moment to servo motor inertia moment	4.0	→	10.0	→	4.0	→	10.0
Position loop gain	120	→	84	→	120	→	84
Speed loop gain	3000	→	4000	→	3000	→	4000
Speed integral compensation	20	→	50	→	20	→	50

8.7 Vibration suppression control filter 2

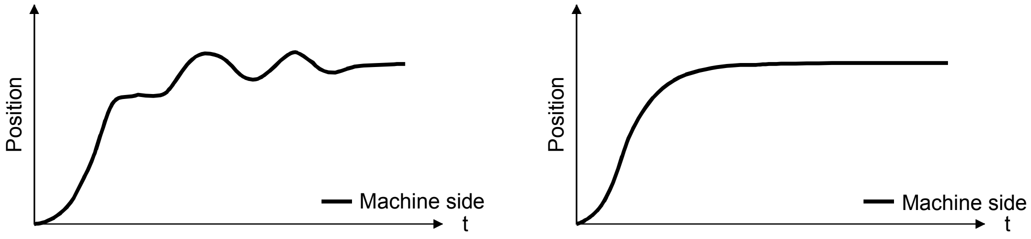
POINT

- By using the advanced vibration suppression control and the vibration suppression control filter 2, the machine side vibration of two frequencies can be suppressed.
- The frequency range of machine vibration, which can be supported by the vibration suppression control filter 2, is between 4.5Hz and 2250Hz. Set a frequency close to the machine vibration frequency and within the range.
- When the parameter of the vibration suppression control filter 2 (parameter No.PB45) is changed during the positioning operation, the changed setting is not reflected. The setting is reflected approximately 150ms after the servo motor stops (after servo lock).

(1) Operation

Vibration suppression control filter 2 has a filter function (notch filter) that lowers the gain of the specified frequency contained in a positioning command. By lowering the gain, machine side vibration, such as workpiece end vibration and base shake, can be suppressed.

Which frequency to lower the gain and how deep to lower the gain can be set.

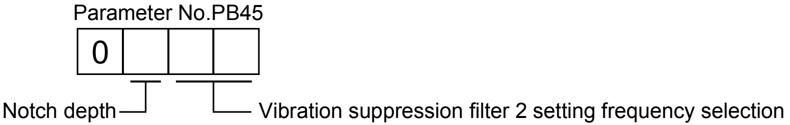


Vibration suppression control filter 2 invalid

Vibration suppression control filter 2 valid

(2) Parameter

Set parameter No.PB45 (vibration suppression control filter 2) as shown below. For the vibration suppression control filter 2, set a frequency close to the vibration frequency [Hz] at the machine side.



Setting	Depth
0	−40.0dB
1	−24.1dB
2	−18.1dB
3	−14.5dB
4	−12.0dB
5	−10.1dB
6	−8.5dB
7	−7.2dB
8	−6.0dB
9	−5.0dB
A	−4.1dB
B	−3.3dB
C	−2.5dB
D	−1.8dB
E	−1.2dB
F	−0.6dB

Setting	Frequency [Hz]	Setting	Frequency [Hz]	Setting	Frequency [Hz]
00	Invalid	20	70	40	17.6
01	2250	21	66	41	16.5
02	1125	22	62	42	15.6
03	750	23	59	43	14.8
04	562	24	56	44	14.1
05	450	25	53	45	13.4
06	375	26	51	46	12.8
07	321	27	48	47	12.2
08	281	28	46	48	11.7
09	250	29	45	49	11.3
0A	225	2A	43	4A	10.8
0B	204	2B	41	4B	10.4
0C	187	2C	40	4C	10.0
0D	173	2D	38	4D	9.7
0E	160	2E	37	4E	9.4
0F	150	2F	36	4F	9.1
10	140	30	35.2	50	8.8
11	132	31	33.1	51	8.3
12	125	32	31.3	52	7.8
13	118	33	29.6	53	7.4
14	112	34	28.1	54	7.0
15	107	35	26.8	55	6.7
16	102	36	25.6	56	6.4
17	97	37	24.5	57	6.1
18	93	38	23.4	58	5.9
19	90	39	22.5	59	5.6
1A	86	3A	21.6	5A	5.4
1B	83	3B	20.8	5B	5.2
1C	80	3C	20.1	5C	5.0
1D	77	3D	19.4	5D	4.9
1E	75	3E	18.8	5E	4.7
1F	72	3F	18.2	5F	4.5

MEMO

9. TROUBLESHOOTING

POINT

- As soon as an alarm occurs, turn off Servo-on (SON) and power off.
- Refer to section 15.6 for the servo amplifiers of 30k to 55kW.

If an alarm/warning has occurred, refer to section 9.1 to 9.3 and remove its cause. In case of a trouble without an alarm/warning, refer to section 9.4 and remove its cause.

9.1 Alarms and warning list

When a fault occurs during operation, the corresponding alarm or warning is displayed. If any alarm or warning has occurred, refer to section 9.2 or 9.3 and take the appropriate action. When an alarm occurs, ALM turns off. Set "□□□1" in parameter No.PD24 to output the alarm code is outputted by ON/OFF of bit0 to bit2. Warnings (AL.92 to AL.EA) have no alarm codes. Any alarm code is output at occurrence of the corresponding alarm. In the normal status, the alarm code is not output.
After its cause has been removed, the alarm can be deactivated in any of the methods marked ○ in the alarm deactivation column.

	Display	(Note 2) Alarm code			Name	Alarm deactivation		
		CN1 22 (bit2)	CN1 23 (bit1)	CN1 24 (bit0)		Power OFF→ON	Press "SET" on current alarm screen.	Alarm reset (RES)
Alarms	AL.10	0	1	0	Undervoltage	○	○	○
	AL.12	0	0	0	Memory error 1 (RAM)	○		
	AL.13	0	0	0	Clock error	○		
	AL.15	0	0	0	Memory error 2 (EEP-ROM)	○		
	AL.16	1	1	0	Encoder error 1 (At power on)	○		
	AL.17	0	0	0	Board error	○		
	AL.19	0	0	0	Memory error 3 (Flash-ROM)	○		
	AL.1A	1	1	0	Motor combination error	○		
	AL.20	1	1	0	Encoder error 2 (during runtime)	○		
	AL.21	1	1	0	Encoder error 3 (during runtime)	○		
	AL.24	1	0	0	Main circuit error	○	○	○
	AL.25	1	1	0	Absolute position erase	○		
	AL.30	0	0	1	Regenerative error	(Note 1) ○	(Note 1) ○	(Note 1) ○
	AL.31	1	0	1	Overspeed	○	○	○
	AL.32	1	0	0	Overcurrent	○		
	AL.33	0	0	1	Overvoltage	○	○	○
	AL.35	1	0	1	Command pulse frequency alarm	○	○	○
	AL.37	0	0	0	Parameter error	○		
	AL.45	0	1	1	Main circuit device overheat	(Note 1) ○	(Note 1) ○	(Note 1) ○
	AL.46	0	1	1	Servo motor overheat	(Note 1) ○	(Note 1) ○	(Note 1) ○
	AL.47	0	1	1	Cooling fan alarm	○		
	AL.50	0	1	1	Overload 1	(Note 1) ○	(Note 1) ○	(Note 1) ○
	AL.51	0	1	1	Overload 2	(Note 1) ○	(Note 1) ○	(Note 1) ○
	AL.52	1	0	1	Error excessive	○	○	○
	AL.8A	0	0	0	Serial communication time-out	○	○	○
	AL.8E	0	0	0	Serial communication error	○	○	○
	88888				Watchdog	○		

Note 1. Deactivate the alarm about 30 minutes of cooling time after removing the cause of occurrence.
2. 0: off
1: on

	Display	Name
Warnings	AL.92	Battery cable disconnection warning
	AL.96	Home position setting error
	AL.99	Stroke limit warning
	AL.9F	Battery warning
	AL.E0	Excessive regeneration warning
	AL.E1	Overload warning 1
	AL.E3	Absolute position counter warning
	AL.E5	ABS time-out warning
	AL.E6	Servo emergency stop warning
	AL.E8	Cooling fan speed reduction warning
	AL.E9	Main circuit off warning
	AL.EA	ABS servo on warning
	AL.EC	Overload warning 2
	AL.ED	Output watt excess warning

9.2 Remedies for alarms

CAUTION

- When any alarm has occurred, eliminate its cause, ensure safety, then reset the alarm, and restart operation. Otherwise, injury may occur.
- If an absolute position erase (AL.25) occurred, always to make home position setting again. Not doing so may cause unexpected operation.
- As soon as an alarm occurs, turn off Servo-on (SON) and power off.

POINT

- When any of the following alarms has occurred, do not deactivate the alarm and resume operation repeatedly. To do so will cause the servo amplifier/servo motor to fail. Remove the cause of occurrence, and leave a cooling time of more than 30 minutes before resuming operation.
  - Regenerative error (AL.30)
  - Main circuit device overheat (AL.45)
  - Servo motor overheat (AL.46)
  - Overload 1 (AL.50)
  - Overload 2 (AL.51)
- The alarm can be deactivated by switching power off, then on press the "SET" button on the current alarm screen or by turning on the reset (RES). For details, refer to section 9.1.

When an alarm occurs, the trouble (ALM) switches off and the dynamic brake is operated to stop the servo motor. At this time, the display indicates the alarm No.

The servo motor comes to a stop. Remove the cause of the alarm in accordance with this section. Use the MR Configurator to refer to a factor of alarm occurrence. The alarm details can be confirmed by the alarm history of MR Configurator.

Display	Name	Definition	Cause	Action	(Note 2) Alarm details
AL.10	Undervoltage	Power supply voltage dropped.	1. Power supply voltage is low. <Checking method> Check that the power supply voltage is the following voltage or more. MR-J3-□A: 160VAC MR-J3-□A1: 83VAC MR-J3-□A4: 280VAC	Check the power supply.	2
			2. Shortage of power supply capacity caused the power supply voltage to drop at start, etc. <Checking method> Check that the bus voltage is the following voltage or more. MR-J3-□A: 200VDC MR-J3-□A1: 158VDC MR-J3-□A4: 380VDC		
			3. The bus voltage dropped to the following value or less. MR-J3-□A: 200VDC MR-J3-□A1: 158VDC MR-J3-□A4: 380VDC		
			4. There was an instantaneous control power failure of 60ms or longer.		1
			5. Faulty parts in the servo amplifier. <Checking method> 1. Alarm (AL.10) occurs if power is switched on after disconnection of all cables but the control circuit power supply cables. 2. Check that the bus voltage is the following voltage or more. MR-J3-□A: 200VDC MR-J3-□A1: 158VDC MR-J3-□A4: 380VDC	Change the servo amplifier.	
			6. Waveform of power supply voltage is distorted. When power supply impedance is high, waveform of power voltage is distorted, and it may recognized as undervoltage.	Set the parameter No.PC27 to "0001".	
AL.12	Memory error 1 (RAM)	RAM, memory fault	Faulty parts in the servo amplifier <Checking method> Alarm (any of AL.12 and AL.13) occurs if power is switched on after disconnection of all cables but the control circuit power supply cables.	Change the servo amplifier.	
AL.13	Clock error	Printed board fault		Change the servo amplifier.	
AL.15	Memory error 2 (EEP-ROM)	EEP-ROM fault	1. Faulty parts in the servo amplifier <Checking method> Alarm (AL.15) occurs if power is switched on after disconnection of all cables but the control circuit power supply cables.	Change the servo amplifier.	
			2. The number of write times to EEP-ROM exceeded 100,000.		

Display	Name	Definition	Cause	Action	(Note 2) Alarm details
AL.16	Encoder error 1 (At power on)	Communication error occurred between encoder and servo amplifier.	1. Encoder connector (CN2) disconnected.	Connect correctly.	44
			2. Encoder cable type (2-wire, 4-wire) selection was incorrect in parameter setting.	Correct the setting in the fourth digit of parameter No. PC22.	
			3. Encoder cable faulty (Wire breakage or shorted)	Repair or change the cable.	
			4. Encoder fault	Change the servo motor.	
			5. A servo motor other than that of MR-J3 series is connected.	Check the combination of the servo amplifier and the servo motor.	63
			6. A communication error occurred due to external noise. <Checking method> 1. Check that the encoder cable and the power cables are wired side by side. 2. Check that the servo amplifier is not influenced by noise of magnetic valves, magnetic contactors or relays. 3. Check the grounding of the servo amplifier and the servo motor. 4. Check that there is no cause of static electricity around. 5. Check that the shield of the encoder cable is made correctly.	Ground correctly or take noise reduction measures.	
AL.17	Board error	CPU/parts fault	Faulty parts in the servo amplifier <Checking method> Alarm (AL.17 or AL.19) occurs if power is switched on after disconnection of all cables but the control circuit power supply cable.	Change the servo amplifier.	
AL.19	Memory error 3 (Flash ROM)	ROM memory fault			
AL.1A	Motor combination error	Incorrect combination of servo amplifier and servo motor.	Incorrect combination of servo amplifier and servo motor connected.	Check the combination of the servo amplifier and the servo motor.	

Display	Name	Definition	Cause	Action	(Note 2) Alarm details
AL.20	Encoder error 2 (during runtime)	Communication error occurred between encoder and servo amplifier.	1. Encoder cable disconnected. <Checking method> Check the connection of the encoder cable.	Connect the servo motor encoder connector to the servo amplifier connector (CN2) correctly.	47
			2. Encoder cable fault. <Checking method> Check that the encoder cable is broken or shorted.	Repair or change the cable.	
			3. The encoder detected high acceleration rate due to oscillation and other causes. <Checking method> Check that the servo motor does not vibrate or does not make unusual noise.	1. Decrease the position loop gain. 2. Reduce the response setting of the auto tuning.	8
			4. Encoder fault.	Change the servo motor.	
			5. A communication error occurred due to external noise. <Checking method> 1. Check that the encoder cable and the power cables are wired side by side. 2. Check that the servo amplifier is not influenced by noise of magnetic valves, magnetic contactors or relays. 3. Check the grounding of the servo amplifier and the servo motor. 4. Check that there is no cause of static electricity around. 5. Check that the shield of the encoder cable is made correctly.	Ground correctly or take noise reduction measures.	
AL.21	Encoder error 3 (during runtime)	Error occurred in encoder.	Detection circuit error in encoder.	Change the servo motor.	

Display	Name	Definition	Cause	Action	(Note 2) Alarm details
AL.24	Main circuit error	Ground fault occurred in servo motor power (U, V, W).	1. Power input wires and servo motor power wires are in contact. (A power input cable and a servo motor power cable are in contact at the main circuit terminal block (TE1).)	Modify the wiring.	
			2. Short or ground fault occurs at a servo motor power cable. (A sheath of a servo motor power cable deteriorated, resulting in short or ground fault.)	Repair the cable.	
			3. Servo amplifier fault. <Checking method> The alarm (AL.24) occurs even after removing servo motor power cables (U, V, W).	Change the servo amplifier.	
			4. Servo motor fault. <Checking method> The servo motor power cables (U, V, W) are disconnected on the servo motor terminal side. After that, the servo motor is turned on, and the alarm (AL.24) does not occur.	Change the servo motor.	
			5. External dynamic brake fault <Checking method> The servo motor power cables (U, V, W) are disconnected on the external dynamic brake terminal side. After that, the servo motor is turned on, and the alarm (AL.24) does not occur.	1. Check parameters and the dynamic brake interlock. 2. Replace the external dynamic brake.	
			6. External noise caused erroneous operation to the overcurrent detection circuit. <Checking method> 1. Check that the servo amplifier is not influenced by noise of magnetic valves, magnetic contactors or relays. 2. Check the grounding of the servo amplifier and the servo motor.	Ground correctly or take noise reduction measures.	

Display	Name	Definition	Cause	Action	(Note 2) Alarm details
AL.25	Absolute position erase	Absolute position data is erased.	1. Voltage drop in encoder. (Battery disconnected.)	After leaving the alarm occurring for a few minutes, switch power off, then on again. Always make home position setting again.	
			2. Battery voltage low.	Change the battery. Always make home position setting again.	
			3. Loose connection of the battery connector, or battery fault	Change the battery. Always make home position setting again. Repair or change the encoder cable.	
			4. Encoder cable fault.		
			5. Encoder fault.	Change the servo motor.	
		Power was switched on for the first time in the absolute position detection system.	6. Home position not set.	After leaving the alarm occurring for a few minutes, switch power off, then on again. Always to make home position setting again.	
AL.30	Regenerative error	Permissible regenerative power of the built-in regenerative resistor or regenerative option is exceeded.	1. Incorrect setting of parameter No. PA02	Set correctly.	1
			2. High-duty operation or continuous regenerative operation caused the permissible regenerative power of the regenerative option to be exceeded. <Checking method> Call the status display MR Comfigurator, and check the regenerative load ratio.	1. Reduce the frequency of positioning. 2. Use the regenerative option of larger capacity. 3. Reduce the load.	
			3. Bus voltage is abnormal. MR-J3-□A(1): 400VDC or more MR-J3-□A4: 800VDC or more	Check the power supply.	
			4. Built-in regenerative resistor or regenerative option is not connected.	Connect correctly.	4
			5. Built-in regenerative resistor or regenerative option faulty.	Change the servo amplifier or regenerative option.	
		Regenerative transistor fault	6. Servo amplifier fault. (Regenerative transistor fault.) <Checking method> 1. The regenerative option has overheat abnormally. 2. The alarm occurs even after removal of the built-in regenerative resistor or regenerative option.	Change the servo amplifier.	
			7. Servo amplifier fault. (Regenerative circuit fault.)	Change the servo amplifier.	2

Display	Name	Definition	Cause	Action	(Note 2) Alarm details
AL.31	Overspeed	Speed has exceeded the instantaneous permissible speed.	1. Input command pulse frequeroy is too high.	Set command pulse frequency correctly.	
			2. Small acceleration/deceleration time constant caused overshoot to be large.	Increase acceleration/ deceleration time constant.	
			3. Servo system is instable to cause overshoot.	1. Re-set servo gain to proper value. 2. If servo gain cannot be set to proper value. 1) Reduce load inertia moment ratio; or 2) Reexamine acceleration/deceleration time constant.	
			4. Electronic gear ratio is large. (Setting by parameters No. PA06, PA07)	Set correctly.	
			5. Encoder faulty.	Change the servo motor.	
AL.32	Overcurrent	Current that flew is higher than the permissible current of the servo amplifier.	1. Short or ground fault occurs at a servo motor power cable. (A sheath of a servo motor power cable deteriorated, resulting in short or ground fault.) <Checking method> The servo motor power cables (U, V, W) are disconnected on the servo motor terminal side. After that, the servo motor is turned on, and the alarm (AL.32) occurs.	Repair the cable.	
			2. External dynamic brake fault <Checking method> The servo motor power cables (U, V, W) are disconnected on the external dynamic brake terminal side. After that, the servo motor is turned on, and the alarm (AL.32) does not occur.	1. Check parameters and the dynamic brake interlock. 2. Replace the external dynamic brake.	
			3. Servo amplifier fault. <Checking method> The servo motor power cables (U, V, W) are disconnected. After that, the servo motor is turned on, and the alarm (AL.32) occurs.	Change the servo amplifier.	
			4. Servo motor fault. <Checking method> The servo motor power cables (U, V, W) are disconnected on the external dynamic brake terminal side. After that, the servo motor is turned on, and the alarm (AL.32) does not occur.	Change the servo motor.	
			5. External noise caused erroneous operation to the overcurrent detection circuit. <Checking method> 1. Check that the servo amplifier is not influenced by noise of magnetic valves, magnetic contactors or relays. 2. Check the grounding of the servo amplifier and the servo motor.	Ground correctly or take noise reduction measures.	
			6. Encoder fault.	Change the servo motor.	2

Display	Name	Definition	Cause	Action	(Note 2) Alarm details
AL.33	Overvoltage	Bus voltage exceeded to following voltage. MR-J3-□A(1): 400VDC or more MR-J3-□A4: 800VDC or more	1. Regenerative option is not used.	Use the regenerative option.	
			2. Though the regenerative option is used, the parameter No.PA02 setting is "□□00 (not used)".	Set correctly.	
			3. Lead of built-in regenerative resistor or regenerative option is open or disconnected.	1. Change the lead. 2. Connect correctly.	
			4. Wire breakage of built-in regenerative resistor or regenerative option	1. For wire breakage of built-in regenerative resistor, change the servo amplifier. 2. For wire breakage of regenerative option, change the regenerative option.	
			5. Capacity of built-in regenerative resistor or regenerative option is insufficient.	Add regenerative option or increase capacity.	
			6. The jumper across BUE-SD of the FR-BU2 brake unit is removed.	Fit the jumper across BUE-SD.	
			7. Impedance at main circuit power supply cable (L_1, L_2, L_3) is high, and leak current from servo motor power supply cable (U, V, W) is large.	Use the regenerative option.	
			8. Ground fault occurred in servo motor power (U, V, W).	Correct the wiring.	
			9. Power supply voltage high.	Check the power supply.	
			10. Servo amplifier fault. (Regenerative transistor fault.)	Change the servo amplifier.	
AL.35	Command pulse frequency error	Input pulse frequency of the command pulse is too high.	1. Frequency of the command pulse is too high.	Change the command pulse frequency to a lower value.	
			2. Noise entered command pulses.	Take action against noise.	
			3. Command device failure	Change the command device.	
AL.37	Parameter error	Parameter setting is incorrect.	1. Regenerative option not used with servo amplifier was selected in parameter No.PA02.	Set parameter No.PA02 correctly.	2
			2. For a drive unit of MR-J3-DU30KA or higher, parameter No.PC22 is set to "□□□1 (Valid)".	Set parameter No.PC22 to "□□□0 (Invalid)" and turn the power off then on.	
			3. The number of write times to EEP-ROM exceeded 100,000 due to parameter write, etc.	Change the servo amplifier.	1, 2
			4. Servo amplifier fault caused the parameter setting to be rewritten.	Change the servo amplifier.	

Display	Name	Definition	Cause	Action	(Note 2) Alarm details
AL.45	Main circuit device overheat	Main circuit device overheat	1. Ambient temperature of servo amplifier is over 55℃ (131℉).	Check environment so that ambient temperature is 0 to 55℃ (32 to 131℉).	
			2. Used beyond the specifications of close mounting.	Use within the range of specifications. (Refer to section 2.1.)	
			3. The power supply was turned on and off continuously by overloaded status.	The drive method is reviewed.	
			4. Foreign matter caught in a cooling fan or heat sinks.	Clean the cooling fan or the heat sinks.	
			5. Servo amplifier fault. (When it occurs immediately after power-on)	Change the servo amplifier.	
AL.46	Servo motor overheat	Servo motor temperature rise actuated the thermal sensor.	1. Ambient temperature of servo motor is over 40℃ (104℉).	Check environment so that ambient temperature is 0 to 40℃ (32 to 104℉).	1, 2, 10, 20
			2. Servo motor is overloaded.	1. Reduce load. 2. Check operation pattern. 3. Use servo motor that provides larger output.	
			3. Thermal sensor in encoder is faulty.	Change the servo motor.	1
AL.47	Cooling fan alarm	The cooling fan of the servo amplifier stopped, or its speed decreased to or below the alarm level.	1. Cooling fan life expiration (Refer to section 2.5.)	Change the cooling fan of the servo amplifier.	
			2. Foreign matter caught in the cooling fan stopped rotation.	Remove the foreign matter.	
			3. The power supply of the cooling fan failed.	Change the servo amplifier.	

Display	Name	Definition	Cause	Action	(Note 2) Alarm details
AL.50	Overload 1	Load exceeded overload protection characteristic of servo amplifier.	1. Servo amplifier is used in excess of its continuous output current.	1. Reduce load. 2. Check operation pattern. 3. Check that the electromagnetic brake is not applied. 4. Check that the machine is not fractioned. 5. Use servo motor and servo amplifier that provides larger output.	1
			2. After Overload 2 (AL.51) occurred, turn OFF/ON the power supply to clear the alarm. Then the overload operation is repeated.	1. Reduce load. 2. Check operation pattern. 3. Use servo motor that provides larger output.	1
			3. The servo system is instable and causes oscillation or hunting.	1. Repeat acceleration/ deceleration to execute auto tuning. 2. Change the auto tuning response setting. 3. Set auto tuning to OFF and make gain adjustment manually. 4. Check that the coupling with the servo motor shaft is not loose.	1, 2
			4. Encoder fault. <Checking method> When the servo motor shaft is rotated with the servo off, the cumulative feedback pulses do not vary in proportion to the rotary angle of the shaft but the indication skips or returns midway.	Change the servo motor.	

Display	Name	Definition	Cause	Action	(Note 2) Alarm details
AL.51	Overload 2	Machine collision or the like caused a continuous maximum current for a few seconds.	1. Servo amplifier fault. <Checking method> The servo motor is disconnected on the machine side and then the servo motor is test-operated. The alarm (AL.51) does not occur. (Check after setting the gain to the initial value.)	Change the servo amplifier.	
			2. The servo system is instable and causes oscillation or hunting.	1. Repeat acceleration/ deceleration to execute auto tuning. 2. Change the auto tuning response setting. 3. Set auto tuning to OFF and make gain adjustment manually. 4. Check that the coupling with the servo motor shaft is not loose.	
			3. Machine struck something.	1. Check operation pattern. 2. Install limit switches. 3. Check that the electromagnetic brake is not applied.	
			4. Incorrect connection of servo motor. Servo amplifier's output terminals U, V, W do not match servo motor's input terminals U, V, W.	Connect correctly.	
			5. Encoder fault. <Checking method> When the servo motor shaft is rotated with the servo off, the cumulative feedback pulses do not vary in proportion to the rotary angle of the shaft but the indication skips or returns midway.	Change the servo motor.	
			6. A power cable is disconnected.	Repair the cable.	
			7. Servo motor fault.	Change the servo motor.	

Display	Name	Definition	Cause	Action	(Note 2) Alarm details
AL.52	Error excessive	The difference between the model position and the actual servo motor position exceeds three rotations. (Refer to the function block diagram in section 1.2.)	1. Acceleration/deceleration time constant is too small.	Increase the acceleration/ deceleration time constant.	
			2. Forward rotation torque limit (parameter No.PA11) or reverse rotation torque limit (parameter No.PA12) are too small.	Increase the torque limit value.	
			3. Motor cannot be started due to torque shortage caused by power supply voltage drop.	1. Check the power supply capacity. 2. Use servo motor which provides larger output.	
			4. Position loop gain 1 (parameter No.PB08) value is small.	Increase set value and adjust to ensure proper operation.	
			5. Servo motor shaft was rotated by external force.	1. When torque is limited, increase the limit value. 2. Reduce load. 3. Use servo motor that provides larger output.	
			6. Machine struck something.	1. Check operation pattern. 2. Install limit switches.	
			7. Encoder faulty	Change the servo motor.	
			8. Incorrect connection of servo motor. Servo amplifier's output terminals U, V, W do not match servo motor's input terminals U, V, W.	Connect correctly.	
			9. A power cable is broken.	Repair the cable.	
			10. A command is input when the torque limit is "0".	Set the torque limit to the proper value.	8
AL.8A	Serial communication time-out error	USB communication or RS-422 communication stopped for longer than the specified time.	1. Communication cable breakage.	Repair or change the communication cable.	
			2. Communication cycle longer than regulated time.	Shorten the communication cycle.	
			3. Incorrect protocol.	Correct protocol.	
AL.8E	Serial communication error	Serial communication error occurred between servo amplifier and communication device (e.g. personal computer).	1. Communication cable fault (Open cable or short circuit)	Repair or change the cable.	1, 2
			2. Communication device (e.g. personal computer) faulty	Change the communication device (e.g. personal computer).	
			3. A character code is faulty.	Check the character codes.	4
			4. A command is faulty.	Check the commands.	8
			5. A data No. is faulty.	Check the data No.	10

Display	Name	Definition	Cause	Action	(Note 2) Alarm details
(Note 1) 88888	Watchdog	CPU, parts faulty	1. Fault of parts in servo amplifier <Checking method> Alarm (88888) occurs if power is switched on after disconnection of all cables but the control circuit power supply cable.	Change the servo amplifier.	
			2. The CPU in the servo motor is malfunctioned due to external noise.	1. Check that the servo amplifier is not influenced by noise of magnetic valves, magnetic contactors or relays. 2. Check the grounding of the servo amplifier and the servo motor.	

Note 1. At power-on, "88888" appears instantaneously, but it is not an error.

2. MR Configurator is required to check the alarm detailed information. The alarm detailed information can be checked on the "alarm history list" window. The window appears by slecting alarm/alarm history on MR Configurator.

9.3 Remedies for warnings

⚠CAUTION	▪ If an absolute position counter warning (AL.E3) occurred, always to make home position setting again. Not doing so may cause unexpected operation.

POINT

- When any of the following alarms has occurred, do not resume operation by switching power of the servo amplifier OFF/ON repeatedly. The servo amplifier and servo motor may become faulty. If the power of the servo amplifier is switched OFF/ON during the alarms, allow more than 30 minutes for cooling before resuming operation.
  - Excessive regenerative warning (AL.E0)
  - Overload warning 1 (AL.E1)

If AL.E6 or AL.EA occurs, the servo off status is established. If any other warning occurs, operation can be continued but an alarm may take place or proper operation may not be performed.
Remove the cause of warning according to this section. Use the MR Configurator to refer to a factor of warning occurrence.

Display	Name	Definition	Cause	Action
AL.92	Battery cable disconnection warning	Absolute position detection system battery voltage is low.	1. Battery cable is open.	Repair cable or changed.
			2. Battery voltage supplied from the servo amplifier to the encoder fell to about 3V or less. (Detected with the encoder)	Change the battery.
			3. An encoder cable is broken.	Repair or replace the encoder cable.
AL.96	Home position setting warning	Home position setting could not be made.	1. The position is out of in-position range at the home position setting.	Set the home position within the in-position range.
			2. A command pulse is input during the home position setting.	Input the command pulse after the home position setting.
			3. Creep speed high.	Reduce creep speed.
AL.99	Stroke limit warning	The stroke end (LSP or LSN) of the direction which gave instructions was turned off.	The forward rotation stroke end (LSP) is turned off at the forward rotation command.	Review the moving range to avoid turning off LSP/LSN.
			The reverse rotation stroke end (LSN) is turned off at the reverse rotation command.	
AL.9F	Battery warning	Voltage of battery for absolute position detection system reduced.	Battery voltage fell to 3.2V or less. (Detected with the servo amplifier)	Change the battery.
AL.E0	Excessive regenerative warning	There is a possibility that regenerative power may exceed permissible regenerative power of built-in regenerative resistor or regenerative option.	Regenerative power increased to 85% or more of permissible regenerative power of built-in regenerative resistor or regenerative option. <Checking method> Call the status display or MR Comfigurator, and check regenerative load ratio.	1. Reduce frequency of positioning. 2. Change the regenerative option for the one with larger capacity. 3. Reduce load. 4. Replace the servo amplifier/ servo motor with one of larger capacity.

Display	Name	Definition	Cause	Action
AL.E1	Overload warning 1	There is a possibility that overload alarm 1 or 2 may occur.	Load increased to 85% or more of overload alarm 1 or 2 occurrence level.	Refer to AL.50, AL.51.
AL.E3	Absolute position counter warning	Absolute position encoder pulses faulty.	1. Noise entered the encoder.	Take noise suppression measures.
			2. Encoder faulty.	Change the servo motor.
		The multi-revolution counter value of the absolute position encoder exceeded the maximum revolution range.	3. The travel distance from the home position exceeded a 32767 rotation or −37268 rotation in succession.	Make home position setting again.
AL.E5	ABS time-out warning		1. Programmable controller ladder program incorrect.	Contact the program.
			2. Reverse rotation start (ST2) ・ Limiting torque (TLC) improper wiring	Connect properly.
AL.E6	Servo emergency stop warning	EMG is off.	External emergency stop was made valid. (EMG was turned off.)	Ensure safety and deactivate emergency stop.
AL.E8	Cooling fan speed reduction warning	The speed of the servo amplifier decreased to or below the warning level. This warning is not displayed with MR-J3-70A/100A among servo amplifiers equipped with a cooling fan.	1. Cooling fan life expiration (Refer to section 2.5.)	Change the cooling fan of the servo amplifier.
			2. The power supply of the cooling fan is broken.	Change the servo amplifier.
			3. Foreign matter is caught in the cooling fan and decreased speed.	Remove the foreign matter.
AL.E9	Main circuit off warning	Servo-on (SON) was switched on with main circuit power off.		Switch on main circuit power.
AL.EA	ABS servo-on warning	Servo-on (SON) turned on more than 1s after servo amplifier had entered absolute position data transfer mode.	1. Programmable controller ladder program incorrect.	1. Correct the program.
			2. Servo-on (SON) improper wiring.	2. Connect properly.
AL.EC	Overload warning 2	Operation, in which a current exceeding the rating flew intensively in any of the U, V and W phases of the servo motor, was repeated.	During a stop, the status in which a current flew intensively in any of the U, V and W phases of the servo motor occurred repeatedly, exceeding the warning level.	1. Reduce the positioning frequency. 2. Reduce the load. 3. Replace the servo amplifier/ servo motor with the one of larger capacity.
AL.ED	Output watt excess warning	The status, in which the output wattage (speed × torque) of the servo motor exceeded the rated output, continued steadily.	Continuous operation was performed with the output wattage (speed × torque) of the servo motor exceeding 150% of the rated output.	1. Reduce the servo motor speed. 2. Reduce the load. 3. Replace the servo amplifier/servo motor with one of larger capacity.

9.4 Troubles without an alarm/warning

POINT

- Even if a servo amplifier, a servo motor, or an encoder malfunctions, the following phenomena may occur.

The following shows the examples of the estimated causes of the troubles without alarms/warnings. Refer to this chapter and remove their causes.

Phenomena	Checkpoint	Estimated cause	Action
A LED indication turns off.	When fixing by disconnecting all the connectors other than the power supply, check if the disconnected cables are not shorted.	An external I/O terminal is shorted.	Check the wiring of the I/O signal.
	Check that the control circuit power is not turned off.	The control circuit power is not turned on.	Turn the control circuit power on.
	Check that the control circuit power voltage is not low.	The control circuit power voltage decreased.	Set the control circuit power voltage within the rated range.
The servo motor does not operate.	Check that a warning (AL.99) does not occur.	The forward rotation stroke end (LSP) or the reverse rotation stroke end (LSN) is not turned on.	Turn on both the forward rotation stroke end (LSP) and the reverse rotation stroke end (LSN).
	Check the connection with the servo motor.	The U, V, W output terminals of the servo amplifier is not connected with each U, V, W input terminals of the servo motor.	Connect each U, V, W phase properly.
	Check that a warning (AL.E9) does not occur.	The servo-on (SON) is turned on while the main circuit power of the servo amplifier is off.	Turn the main circuit power on.
	Check that the servo alarm/ warning is occurring.	A servo alarm is occurring.	Check the details of the alarm and remove its cause.
	Check the external input signal is on or off. 1. Check the external I/O signal display in the diagnostic mode. 2. Check that the input signal is ON or OFF on the "I/O interface display" command of the "Monitor" menu on MR Configurator.	The servo-on (SON) is off.	Turn on the servo-on (SON).
		Reset (RES) is on.	Turn reset (RES) off.
		<Speed control mode> 1. Both the forward rotation start (ST1) and the reverse rotation start (ST2) are off. 2. Both the forward rotation start (ST1) and the reverse rotation start (ST2) are on.	Input the forward rotation start (ST1) and the reverse rotation start (ST2) properly.
		<Torque control mode> 1. Both the forward rotation selection (RS1) and the reverse rotation selection (RS2) are off. 2. Both the forward rotation selection (RS1) and the reverse rotation selection (RS2) are on.	Input the forward rotation selection (RS1) and the reverse rotation selection (RS2) properly.
		<Speed control mode/torque control mode> The setting of the speed selection 1 (SP1), the speed selection 2 (SP2) or the speed selection 3 (SP3) is incorrect.	1. Review the wiring. 2. Check the setting of the speed selection 1 (SP1), the speed selection 2 (SP2) and the speed selection 3 (SPV).

Phenomena	Checkpoint	Estimated cause	Action
The servo motor does not operate.	Check the cumulative command pulses with the status display or MR Configurator. The display does not change even if the pulse train command is input.	The wiring of the command pulse train signal is incorrect.	Check the type of the command pulse train (the differential receiver system or the open collector system). Supply an external power (24VDC) between OPC and DOCOM for the open collector system.
		The command pulses are not input.	Review the controller setting.
		The settings of the parameter No.PA13 (command pulse input form) are incorrect.	Set the same value as the pulse output form of the controller.
	Check the settings of the parameter No.PA01 (control mode).	The settings of the parameter No.PA01 (control mode) are incorrect.	Review the settings of the parameter No.PA01 (control mode).
	Check that the generated torque does not exceed the torque limit value. 1. Check "instantaneous occurrence torque" with "status display". 2. Check the torque ripple with the "Graph" command on the "Monitor" menu on MR Configurator.	1. The maximum torque is lacking. The servo capacity is lacking. Or the load is too large.	1. Change the mass or the shape of the work to reduce the load. 2. Make the acceleration/ deceleration time shorter to make the effective load ratio lower.
		2. Unintended torque limit is valid. Or the setting of the torque limit is 0 (no generating torque). (Set with the parameter No.PA11/ PA12/PC35.)	Review the torque limit setting.
	Check the status of the analog input voltage. 1. Check with the status display. 2. Check with the "Display all" command on the "Monitor" menu on MR Configurator.	<Position control mode> The input voltage of the analog torque limit (TLA) is incorrect.	Review the settings of the analog torque limit (TLA) and the analog input voltage.
		<Speed control mode> The input voltage of the analog speed command (VC) or that of the analog torque limit (TLA) is incorrect.	Review the settings of the analog speed command (VC), the analog torque limit (TLA) and the analog input voltage.
		<Torque control mode> The input voltage of the analog torque command (TC) or that of the analog speed limit (TLA) is incorrect.	Review the settings of the analog torque command (TC), the analog speed limit (VLA) and the analog input voltage.
	Check that machine interference occurs.	Machine interference occurs.	Eliminate the machine interference.
	Check the power supply for the servo motor with an electromagnetic brake.	The electromagnetic brake is not released.	Turn the electromagnetic brake power on to release the brake.
	The ABSM signal is on while the absolute position detection system is used.	1. The servo amplifier operates in the ABS transfer mode. 2. The absolute position data transfer is not complete.	Set the servo amplifier setting (parameter No.PA03), wiring and ladder program of the controller properly.
	Check the electronic gear settings.	The electronic gear settings are incorrect.	Set the proper electronic gear.

Phenomena	Checkpoint	Estimated cause	Action
The servo motor speed is not accelerated. Or too fast.	Check the settings of the speed command, the speed limit and the electronic gear.	The setting of the speed command, the speed limit or the electronic gear is incorrect.	Review the settings of the speed command, the speed limit and the electronic gear is incorrect.
	Check the external input signal is on or off. 1. Check with the external I/O signal display in the diagnostic mode. 2. Check the I/O signal status on the "I/O interface display" command on the "Monitor" menu on MR Configurator.	<Speed control mode/torque control mode> The setting of the speed selection 1 (SP1), the speed selection 2 (SP2) or the speed selection 3 (SP3) is incorrect.	1. Review the wiring. 2. Check the setting of the speed selection 1 (SP1), the speed selection 2 (SP2) and the speed selection 3 (SP3).
	Check the power supply cable of the servo motor.	An output circuit is open.	Review the wiring of the servo motor power supply cable.
	Check that the main circuit power voltage is not low.	The main circuit power voltage decreased.	1. Set the main circuit power supply within the specified range of the permissible voltage fluctuation. 2. Review the wiring of the main circuit power supply.
	Check the power supply for the servo motor with an electromagnetic brake.	The electromagnetic brake is not released.	Turn the electromagnetic brake power on to release the brake.
The servo motor vibrates due to low frequency.	If the safe operation is possible, repeat acceleration/deceleration 4 times or more to complete the auto tuning.	The load to motor inertia moment ratio by the auto tuning is not estimated correctly. The load to motor inertia moment ratio setting (parameter No.PB06) is incorrect when the auto tuning mode 2 or the manual mode is used.	Adjust the gains. (Refer to chapter 7.) Review the load to motor inertia moment ratio (parameter No.PB06) when the auto tuning mode 2 or the manual mode is used.
	Check commands from the controller.	Commands from the controller are unstable.	1. Review the commands from the controller. 2. Check the command cable if errors do not occur such as breaking.
	Check the mechanical part if errors do not occur. (Examples) 1. Check that the timing belt is not loose. 2. Check that the machine is not worn.	The load of the mechanical part is changed.	1. Adjust the gains again. (Refer to chapter 7.) 2. Maintain the mechanical part.
	Check the machine required torque does not exceed the maximum torque of the servo motor.	The acceleration/deceleration torque overshot at stop due to exceed its servo motor performance.	Reduce loads by setting the acceleration/deceleration longer or making the work mass lighter, etc.
	Increase the auto tuning response (parameter No.PA09). (except the manual mode)	1. The servo gain is low. 2. The auto tuning response is low.	Increase the auto tuning response and then adjust the gains again. (Refer to chapter 7.)

Phenomena	Checkpoint	Estimated cause	Action
Unusual noise is generated from the servo amplifier.	1. If the safe operation is possible, repeat acceleration/deceleration 4 times or more to complete the auto tuning. 2. Reduce the auto tuning response (parameter No.PA09).	1. The servo gain is high. 2. The auto tuning response is high.	Reduce the auto tuning response and then adjust the gains again. (Refer to chapter 7.)
	If the safe operation is possible, remove the load and then check the noise with only the servo motor.	When unusual noise is generated, the cause is the bearing life.	Replace the servo motor.
		When unusual noise is not generated, the cause is the backlash increase on the machine side.	Maintain on the machine side.
	Check that the brake is not dragged for the servo motor with an electromagnetic brake.	1. The electromagnetic brake release sequence is incorrect. 2. The power supply for the electromagnetic brake is faulty.	1. Review the electromagnetic brake release sequence. 2. Check the power supply for the electromagnetic brake.
	The brake clacks for the servo motor with an electromagnetic brake.	This sound is from a clearance of the brake joint part. This is not a malfunction.	
The servo motor vibrates.	1. If the safe operation is possible, repeat acceleration/deceleration 4 times or more to complete the auto tuning. 2. Reduce the auto tuning response (parameter No.PA09). (except the manual mode)	1. The servo gain is too high. 2. The auto tuning response is too high.	Reduce the auto tuning response and then adjust the gains again. (Refer to chapter 7.)
	If the safe operation is possible, execute the adaptive tuning.	The machine vibrates (in sympathy).	Adjust the machine resonance suppression filter. (Refer to section 8.2)
	If the safe operation is possible, execute the tuning with the advanced gain search on MR Configurator MRZJW3-SETUP221 (CS2 or later).	The machine vibrates (in sympathy).	Adjust the gains. (Refer to chapter 7.)
	If the safe operation is possible, execute the tuning with the advanced vibration suppression control.	A machine terminal vibrates.	Adjust the filter. (Refer to section 8.4)
	Display the cumulative feedback pulses with the "High speed monitor" command on the "Monitor" menu on MR Configurator. Check the numerical values are not skipped.	Noises are overlapped in the encoder cable. This causes miscounting of the cumulative feedback pulses.	Reduce the noises by setting the encoder cable apart from the power supply cable, etc.
	Check that the mechanical parts are not unstable or do not have backlashes.	The servo motor and the machine (gear, coupling, etc.) have backlashes.	Adjust the coupling or the backlash of the mechanical parts.
	Check the mounting part of the servo motor.	The mounting part of the servo motor is not enough rigid.	Improve the rigidity by using a thicker board for the mounting part, backing up with ribs, etc.
	Check the power supply cable of the servo motor.	An output circuit is open.	Review the wiring of the servo motor power supply cable.
	Check that the degree of vibration changes depending on the motor speed.	The unbalanced torque is big on the machine side.	Adjust the balance on the machine side.

Phenomena	Checkpoint	Estimated cause	Action
The servo motor vibrates.	Check the mounting accuracy of the servo motor and the machine.	The eccentricity is big by the core gaps.	Review the direct connection accuracy.
	Check the axial end load on the servo motor.	The axial end load on the servo motor is large.	Adjust the axial end load within the specifications of the servo motor. Refer to Servo motor Instruction Manual (Vol.2) for details of the axial end load on the servo motor.
	Check the vibration from the outside.	The outside vibration propagated to the servo motor.	Control the vibration from the outside source.
Rotation accuracy is not satisfactory. (The speed is unstable.)	1. If the safe operation is possible, repeat acceleration/deceleration 4 times or more to complete the auto tuning. 2. Increase the auto tuning response (parameter No.PA09). (except the manual mode)	1. The servo gain is low. 2. The auto tuning response is low.	Increase the auto tuning response and then adjust the gains again. (Refer to chapter 7.)
	Check if the limiting torque (TLC) is not on. 1. Check with the external I/O signal display in the diagnostic mode. 2. Check the torque ripple with the "I/O interface display" command on the "Monitor" menu on MR Configurator.	Unintended torque limit is valid. (The torque limit (TLC) is on while the torque limit is valid.)	Release the torque limit.
	Check if the maximum torque does not exceed the torque limit value. 1. Check "instantaneous torque" on the status display. 2. Check the torque ripple with the "Graph" command on the "Monitor" menu on MR Configurator.	The maximum torque is lacking. 1. The servo capacity is lacking. 2. The load is too large.	1. Change the mass or the shape of the work to reduce the load. 2. Make the acceleration/ deceleration time shorter to make the effective load ratio lower.
		The torque limit settings are incorrect. (Set with the parameter No.PA11/ PA12/PC35.)	Review the torque limit setting.
	Check the status of the analog input voltage. 1. Check with the status display. 2. Check with the "Display all" command on the "Monitor" menu on MR Configurator.	Input voltage of the analog speed command (VC) or the analog speed limit (VLA) is instable.	Review the settings of the analog speed command (VC), the analog speed limit (VLA) and the analog input voltage.
	Check commands from the controller. Check the ripple of the command frequency with the "Graph" command on the "Monitor" menu on MR Configurator.	Commands from the controller are unstable.	1. Review the commands from the controller. 2. Check the command cable if errors do not occur such as breaking.
The servo motor wobbles at stop.	1. If the safe operation is possible, repeat acceleration/deceleration 4 times or more to complete the auto tuning. 2. Increase the auto tuning response (parameter No.PA09). (except the manual mode)	1. The servo gain is low. 2. The auto tuning response is low.	Increase the auto tuning response and then adjust the gains again. (Refer to chapter 7.)

Phenomena	Checkpoint	Estimated cause	Action
The servo motor starts immediately when the servo amplifier power supply is turned on/The servo motor starts immediately when servo-on is executed.	Check that the servo-on (SON) is not on. 1. Check with the external I/O signal display in the diagnostic mode. 2. Check with the "I/O interface display" command on the "Monitor" menu on MR Configurator.	The servo-on (SON) is on status at power-on.	1. Review the wiring of the servo-on (SON). 2. Review the sequence of the servo-on (SON).
	Check the brake release timing for the servo motor with an electromagnetic brake.	1. The electromagnetic brake release sequence is incorrect. 2. The power supply for the electromagnetic brake is faulty.	1. Review the electromagnetic brake release sequence. 2. Check the power supply for the electromagnetic brake.
	Check the status of the analog speed command (VC) and the analog torque command (TC). 1. Check with the status display. 2. Check with the "Display all" command on the "Monitor" menu on MR Configurator.	1. The analog speed command (VC) and the analog torque command (TC) has already input at power-on. 2. The offset voltage of the analog speed command (VC) or the analog torque command (TC) is incorrect.	Set the offset voltage of the analog speed command (VC) and the analog torque command (TC) properly.
	Check the power supply cable of the servo motor.	An output circuit is open.	Review the wiring of the servo motor power supply cable.
The position is misaligned at home position return.	A certain amount (one revolution) of misalignment occurs.	The zero pulse detection occurs near the dog off position. (dog type home position return)	Adjust the proximity dog installation.
	Check the in-position range (parameter No.PA10).	The in-position range is too large.	Set the in-position range smaller than the current setting.
	Check that the proximity dog signal is set properly.	1. The proximity dog switch is malfunction. 2. The proximity dog switch is not installed properly.	1. Repair or replace the proximity dog switch. 2. Adjust the proximity dog switch installation.
	Check the proximity dog switch installation.	The proximity dog switch is misaligned or not installed properly.	Adjust the proximity dog switch installation.
	Check the controller program. 1. The home position address settings 2. The sequence programs and others	The controller programs are incorrect.	Review the controller programs.

Phenomena	Checkpoint	Estimated cause	Action
The position is misaligned in operation after the home position return.	Check the servo alarm/warning.	1. A servo alarm is occurring. 2. The servo motor coasts due to a servo alarm.	Check the details of the alarm and remove its cause.
	The output pulse counter and the servo amplifier cumulative command pulses of the controller do not match.	1. An output pulses miscounting due to noises. 2. A shield of a command cable is made incorrectly. 3. A command cable is connected loosely or broken.	1. Check that the shield of the command cable is made correctly. 2. When wiring with the open collector system, change it to the differential system. 3. Wire apart from the strong electric circuit. 4. Install the data line filters. (Refer to section 12.17.)
		The servo-on (SON) is turned off.	Review the wiring and the controller programs in order that the servo-on (SON) is not turned to off in operation.
		The command pulses voltage level is low at the open collector system. (normal value: 24VDC)	Review the wiring and command pulse specifications. Replace the servo amplifier if an error cannot be detected.
		The command pulses ripple error occurs due to a long command cable.	Shorten the wiring length. Differential system: 10m or shorter Open collector system: 2m or shorter
	The cumulative feedback pulses x the travel distance per pulse does not match with the actual machine position.	1. A machine slipped. 2. A machine backlash is big.	Adjust the machine parts.
The position is misaligned in operation after the home position return.	The cumulative feedback pulses do not match with the cumulative command pulses × the electronic gear setting value.	Temporary breaking of a power line	Review the wiring.
		1. The servo gain is low. 2. The auto tuning response is low. 3. The setting time is late.	Increase the auto tuning response and then adjust the gains again. (Refer to chapter 7.)
		1. The forward rotation stroke end (LSP) or the reverse rotation stroke end (LSN) is turned off. (AL.99 occurred.) 2. Clear (CR) or reset (RES) is turned on.	1. Review the wiring and the sequence of each signal. 2. If a noise may malfunction greatly, make the input filter setting (parameter No.PD19) value bigger.
	1. If the safe operation is possible, repeat acceleration/deceleration 4 times or more to complete the auto tuning. 2. Increase the auto tuning response (parameter No.PA09). (except the manual mode)	The auto tuning response is low.	Increase the auto tuning response and then adjust the gains again. (Refer to chapter 7.)
	Check the settings as follows for the geared servo motor. 1. The travel distance per revolution of the servo motor (Set by the controller.) 2. Command input pulses per revolution (parameter No.PA05) 3. Electronic gear (parameter No.PA06/PA07)	The calculation of the reduction ratio is not correct.	Review the setting of the reduction ratio.
	Check the in-position range (parameter No.PA10).	The in-position range is too large.	Set the in-position range smaller than the current setting.

Phenomena	Checkpoint	Estimated cause	Action
The absolute position reconstruction position is misaligned at recovery by the absolute position detection system.	Check the settings as follows for the geared servo motor. 1. The travel distance per servo motor revolution (Set with the controller.) 2. Command input pulses per revolution (parameter No.PA05) 3. Electronic gear (parameter No.PA06/PA07)	The calculation of the reduction ratio is not correct.	Review the setting of the reduction ratio.
	The positioning after is not misaligned after the home position return.	The maximum permissible speed at power failure (3000r/min) is exceeded while the servo amplifier is off.	Review the machine configuration in order that the servo motor speed does not exceed 3000r/min.
		The transfer data to the controller is incorrect.	Review the controller programs.
The overshoot/ undershoot occurs.	1. Check that the overshoot/ undershoot occurs to confirm the speed ripple with the "Graph" command on the "Monitor" menu on MR Configurator. 2. If the safe operation is possible, repeat acceleration/deceleration 4 times or more to complete the auto tuning.	1. The servo gain is too low or too high. 2. The auto tuning response is low or too high.	Adjust the auto tuning response and then adjust the gains again. (Refer to chapter 7.)
	Check if the maximum torque does not exceed the torque limit value. 1. Check the "instantaneous torque" with the status display. 2. Check the torque ripple with the "Graph" command on the "Monitor" menu on MR Configurator.	The maximum torque is lacking. 1. The servo capacity is lacking. 2. The load is too large.	1. Change the mass or the shape of the work to reduce the load. 2. Make the acceleration/ deceleration time shorter to make the effective load ratio lower.
		The torque limit settings are incorrect. (Set with the parameter No.PA11/ PA12/PC35.)	Review the torque limit setting.
	Check that the machine parts are not unstable or do not have backlashes.	The servo motor and the machine (gear, coupling, etc.) have backlashes.	Adjust the coupling or the backlash of the mechanical parts.
The communication cannot be made with the servo amplifier by MR Configurator.	Check that the status is on-line.	The status is off-line.	Set the status to on-line. Select "On-line" on "System settings" on the "Setup" menu.
	Check that the communication cables are not damaged.	A communication cable is faulty.	Replace the communication cable.
	Check the communication settings (baud rate and port). Check with the "system settings" on the "setup" menu.	The communication setting is incorrect.	Set the communication settings correctly.
	Check that the model selection is set correctly. Check with the "System settings" command on the "Setup" menu.	The other model, which differs from the one connected on the model selection, is selected.	Set the model settings correctly.
	Check that "MITSUBISHI MELSERVO USB Controller" is displayed under the controller by the device manager of the personal computer.	The device is not set correctly.	Delete the unknown device or other devices. Turn the servo amplifier power on and then re-set with found new hardware wizard. Refer to the MR Configurator help for details.

Phenomena	Checkpoint	Estimated cause	Action
An abnormal value is displayed on the monitor value on MR Configurator.	Check that the model selection is set correctly. Check with the "System settings" command on the "Setup" menu.	The other model, which differs from the one connected on the model selection, is selected.	Set the model settings correctly.
The electromagnetic brake does not work for the servo motor with the electromagnetic brake.	Remove the servo motor from the machine and remove all the wiring. Check that the servo motor shaft can be turned over by the hand. (If the shaft can be turned over, the electromagnetic brake is malfunction.)	The electromagnetic brake reached the end of its usefulness or malfunctioned. Refer to Servo motor Instruction Manual (Vol.2) for details of the life of the electromagnetic brake.	Replace the servo motor.
The servo motor coasting amount is enlarged.	Check that a load is not increased.	If a load is increased, the value exceeded the permissible load to motor inertia moment ratio of the dynamic brake. (Refer to section 11.3)	1. Reduce the load. 2. Replace the servo amplifier.
	For the servo motor with an electromagnetic brake 1. Check that the external relay, which is connected to the electromagnetic brake interlock (MBR), operates properly. 2. Check that the electromagnetic brake is not malfunction.	1. An external relay malfunctions. 2. The electromagnetic brake interlock (MBR) wiring is incorrect. 3. The electromagnetic brake reached the end of its usefulness or malfunctioned.	1. Replace the external relay. 2. Review the wiring. 3. Replace the servo motor.

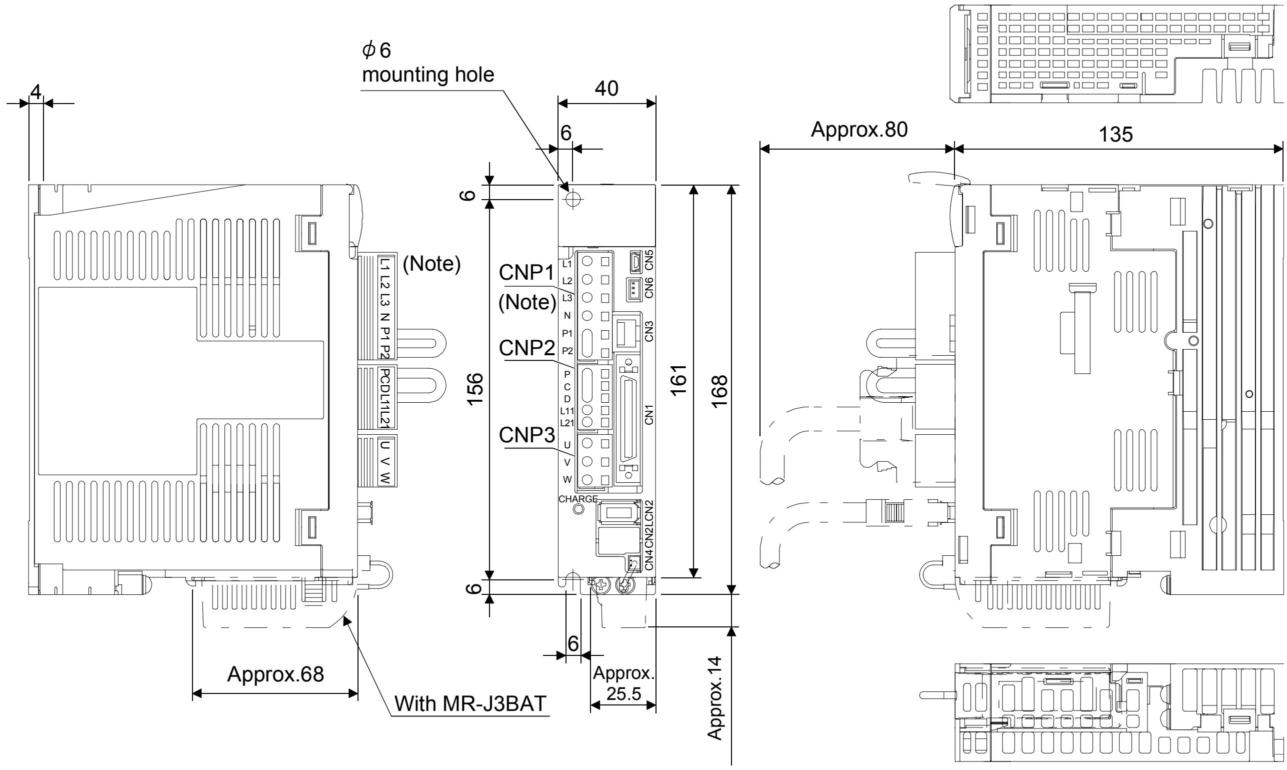
MEMO

10. OUTLINE DRAWINGS

10.1 Servo amplifier

(1) MR-J3-10A・MR-J3-20A
MR-J3-10A1・MR-J3-20A1

[Unit: mm]



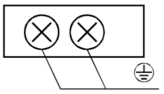
Note. This data applies to the 3-phase or 1-phase 200 to 230VAC power supply models.
For 1-phase, 100 to 120VAC power supply, refer to the terminal signal layout.

Mass: 0.8 [kg] (1.76 [lb])

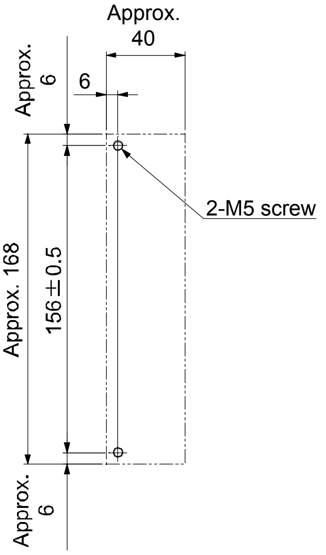
Terminal signal layout

	For 1-phase 100 to 120VAC		For 3-phase 200 to 230VAC and 1-phase 230VAC
CNP1	L_1	CNP1	L_1
			L_2
	L_2		L_3
	N		N
	P_1		P_1
	P_2		P_2
CNP2	P	CNP2	P
	C		C
	D		D
	L_{11}		L_{11}
	L_{21}		L_{21}
CNP3	U	CNP3	U
	V		V
	W		W

PE terminal



Screw size: M4
Tightening torque: 1.2 [N・m] (10.6 [lb・in])

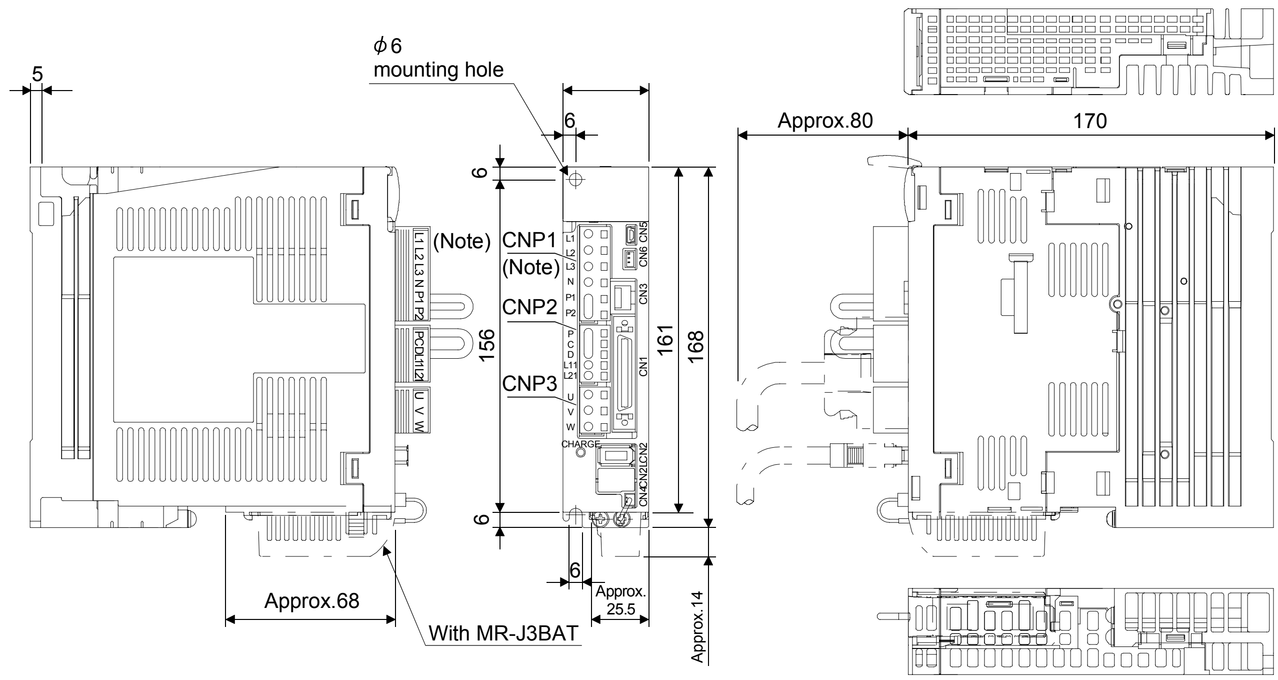


Mounting hole process drawing

Mounting screw
Screw size: M5
Tightening torque: 3.24[N・m] (28.7[lb・in])

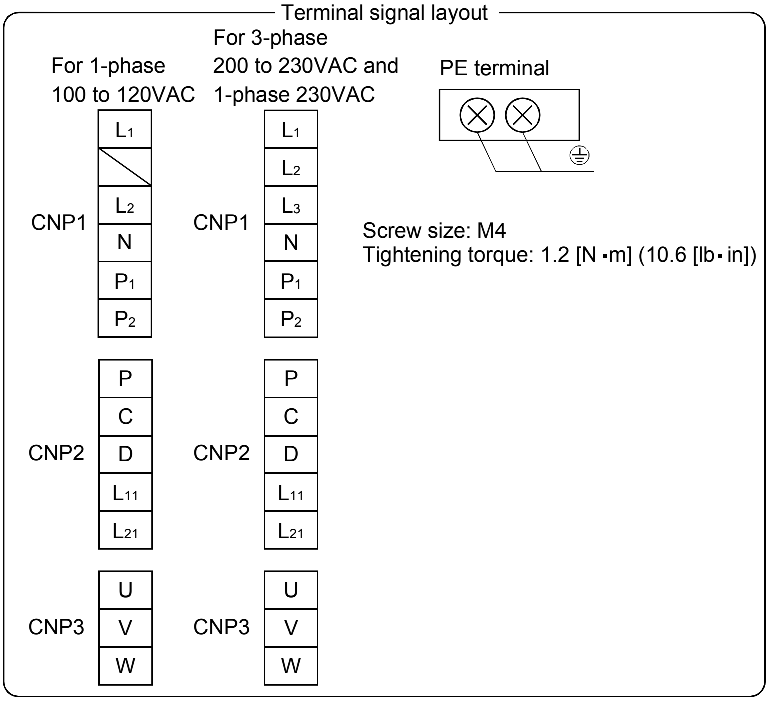
(2) MR-J3-40A・MR-J3-60A
MR-J3-40A1

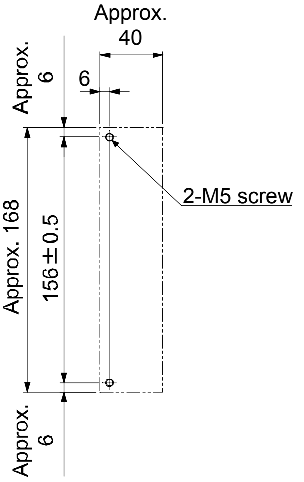
[Unit: mm]



Note. This data applies to the 3-phase or 1-phase 200 to 230VAC and 1-phase 230VAC power supply models.
For 1-phase, 100 to 120VAC power supply, refer to the terminal signal layout.

Mass: 1.0 [kg] (2.21 [lb])



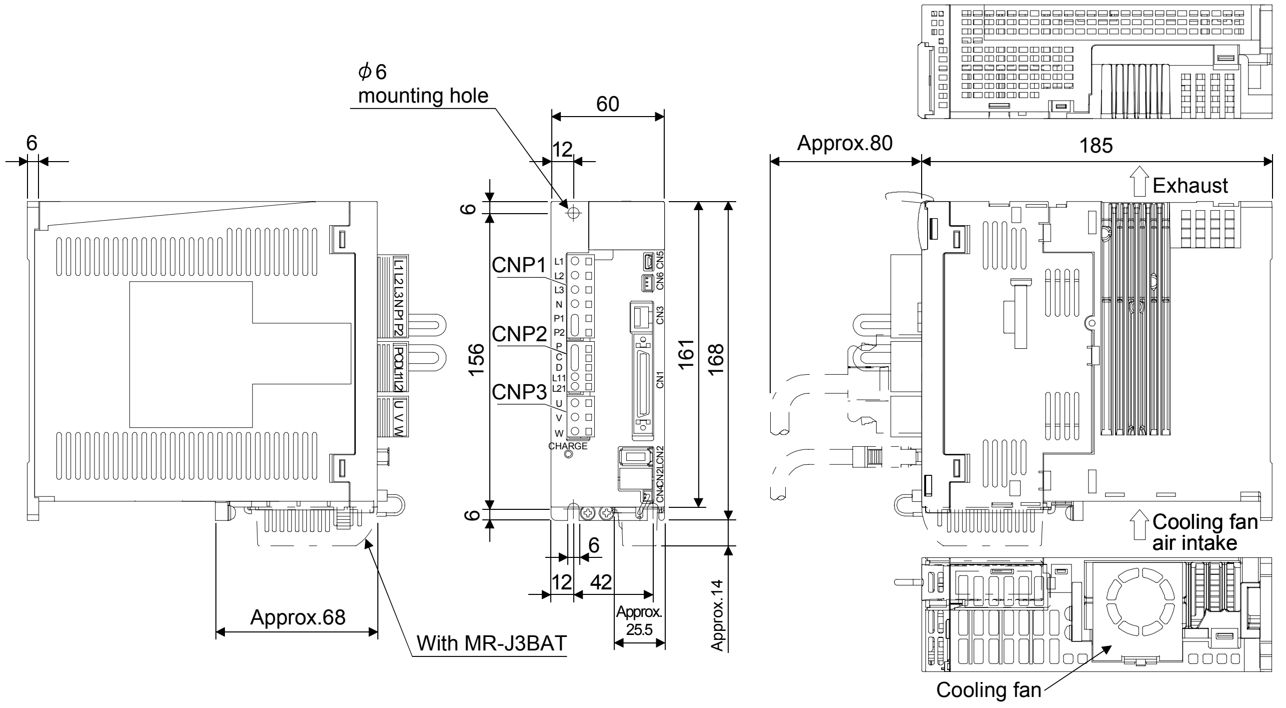


Mounting hole process drawing

Mounting screw
Screw size: M5
Tightening torque: 3.24[N・m] (28.7[lb・in])

(3) MR-J3-70A・MR-J3-100A

[Unit: mm]



Mass: 1.4 [kg] (3.09 [lb])

Terminal signal layout

CNP1

L_1
L_2
L_3
N
P_1
P_2

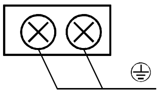
CNP2

P
C
D
L_{11}
L_{21}

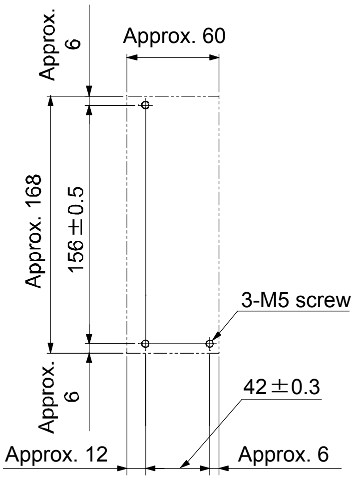
CNP3

U
V
W

PE terminal



Screw size: M4
Tightening torque: 1.2 [N・m] (10.6 [lb・in])

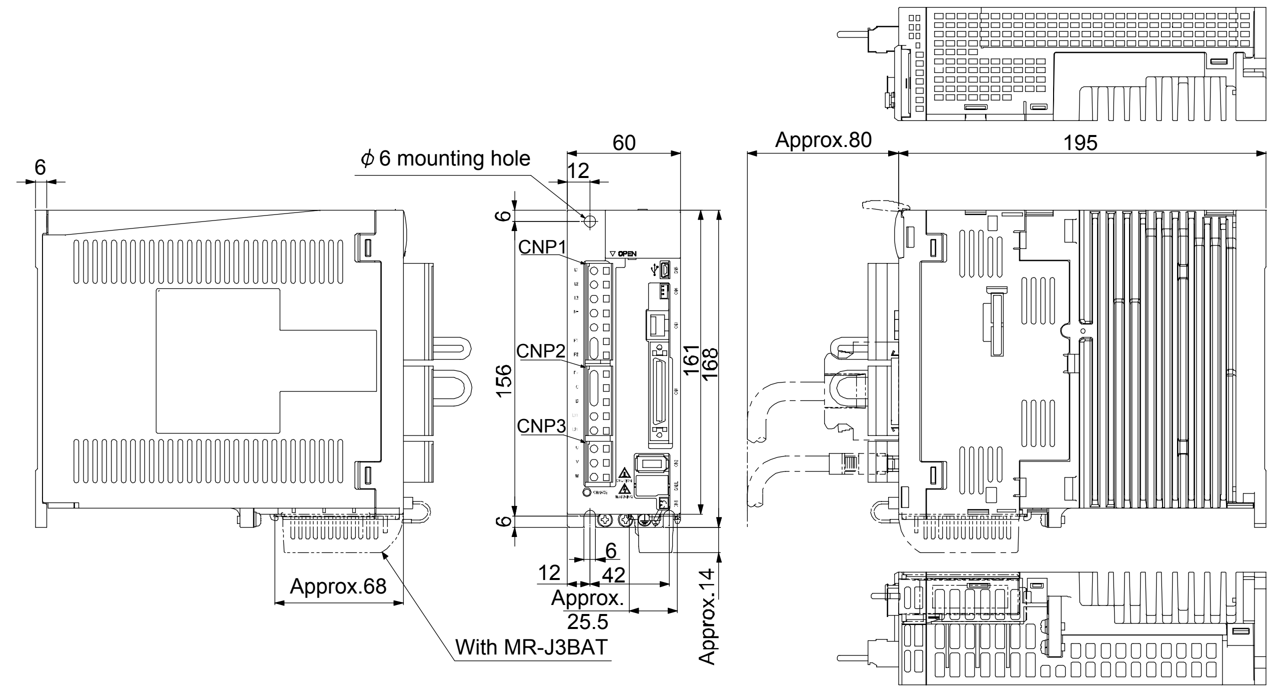


Mounting hole process drawing

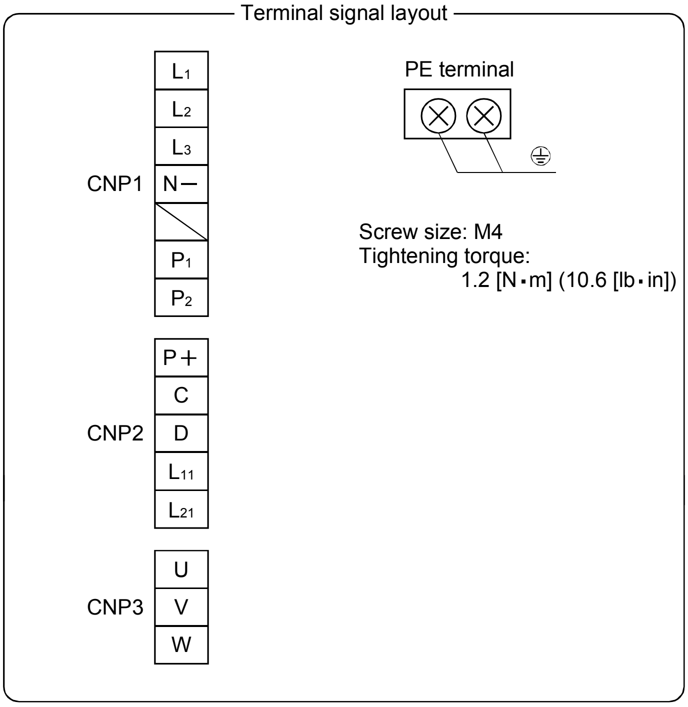
Mounting screw
Screw size: M5
Tightening torque: 3.24[N・m] (28.7[lb・in])

(4) MR-J3-60A4 · MR-J3-100A4

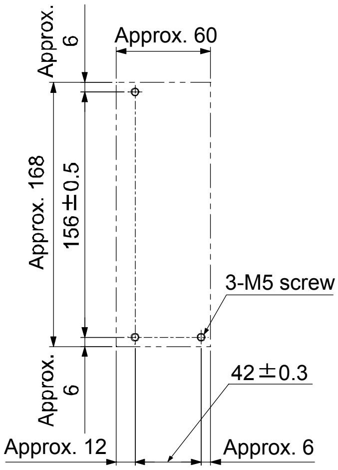
[Unit: mm]



Mass: 1.7 [kg] (3.75 [lb])



Screw size: M4
Tightening torque:
1.2 [N·m] (10.6 [lb·in])



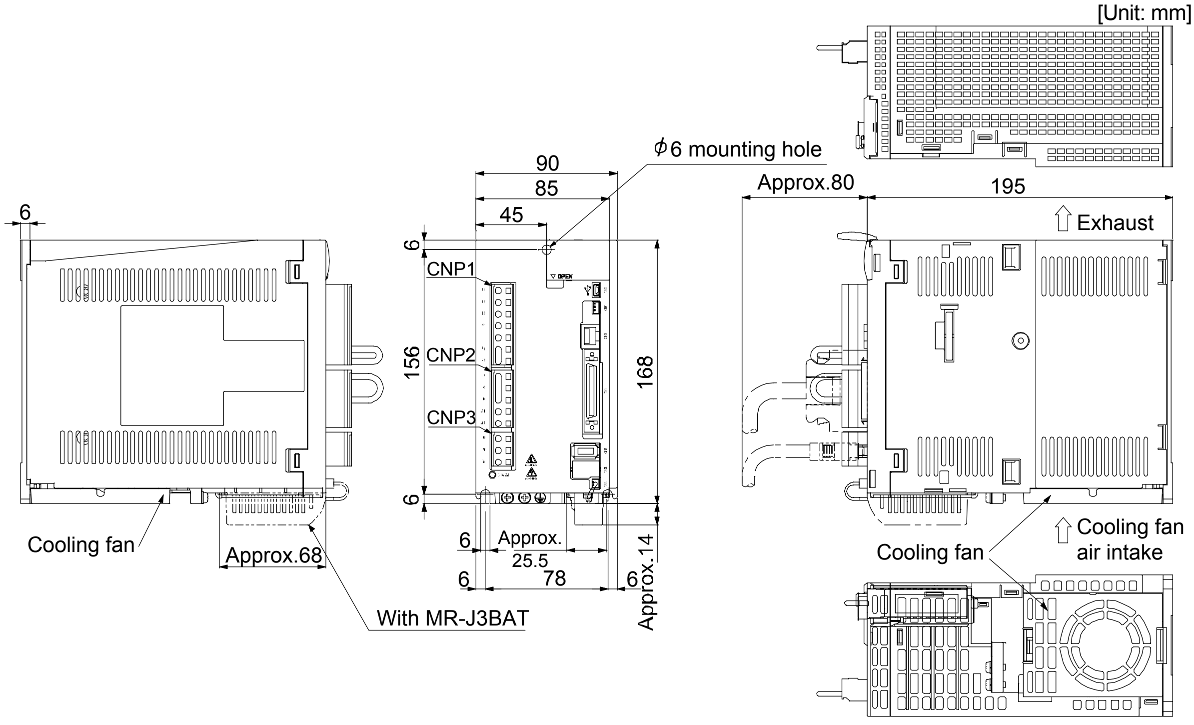
Mounting hole process drawing

Mounting screw
Screw size: M5
Tightening torque: 3.24[N · m] (28.7[lb · in])

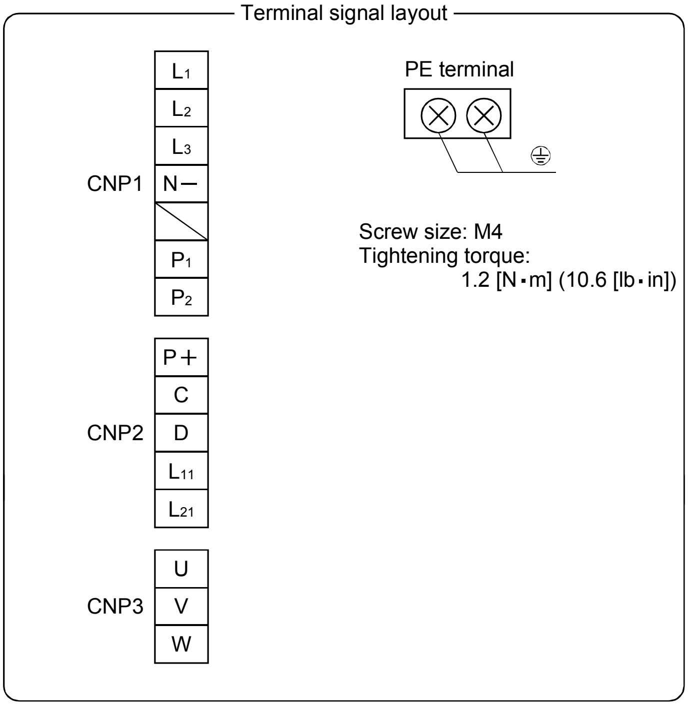
(5) MR-J3-200A(4)

POINT

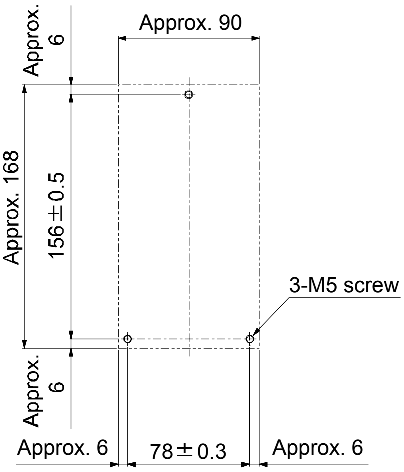
- Connectors (CNP1, CNP2, and CNP3) and appearance of MR-J3-200A servo amplifier have been changed from April 2008 production. Model name of the servo amplifier before March 2008 is changed to MR-J3-200A-RT. For MR-J3-200A-RT, refer to appendix 5.



Mass: 2.1 [kg] (4.63 [lb])



Screw size: M4
Tightening torque:
1.2 [N•m] (10.6 [lb•in])

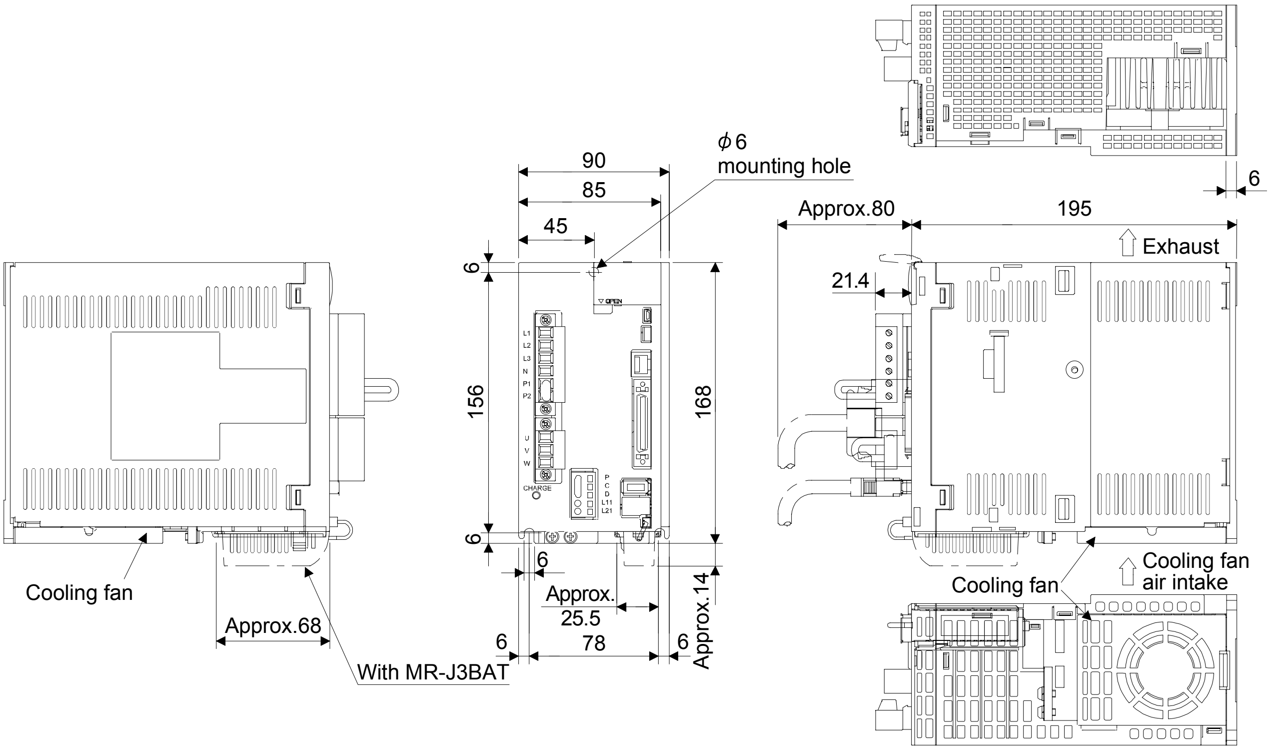


Mounting hole process drawing

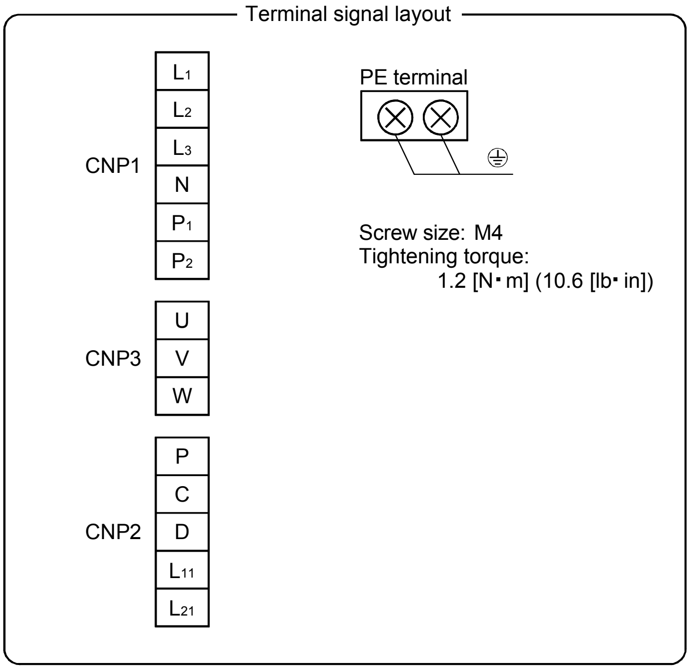
Mounting screw
Screw size: M5
Tightening torque: 3.24[N • m] (28.7[lb • in])

(6) MR-J3-350A

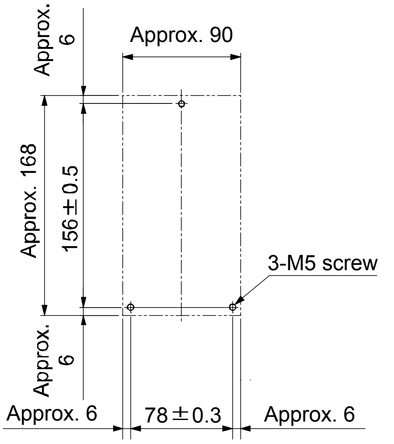
[Unit: mm]



Mass: 2.1 [kg] (4.63 [lb])



Screw size: M4
Tightening torque:
1.2 [N • m] (10.6 [lb • in])

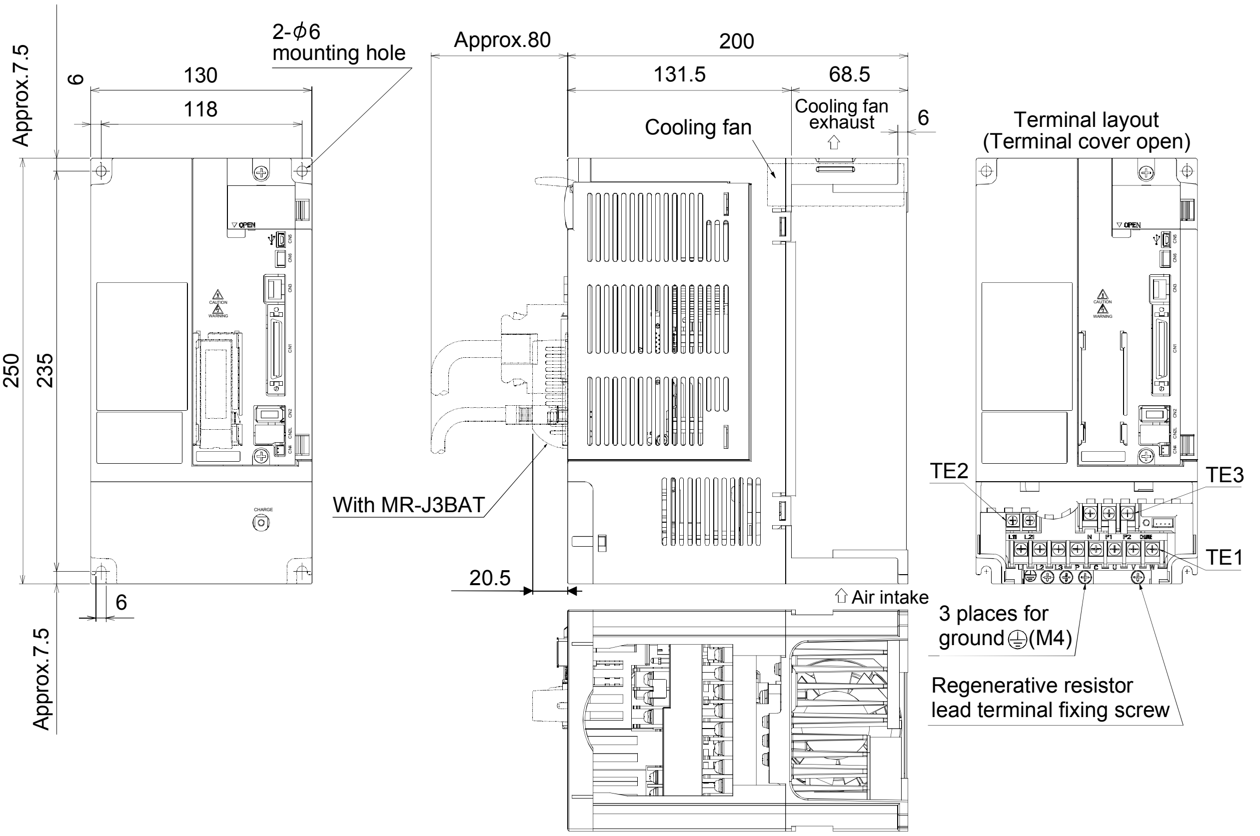


Mounting hole process drawing

Mounting screw
Screw size: M5
Tightening torque: 3.24[N • m] (28.7[lb • in])

(7) MR-J3-350A4 · MR-J3-500A (4)

[Unit: mm]



Mass: 4.6 [kg] (10.1 [lb])

Terminal signal layout

TE1

L_1	L_2	L_3	P	C	U	V	W

Terminal screw: M4
Tightening torque: 1.2[N·m]
(10.6 [lb·in])

TE2

L_{11}	L_{21}

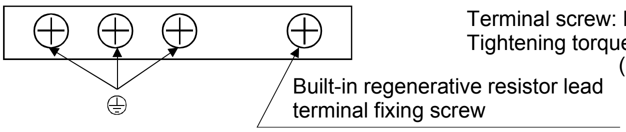
Terminal screw: M3.5(Note)
Tightening torque: 0.8[N·m]
(7.08 [lb·in])

TE3

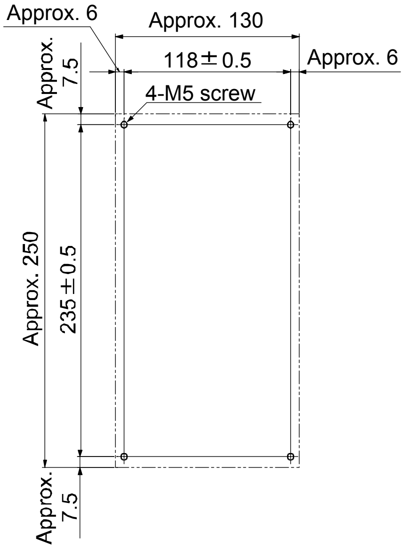
N	P_1	P_2

Terminal screw: M4
Tightening torque: 1.2[N·m]
(10.6 [lb·in])

PE terminal



Terminal screw: M4
Tightening torque: 1.2[N·m]
(10.6 [lb·in])



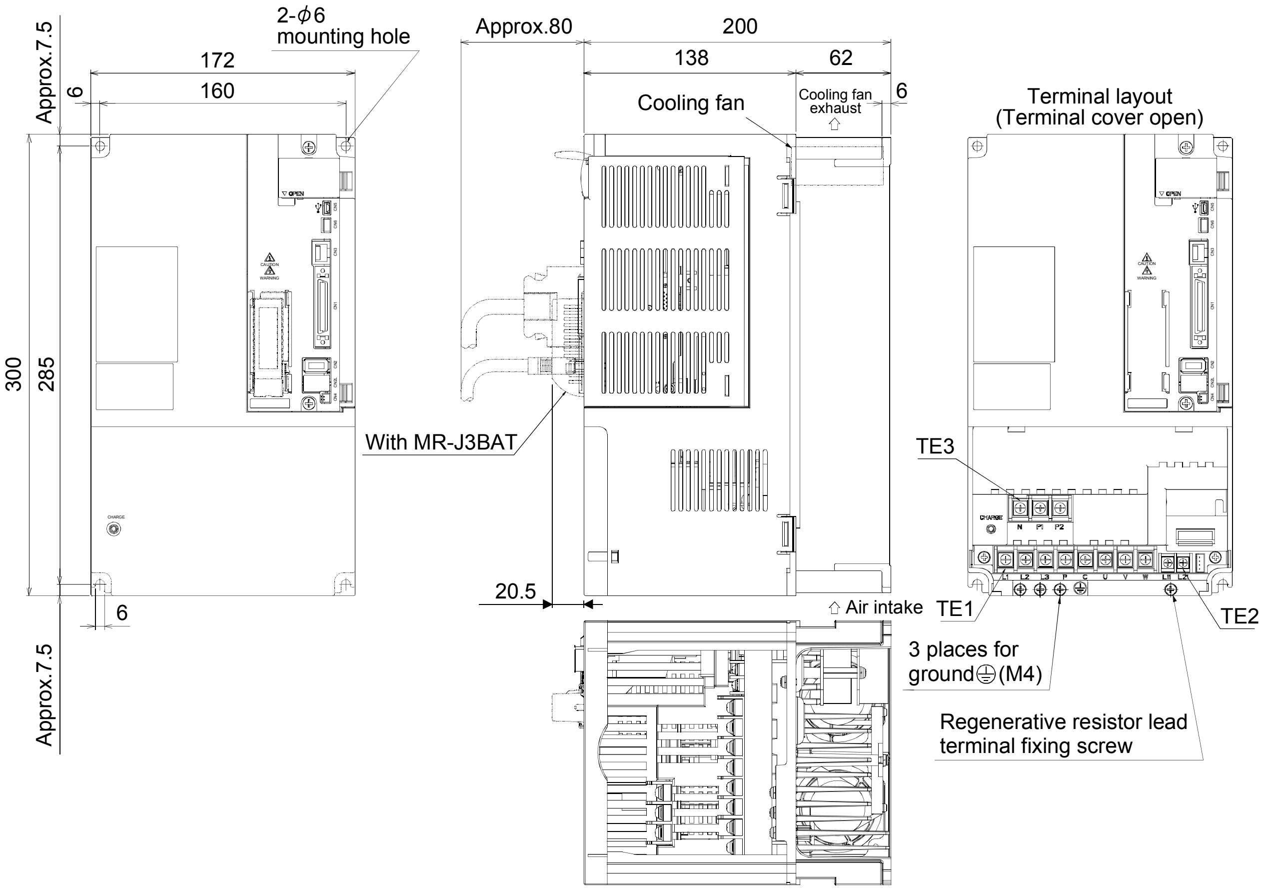
Mounting hole process drawing

Mounting screw
Screw size: M5
Tightening torque: 3.24[N · m] (28.7[lb · in])

Note. Screw size is M3.5 for the control circuit terminal block (TE2) of the servo amplifier manufactured in April 2007 or later. Screw size is M3 for the control terminal block (TE2) of the servo amplifier manufactured in March 2007 or earlier.

(8) MR-J3-700A (4)

[Unit: mm]



Mass: 6.2 [kg] (13.7 [lb])

Terminal signal layout

TE1

L_1	L_2	L_3	P	C	U	V	W

Terminal screw: M4
Tightening torque: 1.2[N•m]
(10.6 [lb•in])

TE2

L_{11}	L_{21}

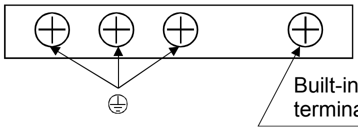
Terminal screw: M3.5(Note)
Tightening torque: 0.8[N•m]
(7.08 [lb•in])

TE3

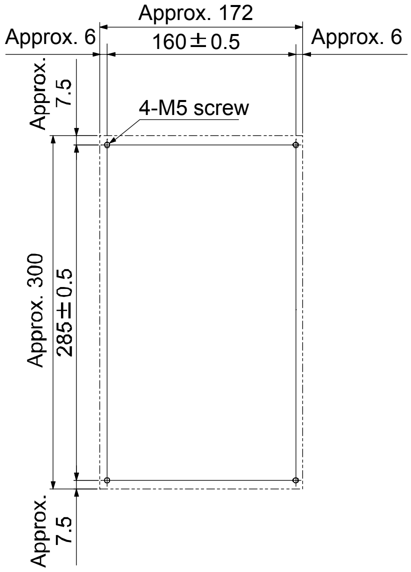
N	P_1	P_2

Terminal screw: M4
Tightening torque: 1.2[N•m]
(10.6 [lb•in])

PE terminal



Terminal screw: M4
Tightening torque: 1.2[N•m]
(10.6 [lb•in])



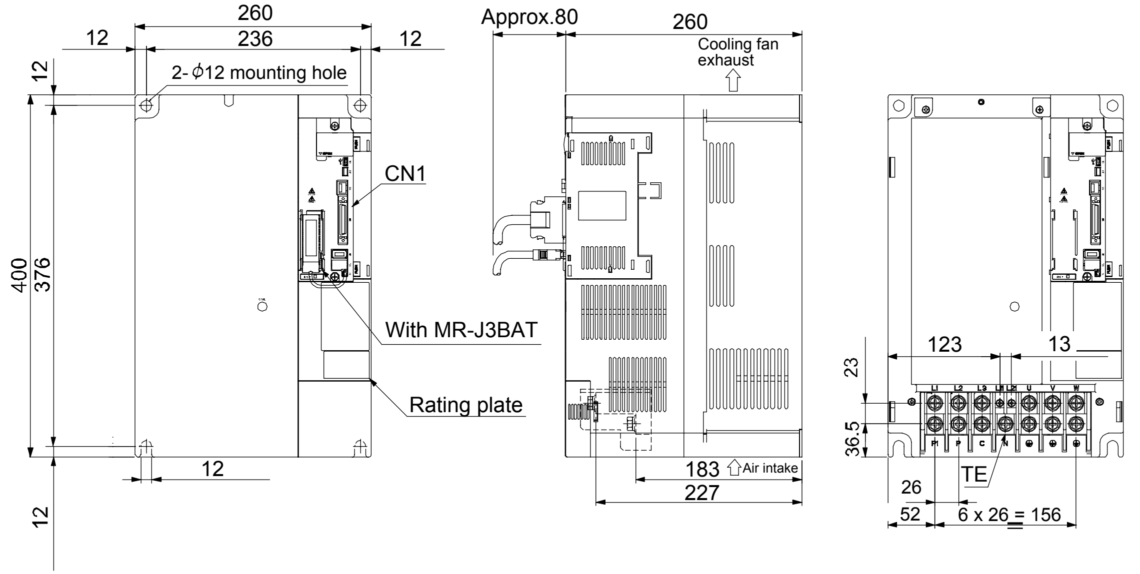
Mounting hole process drawing

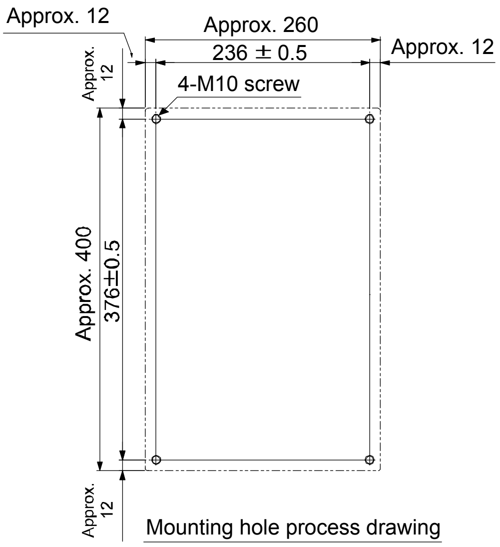
Note. Screw size is M3.5 for the control circuit terminal block (TE2) of the servo amplifier manufactured in April 2007 or later. Screw size is M3 for the control terminal block (TE2) of the servo amplifier manufactured in March 2007 or earlier.

Mounting screw
Screw size: M5
Tightening torque: 3.24[N • m] (28.7[lb • in])

(9) MR-J3-11KA(4) to MR-J3-22KA(4)

[Unit: mm]





Mounting hole process drawing

Servo amplifier	Mass[kg]([lb])
MR-J3-11KA(4)	18.0 (40)
MR-J3-15KA(4)	18.0 (40)
MR-J3-22KA(4)	19.0 (42)

Terminal signal layout

TE

L_1	L_2	L_3	L_{11} L_{21}	U	V	W
P_1	P	C	N	⏚	⏚	⏚

		L_1・L_2・L_3・U・V・W P_1・P・C・N・⏚	L_{11}・L_{21}
MR-J3-11KA(4) MR-J3-15KA(4)	Screw size	M6	M4
	Tightening torque [(lb:in)][N・m]	3.0	1.2
MR-J3-22KA(4)	Screw size	M8	M4
	Tightening torque [(lb:in)][N・m]	6.0	1.2

Mounting screw

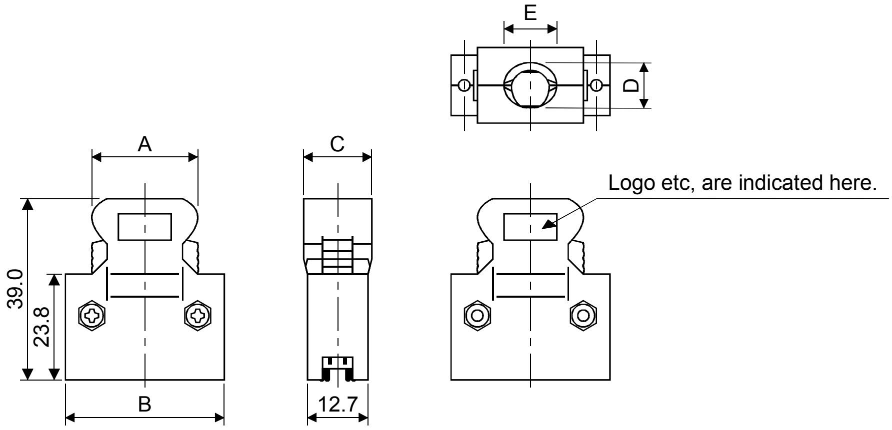
Servo amplifier	Screw size	Tightening torque [N・m][(lb:in)]
MR-J3-11KA(4) MR-J3-15KA4) MR-J3-22KA(4)	M10	26.5 (234.5)

10.2 Connector

(1) Miniature delta ribbon (MDR) system (3M)

(a) One-touch lock type

[Unit: mm]

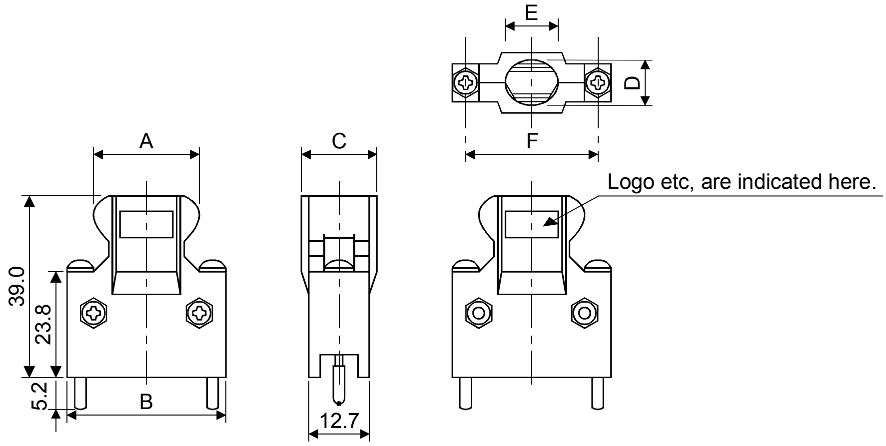


Connector	Shell kit	Each type of dimension				
		A	B	C	D	E
10150-3000PE	10350-52F0-008	41.1	52.4	18.0	14.0	17.0

(b) Jack screw M2.6 type

This is not available as option.

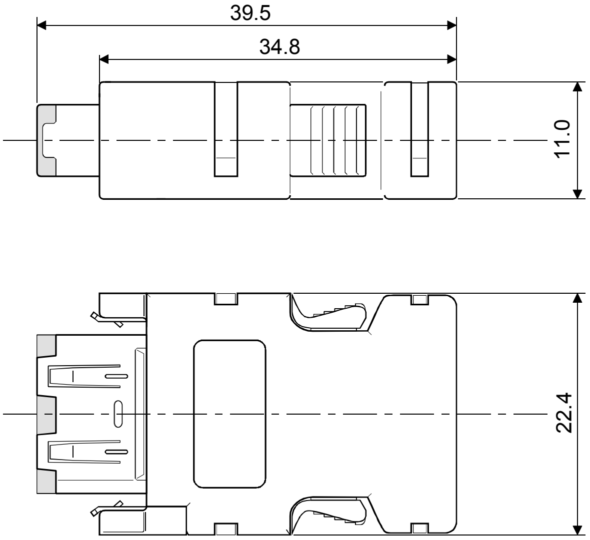
[Unit: mm]



Connector	Shell kit	Each type of dimension					
		A	B	C	D	E	F
10150-3000PE	10350-52A0-008	41.1	52.4	18.0	14.0	17.0	46.5

(2) SCR connector system (3M)
Receptacle: 36210-0100PL
Shell kit : 36310-3200-008

[Unit: mm]

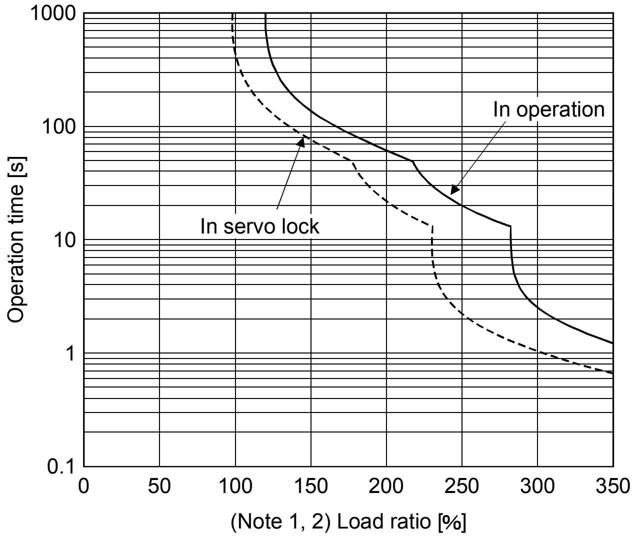


MEMO

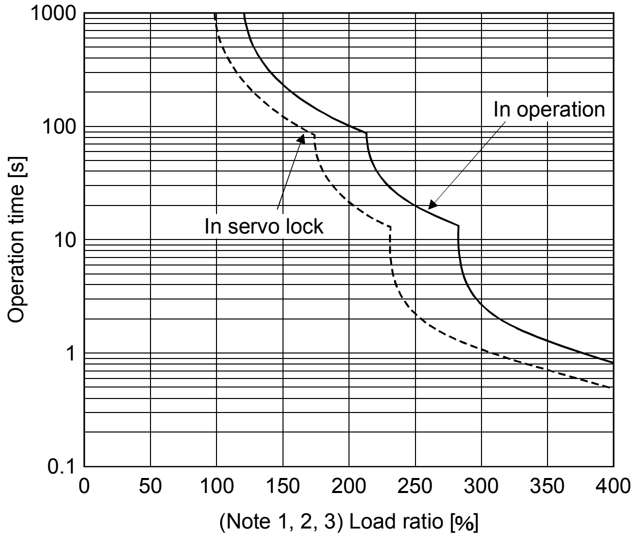
11. CHARACTERISTICS

11.1 Overload protection characteristics

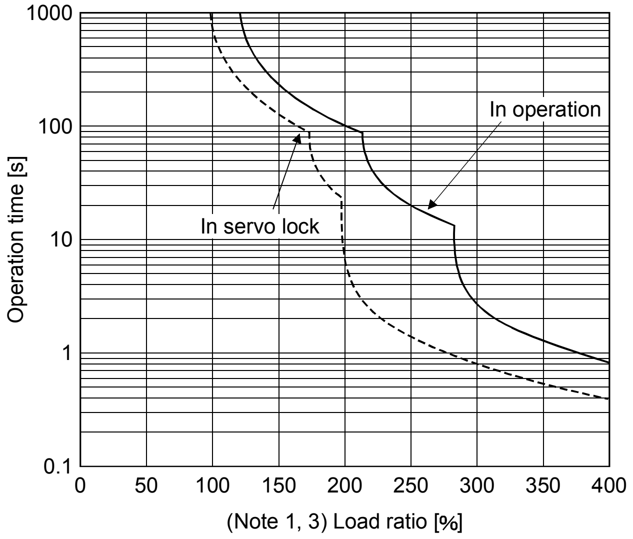
An electronic thermal relay is built in the servo amplifier to protect the servo motor, servo amplifier and servo motor power line from overloads. Overload 1 alarm (AL.50) occurs if overload operation performed is above the electronic thermal relay protection curve shown in any of Figs 11.1. Overload 2 alarm (AL.51) occurs if the maximum current flows continuously for several seconds due to machine collision, etc. Use the equipment on the left-hand side area of the continuous or broken line in the graph.
In a machine like the one for vertical lift application where unbalanced torque will be produced, it is recommended to use the machine so that the unbalanced torque is 70% or less of the rated torque.
When you carry out adhesion mounting of the servo amplifier, make circumference temperature into 0 to 45℃ (32 to 113℉), or use it at 75% or smaller effective load ratio.
Servo amplifier MR-J3 series has solid-state servo motor overload protection. (The motor full load current is 115% rated current.)



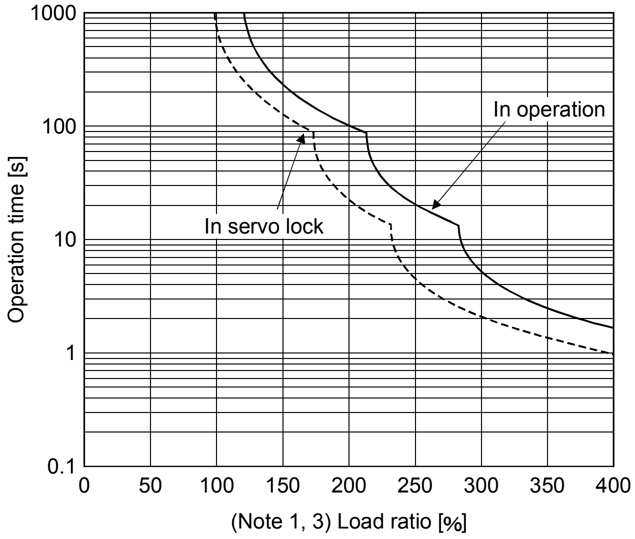
MR-J3-10A(1)



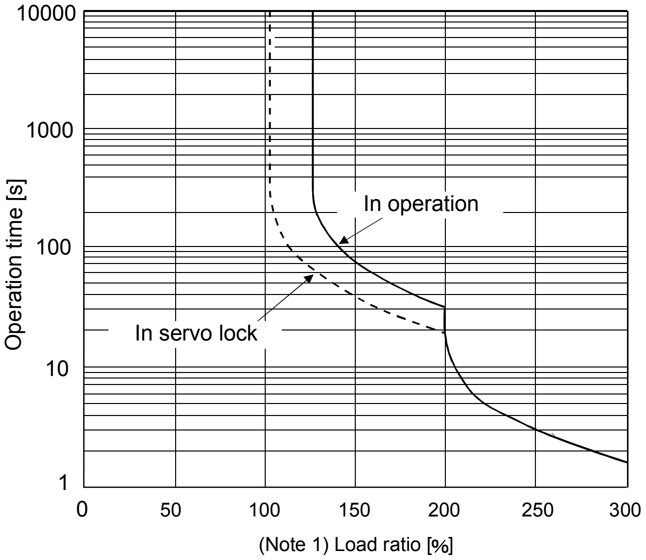
MR-J3-20A(1) · MR-J3-40A(1)
MR-J3-60A(4) to MR-J3-100A(4)



MR-J3-200A(4) · MR-J3-350A(4)



MR-J3-500A(4) · MR-J3-700A(4)



MR-J3-11KA(4) to MR-J3-22KA(4)

Note 1. If operation that generates torque more than 100% of the rating is performed with an abnormally high frequency in a servo motor stop status (servo lock status) or in a 30r/min or less low-speed operation status, the servo amplifier may fail even when the electronic thermal relay protection is not activated.

2. The operation time at the load ratio of 300 to 350% applies when the maximum torque of HF-KP servo motor is increased to 350%.

3. The operation time at the load ratio of 300 to 400% applies when the maximum torque of HF-JP servo motor is increased to 400%.

Fig 11.1 Electronic thermal relay protection characteristics

11.2 Power supply equipment capacity and generated loss

(1) Amount of heat generated by the servo amplifier

Table 11.1 indicates servo amplifiers' power supply capacities and losses generated under rated load. For thermal design of an enclosure, use the values in Table 11.1 in consideration for the worst operating conditions. The actual amount of generated heat will be intermediate between values at rated torque and servo off according to the duty used during operation. When the servo motor is run at less than the maximum speed, the power supply capacity will be smaller than the value in the table, but the servo amplifier's generated heat will not change.

Table 11.1 Power supply capacity and generated heat per servo amplifier at rated output

Servo amplifier	Servo motor	(Note 1) Power supply capacity [kVA]	(Note 2) Servo amplifier-generated heat [W]		Area required for heat dissipation [m^2]
			At rated torque	With servo off	
MR-J3-10A(1)	HF-MP053	0.3	25	15	0.5
	HF-MP13	0.3	25	15	0.5
	HF-KP053 · 13	0.3	25	15	0.5
MR-J3-20A(1)	HF-MP23	0.5	25	15	0.5
	HF-KP23	0.5	25	15	0.5
MR-J3-40A(1)	HF-MP43	0.9	35	15	0.7
	HF-KP43	0.9	35	15	0.7
MR-J3-60A(4)	HF-SP52(4)	1.0	40	15	0.8
	HF-SP51	1.0	40	15	0.8
	HC-LP52	1.0	40	15	0.8
	HF-JP53(4)	1.0	40	15	0.8
MR-J3-70A	HF-MP73	1.3	50	15	1.0
	HF-KP73	1.3	50	15	1.0
	HC-UP72	1.3	50	15	1.0
	HF-JP73	1.3	50	15	1.0
MR-J3-100A(4)	HF-SP102(4)	1.7	50	15	1.0
	HF-SP81	1.5	50	15	1.0
	HC-LP102	1.7	50	15	1.0
	HF-JP734	1.3	50	15	1.0
	HF-JP103(4)	1.7	50	15	1.0
MR-J3-200A(4)	HF-SP152(4)	2.5	90	20	1.8
	HF-SP202(4)	3.5	90	20	1.8
	HF-SP121	2.1	90	20	1.8
	HF-SP201	3.5	90	20	1.8
	HC-RP103	1.8	50	15	1.0
	HC-RP153	2.5	90	20	1.8
	HC-UP152	2.5	90	20	1.8
	HC-LP152	2.5	90	20	1.8
	HF-JP153(4)	2.5	90	20	1.8
	HF-JP203(4)	3.5	90	20	1.8
MR-J3-350A(4)	HF-SP352(4)	5.5	130	20 (25) (Note 3)	2.7
	HC-RP203	3.5	90	20	1.8
	HC-UP202	3.5	90	20	1.8
	HC-LP202	3.5	90	20	1.8
	HF-SP301	4.8	120	20	2.4
	HF-JP353(4)	5.5	160	25	2.7

Servo amplifier	Servo motor	(Note 1) Power supply capacity [kVA]	(Note 2) Servo amplifier-generated heat [W]		Area required for heat dissipation [m²]
			At rated torque	With servo off	
MR-J3-500A(4)	HF-SP502(4)	7.5	195	25	3.9
	HC-RP353	5.5	135	25	2.7
	HC-RP503	7.5	195	25	3.9
	HC-UP352	5.5	195	25	3.9
	HC-UP502	7.5	195	25	3.9
	HC-LP302	4.5	120	25	2.4
	HA-LP502	7.5	195	25	3.9
	HF-SP421	6.7	160	25	3.2
	HF-JP503(4)	7.5	195	25	3.9
MR-J3-700A(4)	HF-SP702(4)	10.0	300	25	6.0
	HA-LP702	10.6	300	25	6.0
	HA-LP601(4)	10.0	260	25	5.2
	HA-LP701M(4)	11.0	300	25	6.0
MR-J3-11KA(4)	HC-LP11K2(4)	16.0	530	45	11.0
	HC-LP801(4)	12.0	390	45	7.8
	HC-LP12K1(4)	18.0	580	45	11.6
	HC-LP11K1M(4)	16.0	530	45	11.0
	HF-JP11K1M(4) (Note 4)	16.0	530	45	11.0
MR-J3-15KA(4)	HC-LP15K2(4)	22.0	640	45	13.0
	HC-LP15K1(4)	22.0	640	45	13.0
	HC-LP15K1M(4)	22.0	640	45	13.0
	HF-JP15K1M(4) (Note 4)	22.0	640	45	13.0
MR-J3-22KA(4)	HC-LP22K2(4)	33.0	850	55	17.0
	HC-LP20K1(4)	30.1	775	55	15.5
	HC-LP25K1	37.6	970	55	19.4
	HC-LP22K1M(4)	33.0	850	55	17.0

Note 1. Note that the power supply capacity will vary according to the power supply impedance. This value is applicable when the power factor improving AC reactor or power factor improving DC reactor is not used.

2. Heat generated during regeneration is not included in the servo amplifier-generated heat. To calculate heat generated by the regenerative option, refer to section 12.2.

3. For 400V class, the value is within the ( ).

4. The servo amplifiers, which support these servo motors, have "-LR" at the end of their model names.

(2) Heat dissipation area for enclosed servo amplifier

The enclosed control box (hereafter called the control box) which will contain the servo amplifier should be designed to ensure that its temperature rise is within +10℃ at the ambient temperature of 40℃. (With a 5℃ (41°F) safety margin, the system should operate within a maximum 55℃ (131°F) limit.) The necessary enclosure heat dissipation area can be calculated by Equation 11.1.

$$A = \frac{P}{K \cdot \Delta T} \quad \cdots\cdots (11.1)$$

where, A : Heat dissipation area [m^2]
P : Loss generated in the control box [W]
ΔT : Difference between internal and ambient temperatures [℃]
K : Heat dissipation coefficient [5 to 6]

When calculating the heat dissipation area with Equation 11.1, assume that P is the sum of all losses generated in the enclosure. Refer to Table 11.1 for heat generated by the servo amplifier. "A" indicates the effective area for heat dissipation, but if the enclosure is directly installed on an insulated wall, that extra amount must be added to the enclosure's surface area.

The required heat dissipation area will vary wit the conditions in the enclosure. If convection in the enclosure is poor and heat builds up, effective heat dissipation will not be possible. Therefore, arrangement of the equipment in the enclosure and the use of a cooling fan should be considered.

Table 11.1 lists the enclosure dissipation area for each servo amplifier when the servo amplifier is operated at the ambient temperature of 40℃ (104°F) under rated load.

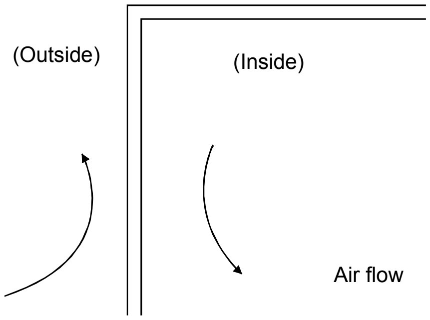


Fig. 11.2 Temperature distribution in enclosure

When air flows along the outer wall of the enclosure, effective heat exchange will be possible, because the temperature slope inside and outside the enclosure will be steeper.

11.3 Dynamic brake characteristics

POINT

- Dynamic brake operates at occurrence of alarm, servo emergency stop warning (AL.E6) and when power is turned off. Do not use dynamic brake to stop in a normal operation as it is the function to stop in emergency.
- Maximum usage time of dynamic brake for a machine operating under recommended load inertia moment ratio is 1000 time while decelerating from rated speed to a stop with frequency of once in 10 minutes.
- Be sure to make emergency stop (EMG) valid after servo motor stops when using emergency stop (EMG) frequently in other than emergency.

11.3.1 Dynamic brake operation

(1) Calculation of coasting distance

Fig. 11.3 shows the pattern in which the servo motor comes to a stop when the dynamic brake is operated. Use Equation 11.2 to calculate an approximate coasting distance to a stop. The dynamic brake time constant τ varies with the servo motor and machine operation speeds. (Refer to (2) (a), (b) in this section.)

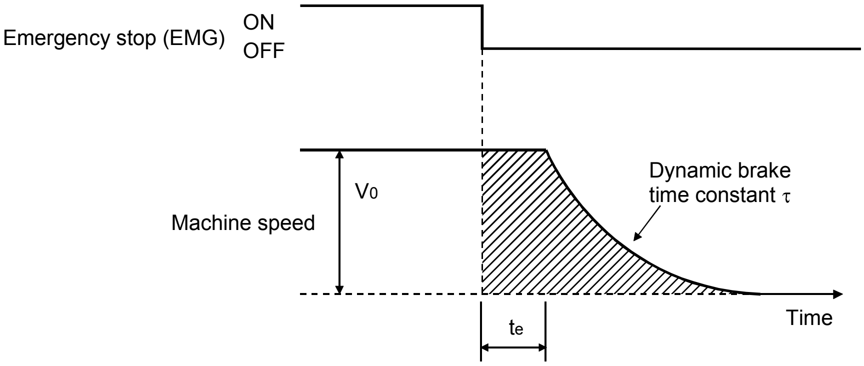


Fig. 11.3 Dynamic brake operation diagram

$$L_{max} = \frac{V_0}{60} \cdot \left\{ t_e + \tau \left[1 + \frac{J_L}{J_M} \right] \right\} \cdots\cdots (11.2)$$

L_{max} : Maximum coasting distance .... [mm][in]

V_o : Machine rapid feed rate .... [mm/min][in/min]

J_M : Servo motor inertial moment .... [kg・cm^2][oz・in^2]

J_L : Load inertia moment converted into equivalent value on servo motor shaft .... [kg・cm^2][oz・in^2]

τ : Dynamic brake time constant .... [s]

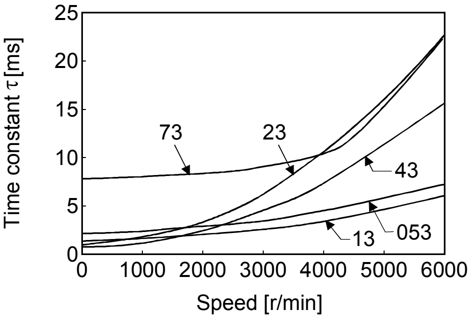
t_e : Delay time of control section .... [s]

For 7kW or lower servo, there is internal relay delay time of about 10ms. For 11k to 22kW servo, there is delay caused by magnetic contactor built into the external dynamic brake (about 50ms) and delay caused by the external relay.

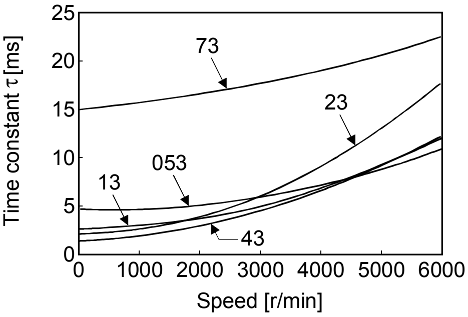
(2) Dynamic brake time constant

The following shows necessary dynamic brake time constant τ for the equations (11.2).

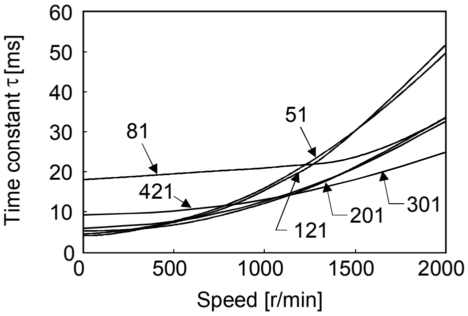
(a) 200V class servo motor



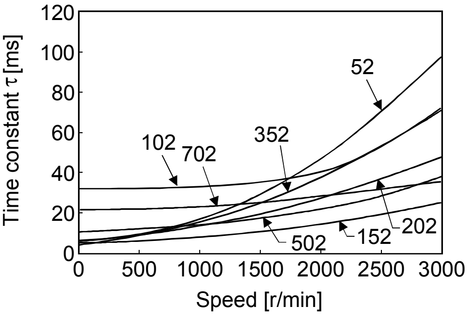
HF-MP series



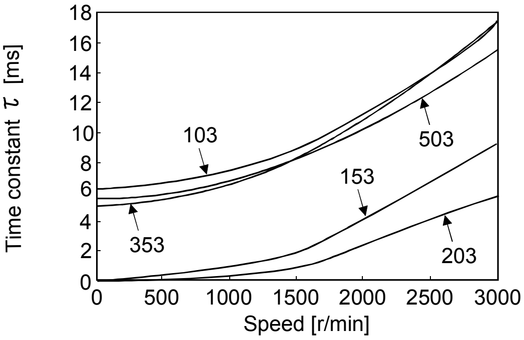
HF-KP series



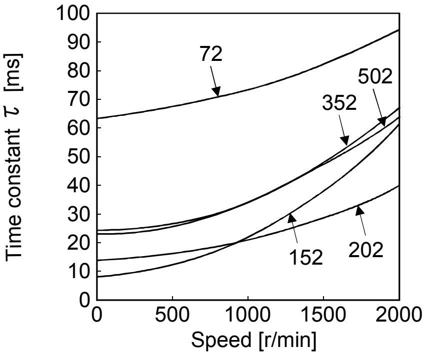
HF-SP1000r/min series



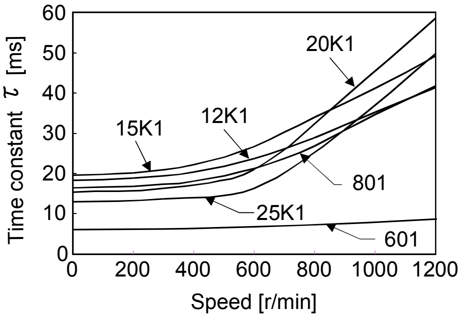
HF-SP2000r/min series



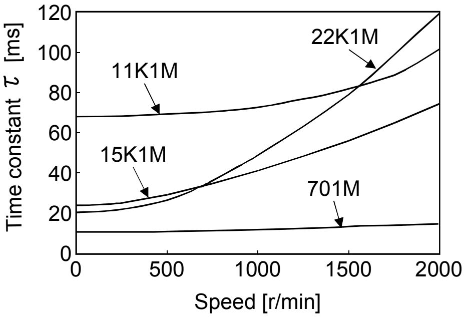
HC-RP series



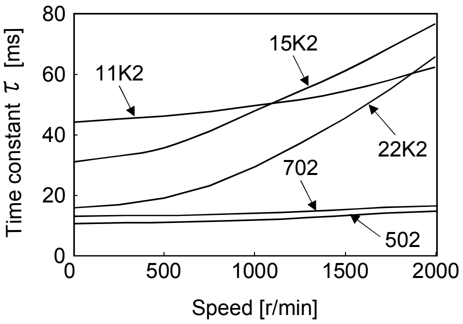
HC-UP series



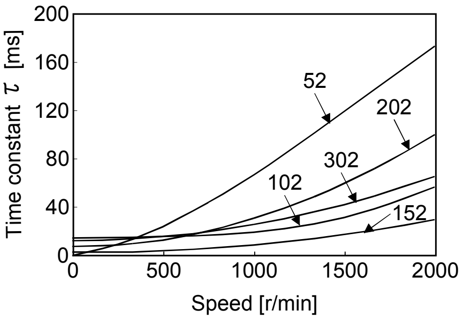
HA-LP1000r/min series



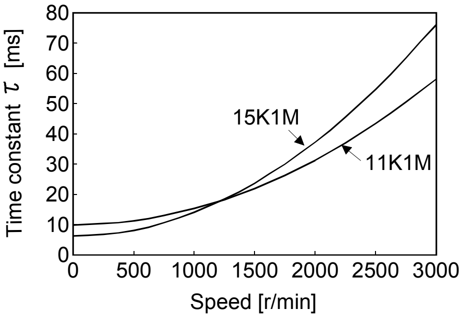
HA-LP1500r/min series



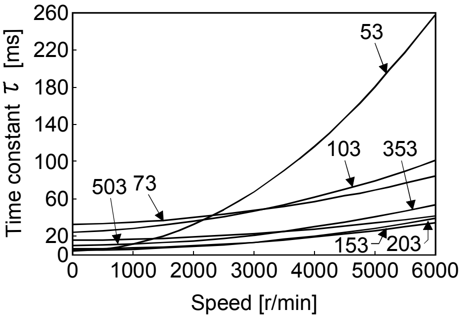
HA-LP2000r/min series



HC-LP series

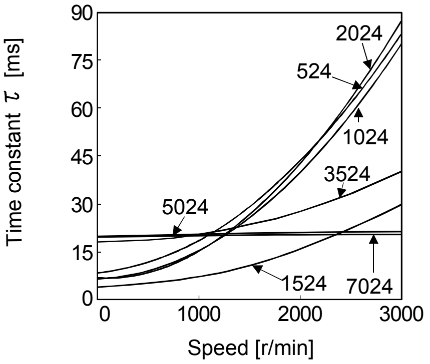


HF-JP1500r/min series

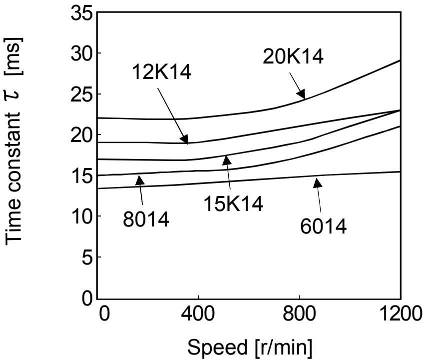


HF-JP3000r/min series

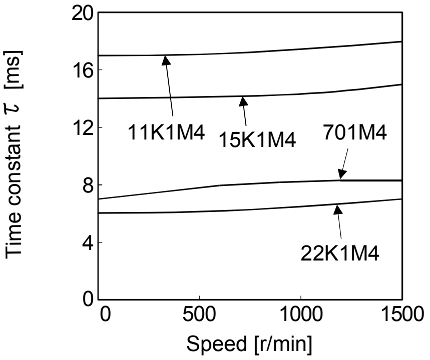
(b) 400V class servo motor



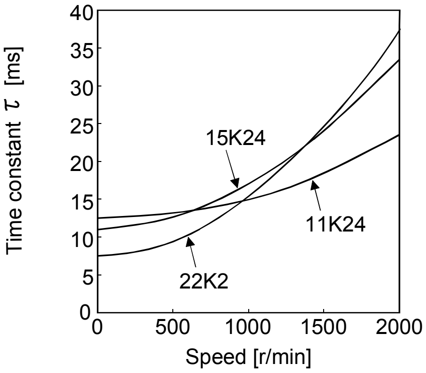
HA-SP2000r/min series



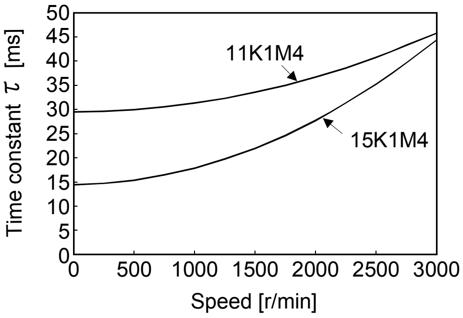
HA-LP1000r/min series



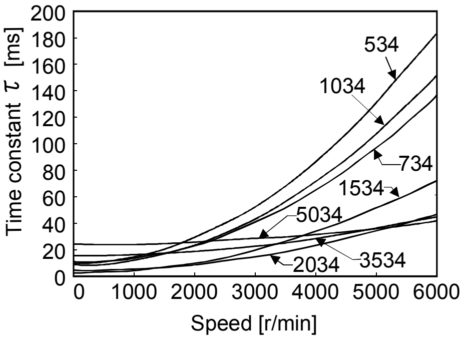
HA-LP1500r/min series



HA-LP2000r/min series



HF-JP1500r/min series



HF-JP3000r/min series

11.3.2 The dynamic brake at the load inertia moment

Use the dynamic brake under the load inertia moment ratio indicated in the following table. If the load inertia moment is higher than this value, the dynamic brake may burn. If there is a possibility that the load inertia moment may exceed the value, contact your local sales office.
The values of the load inertia moment ratio in the table are the values at the maximum rotation speed of the servo motor.

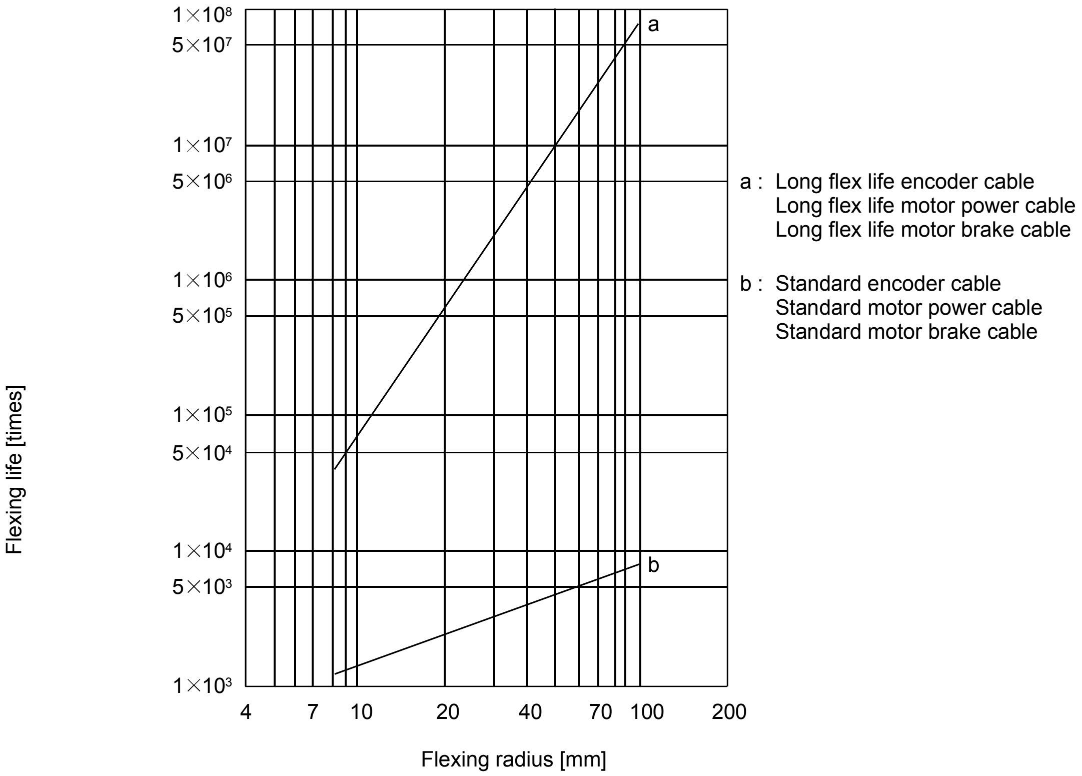
Servo amplifier	Servo motor											
	HF-KP□	HF-MP□	HF-SP□1	HF-SP□2	HC-RP□	HC-UP□	HC-LP□	HA-LP□1	HA-LP□1M	HA-LP□2	HF-JP□	HF-JP□1M
MR-J3-10A(1)	30	30										
MR-J3-20A(1)	30	30										
MR-J3-40A(1)	30	30										
MR-J3-60A			30	30			30				30	
MR-J3-70A	30	30				30						
MR-J3-100A			30	30			30				30	
MR-J3-200A			30	30	30	30	30				30	
MR-J3-350A			16	16	16	16	16				16 (Note 3)	
MR-J3-500A			15	15	15	15	15			15	15 (Note 3)	
MR-J3-700A				5 (Note 1)				5 (Note 1)	5 (Note 1)	5 (Note 1)		
MR-J3-11KA (Note 2)								30	30	30		10 (Note 3)
MR-J3-15KA (Note 2)								30	30	30		10 (Note 3)
MR-J3-22KA (Note 2)								30	30	30		

Servo amplifier	Servo motor					
	HF-SP□4	HA-LP□14	HA-LP□1M4	HA-LP□24	HF-JP□4	HF-JP□1M4
MR-J3-60A4	5 (Note 1)				30	
MR-J3-100A4	5 (Note 1)				30	
MR-J3-200A4	5 (Note 1)				30	
MR-J3-350A4	5 (Note 1)				30	
MR-J3-500A4	5 (Note 1)				15 (Note 3)	
MR-J3-700A4	5 (Note 1)	10	10			
MR-J3-11KA4 (Note 2)		30	30	30		10 (Note 3)
MR-J3-15KA4 (Note 2)		30	30	30		10 (Note 3)
MR-J3-22KA4 (Note 2)		30	30	30		

Note 1. The load inertia moment ratio is 15 at the rated rotation speed.
2. When the external dynamic brake is used.
3. The load inertia moment ratio is 30 at the rated rotation speed.

11.4 Cable flexing life

The flexing life of the cables is shown below. This graph calculated values. Since they are not guaranteed values, provide a little allowance for these values.



11.5 Inrush currents at power-on of main circuit and control circuit

The following table indicates the inrush currents (reference data) that will flow when the maximum permissible voltage (200V class: 253VAC, 400V class: 528VAC) is applied at the power supply capacity of 2500kVA and the wiring length of 1m.

Servo amplifier	Inrush currents ($A_{0\text{-}p}$)	
	Main circuit power supply (L_1, L_2, L_3)	Control circuit power supply (L_{11}, L_{21})
MR-J3-10A1 to 40A1	38A (Attenuated to approx. 14A in 10ms)	20 to 30A (Attenuated to approx. 0A in 1 to 2ms)
MR-J3-10A to 60A	30A (Attenuated to approx. 5A in 10ms)	
MR-J3-70A · 100A	54A (Attenuated to approx. 12A in 10ms)	
MR-J3-200A · 350A	120A (Attenuated to approx. 12A in 20ms)	
MR-J3-500A	44A (Attenuated to approx. 20A in 20ms)	30A (Attenuated to approx. 0A in 3ms)
MR-J3-700A	88A (Attenuated to approx. 20A in 20ms)	
MR-J3-11KA	235A (Attenuated to approx. 20A in 20ms)	
MR-J3-15KA		
MR-J3-22KA		
MR-J3-60A4 · 100A4	100A (Attenuated to approx. 5A in 10ms)	40 to 50A (Attenuated to approx. 0A in 2ms)
MR-J3-200A4	120A (Attenuated to approx. 12A in 20ms)	
MR-J3-350A4 · 500A4	66A (Attenuated to approx. 10A in 20ms)	41A (Attenuated to approx. 0A in 3ms)
MR-J3-700A4	67A (Attenuated to approx. 34A in 20ms)	
MR-J3-11KA4	325A (Attenuated to approx. 20A in 20ms)	45A (Attenuated to approx. 0A in 3ms)
MR-J3-15KA4		
MR-J3-22KA4		

Since large inrush currents flow in the power supplies, always use no-fuse breakers and magnetic contactors. (Refer to section 12.12.)
When circuit protectors are used, it is recommended to use the inertia delay type that will not be tripped by an inrush current.

MEMO

12. OPTIONS AND AUXILIARY EQUIPMENT

⚠WARNING	・Before connecting any option or peripheral equipment, turn off the power and wait for 15 minutes or longer until the charge lamp turns off. Then, confirm that the voltage between P(＋) and N(－) is safe with a voltage tester and others. Otherwise, an electric shock may occur. In addition, always confirm from the front of the servo amplifier whether the charge lamp is off or not.

⚠CAUTION	・Use the specified auxiliary equipment and options. Unspecified ones may lead to a fault or fire.

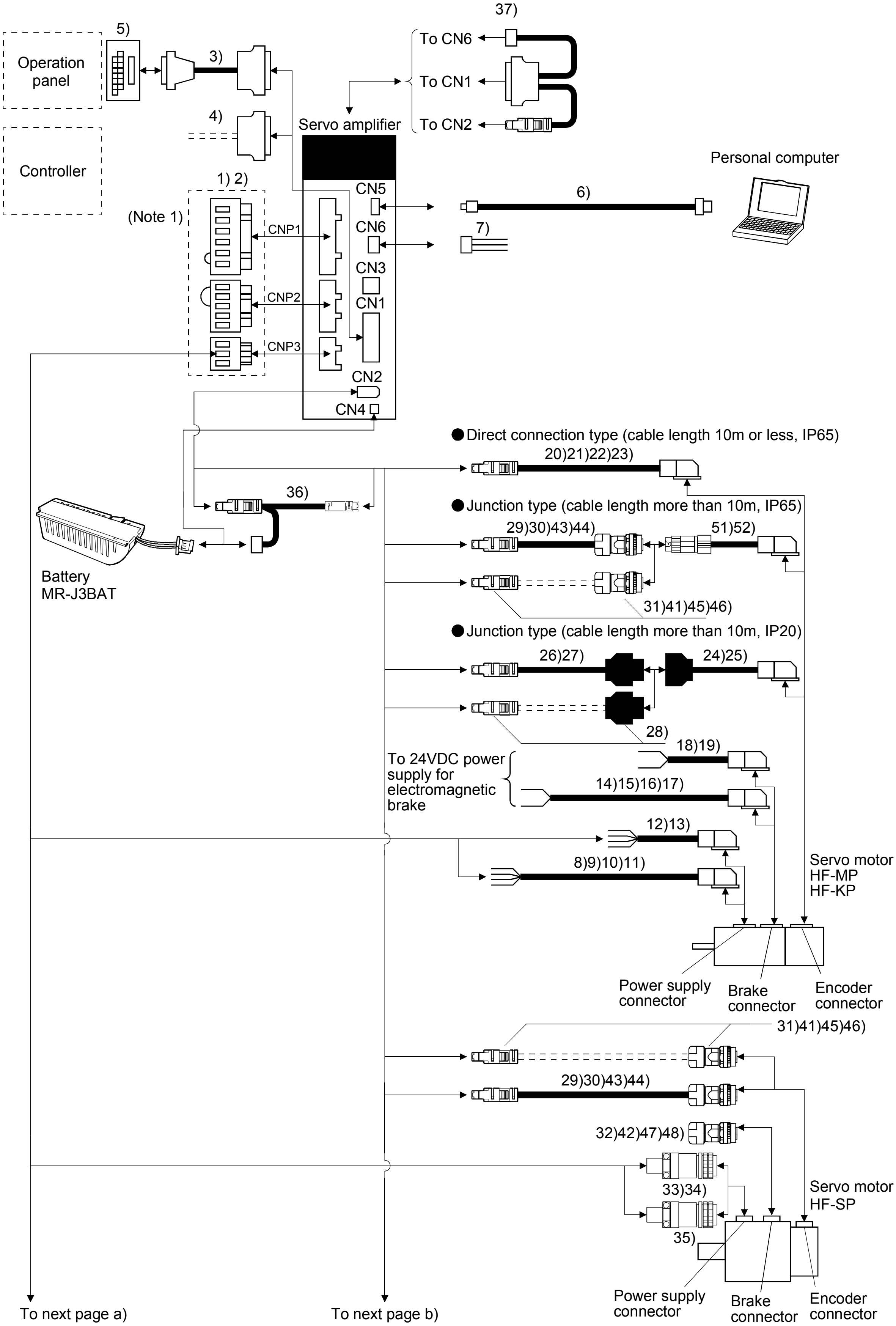
12.1 Cable/connector sets

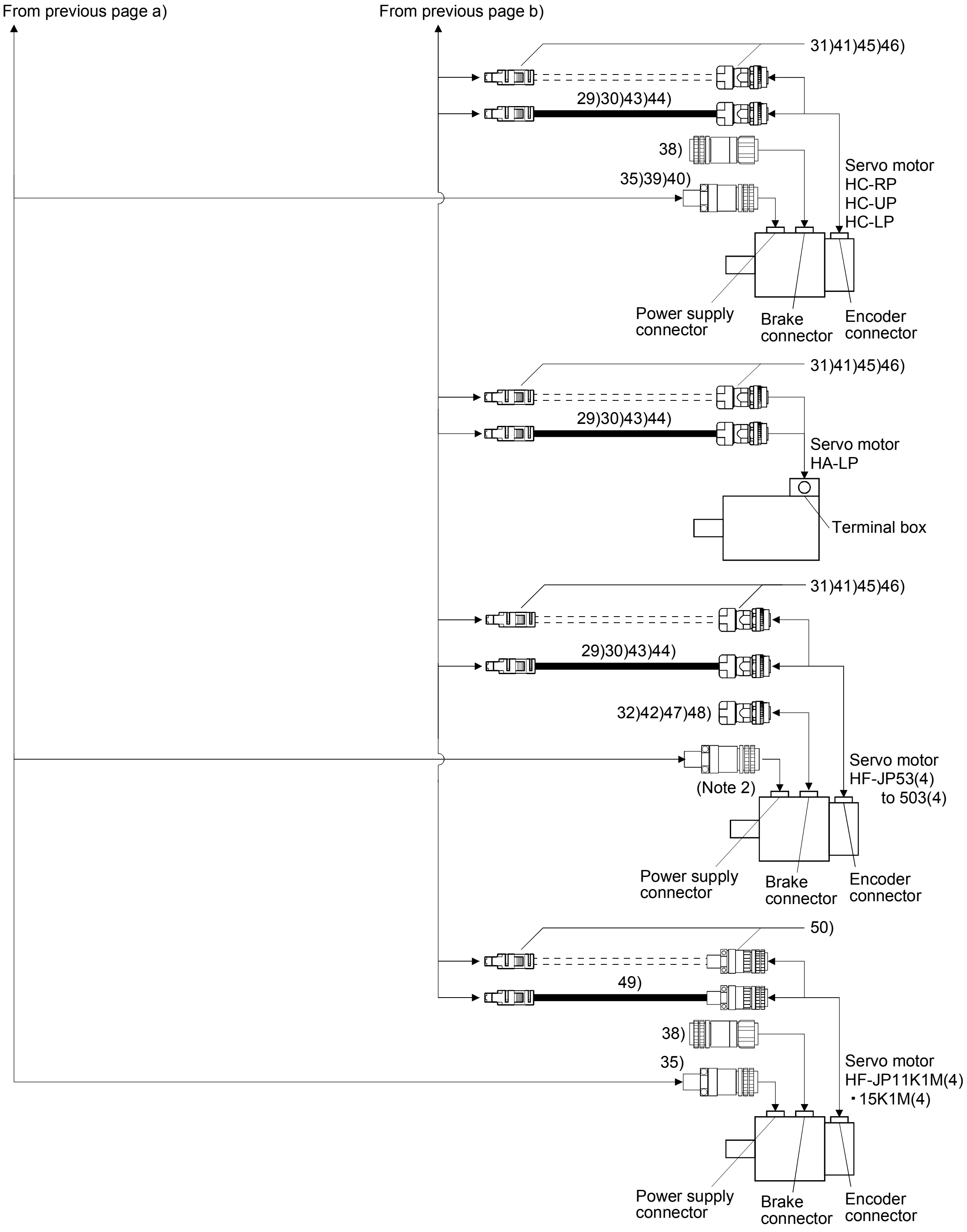
POINT

- The IP rating indicated is the cable's or connector's protection against ingress of dust and water when the cable or connector is connected to a servo amplifier or servo motor. If the IP rating of the cable, connector, servo amplifier and servo motor vary, the overall IP rating depends on the lowest IP rating of all components.

As the cables and connectors used with this servo, purchase the options indicated in this section.

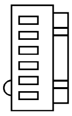
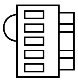
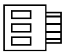
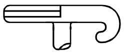
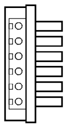
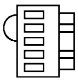
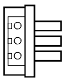
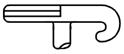
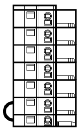
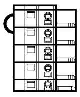
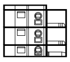
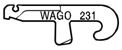
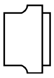
12.1.1 Combinations of cable/connector sets

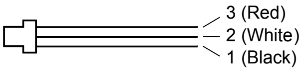
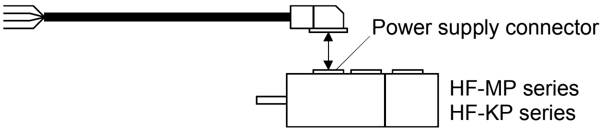
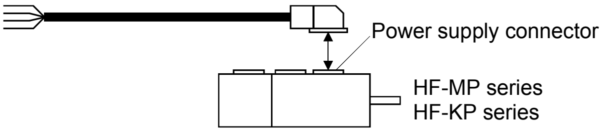
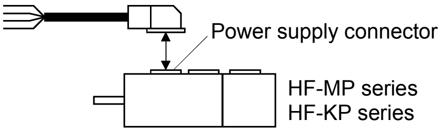
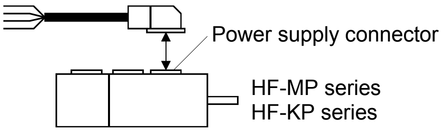
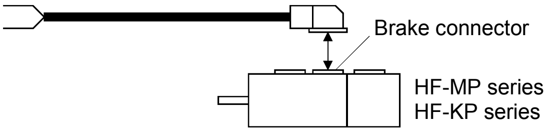
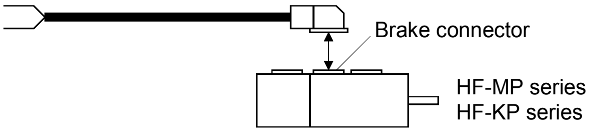


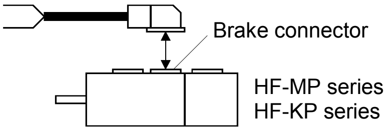
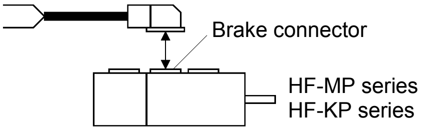
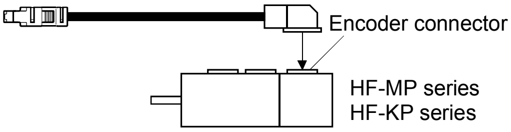
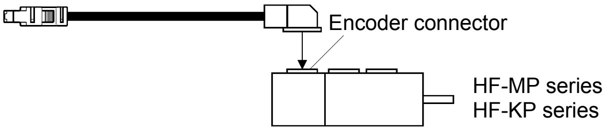
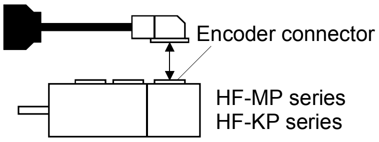
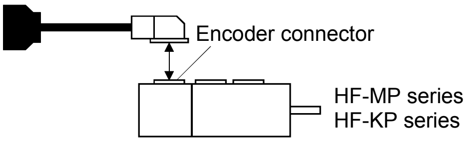


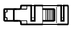
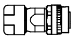
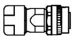
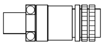
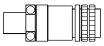
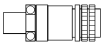
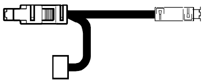
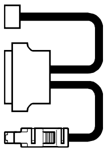
Note 1. Connectors for 3.5kW or less. For 5kW or more, terminal blocks.

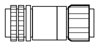
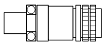
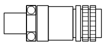
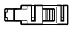
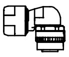
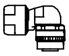
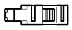
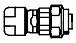
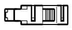
2. Use 33) for HF-JP53 to 203, and 534 to 5034. Use 34) for HF-JP353 and 503.

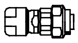
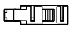
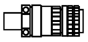
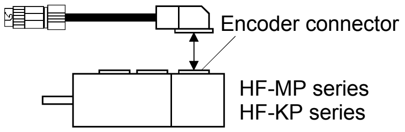
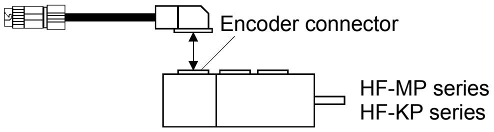
No.	Product	Model	Description	Application
1)	Servo amplifier power supply connector		 CNP1 connector: 54928-0670 (Molex) CNP2 connector: 54927-0520 (Molex) CNP3 connector: 54928-0370 (Molex) <Applicable cable example> Wire size: 0.14 to 2.5mm^2 (AWG26 to AWG14) Cable finish OD: to ϕ3.8mm  REC. Lever: 54932-0000 (Molex)	Supplied with servo amplifiers of 1kW or less in 100V class and 200V class
2)	Servo amplifier power supply connector		 CNP1 connector: PC 4/6-STF-7,62-CRWH (Phoenix Contact) CNP2 connector: 54927-0520 (Molex) CNP3 connector: PC 4/3-STF-7,62-CRWH (Phoenix Contact) <Applicable cable example> Wire size: 0.2 to 5.5mm^2 (AWG24 to AWG10) Cable finish OD: to ϕ5mm  REC. Lever: 54932-0000 (Molex)	Supplied with servo amplifiers of 3.5kW in 200V class
			 CNP1 connector: 721-207/026-000 (Plug) (WAGO) CNP2 connector: 721-205/026-000 (Plug) (WAGO) CNP3 connector: 721-203/026-000 (Plug) (WAGO) <Applicable cable example> Wire size: 0.08 to 2.5mm^2 (AWG28 to AWG12) Cable finish OD: to ϕ4.1mm  REC. Lever: 231-131 (WAGO)	Supplied with servo amplifiers of 2kW in 200V class and 2kW in 400V class
3)	Junction terminal block cable	MR-J2M-CN1TBL☐M Cable length: 0.5・1m (Refer to section 12.7)	For junction terminal block connector Connector: D7950-B500FL (3M) CN1 connector Connector: 10150-6000EL Shell kit: 10350-3210-000 (3M or equivalent) 	For junction terminal block connection
4)	CN1 connector set	MR-J3CN1	Connector: 10150-3000PE Shell kit: 10350-52F0-008 (3M or equivalent) 	
5)	Junction terminal block cable	MR-TB50	Refer to section 12.7.	

No.	Product	Model	Description	Application
6)	USB cable	MR-J3USBCBL3M Cable length: 3m	For CN5 connector minB connector (5 pins) For personal computer connector A connector 	For connection with PC-AT compatible personal computer
7)	Monitoring cable	MR-J3CN6CBL1M Cable length: 1m	 CN6 connector Housing: 51004-0300 Terminal: 50011-8100 (Molex)	
8)	Motor power supply cable	MR-PWS1CBL□M-A1-L Cable length: 2・5・10m	 Refer to section 12.1.3 for details.	IP65 Load side lead
9)	Motor power supply cable	MR-PWS1CBL□M-A1-H Cable length: 2・5・10m		IP65 Load side lead Long flex life
10)	Motor power supply cable	MR-PWS1CBL□M-A2-L Cable length: 2・5・10m	 Refer to section 12.1.3 for details.	IP65 Opposite-to-load side lead
11)	Motor power supply cable	MR-PWS1CBL□M-A2-H Cable length: 2・5・10m		IP65 Opposite-to-load side lead Long flex life
12)	Motor power supply cable	MR-PWS2CBL03M-A1-L Cable length: 0.3m	 Refer to section 12.1.3 for details.	IP55 Load side lead
13)	Motor power supply cable	MR-PWS2CBL03M-A2-L Cable length: 0.3m	 Refer to section 12.1.3 for details.	IP55 Opposite-to-load side lead
14)	Motor brake cable	MR-BKS1CBL□M-A1-L Cable length: 2・5・10m	 Refer to section 12.1.4 for details.	IP65 Load side lead
15)	Motor brake cable	MR-BKS1CBL□M-A1-H Cable length: 2・5・10m		IP65 Load side lead Long flex life
16)	Motor brake cable	MR-BKS1CBL□M-A2-L Cable length: 2・5・10m	 Refer to section 12.1.4 for details.	IP65 Opposite-to-load side lead
17)	Motor brake cable	MR-BKS1CBL□M-A2-H Cable length: 2・5・10m		IP65 Opposite-to-load side lead Long flex life

No.	Product	Model	Description	Application
18)	Motor brake cable	MR-BKS2CBL03M-A1-L Cable length: 0.3m	 Refer to section 12.1.4 for details.	IP55 Load side lead
19)	Motor brake cable	MR-BKS2CBL03M-A2-L Cable length: 0.3m	 Refer to section 12.1.4 for details.	IP55 Opposite-to-load side lead
20)	Encoder cable	MR-J3ENCBL□M-A1-L Cable length: 2・5・10m	 Refer to section 12.1.2 (1) for details.	IP65 Load side lead
21)	Encoder cable	MR-J3ENCBL□M-A1-H Cable length: 2・5・10m		IP65 Opposite-to-load side lead Long flex life
22)	Encoder cable	MR-J3ENCBL□M-A2-L Cable length: 2・5・10m	 Refer to section 12.1.2 (1) for details.	IP65 Opposite-to-load side lead
23)	Encoder cable	MR-J3ENCBL□M-A2-H Cable length: 2・5・10m		IP65 Opposite-to-load side lead Long flex life
24)	Encoder cable	MR-J3JCBL03M-A1-L Cable length: 0.3m	 Refer to section 12.1.2 (3) for details.	IP20 Load side lead
25)	Encoder cable	MR-J3JCBL03M-A2-L Cable length: 0.3m	 Refer to section 12.1.2 (3) for details.	IP20 Opposite-to-load side lead
26)	Encoder cable	MR-EKCBL□M-L Cable length: 20・30m	 For HF-MP・HF-KP series Refer to section 12.1.2 (2) for details.	IP20
27)	Encoder cable	MR-EKCBL□M-H Cable length: 20・30・40・50m		IP20 Long flex life
28)	Encoder connector set	MR-ECNM	 For HF-MP・HF-KP series Refer to section 12.1.2 (2) for details.	IP20

No.	Product	Model	Description	Application
29)	Encoder cable	MR-J3ENSCBL☐M-L Cable length: 2 · 5 · 10 · 20 · 30m	 For HF-SP · HC-UP · HC-LP · HC-RP · HA-LP series · HF-JP53(4) to 503(4) Refer to section 12.1.2 (5) for details.	IP67 Standard flex life
30)	Encoder cable	MR-J3ENSCBL☐M-H Cable length: 2 · 5 · 10 · 20 · 30 · 40 · 50m		IP67 Long flex life
31)	Encoder connector set	MR-J3SCNS	  For HF-SP · HC-UP · HC-LP · HC-RP · HA-LP series · HF-JP53(4) to 503(4) Refer to section 12.1.2 (4) for details.	IP67
32)	Brake connector set	MR-BKCNS1	Straight plug: CM10-SP2S-L(D6) Socket contact: CM10-#22SC(S2)(D8)-100 (DDK)  For HF-SP series · HF-JP53(4) to 503(4)	IP67
33)	Power supply connector set	MR-PWCNS4	Plug: CE05-6A18-10SD-D-BSS Cable clamp: CE3057-10A-1-D (DDK) Example of applicable cable Applicable wire size: 2 to 3.5mm^2 (AWG14 to AWG12) Cable finish ϕD: ϕ10.5 to 14.1mm  For HF-SP51 · 81 For HF-SP52 to 152 For HF-JP53 to 203 For HF-JP534 to 5034	IP67
34)	Power supply connector set	MR-PWCNS5	Plug: CE05-6A22-22D-D-BSS Cable clamp: CE3057-12A-1-D (DDK) Example of applicable cable Applicable wire size: 5.5 to 8mm^2 (AWG10 to AWG8) Cable finish ϕD: ϕ12.5 to 16mm  For HF-SP121 to 301 For HF-SP202 to 502 For HF-JP353 to 503	IP67
35)	Power supply connector set	MR-PWCNS3	Plug: CE05-6A32-17SD-D-BSS Cable clamp: CE3057-20A-1-D (DDK) Example of applicable cable Applicable wire size: 14 to 22mm^2 (AWG6 to AWG4) Cable finish ϕD: ϕ22 to 23.8mm  For HF-SP421 For HF-SP702 For HA-LP702 For HF-JP11K1M(4) · 15K1M(4)	IP67 Be sure to use this when corresponding to IEC/EN Standard.
36)	Cable for connecting battery	MR-J3BTCBL03M	 Refer to section 12.1.2 (7) for details.	For connection of battery
37)	Diagnosis cable	MR-J3ACHECK	 Necessary for amplifier diagnosis function of MR Configurator. Refer to section 12.8 (2) (c) for details.	For diagnosis of servo amplifier

No.	Product	Model	Description	Application
38)	Brake connector set	MR-BKCN	Plug: D/MS3106A10SL-4S(D190) (DDK) For cable connector: YSO10-5-8(Daiwa Dengyo) Example of applicable cable Applicable wire size: 0.3 to 25mm^2 (AWG22 to AWG16) Cable finish: ϕ5 to 8.3mm  For HA-LP For HC-UP For HC-LP For HF-JP11K1M(4) ・ 15K1M(4)	IEC/EN standard compliant IP65
39)	Power supply connector set	MR-PWCNS1	Plug: CE05-6A22-23SD-D-BSS Cable clamp: CE3057-12A-2-D (DDK) Example of applicable cable Applicable wire size: 2 to 3.5mm^2 (AWG14 to AWG12) Cable finish: ϕ9.5 to 13mm  For HC-UP For HC-LP For HC-RP	Be sure to use this when corresponding to IEC/EN standard IP65
40)	Power supply connector set	MR-PWCNS2	Plug: CE05-6A24-10SD-D-BSS Cable clamp: CE3057-16A-2-D (DDK) Example of applicable cable Applicable wire size: 5.5 to 8mm^2 (AWG10 to AWG8) Cable finish: ϕ13 to 15.5mm  For HA-LP For HC-UP For HC-LP For HC-RP	
41)	Encoder connector set	MR-J3SCNSA	  For HF-SP ・ HA-LP ・ HC-UP ・ HC-LP ・ HC-RP series ・ HF-JP53(4) to 503(4) Refer to section 12.1.2 (5) for details.	IP67
42)	Brake connector set	MR-BKCNS1A	Angle plug: CM10-AP2S-L(D6) Socket contact: CM10-# 22SC(S2)(D8)-100 (DDK)  For HF-SP series ・ HF-JP53(4) to 503(4)	IP67
43)	Encoder cable	MR-J3ENSCBL☐M-L-S06 Cable length: 2 ・ 5 ・ 10 ・ 20 ・ 30m	 For HF-SP ・ HA-LP ・ HC-UP ・ HC-LP ・ HC-RP series ・ HF-JP53(4) to 503(4) Refer to section 12.1.2 (5) for details.	IP67 Standard flex life (Note)
44)	Encoder cable	MR-J3ENSCBL☐M-H-S06 Cable length: 2 ・ 5 ・ 10 ・ 20 ・ 30 ・ 40 ・ 50m		IP67 Long flex life (Note)
45)	Encoder connector set	MR-J3SCNS-S06	  For HF-SP ・ HA-LP ・ HC-UP ・ HC-LP ・ HC-RP series ・ HF-JP53(4) to 503(4) Refer to section 12.1.2 (5) for details.	IP67 (Note)
46)	Encoder connector set	MR-J3SCNSA-S06	  For HF-SP ・ HA-LP ・ HC-UP ・ HC-LP ・ HC-RP series ・ HF-JP53(4) to 503(4) Refer to section 12.1.2 (5) for details.	IP67 (Note)

No.	Product	Model	Description	Application
47)	Brake connector set	MR-BKCNS1-S06	Straight plug: CM10-SP2S-VP-L Socket contact: CM10-#22SC (S2) (D8)-100 (DDK)  For HF-SP series ・ HF-JP53(4) to 503(4)	IP67 (Note)
48)	Brake connector set	MR-BKCNS1A-S06	Angle plug: CM10-AP2S-VP-L Socket contact: CM10-#22SC (S2) (D8)-100 (DDK)  For HF-SP series ・ HF-JP53(4) to 503(4)	IP67 (Note)
49)	Encoder cable for IP67	MR-ENECBL☐M-H Refer to section 12.1.2 (6).	Receptacle: 36210-0100PL Shell kit: 36310-3200-008 (3M) or Connector set: 54599-1019 (Molex) Plug: D/MS3106A20-29S(D190) Cable clamp: CE3057-12A-3-D Back shell: CE02-20BS-S-D (DDK) 	Long flex life IP67 It is not a resistance to oil.
50)	Encoder connector set	MR-ENECNS	Receptacle: 36210-0100PL Shell kit: 36310-3200-008 (3M) or Connector set: 54599-1019 (Molex) Plug: D/MS3106A20-29S(D190) Cable clamp: CE3057-12A-3-D Back shell: CE02-20BS-S-D (DDK)  	IP67
51)	Encoder cable	MR-J3JSCBL03M-A1-L Cable length: 0.3m	 Refer to section 12.1.2 (4) for details.	IP65 Load side lead
52)	Encoder cable	MR-J3JSCBL03M-A2-L Cable length: 0.3m	 Refer to section 12.1.2 (4) for details.	IP65 Opposite-to-load side lead

Note. Use this option when the connector is expected to receive large vibration and shock.

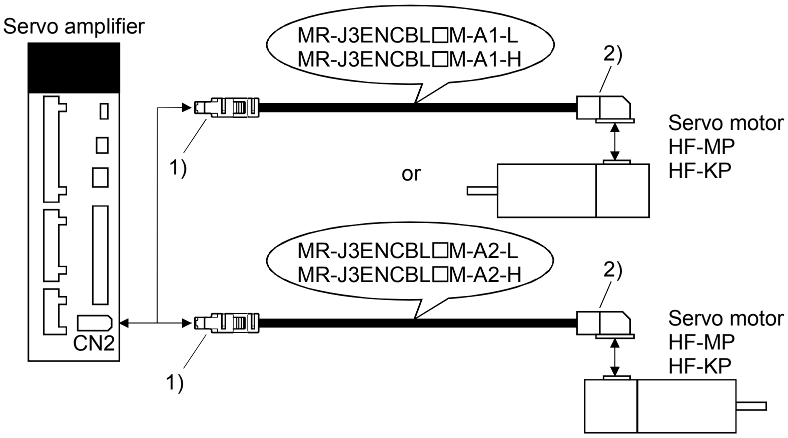
12.1.2 Encoder cable/connector sets

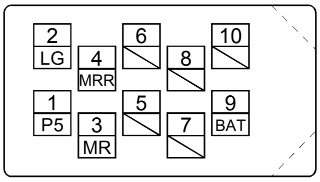
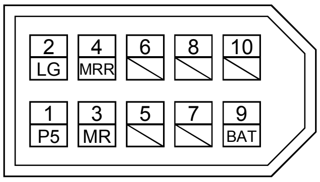
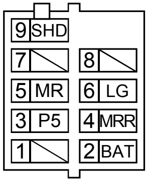
(1) MR-J3ENCBL□M-A1-L/H・MR-J3ENCBL□M-A2-L/H

These cables are encoder cables for the HF-MP・HF-KP series servo motors. The numerals in the Cable Length field of the table are the symbols entered in the □ part of the cable model. The cables of the lengths with the symbols are available.

Cable model	Cable length							IP rating	Flex life	Application
	2m	5m	10m	20m	30m	40m	50m			
MR-J3ENCBL□M-A1-L	2	5	10					IP65	Standard	For HF-MP・HF-KP servo motor Load side lead
MR-J3ENCBL□M-A1-H	2	5	10					IP65	Long flex life	
MR-J3ENCBL□M-A2-L	2	5	10					IP65	Standard	For HF-MP・HF-KP servo motor Opposite-to-load side lead
MR-J3ENCBL□M-A2-H	2	5	10					IP65	Long flex life	

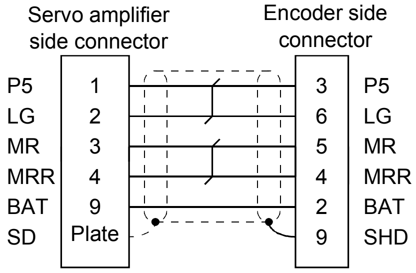
(a) Connection of servo amplifier and servo motor



Cable model	1) For CN2 connector	2) For encoder connector
MR-J3ENCBL□M-A1-L	Receptacle: 36210-0100PL Shell kit: 36310-3200-008 (3M) (Note) Signal layout  View seen from wiring side. or Connector set: 54599-1019 (Molex) (Note) Signal layout  View seen from wiring side. Note. Keep open the pins shown with ⧅. Especially, pin 10 is provided for manufacturer adjustment. If it is connected with any other pin, the servo amplifier cannot operate normally.	Connector: 1674320-1 Crimping tool for ground clip: 1596970-1 Crimping tool for receptacle contact: 1596847-1 (Tyco Electronics) (Note) Signal layout  View seen from wiring side. Note. Keep open the pin shown with an ⧅.
MR-J3ENCBL□M-A1-H		
MR-J3ENCBL□M-A2-L		
MR-J3ENCBL□M-A2-H		

(b) Cable internal wiring diagram

MR-J3ENCBL2M-L/-H
MR-J3ENCBL5M-L/-H
MR-J3ENCBL10M-L/-H



(2) MR-EKCBL□M-L/H

POINT

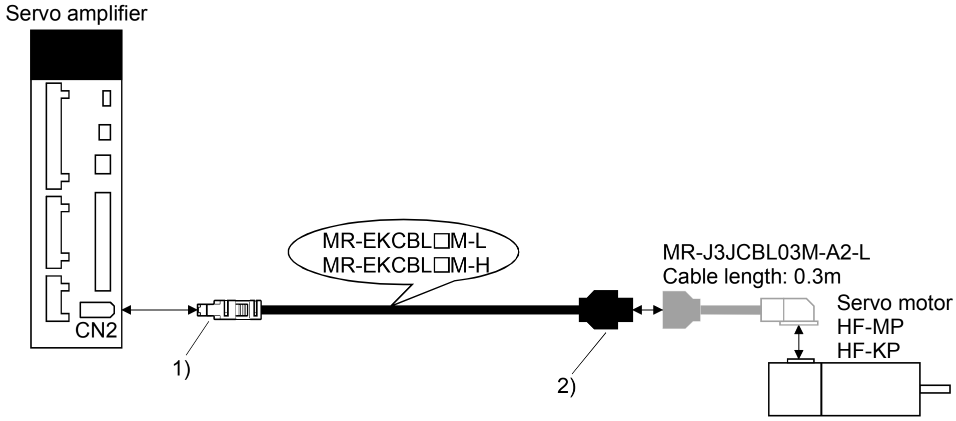
- The following encoder cables are of four-wire type. When using any of these encoder cables, set parameter No.PC22 to "1□□□" to select the four-wire type.
  MR-EKCBL30M-L
  MR-EKCBL30M-H
  MR-EKCBL40M-H
  MR-EKCBL50M-H

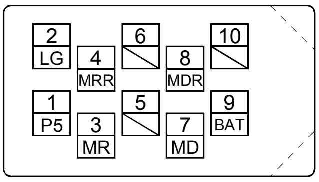
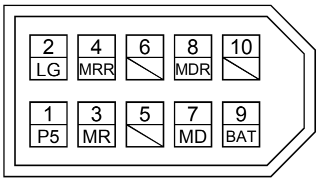
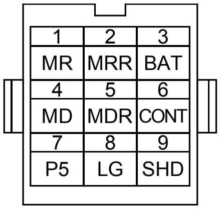
The servo amplifier and servo motor cannot be connected with these cables only. The servo motor side encoder cable (MR-J3JCBL03M-A1-L or MR-J3JCBL03M-A2-L) is required.
The numerals in the Cable Length field of the table are the symbols entered in the □ part of the cable model. The cables of the lengths with the symbols are available.

Cable model	Cable length							IP rating	Flex life	Application
	2m	5m	10m	20m	30m	40m	50m			
MR-EKCBL□M-L				20	(Note) 30			IP20	Standard	For HF-MP・HF-KP servo motor Use in combination with MR-J3JCBL03M-A1-L or MR-J3JCBL03M-A2-L.
MR-EKCBL□M-H				20	(Note) 30	(Note) 40	(Note) 50	IP20	Long flex life	

Note. Four-wire type cable.

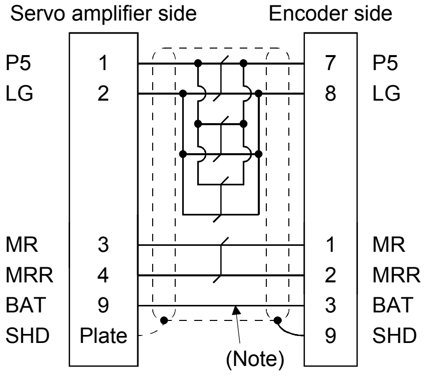
(a) Connection of servo amplifier and servo motor



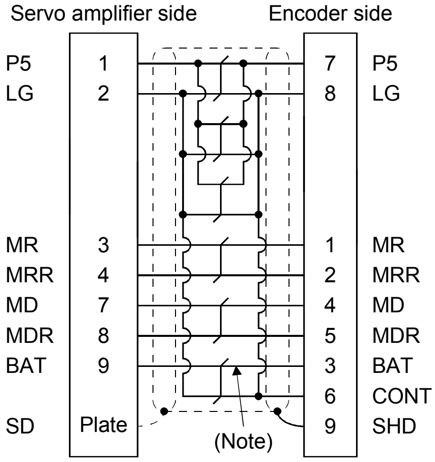
Cable model	1) CN2 connector	2) Junction connector
MR-EKCBL□M-L	Receptacle: 36210-0100PL Shell kit: 36310-3200-008 (3M) Connector set: 54599-1019 (Molex) (Note) Signal layout  View seen from wiring side. or (Note) Signal layout  View seen from wiring side. Note. Keep open the pins shown with ⧅. Especially, pin 10 is provided for manufacturer adjustment. If it is connected with any other pin, the servo amplifier cannot operate normally.	Housing: 1-172161-9 Connector pin: 170359-1 (Tyco Electronics or equivalent) Cable clamp: MTI-0002 (Toa Electric Industries) Signal layout  View seen from wiring side.
MR-EKCBL□M-H		

(b) Internal wiring diagram

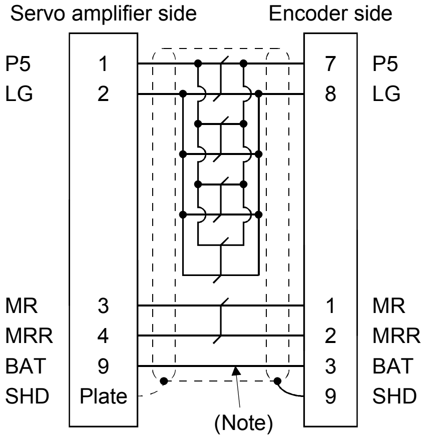
MR-EKCBL20M-L



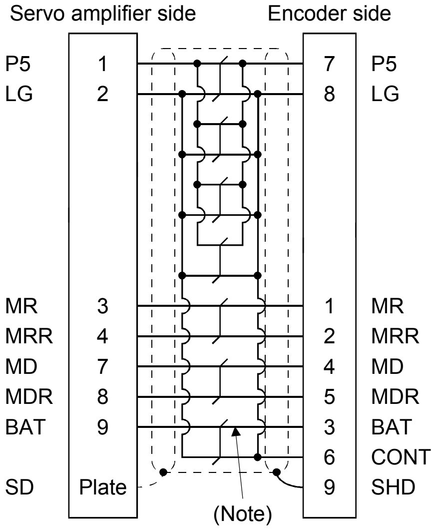
MR-EKCBL30M-L



MR-EKCBL20M-H



MR-EKCBL30M-H
MR-EKCBL40M-H
MR-EKCBL50M-H



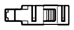
Note. Always make connection for use in an absolute position detection system. Wiring is not necessary for use in an incremental system.

When fabricating the cable, use the wiring diagram corresponding to the length indicated below.

Cable flex life	Applicable wiring diagram	
	Less than 30m	30 to 50m
Standard	MR-EKCBL20M-L	
Long flex life	MR-EKCBL20M-H	MR-EKCBL30M-H MR-EKCBL40M-H MR-EKCBL50M-H

(c) When fabricating the encoder cable

When fabricating the cable, prepare the following parts and fabricate it according to the wiring diagram in (b). Refer to section 12.11 for the specifications of the used cable.

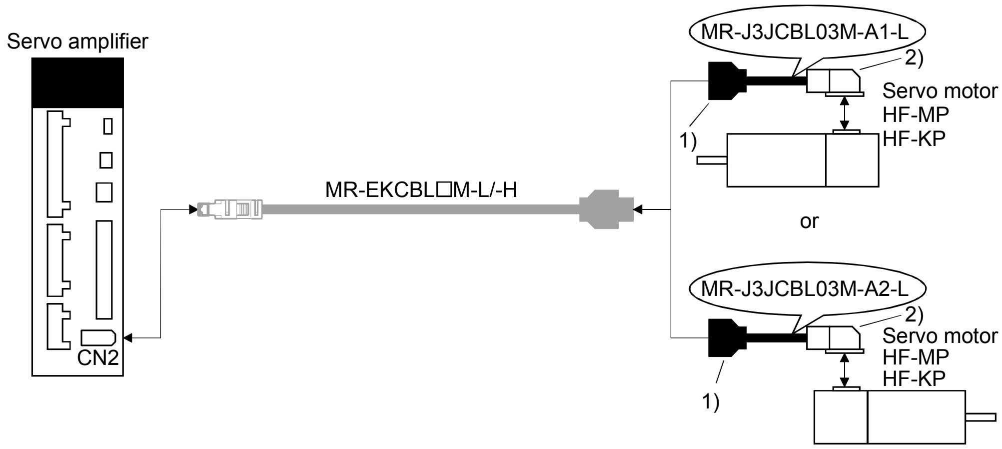
Parts	Description
Connector set	MR-ECNM  Servo amplifier side connector Receptacle: 36210-0100PL Shell kit: 36310-3200-008 (3M) or Connector set: 54599-1019 (Molex)  Encoder side connector Housing: 1-172161-9 Connector pin: 170359-1 (Tyco Electronics or equivalent) Cable clamp: MTI-0002 (Toa Electric Industries)

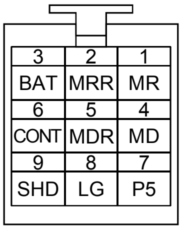
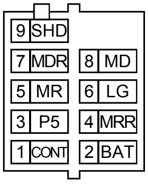
(3) MR-J3JCBL03M-A1-L・MR-J3JCBL03M-A2-L

The servo amplifier and servo motor cannot be connected with these cables only. The servo motor side encoder cable (MR-EKCBL□M-L/H) is required.

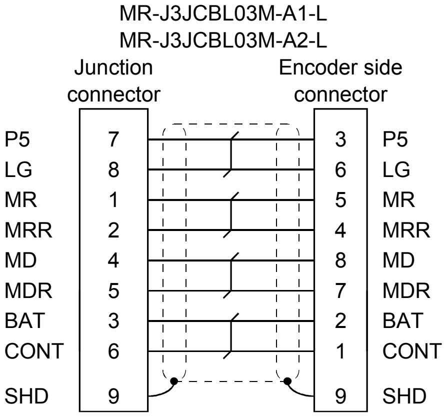
Cable model	Cable length	IP rating	Flex life	Application
MR-J3JCBL03M-A1-L	0.3m	IP20	Standard	For HF-MP・HF-KP servo motor Load side lead Use in combination with MR-EKCBL □M-L/H.
MR-J3JCBL03M-A2-L				For HF-MP・HF-KP servo motor Opposite-to-load side lead Use in combination with MR-EKCBL □M-L/H.

(a) Connection of servo amplifier and servo motor



Cable model	1) Junction connector	2) For encoder connector
MR-J3JCBL03M-A1-L	Housing: 1-172169-9 Contact: 1473226-1 Cable clamp: 316454-1 Crimping tool: 91529-1 (Tyco Electronics) Signal layout  View seen from wiring side.	Connector: 1674320-1 Crimping tool for ground clip: 1596970-1 Crimping tool for receptacle contact: 1596847-1 (Tyco Electronics) Signal layout  View seen from wiring
MR-J3JCBL03M-A2-L		

(b) Internal wiring diagram

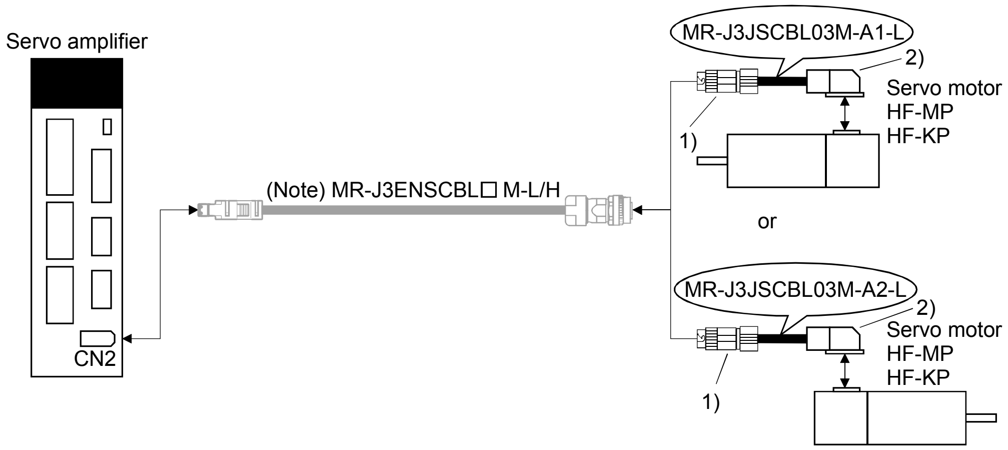


(4) MR-J3JSCBL03M-A1-L・MR-J3JSCBL03M-A2-L

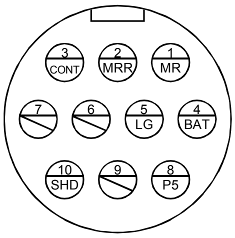
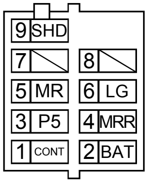
The servo amplifier and servo motor cannot be connected with these cables only.
The servo motor side encoder cable (MR-J3ENSCBL□M-L/H) is required.

Cable model	Cable length	IP rating	Flex life	Application
MR-J3JSCBL03M-A1-L	0.3m	IP65	Standard	For HF-KP・HF-MP servo motor Load side lead Use in combination with MR-J3ENSCBL□M-L/H.
MR-J3JSCBL03M-A2-L				For HF-KP・HF-MP servo motor Opposite-to-load side lead Use in combination with MR-J3ENSCBL□M-L/H.

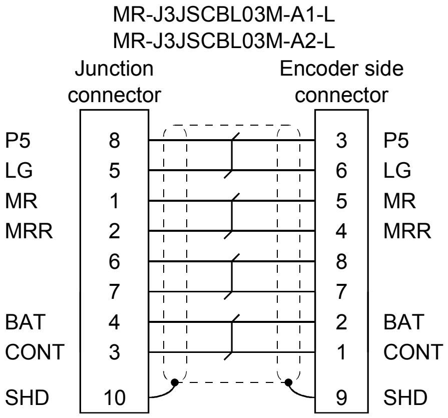
(a) Connection of servo amplifier and servo motor



Note. For details of this cable, refer to (5) in this section.
MR-J3ENSCBL□ M-L-S06 and MR-J3ENSCBL□M-H-S06 cannot be used.

Cable model	1) Junction connector	2) For encoder connector
MR-J3JSCBL03M-A1-L MR-J3JSCBL03M-A2-L	Receptacle: CM10-CR10P-M (DDK) Applicable wire size: AWG12 or less (Note) Signal layout  View seen from wiring side. Note. Keep open the pin shown with an ⊘.	Connector: 1674320-1 Crimping tool for ground clip: 1596970-1 Crimping tool for receptacle contact: 1596847-1 (Tyco Electronics) (Note) Signal layout  View seen from wiring side. Note. Keep open the pin shown with an ⧄.

(b) Cable internal wiring diagram



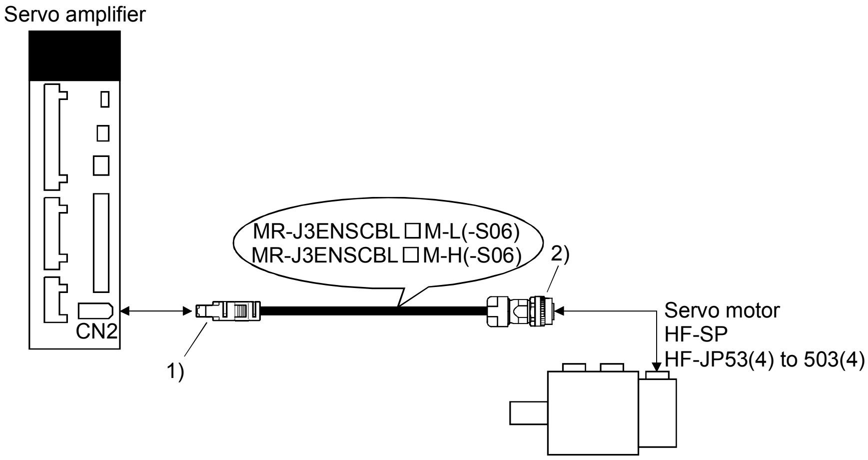
(5) MR-J3ENSCBL□M-L(-S06) ・ MR-J3ENSCBL□M-H(-S06)

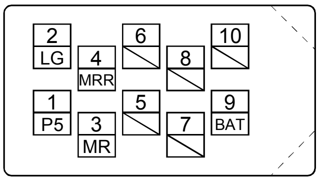
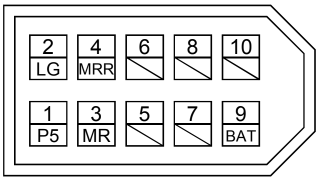
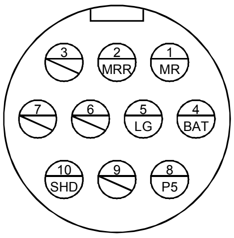
These cables are encoder cables for HF-SP ・ HA-LP ・ HC-RP ・ HC-UP ・ HC-LP series ・ HF-JP53(4) to 503(4) servo motors. The number in the cable length column of the table indicates the symbol filling the square □ in the cable model. Cable lengths corresponding to the specified symbols are prepared.

Cable model	Cable length							IP rating	Flex life	Application
	2m	5m	10m	20m	30m	40m	50m			
MR-J3ENSCBL□M-L	2	5	10	20	30			IP67	Standard	For HF-SP ・ HA-LP ・ HC-RP ・ HC-UP ・ HC-LP series ・ HF-JP53(4) to 503(4) servo motor
MR- J3ENSCBL□M-H	2	5	10	20	30	40	50	IP67	Long flex life	
MR-J3ENSCBL□M-L-S06	2	5	10	20	30			IP67	Standard	For HF-SP ・ HA-LP ・ HC-RP ・ HC-UP ・ HC-LP series ・ HF-JP53(4) to 503(4) servo motor (Note)
MR-J3ENSCBL□M-H-S06	2	5	10	20	30	40	50	IP67	Long flex life	

Note. Use this option when the connector is expected to receive large vibration and shock. The connector at the servo motor side can be removed up to 5 times. To install or remove the connector, use the dedicated tool 357J-52780T (DDK) or a spanner with jaw size of 21mm.

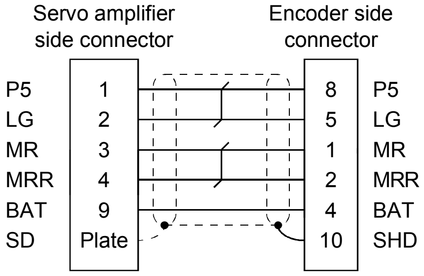
(a) Connection of servo amplifier and servo motor



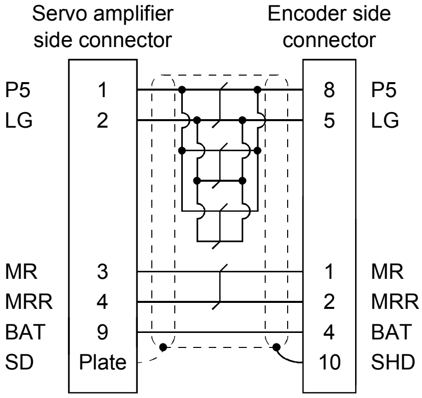
Cable model	1) For CN2 connector	2) For encoder connector
MR-J3ENSCBL□M-L (-S06)	Receptacle: 36210-0100PL Shell kit: 36310-3200-008 (3M) Connector set: 54599-1019 (Molex) (Note) Signal layout  View seen from wiring side. or (Note) Signal layout  View seen from wiring side. Note. Keep open the pins shown with ⧅. Especially, pin 10 is provided for manufacturer adjustment. If it is connected with any other pin, the servo amplifier cannot operate normally.	In case of 10m or shorter cables Straight plug: CM10-SP10S-M(D6) or CM10-SP10S-VP-M Socket contact: CM10-#22SC(C1)(D8)-100 Crimping tool: 357J-50446 (DDK) Applicable cable AWG20 to 22 In case of 20m or longer cables Straight plug: CM10-SP10S-M(D6) or CM10-SP10S-VP-M Socket contact: CM10-#22SC(C2)(D8)-100 Crimping tool: 357J-50447 (DDK) Applicable cable AWG23 to 28 (Note) Signal layout  View seen from wiring side Note. Keep open the pin shown with an ⦸.
MR-J3ENSCBL□M-H (-S06)		

(b) Internal wiring diagram

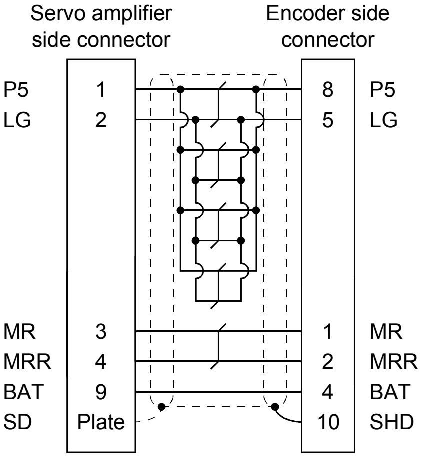
MR-J3ENSCBL2M-L(-S06)/H(-S06)
MR-J3ENSCBL5M-L(-S06)/H(-S06)
MR-J3ENSCBL10M-L(-S06)/H(-S06)



MR-J3ENSCBL20M-L(-S06)
MR-J3ENSCBL30M-L(-S06)

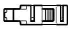
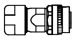
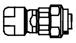
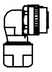
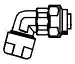


MR-J3ENSCBL20M-H(-S06)
MR-J3ENSCBL30M-H(-S06)
MR-J3ENSCBL40M-H(-S06)
MR-J3ENSCBL50M-H(-S06)



(c) When fabricating the encoder cable

When fabricating the cable, prepare the following parts and fabricate it according to the wiring diagram in (b). Refer to section 12.11 for the specifications of the used cable.

Parts (Connector set)	Description	
MR-J3SCNS	 Servo amplifier side connector Receptacle: 36210-0100PL Shell kit: 36310-3200-008 (3M) or Connector set: 54599-1019 (Molex)	 Encoder side connector Straight plug: CM10-SP10S-M(D6) Socket contact: CM10-#22SC(S1)(D8)-100 Applicable wire size: AWG20 or less Recommended tightening jig: 357J-51456T (DDK)
MR-J3SCNS-S06 (Note)		 Encoder side connector Straight plug: CM10-SP10S-VP-M Socket contact: CM10-#22SC(S1)(D8)-100 Applicable wire size: AWG20 or less (DDK)
MR-J3SCNSA		 Encoder side connector Angle plug: CM10-AP10S-M(D6) Socket contact: CM10-#22SC(S1)(D8)-100 Applicable wire size: AWG20 or less (DDK)
MR-J3SCNSA-S06 (Note)		 Encoder side connector Angle plug: CM10-AP10S-VP-M Socket contact: CM10-#22SC(S1)(D8)-100 Applicable wire size: AWG20 or less (DDK)

Note. Use this option when the connector is expected to receive large vibration and shock. The connector at the servo motor side can be removed up to 5 times. To install or remove the connector, use the dedicated tool 357J-52780T (DDK) or a spanner with jaw size of 21mm.

(6) MR-ENECBL☐M-H

POINT

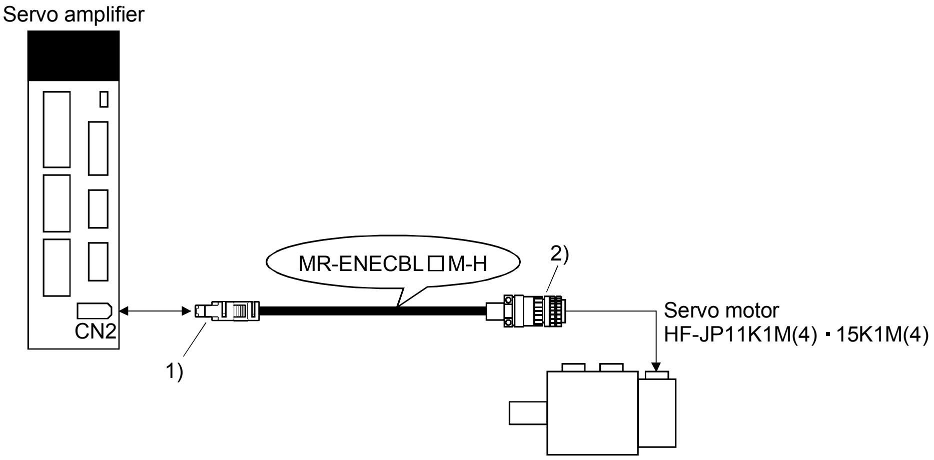
- The following encoder cables are of four-wire type. When using any of these encoder cables, set parameter No. PC22 to "1☐☐☐" to select the four-wire type.
  MR-ENECBL30M-H
  MR-ENECBL40M-H
  MR-ENECBL50M-H

These cables are encoder cables for HF-JP11K1M(4) · 15K1M(4) servo motors.
The number in the cable length column of the table indicates the symbol filling the square ☐ in the cable model. Cable lengths corresponding to the specified symbols are prepared.

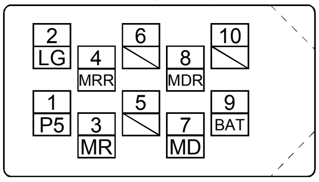
Cable model	Cable length							IP rating	Flex life	Application
	2m	5m	10m	20m	30m	40m	50m			
MR-ENECBL☐M-H	2	5	10	20	(Note) 30	(Note) 40	(Note) 50	IP67	Long flex life	For HF-JP11K1M(4) · 15K1M(4) servo motor

Note. Four-wire type cable.

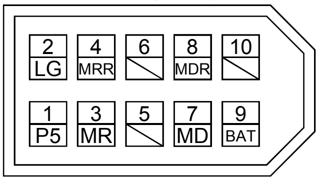
(a) Connection of servo amplifier and servo motor

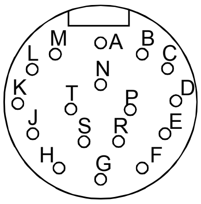


<table>
<tr><th>Cable model</th><th colspan="2">1) For CN2 connector</th><th>2) For encoder connector</th></tr>
<tr>
<td>MR-ENECBL□M-H</td>
<td>Receptacle: 36210-0100PL
Shell kit: 36310-3200-008
(3M)

(Note) Signal layout

View seen from wiring side</td>
<td>Connector set: 54599-1019
(Molex)

or

(Note) Signal layout

View seen from wiring side</td>
<td>Plug: D/MS3106A20-29S(D190)
Cable clamp: CE3057-12A-3-D
Back shell: CE02-20BS-S-D

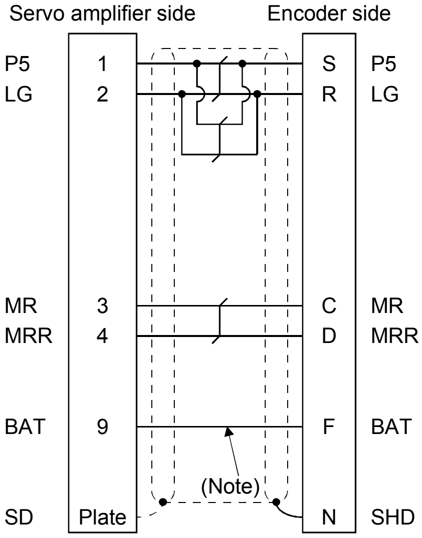
(Note) Signal layout

View seen from wiring side
<table>
<tr><th>Pin</th><th>Signal</th></tr>
<tr><td>A</td><td>MD</td></tr>
<tr><td>B</td><td>MDR</td></tr>
<tr><td>C</td><td>MR</td></tr>
<tr><td>D</td><td>MRR</td></tr>
<tr><td>E</td><td>╲</td></tr>
<tr><td>F</td><td>BAT</td></tr>
<tr><td>G</td><td>╲</td></tr>
<tr><td>H</td><td>╲</td></tr>
<tr><td>J</td><td>╲</td></tr>
</table>
<table>
<tr><th>Pin</th><th>Signal</th></tr>
<tr><td>K</td><td>╲</td></tr>
<tr><td>L</td><td>╲</td></tr>
<tr><td>M</td><td>CONT</td></tr>
<tr><td>N</td><td>SHD</td></tr>
<tr><td>P</td><td>╲</td></tr>
<tr><td>R</td><td>LG</td></tr>
<tr><td>S</td><td>P5</td></tr>
<tr><td>T</td><td>╲</td></tr>
</table>
Note. Keep open the pin shown with an ╲.</td>
</tr>
<tr><td></td><td colspan="2">Note. Keep open the pins shown with ╲. Especially, pin 10 is provided for manufacturer adjustment. If it is connected with any other pin, the servo amplifier cannot operate normally.</td><td></td></tr>
</table>

(b) Cable internal wiring diagram

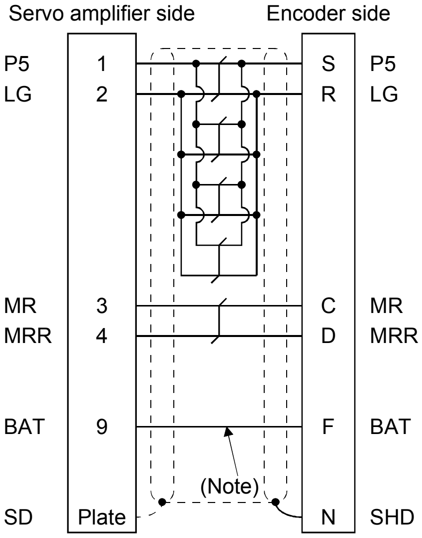
1) For less than 30m

To fabricate, use the connector set MR-ECNS (IP20 compatible) or MR-ENECNS (IP67 compatible). Use the following wiring diagram to fabricate a cable shorter than 30m.

MR-ENECBL2M-H
MR-ENECBL5M-H
MR-ENECBL10M-H



MR-ENECBL20M-H

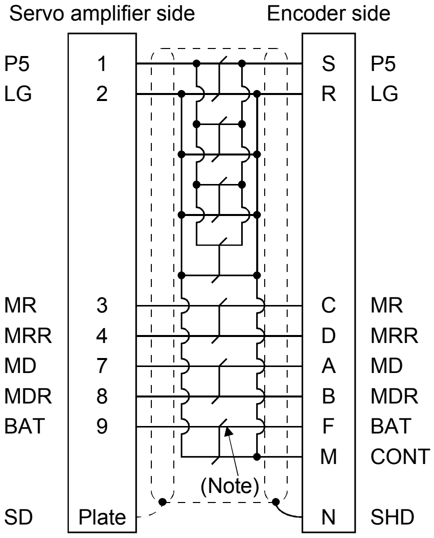


Note. Always make connection for use in an absolute position detection system.
Wiring is not necessary for use in an incremental system.

2) For 30m or more

To fabricate, use the connector set MR-ECNS (IP20 compatible) or MR-ENECNS (IP67 compatible). Use the following wiring diagram to fabricate a cable up to 50m.

MR-ENECBL30M-H
MR-ENECBL40M-H
MR-ENECBL50M-H



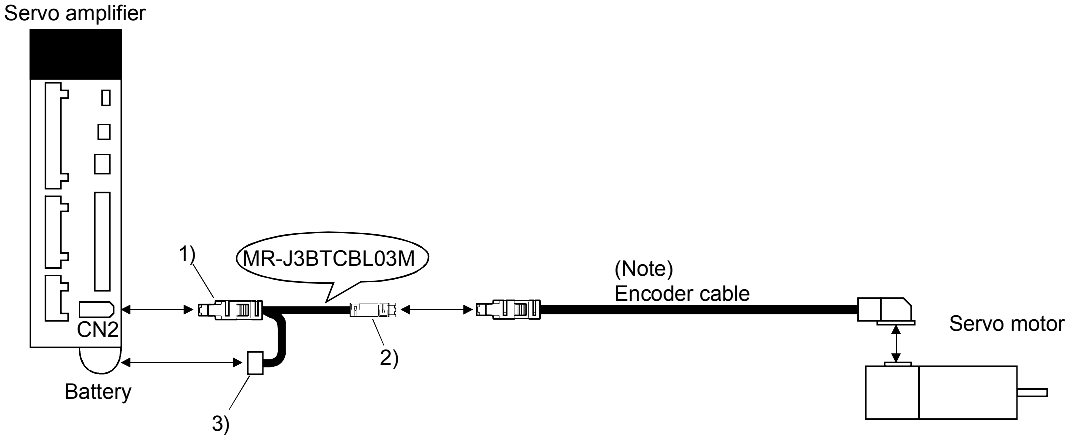
Note. Always make connection for use in an absolute position detection system.
Wiring is not necessary for use in an incremental system.

(7) MR-J3BTCBL03M

This cable is a battery connection cable. Use this cable to retain the current position even if the detector cable is disconnected from the servo amplifier.

Cable model	Cable length	Application
MR-J3BTCBL03M	0.3m	For HF-MP · HF-KP · HF-SP · HA-LP · HC-RP · HC-UP · HC-LP · HF-JP series servo motor

(a) Connection of servo amplifier and servo motor



Note. For the detector cable, refer to (1), (2), (3) and (4) in this section.

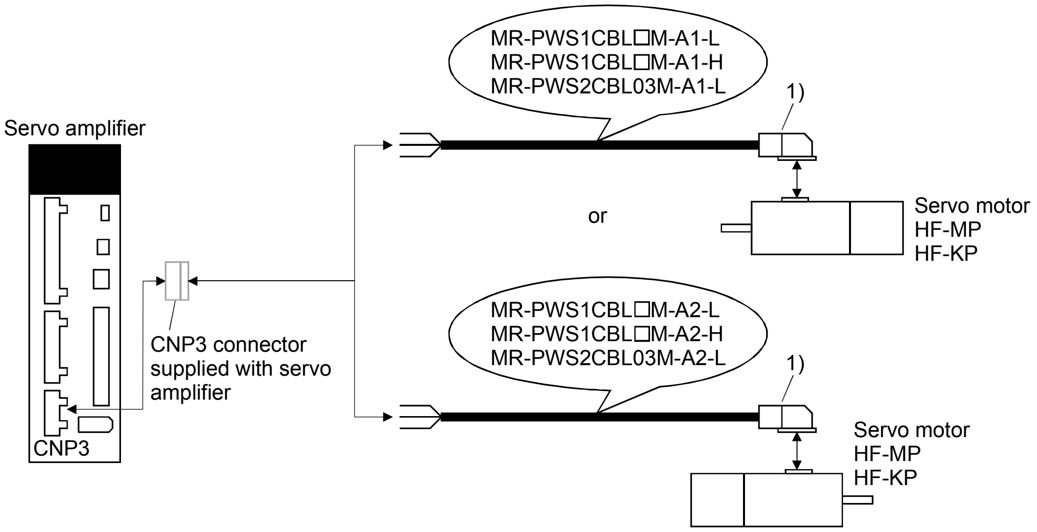
Cable model	1) For CN2 connector	2) Junction connector	3) For battery connector
MR-J3BTCBL03M	Receptacle: 36210-0100PL Shell kit: 36310-3200-008 (3M) or Connector set: 54599-1019 (Molex)	Plug: 36110-3000FD Shell kit: 36310-F200-008 (3M)	Connector: DF3-2EP-2C Contact: DF3-EP2428PCA (Hirose Denki)

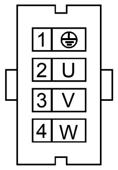
12.1.3 Motor power supply cables

These are motor power supply cables for the HF-MP・HF-KP series servo motors. The numerals in the Cable Length field of the table are the symbols entered in the ☐ part of the cable model. The cables of the lengths with the symbols are available.
Refer to section 3.10 when wiring.

Cable model	Cable length				IP rating	Flex life	Application
	0.3m	2m	5m	10m			
MR-PWS1CBL☐M-A1-L		2	5	10	IP65	Standard	For HF-MP・HF-KP servo motor Load side lead
MR-PWS1CBL☐M-A2-L		2	5	10	IP65	Standard	For HF-MP・HF-KP servo motor Opposite-to-load side lead
MR-PWS1CBL☐M-A1-H		2	5	10	IP65	Long flex life	For HF-MP・HF-KP servo motor Load side lead
MR-PWS1CBL☐M-A2-H		2	5	10	IP65	Long flex life	For HF-MP・HF-KP servo motor Opposite-to-load side lead
MR-PWS2CBL☐M-A1-L	03				IP55	Standard	For HF-MP・HF-KP servo motor Load side lead
MR-PWS2CBL☐M-A2-L	03				IP55	Standard	For HF-MP・HF-KP servo motor Opposite-to-load side lead

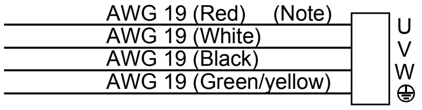
(1) Connection of servo amplifier and servo motor



Cable model	1) For motor power supply connector	
MR-PWS1CBL☐M-A1-L	Connector: JN4FT04SJ1-R Hood, socket insulator Bushing, ground nut Contact: ST-TMH-S-C1B-100-(A534G) Crimping tool: CT160-3-TMH5B (Japan Aviation Electronics Industry)	Signal layout  View seen from wiring side.
MR-PWS1CBL☐M-A2-L		
MR-PWS1CBL☐M-A1-H		
MR-PWS1CBL☐M-A2-H		
MR-PWS2CBL03M-A1-L	Connector: JN4FT04SJ2-R Hood, socket insulator Bushing, ground nut Contact: ST-TMH-S-C1B-100-(A534G) Crimping tool: CT160-3-TMH5B (Japan Aviation Electronics Industry)	
MR-PWS2CBL03M-A2-L		

(2) Internal wiring diagram

MR-PWS1CBL☐M-A1-H MR-PWS1CBL☐M-A2-H
MR-PWS2CBL03M-A1-L MR-PWS2CBL03M-A2-L



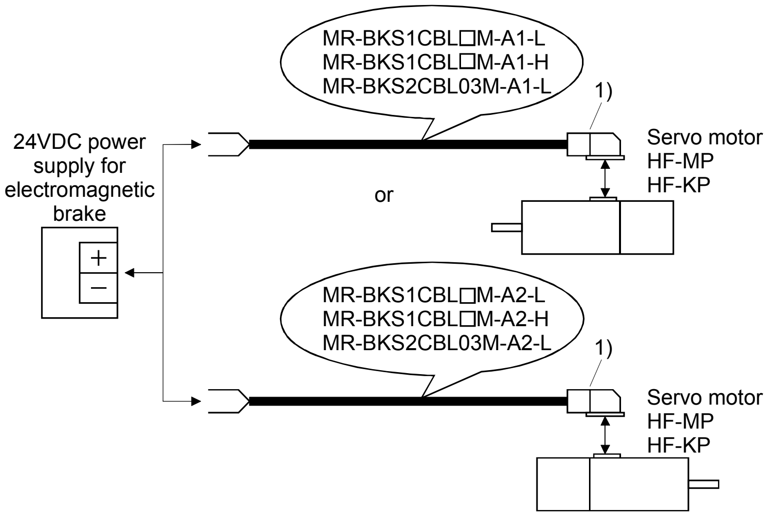
Note. These are not shielded cables.

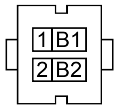
12.1.4 Motor brake cables

These are motor brake cables for the HF-MP・HF-KP series servo motors. The numerals in the Cable Length field of the table are the symbols entered in the □ part of the cable model. The cables of the lengths with the symbols are available.
Refer to section 3.11 when wiring.

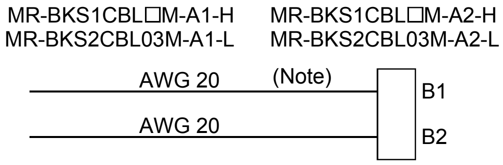
Cable model	Cable length				IP rating	Flex life	Application
	0.3m	2m	5m	10m			
MR-BKS1CBL□M-A1-L		2	5	10	IP65	Standard	For HF-MP・HF-KP servo motor Load side lead
MR-BKS1CBL□M-A2-L		2	5	10	IP65	Standard	For HF-MP・HF-KP servo motor Opposite-to-load side lead
MR-BKS1CBL□M-A1-H		2	5	10	IP65	Long flex life	For HF-MP・HF-KP servo motor Load side lead
MR-BKS1CBL□M-A2-H		2	5	10	IP65	Long flex life	For HF-MP・HF-KP servo motor Opposite-to-load side lead
MR-BKS2CBL□M-A1-L	03				IP55	Standard	For HF-MP・HF-KP servo motor Load side lead
MR-BKS2CBL□M-A2-L	03				IP55	Standard	For HF-MP・HF-KP servo motor Opposite-to-load side lead

(1) Connection of servo amplifier and servo motor



Cable model	1) For motor brake connector	
MR-BKS1CBL□M-A1-L	Connector: JN4FT02SJ1-R Hood, socket insulator Bushing, ground nut Contact: ST-TMH-S-C1B-100-(A534G) Crimping tool: CT160-3-TMH5B (Japan Aviation Electronics Industry)	Signal layout  View seen from wiring side.
MR-BKS1CBL□M-A2-L		
MR-BKS1CBL□M-A1-H		
MR-BKS1CBL□M-A2-H		
MR-BKS2CBL03M-A1-L	Connector: JN4FT02SJ2-R Hood, socket insulator Bushing, ground nut Contact: ST-TMH-S-C1B-100-(A534G) Crimping tool: CT160-3-TMH5B (Japan Aviation Electronics Industry)	
MR-BKS2CBL03M-A2-L		

(2) Internal wiring diagram



Note. These are not shielded cables.

12.2 Regenerative options

CAUTION	· The specified combinations of regenerative options and servo amplifiers may only be used. Otherwise, a fire may occur.

(1) Combination and regenerative power

The power values in the table are resistor-generated powers and not rated powers.

Servo amplifier	Regenerative power [W]							
	Built-in regenerative resistor	MR-RB032 [40Ω]	MR-RB12 [40Ω]	MR-RB30 [13Ω]	MR-RB31 [6.7Ω]	MR-RB32 [40Ω]	(Note 1) MR-RB50 [13Ω]	(Note 1) MR-MB51 [6.7Ω]
MR-J3-10A (1)		30						
MR-J3-20A (1)	10	30	100					
MR-J3-40A (1)	10	30	100					
MR-J3-60A	10	30	100					
MR-J3-70A	20	30	100			300		
MR-J3-100A	20	30	100			300		
MR-J3-200A	100			300			500	
MR-J3-350A	100			300			500	
MR-J3-500A	130				300			500
MR-J3-700A	170				300			500

Servo amplifier	Regenerative power [W]						
	Built-in regenerative resistor	MR-RB1H-4 [82Ω]	(Note 1) MR-RB3M-4 [120Ω]	(Note 1) MR-RB3G-4 [47Ω]	(Note 1) MR-RB5G-4 [47Ω]	(Note 1) MR-RB34-4 [26Ω]	(Note 1) MR-RB54-4 [26Ω]
MR-J3-60A4	15	100	300				
MR-J3-100A4	15	100	300				
MR-J3-200A4	100			300	500		
MR-J3-350A4	100			300	500		
MR-J3-500A4	130					300	500
MR-J3-700A4	170					300	500

Servo amplifier	(Note 2) Regenerative power [W]						
	External regenerative resistor (Accessory)	MR-RB5E [6Ω]	MR-RB9P [4.5Ω]	MR-RB9F [3Ω]	MR-RB6B-4 [20Ω]	MR-RB60-4 [12.5Ω]	MR-RB6K-4 [10Ω]
MR-J3-11KA	500 (800)	500 (800)					
MR-J3-15KA	850 (1300)		850 (1300)				
MR-J3-22KA	850 (1300)			850 (1300)			
MR-J3-11KA4	500 (800)				500 (800)		
MR-J3-15KA4	850 (1300)					850 (1300)	
MR-J3-22KA4	850 (1300)						850 (1300)

Servo amplifier	(Note 2) Regenerative power [W]				
	External regenerative resistor (Accessory)	MR-RB5R [3.2Ω]	MR-RB9F [3Ω]	MR-RB5K-4 [10Ω]	MR-RB6K-4 [10Ω]
MR-J3-11KA-LR	500 (800)	500 (800)			
MR-J3-11KA-LW		500 (800)			
MR-J3-15KA-LR	850 (1300)		850 (1300)		
MR-J3-15KA-LW			850 (1300)		
MR-J3-11KA4-LR	500 (800)			500 (800)	
MR-J3-11KA4-LW				500 (800)	
MR-J3-15KA4-LR	850 (1300)				850 (1300)
MR-J3-15KA4-LW					850 (1300)

Note 1. Always install a cooling fan.

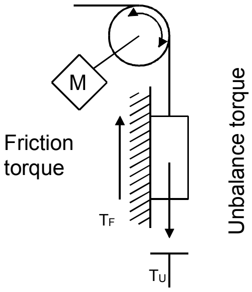
2. Values in parentheses assume the installation of a cooling fan.

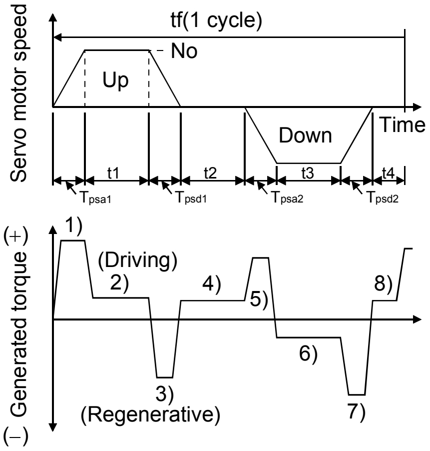
(2) Selection of the regenerative option

Use the following method when regeneration occurs continuously in vertical motion applications or when it is desired to make an in-depth selection of the regenerative option.

(a) Regenerative energy calculation

Use the following table to calculate the regenerative energy.





Formulas for calculating torque and energy in operation

Regenerative power	Torque applied to servo motor [N・m]	Energy [J]
1)	$T_1 = \frac{(J_L+J_M)\cdot N_0}{9.55\times10^4}\cdot\frac{1}{T_{psa1}} + T_U + T_F$	$E_1 = \frac{0.1047}{2}\cdot N_0\cdot T_1\cdot T_{psa1}$
2)	$T_2 = T_U + T_F$	$E_2 = 0.1047\cdot N_0\cdot T_2\cdot t_1$
3)	$T_3 = \frac{-(J_L+J_M)\cdot N_0}{9.55\times10^4}\cdot\frac{1}{T_{psd1}} + T_U + T_F$	$E_3 = \frac{0.1047}{2}\cdot N_0\cdot T_3\cdot T_{psd1}$
4), 8)	$T_4 = T_U$	$E_4 \geq 0$ (No regeneration)
5)	$T_5 = \frac{(J_L+J_M)\cdot N_0}{9.55\times10^4}\cdot\frac{1}{T_{psa2}} - T_U + T_F$	$E_5 = \frac{0.1047}{2}\cdot N_0\cdot T_5\cdot T_{psa2}$
6)	$T_6 = -T_U + T_F$	$E_6 = 0.1047\cdot N_0\cdot T_6\cdot t_3$
7)	$T_7 = \frac{-(J_L+J_M)\cdot N_0}{9.55\times10^4}\cdot\frac{1}{T_{psd2}} - T_U + T_F$	$E_7 = \frac{0.1047}{2}\cdot N_0\cdot T_7\cdot T_{psd2}$

From the calculation results in 1) to 8), find the absolute value (Es) of the sum total of negative energies.

(b) Losses of servo motor and servo amplifier in regenerative mode

The following table lists the efficiencies and other data of the servo motor and servo amplifier in the regenerative mode.

Servo amplifier	Inverse efficiency [%]	Capacitor charging [J]
MR-J3-10A	55	9
MR-J3-10A1	55	4
MR-J3-20A	70	9
MR-J3-20A1	70	4
MR-J3-40A	85	11
MR-J3-40A1	85	10
MR-J3-60A(4)	85	11
MR-J3-70A	80	18
MR-J3-100A	80	18
MR-J3-100A4	80	12

Servo amplifier	Inverse efficiency [%]	Capacitor charging [J]
MR-J3-200A	85	40
MR-J3-200A4	85	25
MR-J3-350A	85	40
MR-J3-350A4	85	36
MR-J3-500A(4)	90	45
MR-J3-700A(4)	90	70
MR-J3-11KA(4)	90	120
MR-J3-15KA(4)	90	170
MR-J3-22KA(4)	90	250

Inverse efficiency (η) : Efficiency including some efficiencies of the servo motor and servo amplifier when rated (regenerative) torque is generated at rated speed. Since the efficiency varies with the speed and generated torque, allow for about 10%.

Capacitor charging (Ec) : Energy charged into the electrolytic capacitor in the servo amplifier.

Subtract the capacitor charging from the result of multiplying the sum total of regenerative energies by the inverse efficiency to calculate the energy consumed by the regenerative option.

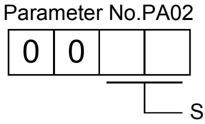
$$ER\ [J] = \eta \cdot Es - Ec$$

Calculate the power consumption of the regenerative option on the basis of single-cycle operation period tf [s] to select the necessary regenerative option.

$$PR\ [W] = ER/tf$$

(3) Parameter setting

Set parameter No.PA02 according to the option to be used.



Selection of regenerative option
00: Regenerative option is not used
- For servo amplifier of 100W, regenerative resistor is not used.
- For servo amplifier of 200 to 7kW, built-in regenerative resistor is used.
- Supplied regenerative resistors or regenerative option is used with the servo amplifier of 11k to 22kW.

01: FR-BU2-(H)･FR-RC-(H)･FR-CV-(H)
02: MR-RB032
03: MR-RB12
04: MR-RB32
05: MR-RB30
06: MR-RB50(Cooling fan is required)
08: MR-RB31
09: MR-RB51(Cooling fan is required)
80: MR-RB1H-4
81: MR-RB3M-4(Cooling fan is required)
82: MR-RB3G-4(Cooling fan is required)
83: MR-RB5G-4(Cooling fan is required)
84: MR-RB34-4(Cooling fan is required)
85: MR-RB54-4(Cooling fan is required)
FA: When the supplied regenerative resistor is cooled by the cooling fan to increase the ability with the servo amplifier of 11k to 22kW.

The following are setting values for regenerative resistor and regenerative option which are used with a servo amplifier of 11k to 22kW.

Regenerative resistor, regenerative option	Setting
Standard supplied regenerative resistor	00
Standard supplied regenerative resistor (with a cooling fan to cool it)	FA
MR-RB5E	00
MR-RB5E (with a cooling fan to cool it)	FA
MR-RB5R	00
MR-RB5R (with a cooling fan to cool it)	FA
MR-RB9P	00
MR-RB9P (with a cooling fan to cool it)	FA
MR-RB9F	00
MR-RB9F (with a cooling fan to cool it)	FA
MR-RB5K-4	00
MR-RB5K-4 (with a cooling fan to cool it)	FA
MR-RB6B-4	00
MR-RB6B-4 (with a cooling fan to cool it)	FA
MR-RB60-4	00
MR-RB60-4 (with a cooling fan to cool it)	FA
MR-RB6K-4	00
MR-RB6K-4 (with a cooling fan to cool it)	FA

(4) Connection of the regenerative option

POINT

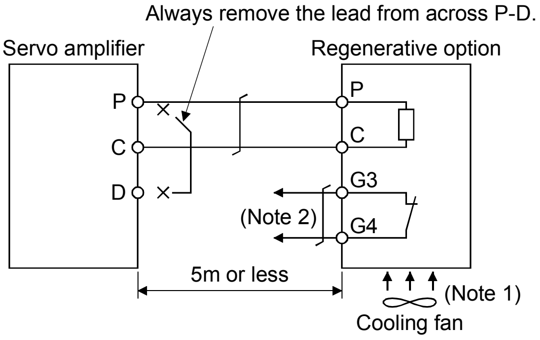
- When the MR-RB50 ・ MR-RB51 ・ MR-RB3M-4 ・ MR-RB3G-4 ・ MR-RB5G-4 ・ MR-RB34-4 ・ MR-RB54-4 is used, a cooling fan is required to cool it. The cooling fan should be prepared by the customer.
- For the sizes of wires used for wiring, refer to section 12.11.

The regenerative option will cause a temperature rise of 100℃ relative to the ambient temperature. Fully examine heat dissipation, installation position, used cables, etc. before installing the option. For wiring, use flame-resistant wire and keep them clear of the regenerative option body. Always use twisted cables of max. 5m length for connection with the servo amplifier.

(a) MR-J3-350A or less ・ MR-J3-200A4 or less

Always remove the wiring from across P-D and fit the regenerative option across P-C.

The G3 and G4 terminals act as a thermal sensor. G3-G4 is disconnected when the regenerative option overheats abnormally.



Note 1. When using the MR-RB50, MR-RB3M-4, MR-RB3G-4 or MR-RB5G-4, forcibly cool it with a cooling fan (92 × 92, minimum air flow: 1.0m^3).

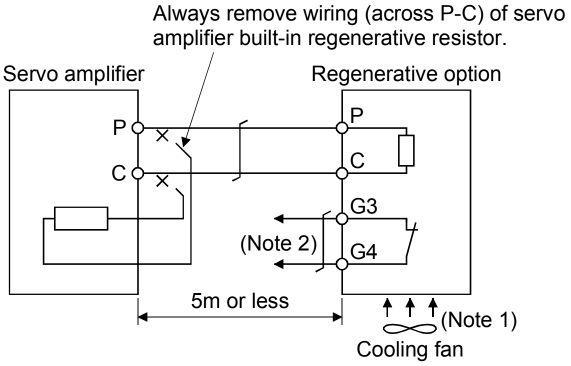
2. Make up a sequence which will switch off the magnetic contactor when abnormal heating occurs.

G3-G4 contact specifications
Maximum voltage: 120V AC/DC
Maximum current: 0.5A/4.8VDC
Maximum capacity: 2.4VA

(b) MR-J3-350A4 · MR-J3-500A(4) · MR-J3-700A(4)

Always remove the wiring (across P-C) of the servo amplifier built-in regenerative resistor and fit the regenerative option across P-C.

The G3 and G4 terminals act as a thermal sensor. G3-G4 is opened when the regenerative option overheats abnormally.

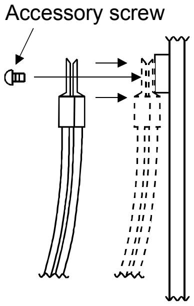


Note 1. When using the MR-RB51 · MR-RB3G-4, MR-RB5G-4, MR-RB34-4 or MR-RB54-4, forcibly cool it with a cooling fan (92 × 92, minimum air flow: 1.0m^3).

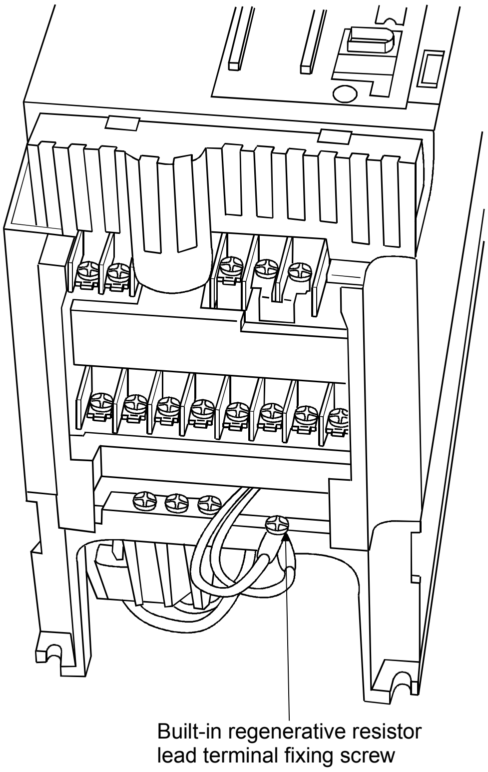
2. Make up a sequence which will switch off the magnetic contactor when abnormal heating occurs.
G3-G4 contact specifications
Maximum voltage: 120V AC/DC
Maximum current: 0.5A/4.8VDC
Maximum capacity: 2.4VA

When using the regenerative option, remove the servo amplifier's built-in regenerative resistor terminals (across P-C), fit them back to back, and secure them to the frame with the accessory screw as shown below.

Mounting method

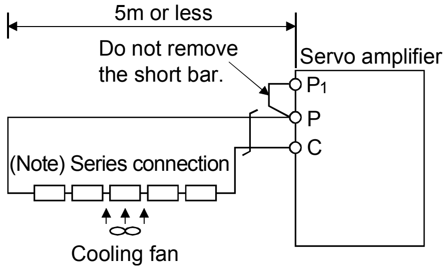


The drawing below shows the MR-J3-350A4 and MR-J3-500A (4). Refer to section 10.1 (6) Outline Drawings for the position of the fixing screw for MR-J3-700A (4).



(c) MR-J3-11KA(4)(-LR) · MR-J3-15KA(4)(-LR) · MR-J3-22KA(4) (when using the supplied regenerative resistor)

When using the regenerative resistors supplied to the servo amplifier, the specified number of resistors (4 or 5 resistors) must be connected in series. If they are connected in parallel or in less than the specified number, the servo amplifier may become faulty and/or the regenerative resistors burn. Install the resistors at intervals of about 70mm. Cooling the resistors with two cooling fans (92 × 92, minimum air flow: 1.0m^3) improves the regeneration capability. In this case, set "□□FA" in parameter No.PA02.



Note. The number of resistors connected in series depends on the resistor type. The thermal sensor is not mounted on the attached regenerative resistor. An abnormal heating of resistor may be generated at a regenerative circuit failure. Install a thermal sensor near the resistor and establish a protective circuit to shut off the main circuit power supply when abnormal heating occurs. The detection level of the thermal sensor varies according to the settings of the resistor. Set the thermal sensor in the most appropriate position on your design basis or use the thermal sensor built-in regenerative option (MR-RB5E, 9P, 9F, 6B-4, 60-4 and 6K-4) provided by Mitsubishi Electric Corporation.

Servo amplifier	Regenerative resistor	Regenerative power [W]		Resistance [Ω]	Number of resistors
		Normal	Cooling		
MR-J3-11KA	GRZG400-1.5Ω	500	800	6	4
MR-J3-11KA-LR	GRZG400-0.8Ω	500	800	0.8	4
MR-J3-15KA	GRZG400-0.9Ω	850	1300	4.5	5
MR-J3-15KA-LR MR-J3-22KA	GRZG400-0.6Ω	850	1300	3	5
MR-J3-11KA4	GRZG400-5.0Ω	500	800	20	4
MR-J3-11KA4-LR	GRZG400-2.5Ω	500	800	2.5	4
MR-J3-15KA4	GRZG400-2.5Ω	850	1300	12.5	5
MR-J3-15KA4-LR MR-J3-22KA4	GRZG400-2.0Ω	850	1300	10	5

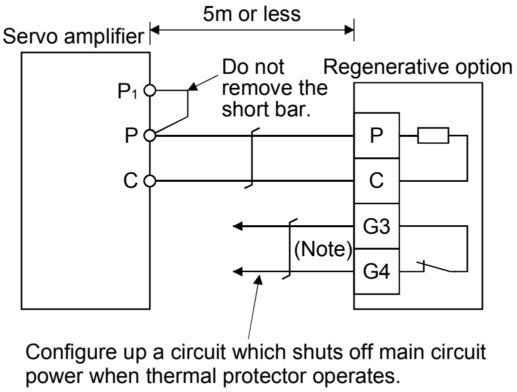
(d) MR-J3-11KA(4)-PX/LW・MR-J3-15KA(4)-PX/LW・MR-J3-22KA(4)-PX (when using the regenerative option)

The MR-J3-11KA(4)-PX to MR-J3-22KA(4)-PX servo amplifiers are not supplied with regenerative resistors. When using any of these servo amplifiers, always use the MR-RB5E, 9P, 9F, 6B-4, 60-4 and 6K-4 regenerative option.

The MR-RB5E, 9P, 9F, 6B-4, 60-4 and 6K-4 are regenerative options that have encased the GRZG400-1.5Ω, GRZG400-0.9Ω, GRZG400-0.6Ω, GRZG400-5.0Ω, GRZG400-2.5Ω, GRZG400-2.0Ω respectively. When using any of these regenerative options, make the same parameter setting as when using the GRZG400-1.5Ω, GRZG400-0.9Ω, GRZG400-0.6Ω, GRZG400-5.0Ω, GRZG400-2.5Ω, GRZG400-2.0Ω (supplied regenerative resistors or regenerative option is used with 11k to 22kW servo amplifier).

Cooling the regenerative option with cooling fans improves regenerative capability.

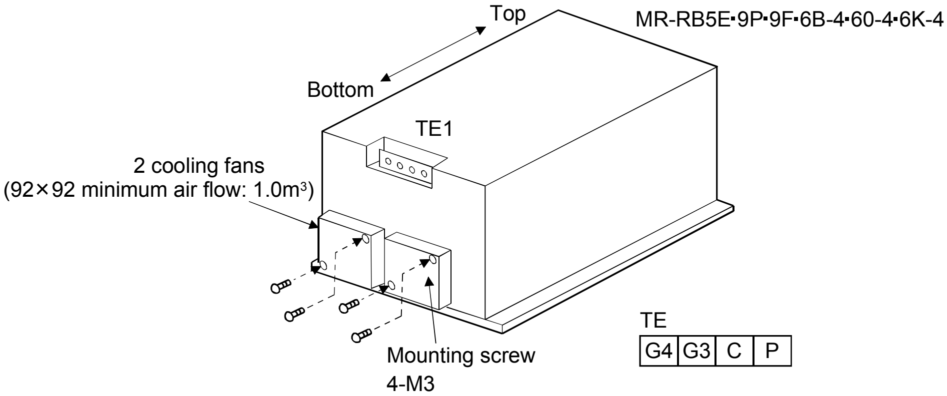
The G3 and G4 terminals are for the thermal protector. G3-G4 is opened when the regenerative option overheats abnormally.



Note. Specifications of contact across G3-G4
Maximum voltage : 120V AC/DC
Maximum current : 0.5A/4.8VDC
Maximum capacity : 2.4VA

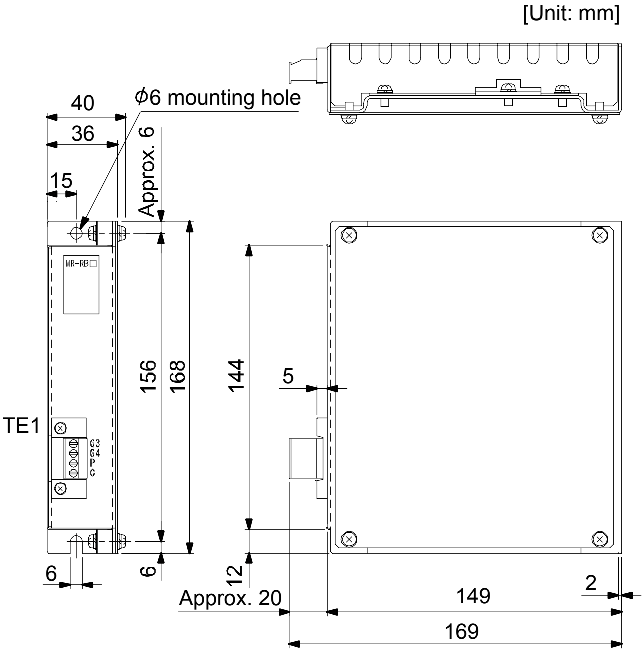
Servo amplifier	Regenerative option model	Resistance [Ω]	Regenerative power [W]	
			Without cooling fans	With cooling fans
MR-J3-11KA-PX	MR-RB5E	6	500	800
MR-J3-11KA-LW	MR-RB5R	3.2	500	800
MR-J3-15KA-PX	MR-RB9P	4.5	850	1300
MR-J3-15KA-LW MR-J3-22KA-PX	MR-RB9F	3	850	1300
MR-J3-11KA4-PX	MR-RB6B-4	20	500	800
MR-J3-11KA4-LW	MR-RB5K-4	10	500	800
MR-J3-15KA4-PX	MR-RB60-4	12.5	850	1300
MR-J3-15KA4-LW MR-J3-22KA4-PX	MR-RB6K-4	10	850	1300

When using cooling fans, install them using the mounting holes provided in the bottom of the regenerative option. In this case, set "□□FA" in parameter No.PA02.



(5) Outline drawings

(a) MR-RB12



- TE1

  Terminal block

G3
G4
P
C

  Applicable wire size: 0.2 to 2.5mm^2 (AWG24 to AWG12)
  Tightening torque: 0.5 to 0.6 [N・m] (4 to 5 [lb・in])

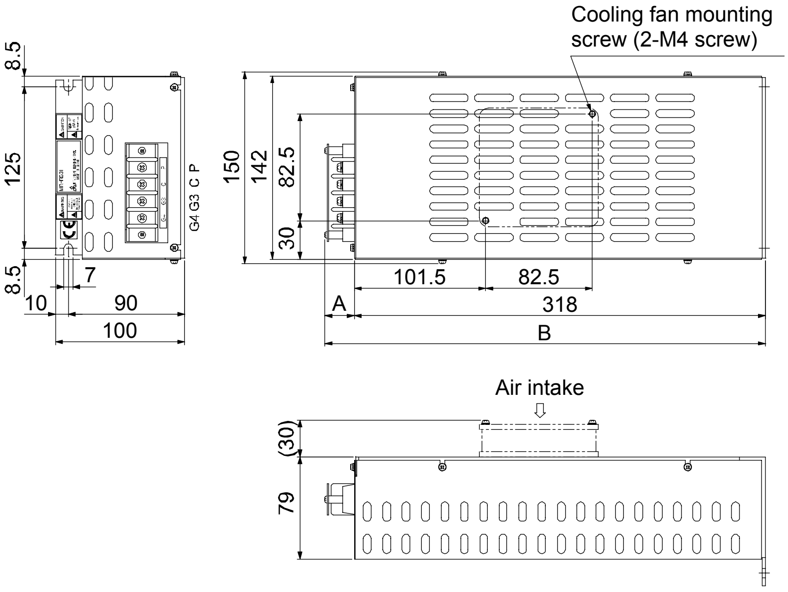
- Mounting screw

  Screw size: M5
  Tightening torque: 3.24 [N・m] (28.7 [lb・in])

Mass: 1.1 [kg] (2.4 [lb])

(b) MR-RB30 · MR-RB31 · MR-RB32 · MR-RB34-4 · MR-RB3M-4 · MR-RB3G-4

[Unit: mm]



· Terminal block

P
C
G3
G4

Terminal screw: M4

Tightening torque: 1.2 [N · m] (10.62 [lb · in])

· Mounting screw

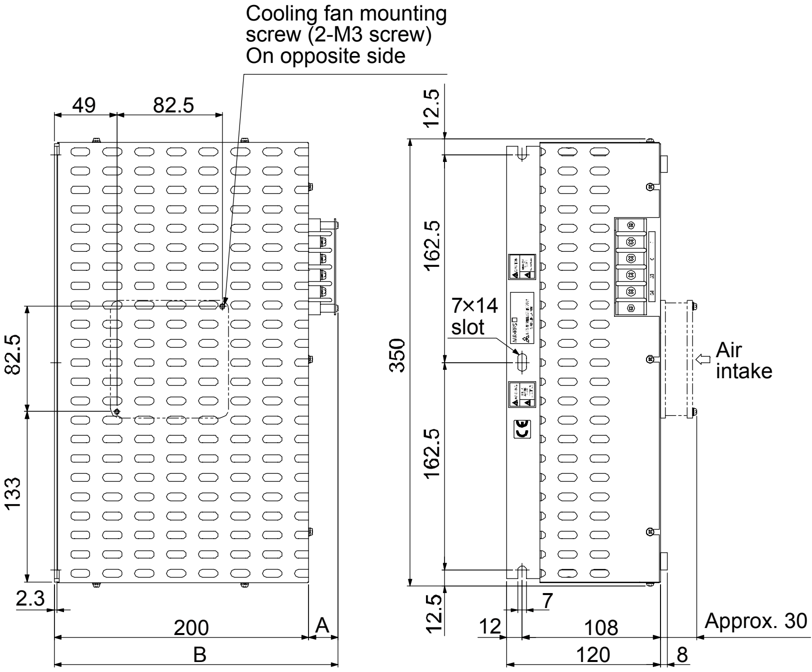
Screw size: M6

Tightening torque: 5.4 [N · m] (47.79 [lb · in])

Regenerative option	Variable dimensions		Mass [kg] (lb)
	A	B	
MR-RB30	17	335	2.9 (6.4)
MR-RB31			
MR-RB32			
MR-RB34-4	23	341	
MR-RB3M-4			
MR-RB3G-4			

(c) MR-RB50 · MR-RB51 · MR-RB54-4 · MR-RB5G-4

[Unit: mm]



· Terminal block

P
C
G3
G4

Terminal screw: M4

Tightening torque: 1.2 [N · m] (10.62 [lb · in])

· Mounting screw

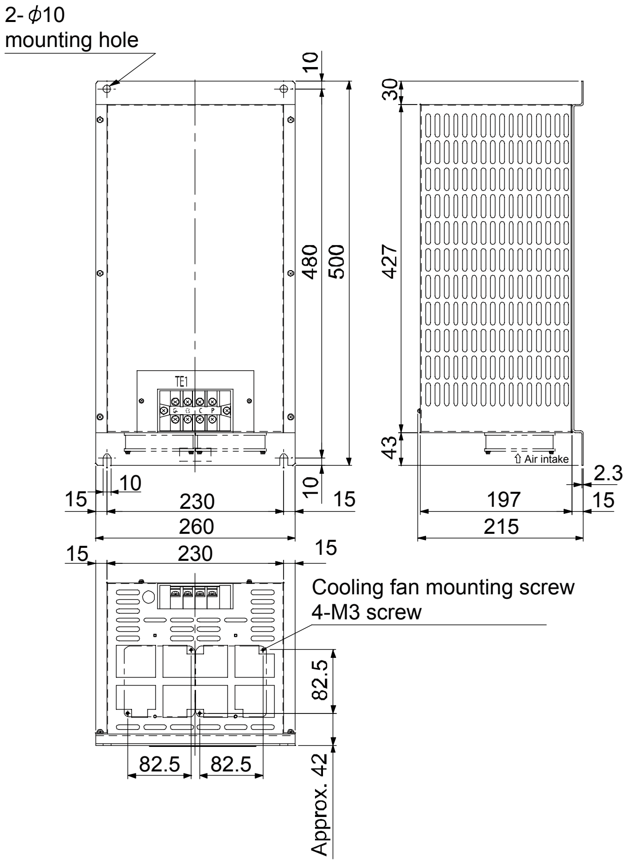
Screw size: M6

Tightening torque: 5.4 [N · m] (47.79 [lb · in])

Regenerative option	Variable dimensions		Mass [kg] (lb)
	A	B	
MR-RB50	17	217	5.6 (12.3)
MR-RB51			
MR-RB54-4	23	223	
MR-RB5G-4			

(d) MR-RB5E・MR-RB5R・MR-RB9P・MR-RB9F・MR-RB5K-4・MR-RB6B-4・MR-RB60-4・MR-RB6K-4

[Unit: mm]



・Terminal block

G4	G3	C	P

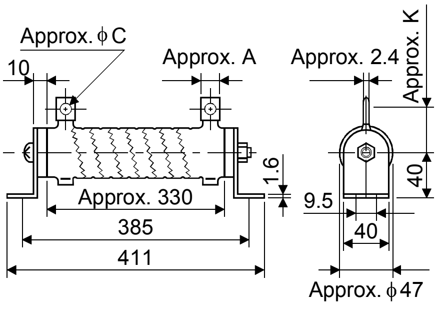
Terminal screw: M5
Tightening torque: 2.0 [N・m] (17.70 [lb・in])

・Mounting screw
Screw size: M8
Tightening torque: 13.2 [N・m] (116.83 [lb・in])

Regenerative option	Mass	
	[kg]	[lb]
MR-RB5E	10	22.0
MR-RB5R	11	24.3
MR-RB9P		
MR-RB9F		
MR-RB5K-4	10	22.0
MR-RB6B-4		
MR-RB60-4	11	24.3
MR-RB6K-4		

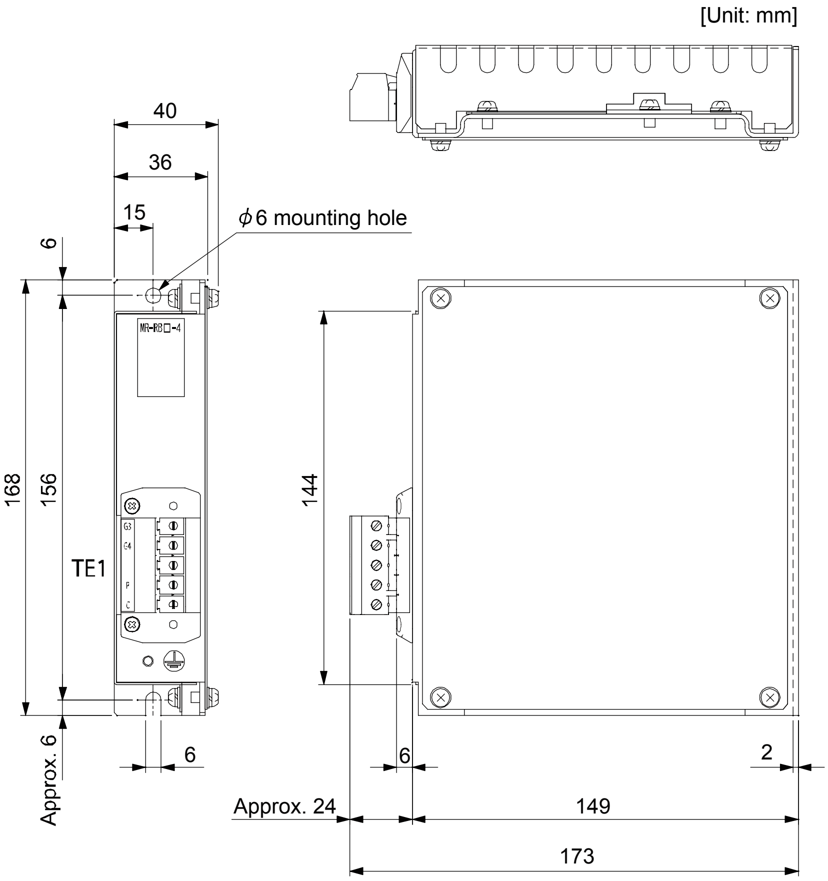
(e) GRZG400-1.5Ω・GRZG400-0.9Ω・GRZG400-0.8Ω・GRZG400-0.6Ω・GRZG400-5.0Ω・GRZG400-2.5Ω・GRZG400-2.0Ω (standard accessories)

[Unit: mm]



Regenerative brake	Variable dimensions			Mounting screw size	Tightening torque [N・m] ([lb・in])	Mass [kg] ([lb])
	A	C	K			
GRZG400-1.5Ω	10	5.5	39	M8	13.2 (116.83)	0.8 (1.76)
GRZG400-0.9Ω						
GRZG400-0.8Ω						
GRZG400-0.6Ω	16	8.2	46			
GRZG400-5.0Ω	10	5.5	39			
GRZG400-2.5Ω						
GRZG400-2.0Ω						

(f) MR-RB1H-4



- Terminal signal layout

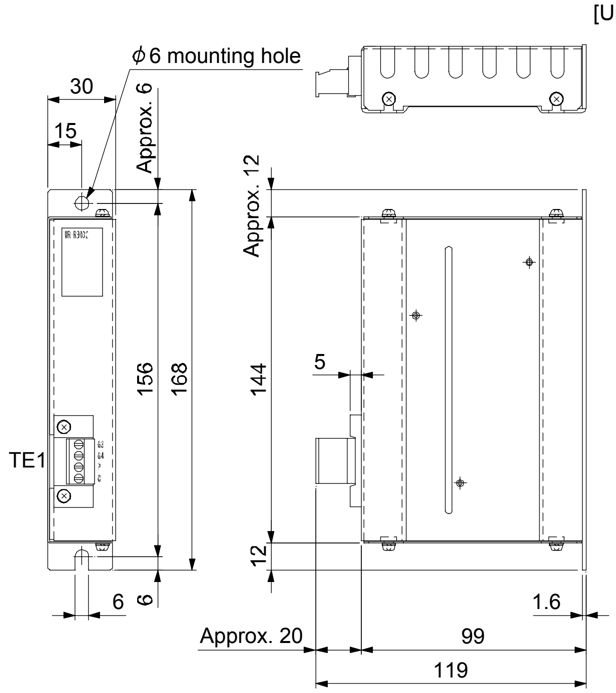
G3
G4
P
C

Applicable wire size: 0.2 to 4.0mm^2
(AWG24 to AWG10)
Tightening torque: 0.5 to 0.6 [N・m]
(4.43 to 5.31 [lb・in])

- Mounting screw
  Screw size: M5
  Tightening torque: 3.24 [N・m]
  (28.32 [lb・in])

Mass: 1.1[kg] (2.4 [lb])

(g) MR-RB032



- TE1
  Terminal block

G3
G4
P
C

Applicable wire size: 0.2 to 2.5mm^2
(AWG24 to AWG12)
Tightening torque: 0.5 to 0.6 [N・m]
(4 to 5 [lb・in])

- Mounting screw
  Screw size: M5
  Tightening torque: 3.24 [N・m]
  (28.7 [lb・in])

Mass: 0.5 [kg] (1.1 [lb])

12.3 FR-BU2-(H) brake unit

POINT

- Use a 200V class brake unit and a resistor unit with a 200V class servo amplifier, and a 400V class brake unit and a resistor unit with a 400V class servo amplifier. Combination of different voltage class units and servo amplifier cannot be used.
- Install a brake unit and a resistor unit on a flat surface vertically. When the unit is installed horizontally or diagonally, the heat dissipation effect diminishes.
- Temperature of the resistor unit case rises to higher than 100℃. Keep cables and flammable materials away from the case.
- Ambient temperature condition of the brake unit is between －10℃ (14℉) and 50℃ (122℉). Note that the condition is different from the ambient temperature condition of the servo amplifier (between 0℃ (32℉) and 55℃ (131℉)).
- Configure the circuit to shut down the power-supply with the alarm output of the brake unit and resistor unit under abnormal condition.
- Use the brake unit with a combination indicated in section 12.3.1.
- For executing a continuous regenerative operation, use FR-RC-(H) power regenerative converter or FR-CV-(H) power regenerative common converter.
- Brake unit and regenerative options (Regenerative resistor) cannot be used simultaneously.

Connect the brake unit to the bus of the servo amplifier. As compared to the MR-RB regenerative option, the brake unit can return larger power. Use the brake unit when the regenerative option cannot provide sufficient regenerative capability.
When using the brake unit, set the parameter No.PA02 of the servo amplifier to "□□01".
When using the brake unit, always refer to the FR-BU2-(H) Brake Unit Instruction Manual.

12.3.1 Selection

Use a combination of servo amplifier, brake unit and resistor unit listed below.

Brake unit		Resistor unit	Number of connected units	Permissible continuous power [kW]	Total resistance [Ω]	Applicable servo amplifier
200V class	FR-BU2-15K	FR-BR-15K	1	0.99	8	MR-J3-500A (Note)
			2(parallel)	1.98	4	MR-J3-500A MR-J3-700A MR-J3-11KA MR-J3-15KA
	FR-BU2-30K	FR-BR-30K	1	1.99	4	MR-J3-500A MR-J3-700A MR-J3-11KA MR-J3-15KA
	FR-BU2-55K	FR-BR-55K	1	3.91	2	MR-J3-11KA MR-J3-15KA MR-J3-22KA
		MT-BR5-55K	1	5.5	2	MR-J3-22KA
400V class	FR-BU2-H30K	FR-BR-H30K	1	1.99	16	MR-J3-500A4 MR-J3-700A4 MR-J3-11KA4
	FR-BU2-H55K	FR-BR-H55K	1	3.91	8	MR-J3-11KA4 MR-J3-15KA4 MR-J3-22KA4
	FR-BU2-H75K	MT-BR5-H75K	1	7.5	6.5	MR-J3-22KA4

Note. The combination is limited only when using with the servo motors HC-LP302, HC-RP353, HA-LP502 or HC-UP352.

12.3.2 Brake unit parameter setting

Normally, when using the FR-BU2-(H), changing parameters is not necessary. Whether a parameter can be changed or not is listed below.

Parameter		Change possible /impossible	Remarks
No.	Name		
0	Brake mode switchover	Impossible	Do not change the parameter.
1	Monitor display data selection	Possible	Refer to the FR-BU2-(H) Brake Unit Instruction Manual.
2	Input terminal function selection 1	Impossible	Do not change the parameter.
3	Input terminal function selection 2		
77	Parameter write selection		
78	Cumulative energization time carrying-over times		
CLr	Parameter clear		
ECL	Alarm history clear		
C1	For manufacturer setting		

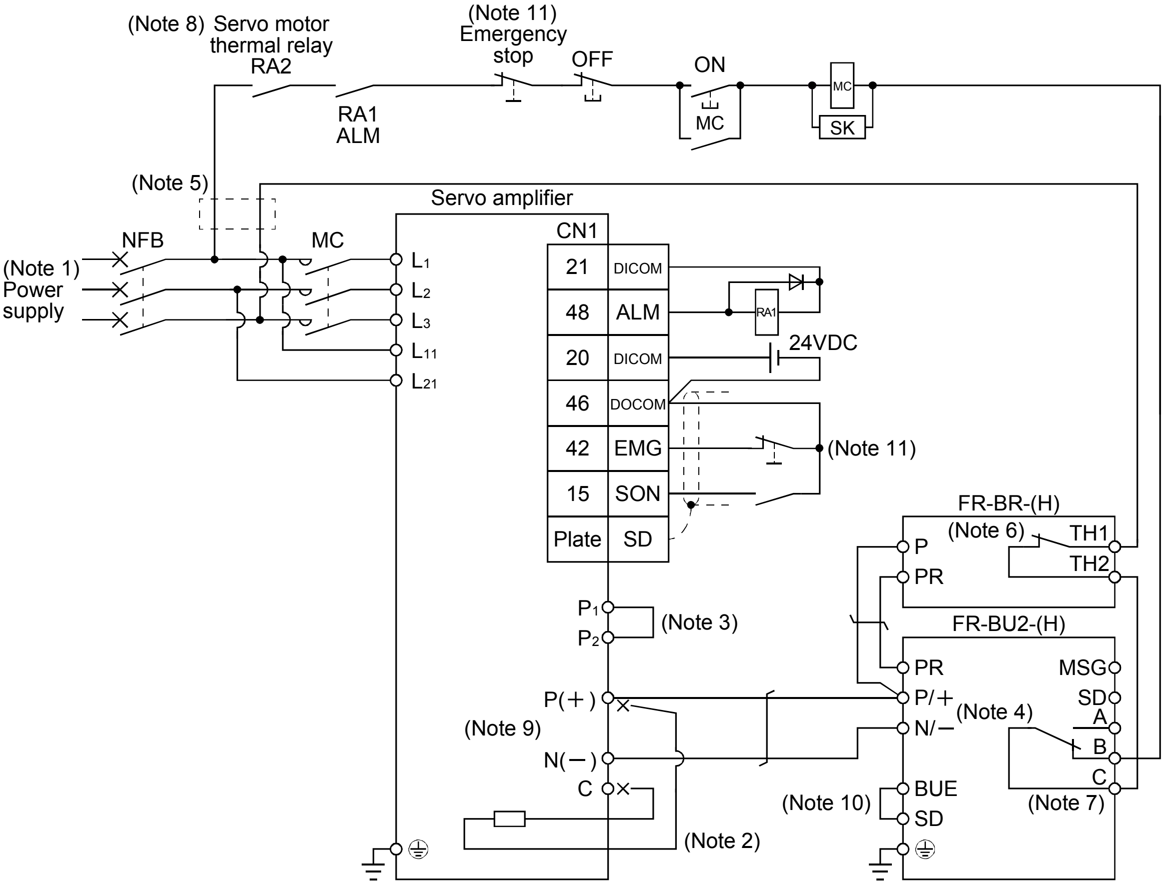
12.3.3 Connection example

POINT

- Connecting PR terminal of the brake unit to P terminal of the servo amplifier results in brake unit malfunction. Always connect the PR terminal of the brake unit to the PR terminal of the resistor unit.

(1) Combination with FR-BR-(H) resistor unit

(a) When connecting a brake unit to a servo amplifier



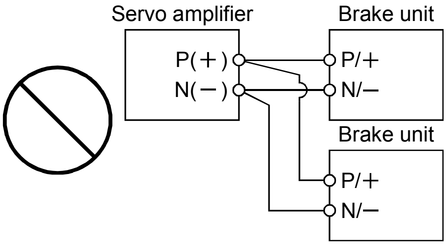
Note 1. For power supply specifications, refer to section 1.3.

2. For the servo amplifier of 5k and 7kW, always disconnect the lead of built-in regenerative resistor, which is connected to the P and C terminals. For the servo amplifier of 11k to 22kW, do not connect a supplied regenerative resistor to the P and C terminals.
3. Always connect P_1 and P_2 terminals (P_1 and P for the servo amplifier of 11k to 22kW) (Factory-wired). When using the power factor improving DC reactor, refer to section 12.13. Use only one of power factor improving DC reactor or power factor improving AC reactor.
4. Connect the P/＋ and N/－ terminals of the brake unit to a correct destination. Incorrect connection results in servo amplifier and brake unit malfunction.
5. For 400VAC class, a step-down transformer is required.
6. Contact rating: 1b contact, 110VAC_5A/220VAC_3A
   Normal condition: TH1-TH2 is conducting. Abnormal condition: TH1-TH2 is not conducting.
7. Contact rating: 230VAC_0.3A/30VDC_0.3A
   Normal condition: B-C is conducting/A-C is not conducting. Abnormal condition: B-C is not conducting/A-C is conducting.
8. For the servo amplifier of 11kW or more, connect the thermal relay censor of the servo amplifier.
9. Do not connect more than one cable to each P(＋) and N(－) terminals of the servo amplifier.
10. Always connect BUE and SD terminals (Factory-wired).
11. Configure the circuit to shut down the main circuit power supply simultaneously with the turn off of emergency stop (EMG) using the external sequence.

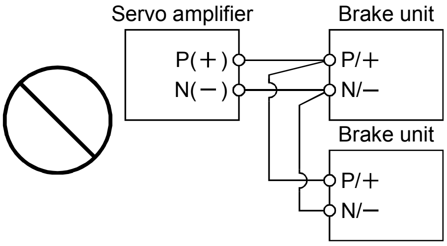
(b) When connecting two brake units to a servo amplifier

POINT

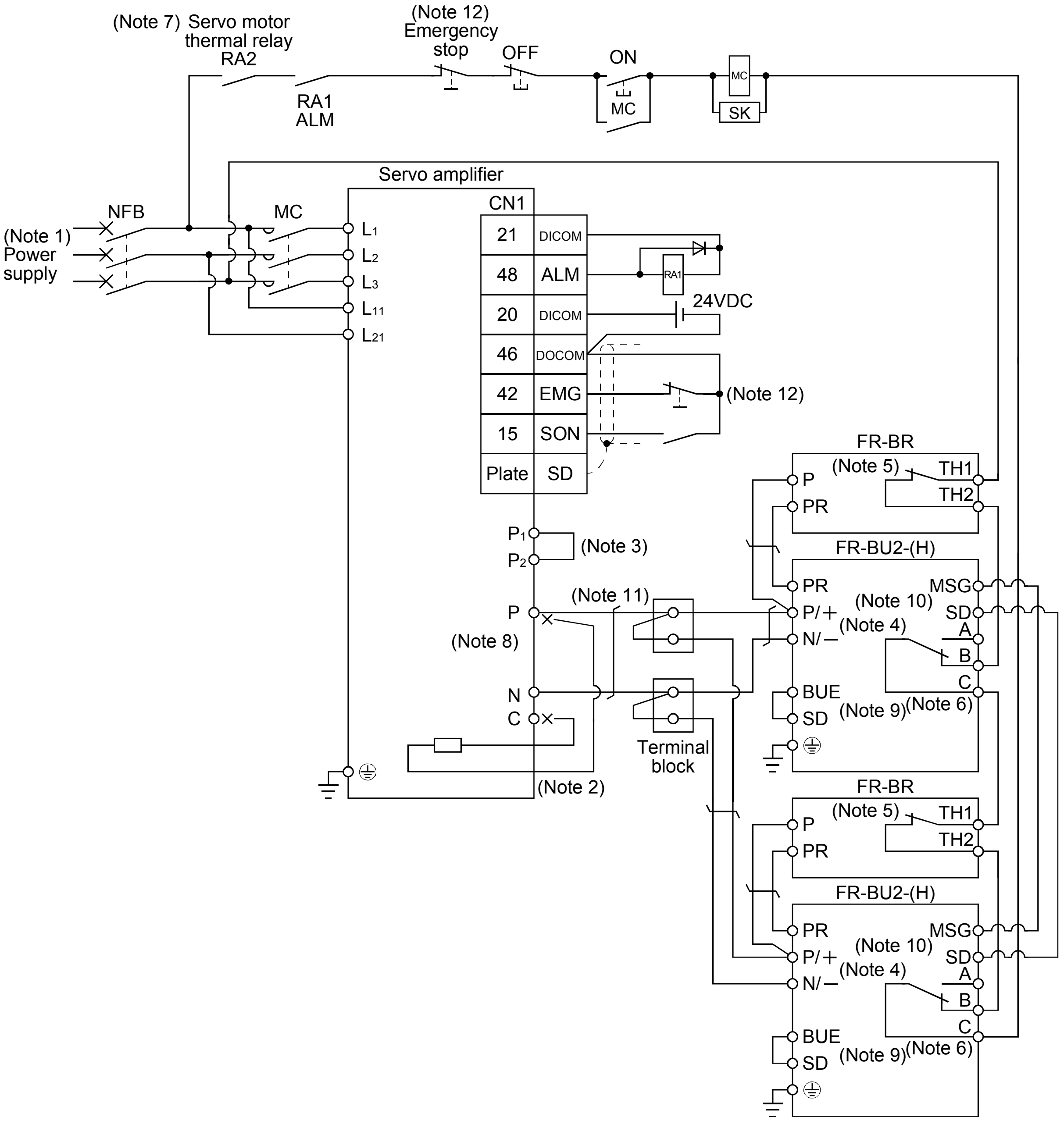
- To use brake units with a parallel connection, use two sets of FR-BU2 brake unit. Combination with other brake unit results in alarm occurrence or malfunction.
- Always connect the master and slave terminals (MSG and SD) of the two brake units.
- Do not connect the servo amplifier and brake units as below. Connect the cables with a terminal block to distribute as indicated in this section.



Connecting two cables to P and N terminals



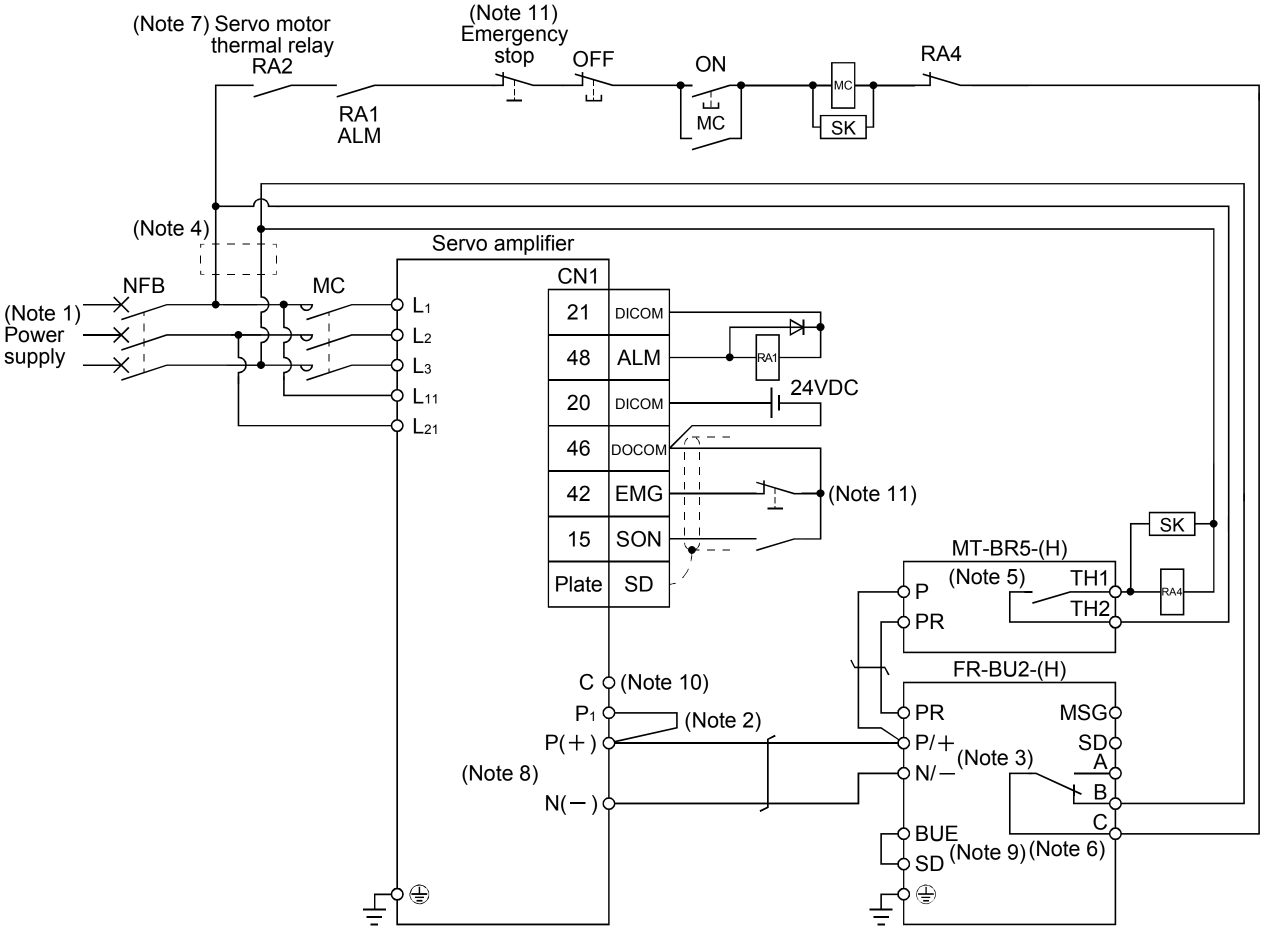
Passing wiring



Note 1. For power supply specifications, refer to section 1.3.

2. For the servo amplifier of 5k and 7kW, always disconnect the lead of built-in regenerative resistor, which is connected to the P and C terminals. For the servo amplifier of 11k and 15kW, do not connect a supplied regenerative resistor to the P and C terminals.
3. Always connect P_1 and P_2 terminals (P_1 and P for the servo amplifier of 11k and 15kW) (Factory-wired). When using the power factor improving DC reactor, refer to section 12.13. Use only one of power factor improving DC reactor or power factor improving AC reactor.
4. Connect the P/＋ and N/－ terminals of the brake unit to a correct destination. Incorrect connection results in servo amplifier and brake unit malfunction.
5. Contact rating: 1b contact, 110VAC_5A/220VAC_3A
   Normal condition: TH1-TH2 is conducting. Abnormal condition: TH1-TH2 is not conducting.
6. Contact rating: 230VAC_0.3A/30VDC_0.3A
   Normal condition: B-C is conducting/A-C is not conducting. Abnormal condition: B-C is not conducting/A-C is conducting.
7. For the servo amplifier of 11kW or more, connect the thermal relay censor of the servo amplifier.
8. Do not connect more than one cable to each P (＋) and N (－) terminals of the servo amplifier.
9. Always connect BUE and SD terminals (Factory-wired).
10. Connect the MSG and SD terminals of the brake unit to a correct destination. Incorrect connection results in servo amplifier and brake unit malfunction.
11. For the cable to connect the terminal block and the P and N terminals of the servo amplifier, use the cable indicated in (4) (b) in this section.
12. Configure the circuit to shut down the main circuit power supply simultaneously with the turn off of emergency stop (EMG) using the external sequence.

(2) Combination with MT-BR5-(H) resistor unit

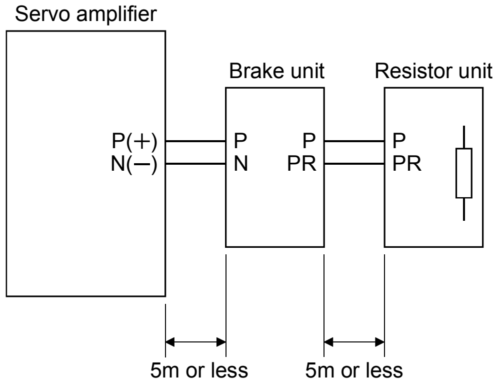


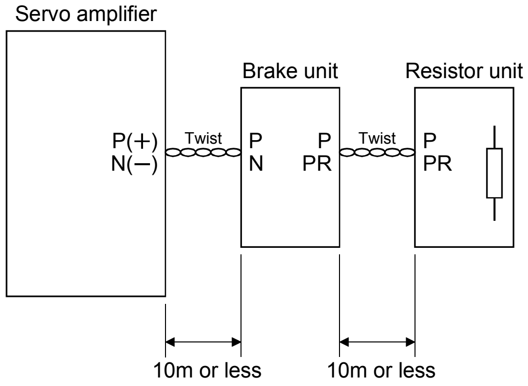
Note 1. For power supply specifications, refer to section 1.3.

2. Always connect P1 and P(+) terminals (Factory-wired). When using the power factor improving DC reactor, refer to section 12.13. Use only one of power factor improving DC reactor or power factor improving AC reactor.
3. Connect the P/+ and N/− terminals of the brake unit to a correct destination. Incorrect connection results in servo amplifier and brake unit malfunction.
4. For the servo amplifier of 400V class, a step-down transformer is required.
5. Contact rating: 1a contact, 110VAC_5A/220VAC_3A
   Normal condition: TH1-TH2 is not conducting. Abnormal condition: TH1-TH2 is conducting.
6. Contact rating: 230VAC_0.3A/30VDC_0.3A
   Normal condition: B-C is conducting/A-C is not conducting. Abnormal condition: B-C is not conducting/A-C is conducting.
7. For the servo amplifier of 11kW or more, connect the thermal relay censor of the servo amplifier.
8. Do not connect more than one cable to each P (+) and N (−) terminals of the servo amplifier.
9. Always connect BUE and SD terminals (Factory-wired).
10. For the servo amplifier of 22kW, do not connect a supplied regenerative resistor to the P and C terminals.
11. Configure the circuit to shut down the main circuit power supply simultaneously with the turn off of emergency stop (EMG) using the external sequence.

(3) Precautions for wiring

The cables between the servo amplifier and the brake unit, and between the resistor unit and the brake unit should be as short as possible. Always twist the cable longer than 5m (twist five times or more per one meter). Even when the cable is twisted, the cable should be less than 10m. Using cables longer than 5m without twisting or twisted cables longer than 10m, may result in the brake unit malfunction.



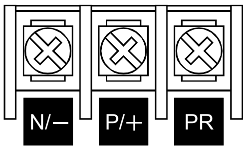


(4) Cables

(a) Cables for the brake unit

For the brake unit, HIV wire (600V Grade heat-resistant polyvinyl chloride insulated wire) is recommended.

1) Main circuit terminal



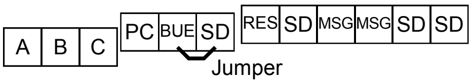
Terminal block

Brake unit		Main circuit terminal screw size	Crimping terminal	Tightening torque [N・m] ([lb・in])	Wire size	
			N/−, P/+, PR, ⏚		N/−, P/+, PR, ⏚	
					HIV wire [mm^2]	AWG
200V class	FR-BU2-15K	M4	5.5-4	1.5(13.3)	3.5	12
	FR-BU2-30K	M5	5.5-5	2.5(22.1)	5.5	10
	FR-BU2-55K	M6	14-6	4.4(38.9)	14	6
400V class	FR-BU2-H30K	M4	5.5-4	1.5(13.3)	3.5	12
	FR-BU2-H55K	M5	5.5-5	2.5(22.1)	5.5	10
	FR-BU2-H75K	M6	14-6	4.4(38.9)	14	6

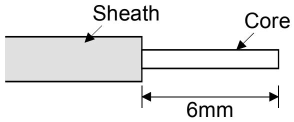
2) Control circuit terminal

POINT

- Undertightening can cause a cable disconnection or malfunction. Overtightening can cause a short circuit or malfunction due to damage to the screw or the brake unit.



Terminal block



Wire the stripped cable after twisting to prevent the cable from becoming loose. In addition, do not solder it.
Screw size: M3
Tightening torque: 0.5 to 0.6N・m
Wire size: 0.3 to 0.75 mm^2
Screw driver: Small flat-blade screwdriver
(Tip thickness: 0.4mm/Tip width 2.5mm)

(b) Cables for connecting the servo amplifier and a distribution terminal block when connecting two sets of the brake unit

Brake unit	Wire size	
	HIV wire [mm^2]	AWG
FR-BU2-15K	8	8

(5) Crimping terminals for P and N terminals of servo amplifier

(a) Recommended crimping terminals

POINT

- Always use recommended crimping terminals or equivalent since some crimping terminals cannot be installed depending on the size.

	Servo amplifier	Brake unit	Number of connected units	Crimping terminal (Manufacturer)	(Note 1) Applicable tool
200V class	MR-J3-500A	FR-BU2-15K	1	FVD5.5-S4 (Japan Solderless Terminals)	c
			2	8-4NS (Japan Solderless Terminals) (Note 2)	d
		FR-BU2-30K	1	FVD5.5-S4 (Japan Solderless Terminals)	c
	MR-J3-700A	FR-BU2-15K	2	8-4NS (Japan Solderless Terminals) (Note 2)	d
		FR-BU2-30K	1	FVD5.5-S4 (Japan Solderless Terminals)	c
	MR-J3-11KA	FR-BU2-15K	2	FVD8-6 (Japan Solderless Terminals)	a
		FR-BU2-30K	1	FVD5.5-6 (Japan Solderless Terminals)	c
		FR-BU2-55K	1	FVD14-6 (Japan Solderless Terminals)	b
	MR-J3-15KA	FR-BU2-15K	2	FVD8-6 (Japan Solderless Terminals)	a
		FR-BU2-30K	1	FVD5.5-6 (Japan Solderless Terminals)	c
		FR-BU2-55K	1	FVD14-6 (Japan Solderless Terminals)	b
	MR-J3-22KA	FR-BU2-55K	1	FVD14-8 (Japan Solderless Terminals)	b
400V class	MR-J3-500A4	FR-BU2-H30K	1	FVD5.5-S4 (Japan Solderless Terminals)	c
	MR-J3-700A4	FR-BU2-H30K	1	FVD5.5-S4 (Japan Solderless Terminals)	c
	MR-J3-11KA4	FR-BU2-H30K	1	FVD5.5-6 (Japan Solderless Terminals)	c
		FR-BU2-H55K	1	FVD5.5-6 (Japan Solderless Terminals)	c
	MR-J3-15KA4	FR-BU2-H55K	1	FVD5.5-6 (Japan Solderless Terminals)	c
	MR-J3-22KA4	FR-BU2-H55K	1	FVD5.5-8 (Japan Solderless Terminals)	c
		FR-BU2-H75K	1	FVD14-8 (Japan Solderless Terminals)	b

Note 1. Symbols in the applicable tool field indicate applicable tools in (5)(b) in this section.

2. Coat the crimping part with an insulation tube.

(b) Applicable tool

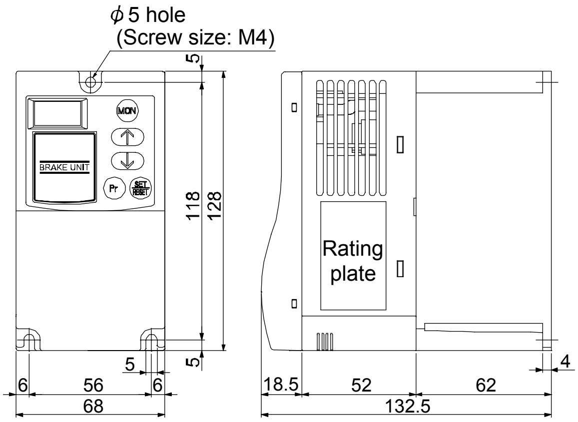
Symbol	Servo amplifier side crimping terminals				
	Crimping terminal	Applicable tool			Manufacturer
		Body	Head	Dice	
a	FVD8-6	YF-1・E-4	YNE-38	DH-111・DH121	Japan Solderless Terminals
b	FVD14-6 FVD14-8	YF-1・E-4	YNE-38	DH-112・DH122	
c	FDV5.5-S4 FDV5.5-6	YNT-1210S			
d	8-4NS	YHT-8S			

12.3.4 Outline dimension drawings

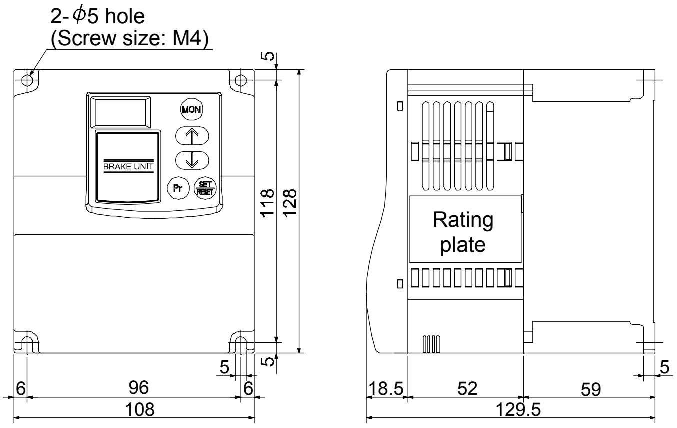
(1) FR-BU2-(H) brake unit

[Unit: mm]

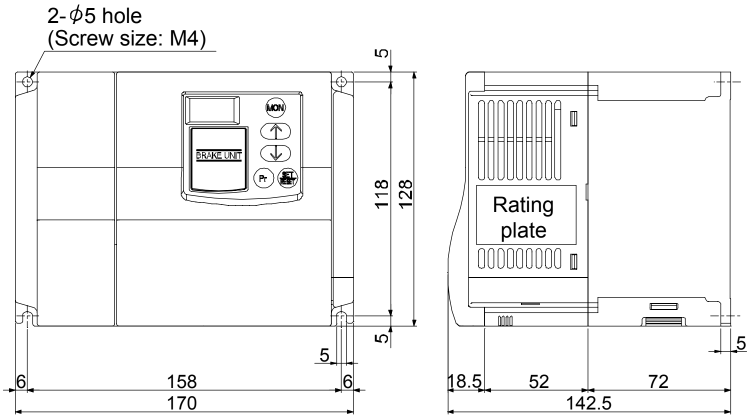
FR-BU2-15K



FR-BU2-30K
FR-BU2-H30K

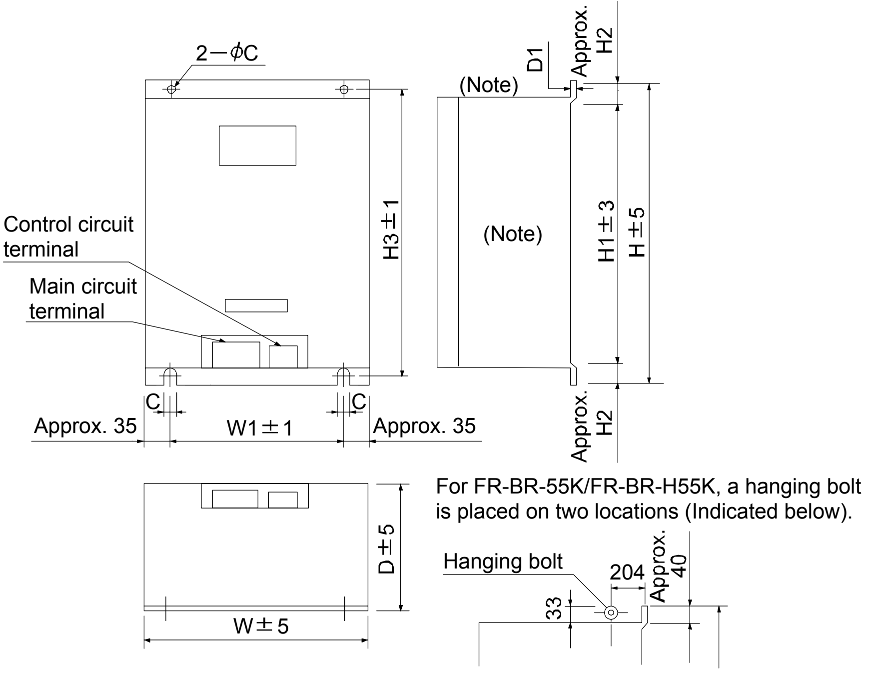


FR-BU2-55K
FR-BU2-H55K, H75K



(2) FR-BR-(H) resistor unit

[Unit: mm]

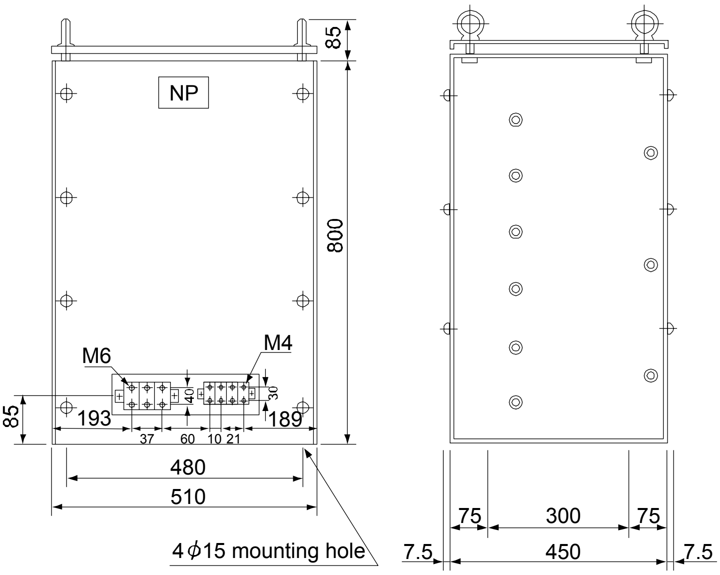


For FR-BR-55K/FR-BR-H55K, a hanging bolt is placed on two locations (Indicated below).

Note. Ventilation ports are provided on both sides and the top. The bottom is open.

Resistor unit		W	W1	H	H1	H2	H3	D	D1	C	Approximate mass [kg]([lb])
200V class	FR-BR-15K	170	100	450	410	20	432	220	3.2	6	15(33.1)
	FR-BR-30K	340	270	600	560	20	582	220	4	10	30(66.1)
	FR-BR-55K	480	410	700	620	40	670	450	3.2	12	70(154)
400V class	FR-BR-H30K	340	270	600	560	20	582	220	4	10	30(66.1)
	FR-BR-H55K	480	410	700	620	40	670	450	3.2	12	70(154)

(3) MT-BR5-(H) resistor unit



[Unit: mm]

Resistor unit		Resistance value	Approximate mass [kg]([lb])
200V class	MT-BR5-55K	2.0Ω	50(110)
400V class	MT-BR5-H75K	6.5Ω	70(154)

12.4 Power regenerative converter

POINT

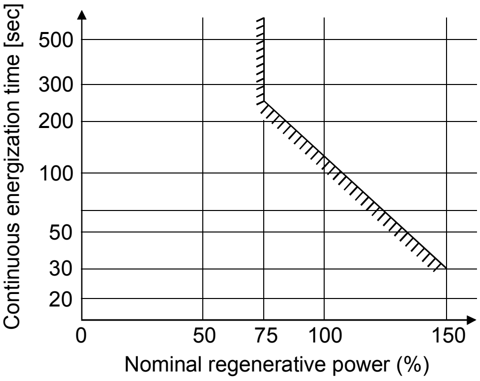
- When using the FR-RC-(H) power regenerative converter, refer to "Power Regeneration Converter FR-RC Instruction Manual (IB(NA)66330)".

When using the power regenerative converter, set "□□01" in parameter No.PA02.

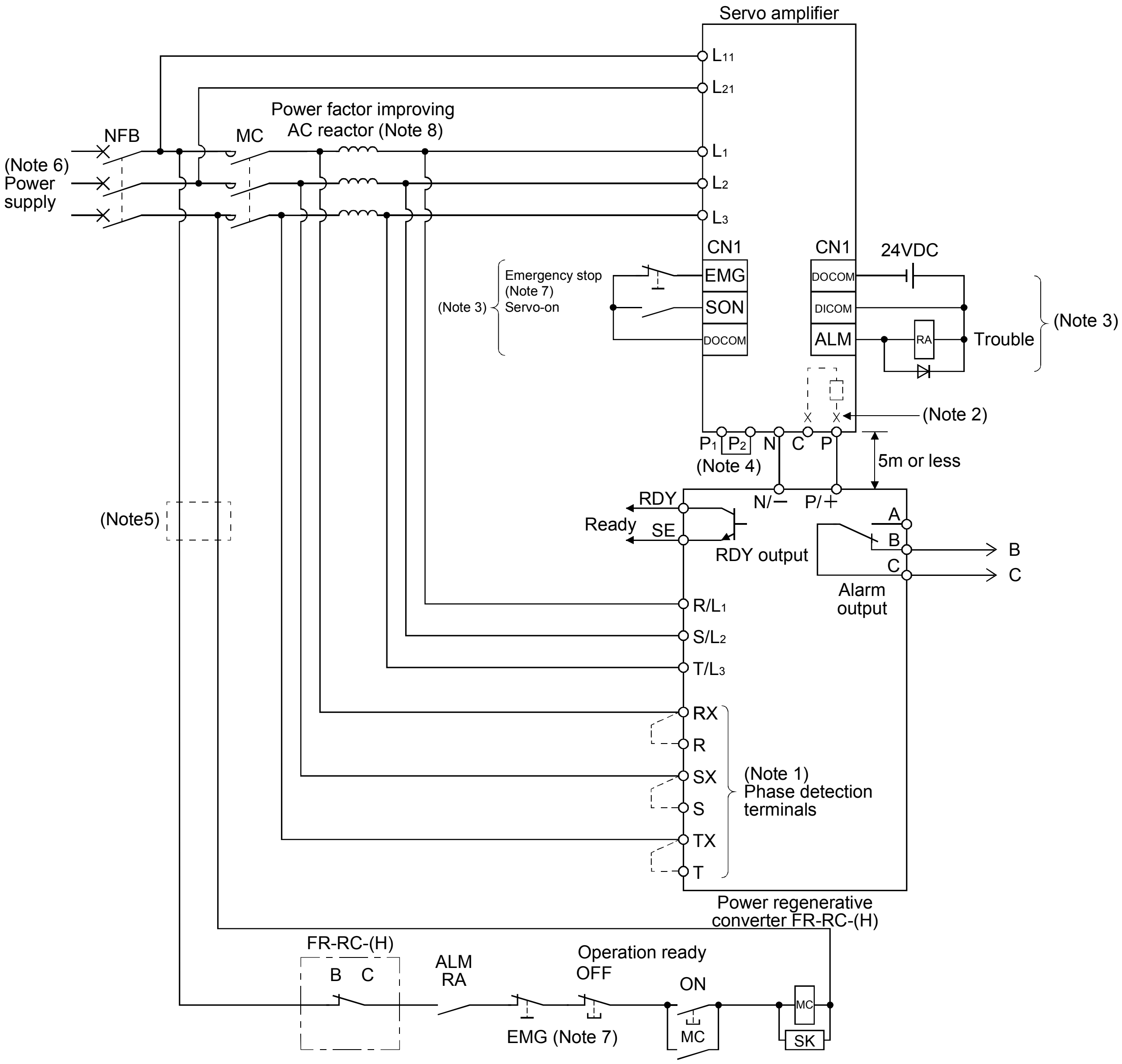
(1) Selection

The converters can continuously return 75% of the nominal regenerative power. They are applied to the servo amplifiers of the 5k to 22kW.

Power regenerative converter	Nominal regenerative power (kW)	Servo amplifier
FR-RC-15K	15	MR-J3-500A MR-J3-700A
FR-RC-30K	30	MR-J3-11KA MR-J3-15KA
FR-RC-55K	55	MR-J3-22KA
FR-RC-H15K	15	MR-J3-500A4 MR-J3-700A4
FR-RC-H30K	30	MR-J3-11KA4 MR-J3-15KA4
FR-RC-H55K	55	MR-J3-22KA4



(2) Connection example

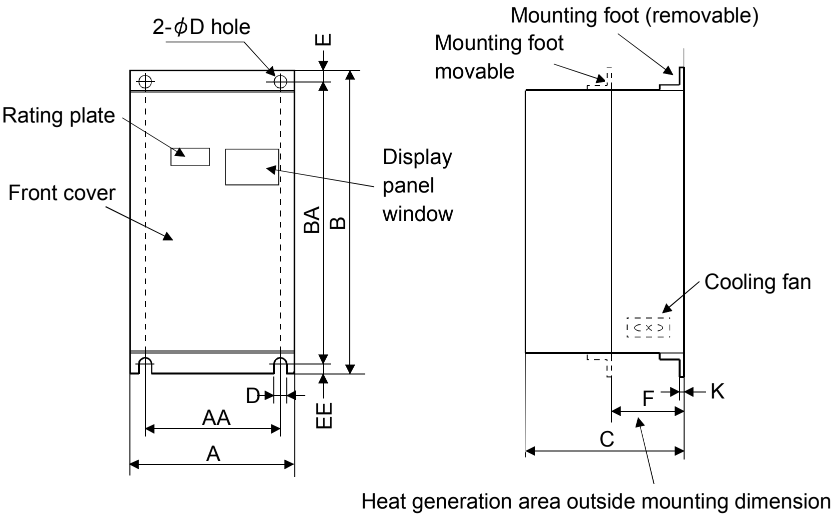


Note 1. When not using the phase detection terminals, fit the jumpers across RX-R, SX-S and TX-T. If the jumpers remain removed, the FR-RC-(H) will not operate.

2. When using servo amplifier of 5kW and 7kW, always remove the lead of built-in regenerative resistor connected to P terminal and C terminal.
3. This diagram is for sink I/O interface. Refer to section 3.8.3 for source I/O interface.
4. Between P_1 and P_2 (P_1 and P for 11kW to 22kW) is connected by default.
5. Stepdown transformer is required for coil voltage of magnetic contactor more than 200V class in 400V class servo amplifiers.
6. Refer to section 1.3 for the power supply specification.
7. Configure the circuit to shut down the main circuit power supply simultaneously with the turn off of emergency stop (EMG) using the external sequence.
8. For selection of power factor improving AC reactors, refer to "Power Regeneration Converter FR-RC Instruction Manual (IB(NA)66330)".

(3) Outside dimensions of the power regenerative converters

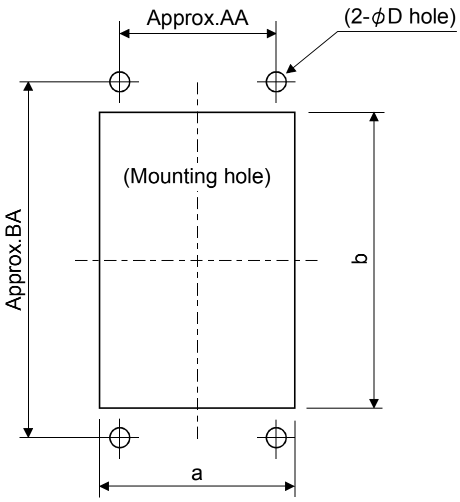
[Unit : mm]



Power regenerative converter	A	AA	B	BA	C	D	E	EE	K	F	Approx. Mass [kg(lb)]
FR-RC-15K	270	200	450	432	195	10	10	8	3.2	87	19 (41.888)
FR-RC-H15K	340	270	600	582	195	10	10	8	3.2	90	31 (68.343)
FR-RC-30K											
FR-RC-H30K											
FR-RC-55K	480	410	700	670	250	12	15	15	3.2	135	55 (121.3)
FR-RC-H55K											

(4) Mounting hole machining dimensions

When the power regenerative converter is fitted to a totally enclosed type box, mount the heat generating area of the converter outside the box to provide heat generation measures. At this time, the mounting hole having the following dimensions is machined in the box.



[Unit : mm]

Model	a	b	D	AA	BA
FR-RC-15K	260	412	10	200	432
FR-RC-H15K	330	562	10	270	582
FR-RC-30K					
FR-RC-H30K					
FR-RC-55K	470	642	12	410	670
FR-RC-H55K					

12.5 Power regenerative common converter

POINT

- Use the FR-CV for the servo amplifier of 200V class and the FR-CV-H for that of 400V class.
- For details of the power regenerative common converter FR-CV-(H), refer to the FR-CV-(H) Installation Guide (IB(NA)0600075).
- Do not supply power to the main circuit power supply terminals (L_1, L_2, L_3) of the servo amplifier. Doing so will fail the servo amplifier and FR-CV-(H).
- Connect the DC power supply between the FR-CV-(H) and servo amplifier with correct polarity. Connection with incorrect polarity will fail the FR-CV-(H) and servo amplifier.
- Two or more FR-CV-(H)'s cannot be installed to improve regeneration capability. Two or more FR-CV-(H)'s cannot be connected to the same DC power supply line.

When using the power regenerative common converter, set parameter No.PA02 to "□□01".

(1) Model

FR－CV－□□

Capacity

Symbol	Capacity [kW]
7.5k	7.5
11k	11
15k	15
22k	22
30k	30
37k	37
55k	55

Symbol	Voltage class
None	200VAC class
H	400VAC class

(2) Selection

The power regenerative common converter FR-CV can be used for the servo amplifier of 200VAC class with 750 to 22kW and that of 400VAC class with 11k to 22kW. The following shows the restrictions on using the FR-CV-(H).

(a) Up to six servo amplifiers can be connected to one FR-CV-(H).

(b) FR-CV-(H) capacity [W] Total of rated capacities [W] of servo amplifiers connected to FR-CV-(H).

(c) The total of used servo motor rated currents should be equal to or less than the applicable current [A] of the FR-CV-(H).

(d) Among the servo amplifiers connected to the FR-CV-(H), the servo amplifier of the maximum capacity should be equal to or less than the maximum connectable capacity [W].

The following table lists the restrictions.

Item	FR-CV-☐						
	7.5K	11K	15K	22K	30K	37K	55K
Maximum number of connected servo amplifiers	6						
Total of connectable servo amplifier capacities [kW]	3.75	5.5	7.5	11	15	18.5	27.5
Total of connectable servo motor rated currents [A]	33	46	61	90	115	145	215
Maximum servo amplifier capacity [kW]	3.5	5	7	11	15	15	22

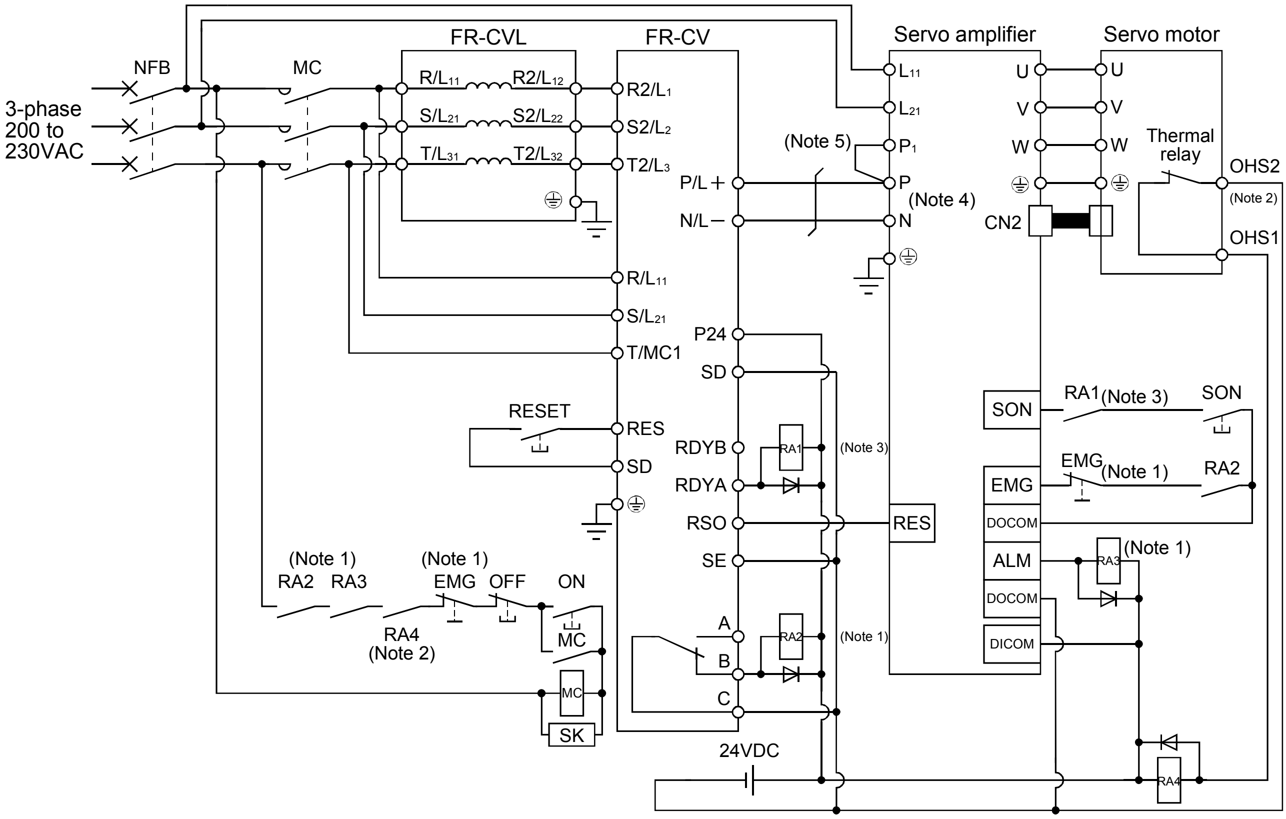
Item	FR-CV-H☐			
	22K	30K	37K	55K
Maximum number of connected servo amplifiers	6			
Total of connectable servo amplifier capacities [kW]	11	15	18.5	27.5
Total of connectable servo motor rated currents [A]	90	115	145	215
Maximum servo amplifier capacity [kW]	11	15	15	22

When using the FR-CV-(H), always install the dedicated stand-alone reactor (FR-CVL-(H)).

Power regenerative common converter	Dedicated stand-alone reactor
FR-CV-7.5K (-AT)	FR-CVL-7.5K
FR-CV-11 K (-AT)	FR-CVL-11K
FR-CV-15K (-AT)	FR-CVL-15K
FR-CV-22K (-AT)	FR-CVL-22K
FR-CV-30K (-AT)	FR-CVL-30K
FR-CV-37K	FR-CVL-37K
FR-CV-55K	FR-CVL-55K
FR-CV-H22K (-AT)	FR-CVL-H22K
FR-CV-H30K (-AT)	FR-CVL-H30K
FR-CV-H37K	FR-CVL-H37K
FR-CV-H55K	FR-CVL-H55K

(3) Connection diagram

(a) 200V class



Note 1. Configure a sequence that will shut off main circuit power at an emergency stop or at FR-CV or servo amplifier alarm occurrence.

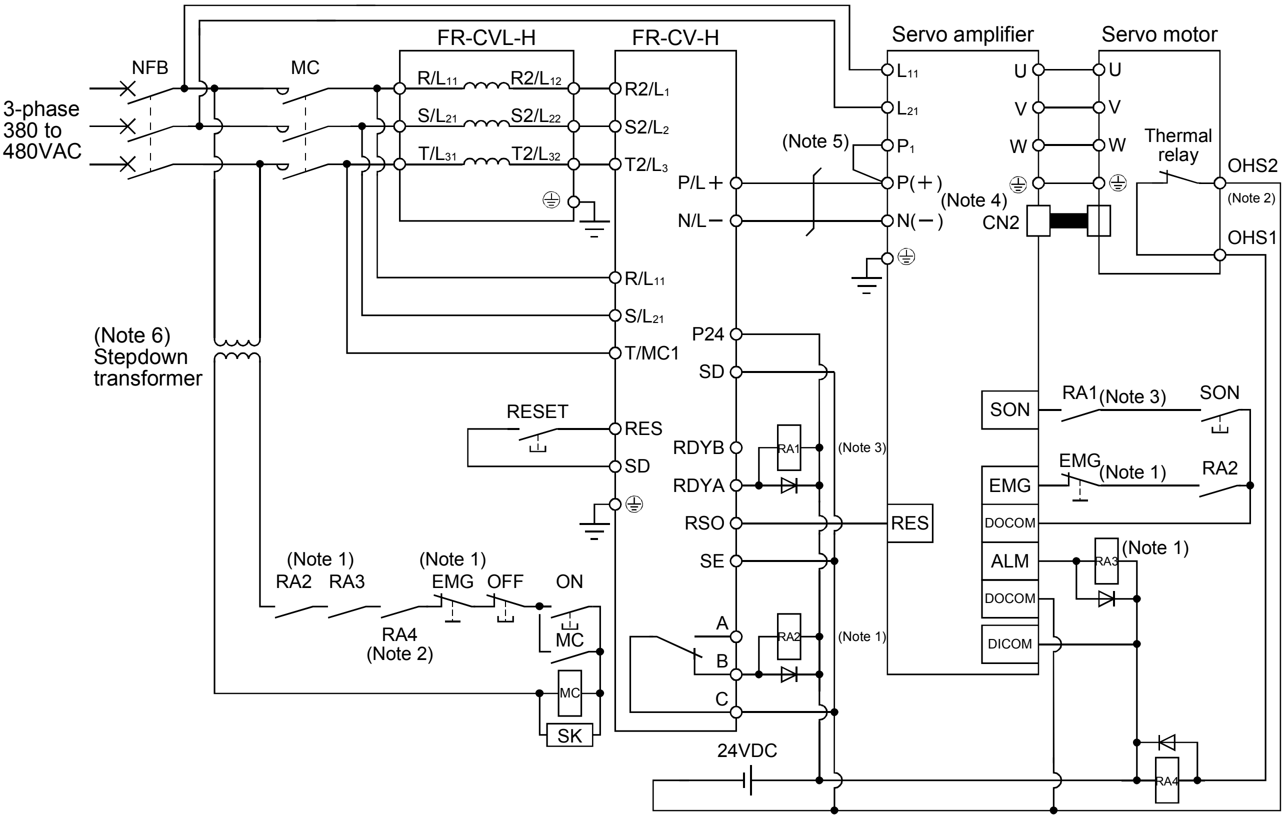
2. For the servo motor with thermal relay, configure a sequence that will shut off main circuit power when the thermal relay operates.

3. For the servo amplifier, configure a sequence that will switch the servo on after the FR-CV is ready.

4. When using the servo amplifier of 7kW or less, make sure to disconnect the wiring of built-in regenerative resistor (3.5kW or less: P-D, 5k/7kW: P-C).

5. When using the servo amplifier of 11k to 22kW, make sure to connect P_1 and P. (Factory-wired.)

(b) 400V class



Note 1. Configure a sequence that will shut off main circuit power at an emergency stop or at FR-CV-H or servo amplifier alarm occurrence.

2. For the servo motor with thermal relay, configure a sequence that will shut off main circuit power when the thermal relay operates.

3. For the servo amplifier, configure a sequence that will switch the servo on after the FR-CV-H is ready.

4. When using the servo amplifier of 7kW or less, make sure to disconnect the wiring of built-in regenerative resistor (2kW or less: P-D, 3.5k to 7kW: P-C.

5. When using the servo amplifier of 11k to 22kW, make sure to connect P_1 and P. (Factory-wired.)

6. Stepdown transformer is required for coil voltage of magnetic contactor more than 200V class servo amplifiers.

(4) Selection example of wires used for wiring

POINT

- Selection condition of wire size is as follows.
  Wire type: 600V Polyvinyl chloride insulated wire (IV wire)
  Construction condition: One wire is constructed in the air

(a) Wire sizes

1) Across P-P (＋), N-N (－)

The following table indicates the connection wire sizes of the DC power supply (P, N terminals) between the FR-CV and servo amplifier.

Total of servo amplifier capacities [kW]	Wires [mm^2]
1 or less	2
2	3.5
5	5.5
7	8
11	14
15	22
22	50

The following table indicates the connection wire sizes of the DC power supply (P (＋), N (－) terminals) between the FR-CV-H and servo amplifier.

Total of servo amplifier capacities [kW]	Wires [mm^2]
1 or less	2
2	3.5
5	5.5
7	8
11	8
15	22
22	22

2) Grounding

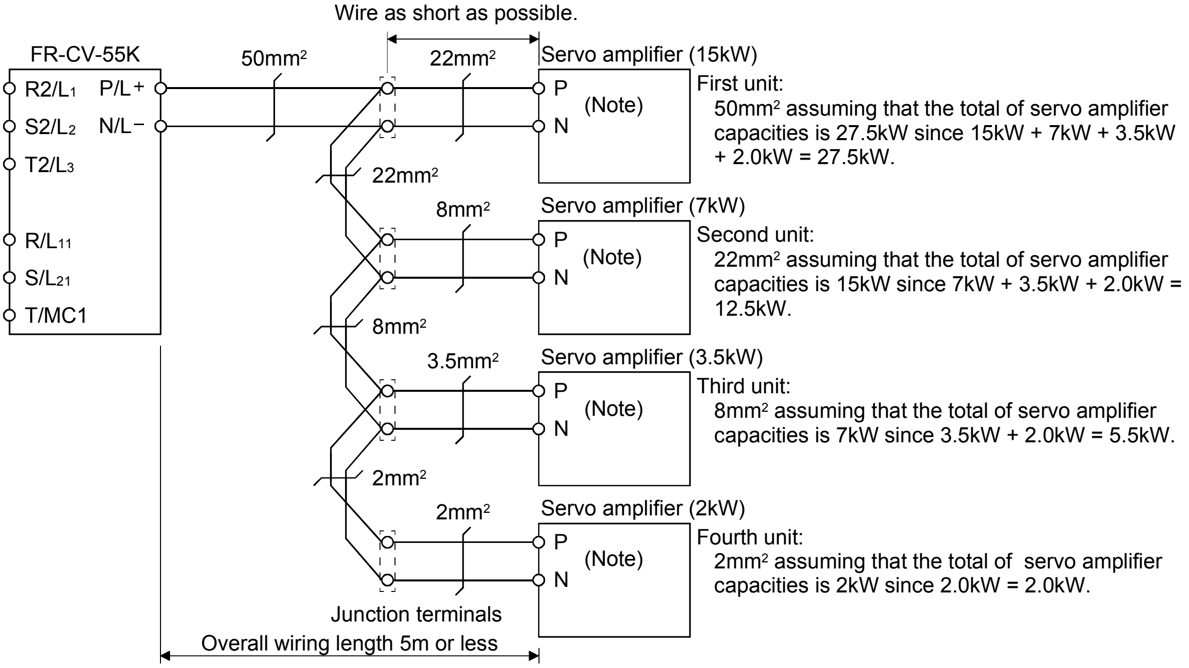
For grounding, use the wire of the size equal to or greater than that indicated in the following table, and make it as short as possible.

Power regenerative common converter	Grounding wire size [mm^2]
FR-CV-7.5K to FR-CV-15K	14
FR-CV-22K・FR-CV-30K	22
FR-CV-37K・FR-CV-55K	38
FR-CV-H22K・FR-CV-H30K	8
FR-CV-H37K・FR-CV-H55K	22

(b) Example of selecting the wire sizes

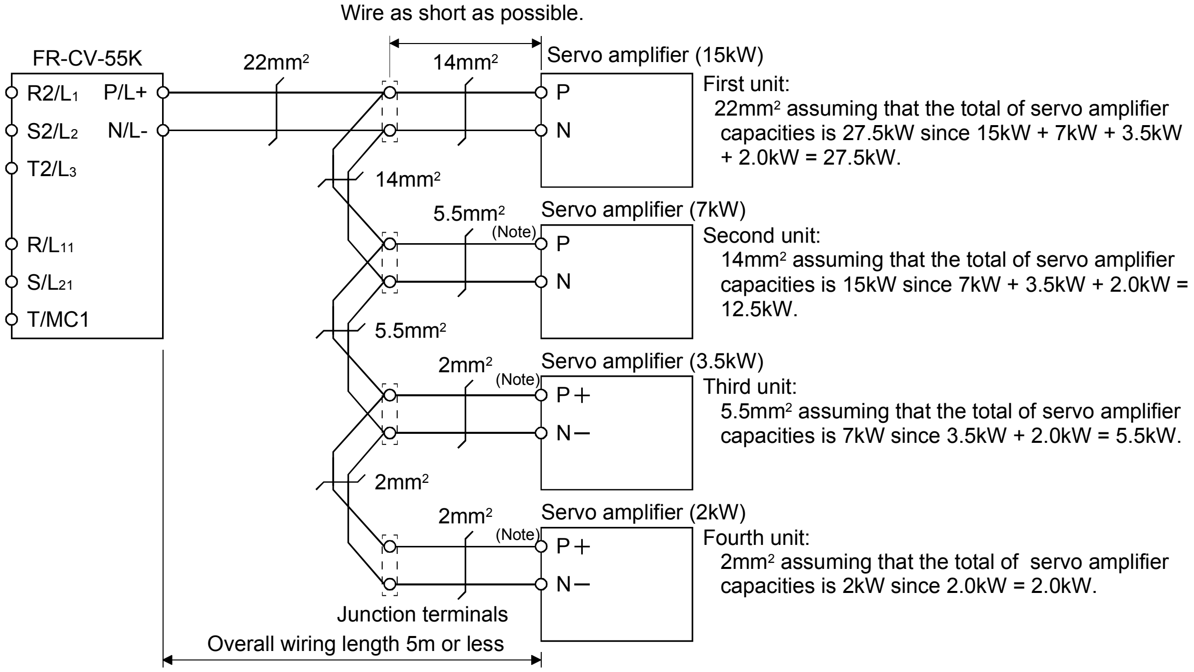
When connecting multiple servo amplifiers, always use junction terminals for wiring the servo amplifier terminals P, N. Also, connect the servo amplifiers in the order of larger to smaller capacities.

1) 200V class



Note. When using the servo amplifier of 7kW or less, make sure to disconnect the wiring of built-in regenerative resistor (3.5kW or less: P-D, 5k/7kW: P-C).

2) 400V class



Note. These servo amplifiers are development forecasted.

(5) Other precautions

(a) Always use the dedicated stand-alone reactor (FR-CVL-(H)) as the power factor improving reactor. Do not use power factor improving AC reactor (FR-BAL-(H)) or power factor improving DC reactor (FR-BEL-(H)).

(b) The inputs/outputs (main circuits) of the FR-CV-(H) and servo amplifiers include high-frequency components and may provide electromagnetic wave interference to communication equipment (such as AM radios) used near them. In this case, interference can be reduced by installing the radio noise filter (FR-BIF-(H)) or line noise filter (FR-BSF01, FR-BLF).

(c) The overall wiring length for connection of the DC power supply between the FR-CV-(H) and servo amplifiers should be 5m or less, and the wiring must be twisted.

(6) Specifications

Power regenerative common converter FR-CV-☐ Item			7.5K	11K	15K	22K	30K	37K	55K
Total of connectable servo amplifier capacities [kW]			3.75	5.5	7.5	11	15	18.5	27.5
Maximum servo amplifier capacity [kW]			3.5	5	7	11	15	15	22
Output	Total of connectable servo motor rated currents [A]		33	46	61	90	115	145	215
	Regenerative braking torque	Short-time rating	Total capacity of applicable servo motors, 300% torque, 60s (Note 1)						
		Continuous rating	100% torque						
Power supply	Rated input AC voltage/frequency		3-phase 200 to 220VAC 50Hz, 200 to 230VAC 60Hz						
	Permissible AC voltage fluctuation		3-phase 170 to 242VAC 50Hz, 170 to 253VAC 60Hz						
	Permissible frequency fluctuation		±5%						
	Power supply capacity (Note 2) [kVA]		17	20	28	41	52	66	100
IP rating (JEM 1030), cooling system			Open type (IP00), forced cooling						
Environmental conditions	Ambient temperature		−10 to 50℃ (non-freezing)						
	Ambient humidity		90%RH or less (non-condensing)						
	Ambience		Indoors (without corrosive gas, flammable gas, oil mist, dust and dirt)						
Altitude, vibration			1000m or less above sea level, 5.9m/s^2 or less						
No-fuse breaker or leakage current breaker			30AF 30A	50AF 50A	100AF 75A	100AF 100A	225AF 125A	225AF 125A	225AF 175A
Magnetic contactor			S-N20	S-N35	S-N50	S-N65	S-N95	S-N95	S-N125

Power regenerative common converter FR-CV-H☐ Item			22K	30K	37K	55K
Total of connectable servo amplifier capacities [kW]			11	15	18.5	27.5
Maximum servo amplifier capacity [kW]			11	15	15	22
Output	Total of connectable servo motor rated currents [A]		43	57	71	110
	Regenerative braking torque	Short-time rating	Total capacity of applicable servo motors, 300% torque, 60s (Note 1)			
		Continuous rating	100% torque			
Power supply	Rated input AC Voltage, frequency		3-phase 380 to 480VAC, 50Hz/60Hz			
	Permissible AC voltage fluctuation		3-phase 323 to 528VAC, 50Hz/60Hz			
	Permissible frequency fluctuation		±5%			
	Power supply capacity [kVA]		41	52	66	100
IP rating (JEM 1030), cooling system			Open type (IP00), forced cooling			
Environmental conditions	Ambient temperature		−10 to 50℃ (non-freezing)			
	Ambient humidity		90%RH or less (non-condensing)			
	Ambience		Indoors (without corrosive gas, flammable gas, oil mist, dust and dirt)			
Altitude, vibration			1000m or less above sea level, 5.9m/s^2 or less			
No-fuse breaker or leakage current breaker			60AF 60A	100AF 175A	100AF 175A	225AF 125A
Magnetic contactor			S-N25	S-N35	S-N35	S-N65

Note 1. This is the time when the protective function of the FR-CV-(H) is activated. The protective function of the servo amplifier is activated in the time indicated in section 11.1.

2. When connecting the capacity of connectable servo amplifier, specify the value of servo amplifier.

12.6 External dynamic brake

⚠CAUTION

- Use an external dynamic brake for a servo amplifier of MR-J3-11KA(4) to MR-J3-22KA(4). Failure to do so will cause an accident because the servo motor does not stop immediately but coasts at an emergency stop and such conditions.Ensure the safety in the entire system.

POINT

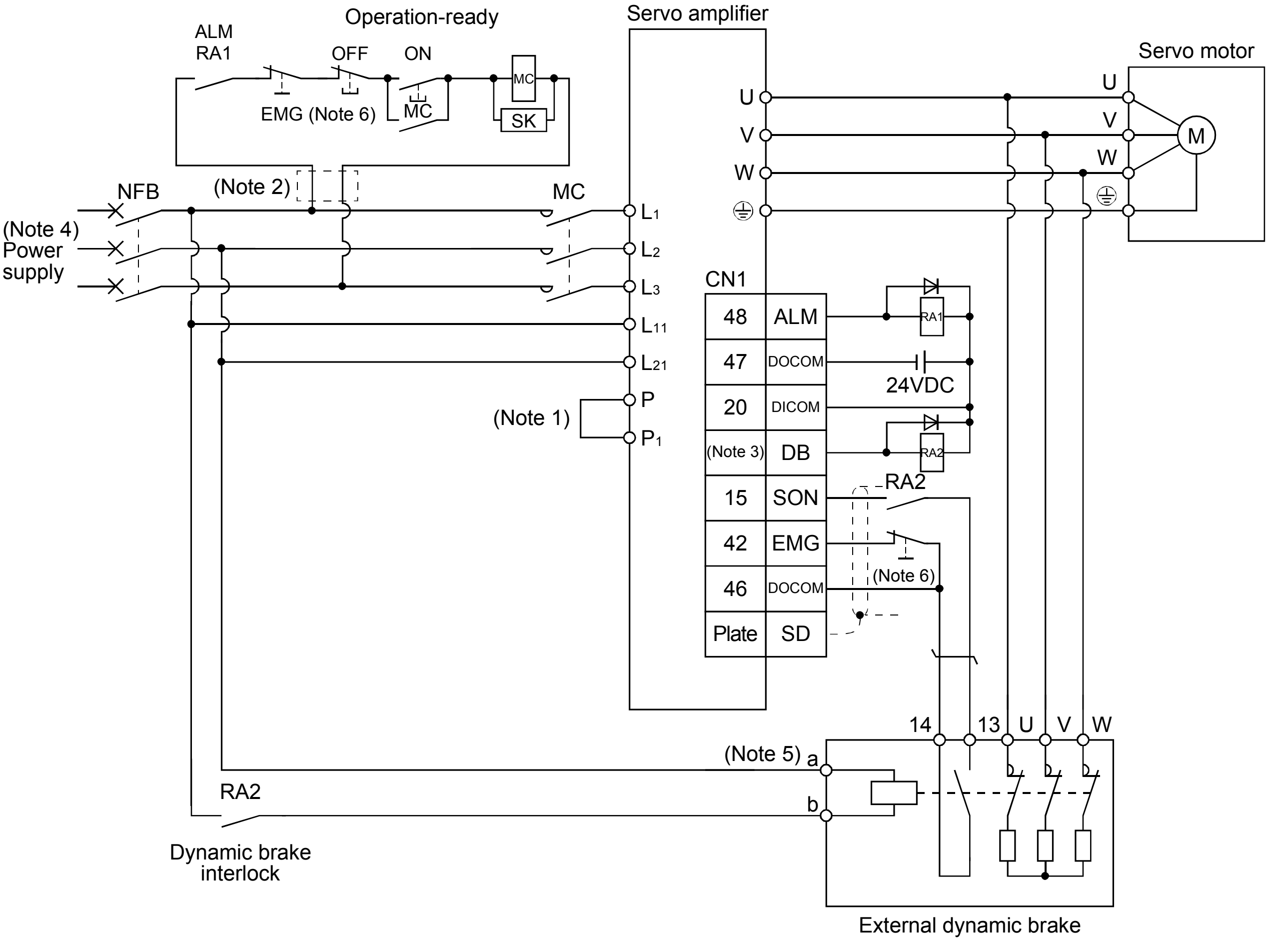
- Configure up a sequence which switches off the magnetic contactor of the brake unit after (or as soon as) the servo on (SON) has been turned off at a power failure or failure.
- For the braking time taken when the dynamic brake is operated, refer to section 11.3.
- The brake unit is rated for a short duration. Do not use it for high duty.
- When using the 400V class dynamic brake, the power supply voltage is restricted to 1-phase 380 to 463VAC (50Hz/60Hz).
- Dynamic brake operates at occurrence of alarm, servo emergency stop warning (AL.E6), and when power is turned off. Do not use dynamic brake to stop in a normal operation as it is the function to stop in emergency.
- Maximum usage time of dynamic brake for a machine operating under recommended load inertia moment ratio is 1000 time while decelerating from rated speed to a stop with frequency of once in 10 minutes.
- Be sure to make emergency stop (EMG) valid after servo motor stops when using emergency stop (EMG) frequently in other than emergency.

(1) Selection of dynamic brake

The dynamic brake is designed to bring the servo motor to a sudden stop when a power failure occurs or the protective circuit is activated, and is built in the 7kW or less servo amplifier. Since it is not built in the 11kW or more servo amplifier, purchase it separately. Assign the dynamic brake interlock (DB) to any of CN1-22 to CN1-25, and CN1-49 pins in parameter No.PD13 to PD16 and PD18.

Servo amplifier	Dynamic brake
MR-J3-11KA	DBU-11K
MR-J3-15KA	DBU-15K
MR-J3-22KA	DBU-22K
MR-J3-11KA4	DBU-11K-4
MR-J3-15KA4	DBU-22K-4
MR-J3-22KA4	

(2) Connection example

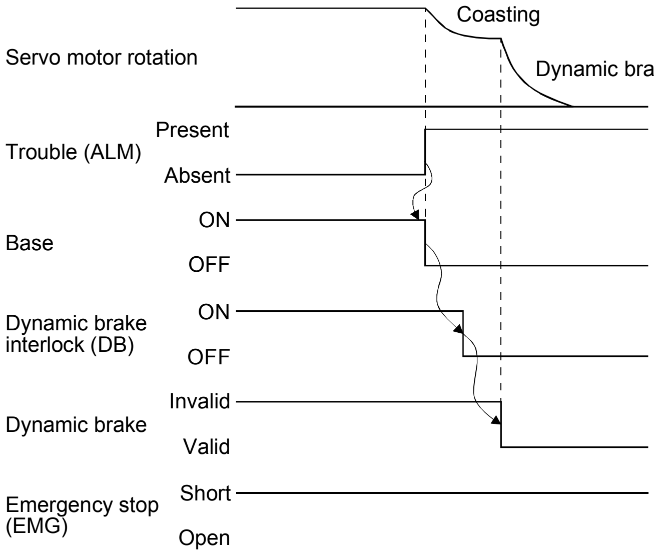


Note 1. For the servo amplifiers from 11k to 22kW, be sure to connect P and P_1. (Factory-wired) When using the power factor DC reactor, refer to section 12.13. Use only one of power factor improving DC reactor or power factor improving AC reactor.

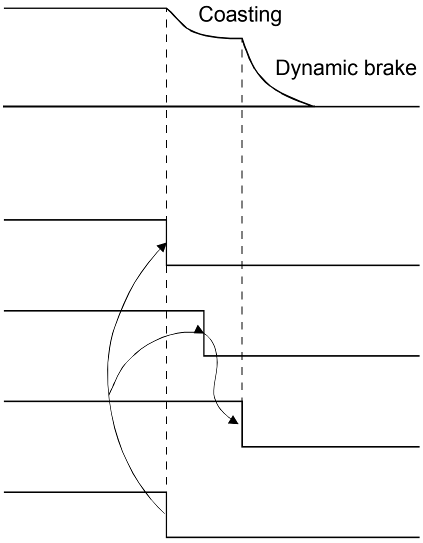
2. For 400VAC class, a step-down transformer is required.
3. Assign the dynamic brake interlock (DB) in the parameters No.PD13 to PD18.
4. For the specification of power supply, refer to section 1.3.
5. The power supply voltage of the inside magnet contactor for 400V class dynamic brake DBU-11K-4 and DBU-22K-4 is restricted as follows. When using these dynamic brakes, use them within the range of the power supply.

Dynamic brake	Power supply voltage
DBU-11K-4 DBU-22K-4	1-phase 380 to 463VAC 50Hz/60Hz

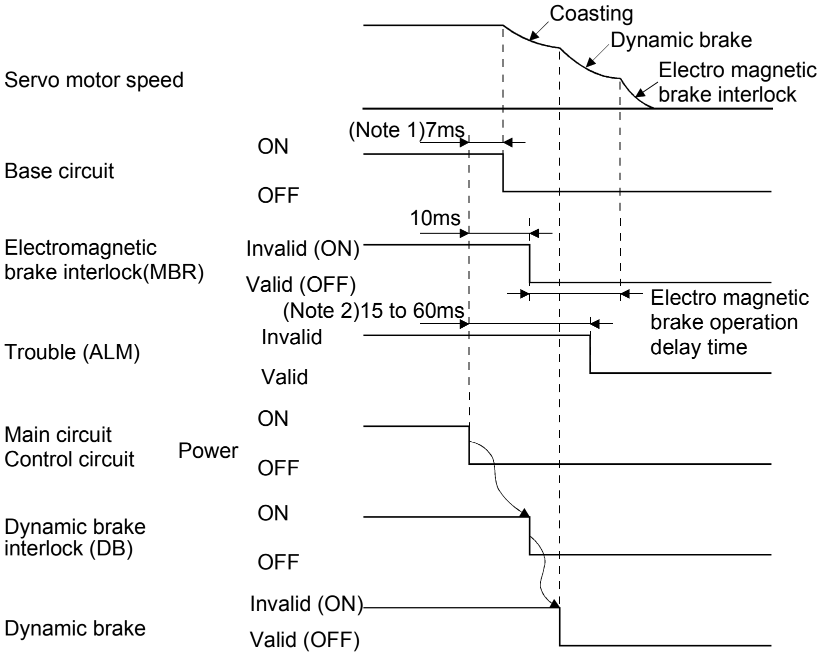
6. Configure the circuit to shut down the main circuit power supply simultaneously with the turn off of emergency stop (EMG) using the external sequence.



a. Timing chart at alarm occurrence



b. Timing chart at Emergency stop (EMG) validity



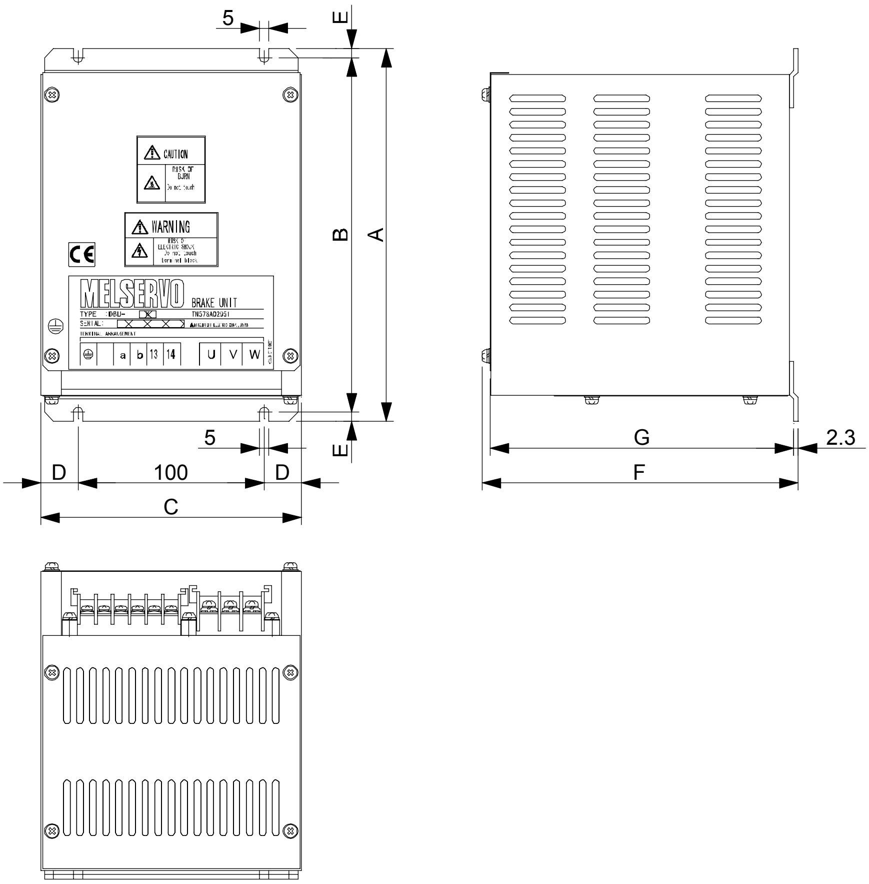
Note 1. When powering OFF, the dynamic brake interlock (DB) will be turned OFF, and the base circuit is turned OFF earlier than usual before an output shortage occurs. (Only when assigning the DB as the output signal in the parameter No.PD13 to PD16 and PD18.)

2. Variable according to the operation status.

c. Timing chart when both of the main and control circuit power are OFF

(3) Outline dimension drawing

(a) DBU-11K・DBU-15K・DBU-22K



Terminal block

E (GND)		a	b	13	14

Screw: M3.5

Tightening torque: 0.8 [N・m](7 [lb・in])

U	V	W

Screw: M4

Tightening torque: 1.2 [N・m](10.6 [lb・in])

Dynamic brake	A	B	C	D	E	F	G	Mass [kg]([lb])	Connection wire [mm^2] (Note)
DBU-11K	200	190	140	20	5	170	163.5	2 (4.41)	5.5
DBU-15K, 22K	250	238	150	25	6	235	228	6 (13.23)	5.5

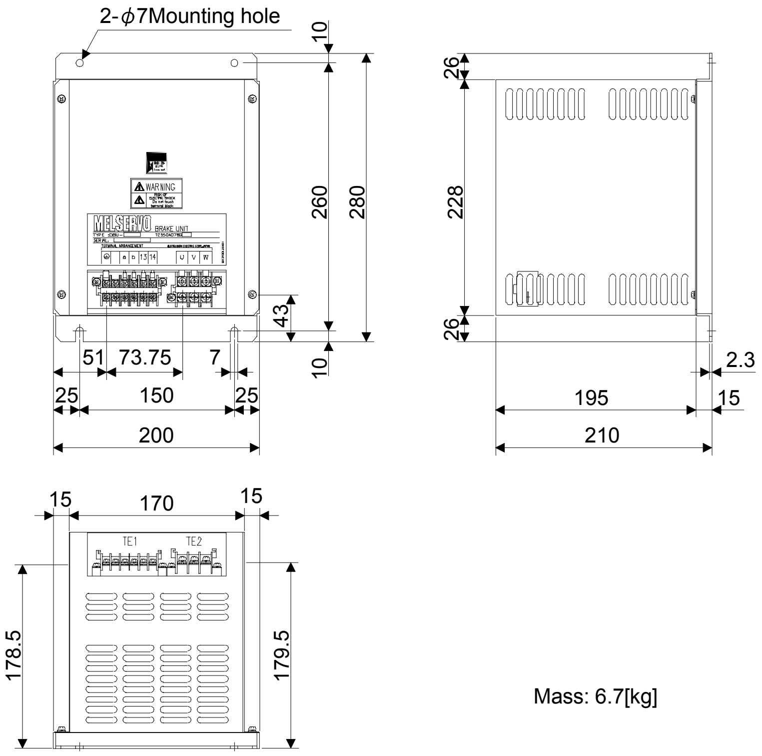
Note. Selection condition of wire size is as follows.

Wire type: 600V Polyvinyl chloride insulated wire (IV wire)

Construction condition: One wire is constructed in the air

(b) DBU-11K-4 ・ DBU-22K-4

[Unit: mm]



Mass: 6.7[kg]

Terminal block

TE1

⏚		a	b	13	14

Screw: M3.5

Tightening torque: 0.8[N・m](7[lb・in])

TE2

U	V	W

Screw: M4

Tightening torque: 1.2[N・m](10.6[lb・in])

Dynamic brake	Wire [mm^2] (Note)	
	a ・ b	U ・ V ・ W
DBU-11K	2	5.5
DBU-15K, 22K	2	5.5

Note. Selection condition of wire size is as follows.

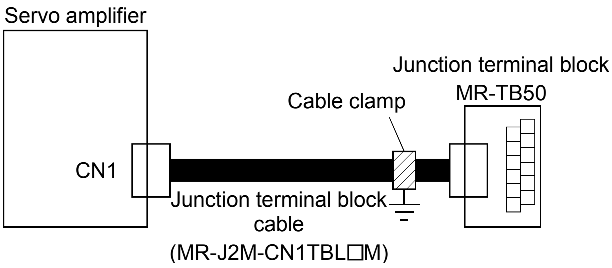
Wire type: 600V Polyvinyl chloride insulated wire (IV wire)

Construction condition: One wire is constructed in the air

12.7 Junction terminal block MR-TB50

(1) How to use the junction terminal block

Always use the junction terminal block (MR-TB50) with the junction terminal block cable (MR-J2M-CN1TBL□M) as a set. A connection example is shown below.



Ground the junction terminal block cable on the junction terminal block side with the standard accessory cable clamp fitting (AERSBAN-ESET). For the use of the cable clamp fitting, refer to section 12.17, (2)(c).

(2) Terminal labels

Use the following junction terminal block labels. This label is supplied with the junction terminal block MR-TB50.

Position control mode

P15R	LG	LAR	LBR	LZR	PG	╲	SON	PC	RES	DICOM	ZSP	TLC	TLA	╲	╲	OP	NP	╲	╲	CR	LSP	LOP	DOCOM	RD
1	3	5	7	9	11	13	15	17	19	21	23	25	27	29	31	33	35	37	39	41	43	45	47	49
	LA	LB	LZ	PP	OPC	╲		TL	DICOM	INP	INP	╲	LG	LG	╲	LG	NG	╲	╲	EMG	LSN	DOCOM	ALM	SD
2	4	6	8	10	12	14	16	18	20	22	24	26	28	30	32	34	36	38	40	42	44	46	48	50

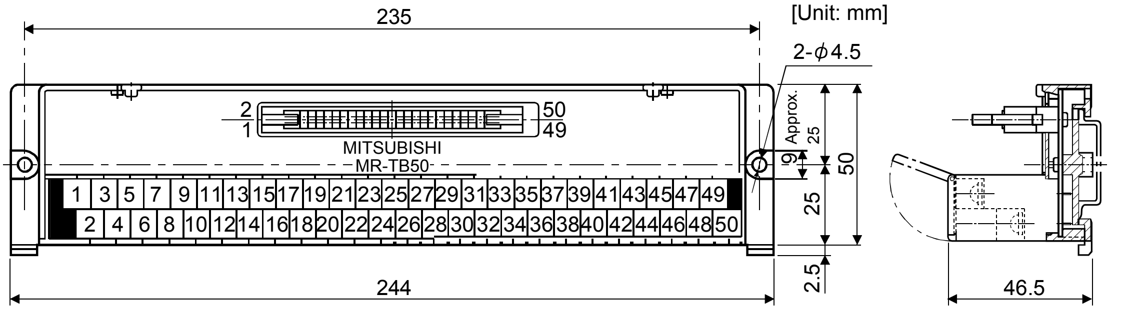
Speed control mode

P15R	LG	LAR	LBR	LZR		╲	SON	ST1	RES	DICOM	ZSP	TLC	TLA	╲	╲	OP		╲	╲	SP1	LSP	LOP	DOCOM	RD
1	3	5	7	9	11	13	15	17	19	21	23	25	27	29	31	33	35	37	39	41	43	45	47	49
VC	LA	LB	LZ			╲	SP2	ST2	DICOM	SA	SA	╲	LG	LG	╲	LG		╲	╲	EMG	LSN	DOCOM	ALM	SD
2	4	6	8	10	12	14	16	18	20	22	24	26	28	30	32	34	36	38	40	42	44	46	48	50

Torque control mode

P15R	LG	LAR	LBR	LZR		╲	SON	RS2	RES	DICOM	ZSP	VLC	TC	╲	╲	OP		╲	╲	SP1		LOP	DOCOM	RD
1	3	5	7	9	11	13	15	17	19	21	23	25	27	29	31	33	35	37	39	41	43	45	47	49
VLA	LA	LB	LZ			╲	SP2	RS1	DICOM			╲	LG	LG	╲	LG		╲	╲	EMG		DOCOM	ALM	SD
2	4	6	8	10	12	14	16	18	20	22	24	26	28	30	32	34	36	38	40	42	44	46	48	50

(3) Outline drawing



Terminal screw: M3.5
Applicable cable: 2mm^2
Crimping terminal width: 7.2mm or less.

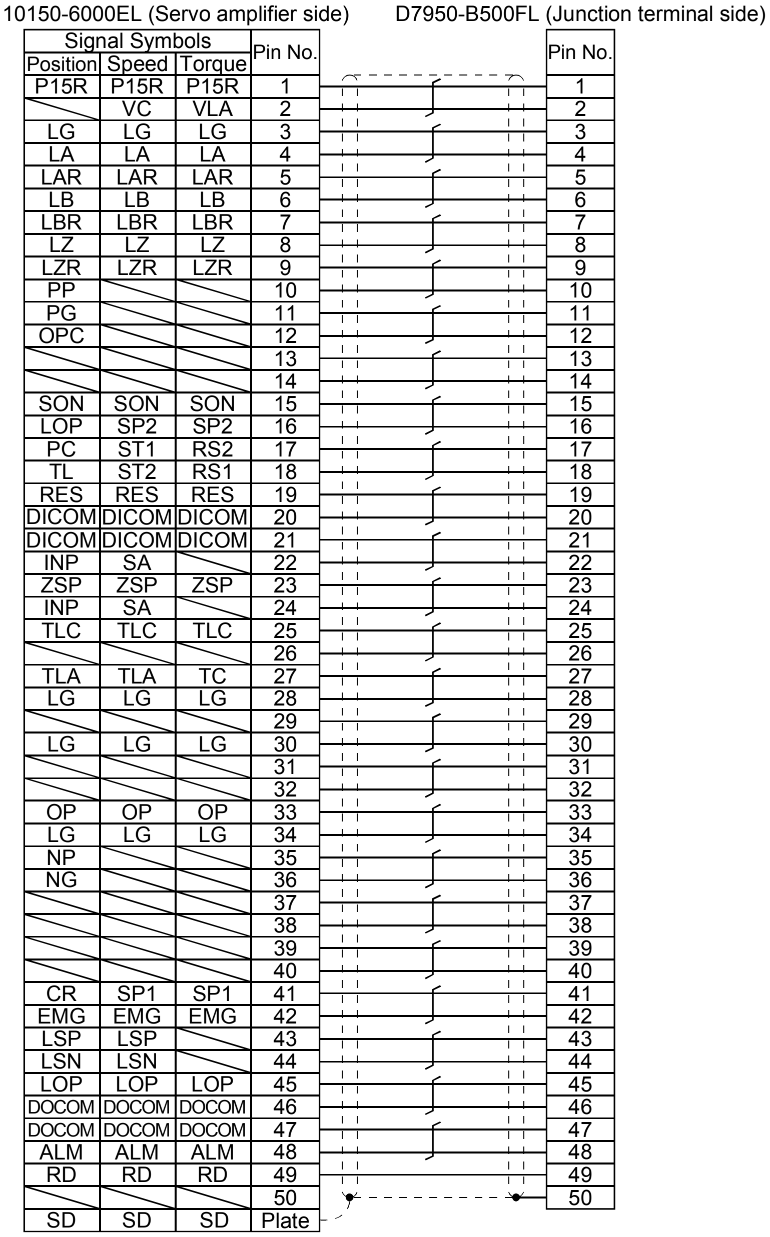
(4) Junction terminal block cable MR-J2M-CN1TBL☐M

(a) Model explanation

Model: MR-J2M-CN1TBL☐M

Symbol	Cable length[m]
05	0.5
1	1

(b) Connection diagram



10150-6000EL (Servo amplifier side)   D7950-B500FL (Junction terminal side)

Signal Symbols			Pin No.	Pin No.
Position	Speed	Torque		
P15R	P15R	P15R	1	1
	VC	VLA	2	2
LG	LG	LG	3	3
LA	LA	LA	4	4
LAR	LAR	LAR	5	5
LB	LB	LB	6	6
LBR	LBR	LBR	7	7
LZ	LZ	LZ	8	8
LZR	LZR	LZR	9	9
PP			10	10
PG			11	11
OPC			12	12
			13	13
			14	14
SON	SON	SON	15	15
LOP	SP2	SP2	16	16
PC	ST1	RS2	17	17
TL	ST2	RS1	18	18
RES	RES	RES	19	19
DICOM	DICOM	DICOM	20	20
DICOM	DICOM	DICOM	21	21
INP	SA		22	22
ZSP	ZSP	ZSP	23	23
INP	SA		24	24
TLC	TLC	TLC	25	25
			26	26
TLA	TLA	TC	27	27
LG	LG	LG	28	28
			29	29
LG	LG	LG	30	30
			31	31
			32	32
OP	OP	OP	33	33
LG	LG	LG	34	34
NP			35	35
NG			36	36
			37	37
			38	38
			39	39
			40	40
CR	SP1	SP1	41	41
EMG	EMG	EMG	42	42
LSP	LSP		43	43
LSN	LSN		44	44
LOP	LOP	LOP	45	45
DOCOM	DOCOM	DOCOM	46	46
DOCOM	DOCOM	DOCOM	47	47
ALM	ALM	ALM	48	48
RD	RD	RD	49	49
			50	50
SD	SD	SD	Plate	

12.8 MR Configurator

The MR Configurator uses the communication function of the servo amplifier to perform parameter setting changes, graph display, test operation, etc. on a personal computer.

(1) Specifications

<table>
<tr><th>Item</th><th>Description</th></tr>
<tr><td>Compatibility with a servo amplifier</td><td>The following table shows MR Configurator software version for each servo amplifier.
<table>
<tr><th rowspan="3">Version</th><th colspan="6">Compatible servo amplifier (Drive unit)</th></tr>
<tr><th colspan="3">200V class</th><th colspan="3">400V class</th></tr>
<tr><th>7kW or less</th><th>11k to 22kW</th><th>30k to 37kW</th><th>7kW or less</th><th>11k to 22kW</th><th>30k to 55kW</th></tr>
<tr><td>B0 to B2</td><td>○</td><td></td><td></td><td></td><td></td><td></td></tr>
<tr><td>B3</td><td>○</td><td></td><td></td><td></td><td></td><td></td></tr>
<tr><td>B4</td><td>○</td><td>○</td><td></td><td></td><td>○</td><td></td></tr>
<tr><td>B5</td><td>○</td><td>○</td><td>○</td><td></td><td>○</td><td>○</td></tr>
<tr><td>B8 or later</td><td>○</td><td>○</td><td>○</td><td>○</td><td>○</td><td>○</td></tr>
</table></td></tr>
<tr><td>Baud rate [bps]</td><td>115200, 57600, 38400, 19200, 9600</td></tr>
<tr><td>Monitor</td><td>Display, high speed monitor, trend graph
Minimum resolution changes with the processing speed of the personal computer.</td></tr>
<tr><td>Alarm</td><td>Display, history, amplifier data</td></tr>
<tr><td>Diagnostic</td><td>Digital I/O, no motor rotation, total power-on time, amplifier version info, motor information, tuning data, absolute encoder data, automatic voltage control, Axis name setting.</td></tr>
<tr><td>Parameters</td><td>Parameter list, turning, change list, detailed information</td></tr>
<tr><td>Test operation</td><td>JOG operation, positioning operation, motor-less operation, Do forced output, program operation.</td></tr>
<tr><td>Advanced function</td><td>Machine analyzer, gain search, machine simulation, robust disturbance compensation, advanced gain search.</td></tr>
<tr><td>File operation</td><td>Data read, save, delete, print</td></tr>
<tr><td>Others</td><td>Automatic demo, help display</td></tr>
</table>

(2) System configuration

(a) Components

To use this software, the following components are required in addition to the servo amplifier and servo motor.

Equipment		(Note 1) Description
(Note 2, 3) Personal computer	OS	IBM PC/AT compatible where the English version of Windows® 98, Windows® Me, Windows® 2000 Professional, Windows® XP Professional, Windows® XP Home Edition, Windows Vista® Home Basic, Windows Vista® Home Premium, Windows Vista® Business, Windows Vista® Ultimate, Windows Vista® Enterprise operates
	Processor	Pentium® 133MHz or more (Windows® 98, Windows® 2000 Professional) Pentium® 150MHz or more (Windows® Me) Pentium® 300MHz or more (Windows® XP Professional, Windows® XP Home Edition) 32-bit (x86) processor of 1GHz or higher (Windows Vista® Home Basic, Windows Vista® Home Premium, Windows Vista® Business, Windows Vista® Ultimate, Windows Vista® Enterprise)
	Memory	24MB or more (Windows® 98) 32MB or more (Windows® Me, Windows® 2000 Professional) 128MB or more (Windows® XP Professional, Windows® XP Home Edition) 512MB or more (Windows Vista® Home Basic) 1GB or more (Windows Vista® Home Premium, Windows Vista® Business, Windows Vista® Ultimate, Windows Vista® Enterprise)
	Hard Disk	130MB or more of free space
Browser		Internet Explorer 4.0 or more
Display		One whose resolution is 1024×768 or more and that can provide a high color (16 bit) display. Connectable with the above personal computer.
Keyboard		Connectable with the above personal computer.
Mouse		Connectable with the above personal computer.
Printer		Connectable with the above personal computer.
USB cable		MR-J3USBCBL3M
RS-422/232C conversion cable		DSV-CABV (Diatrend) is recommended.

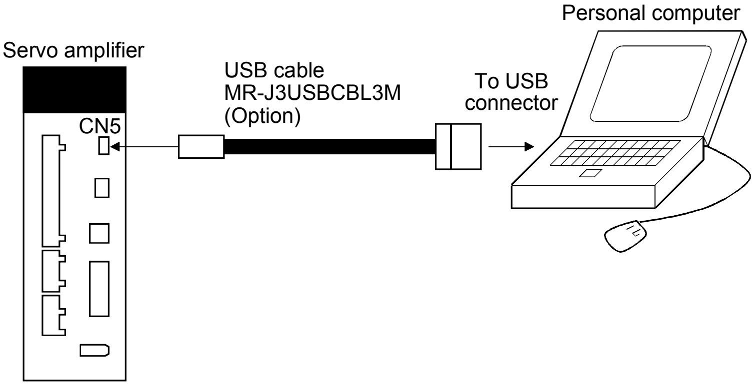
Note 1. Windows and Windows Vista is the registered trademarks of Microsoft Corporation in the United States and other countries. Pentium is the registered trademarks of Intel Corporation.

2. On some personal computers, MR Configurator may not run properly.

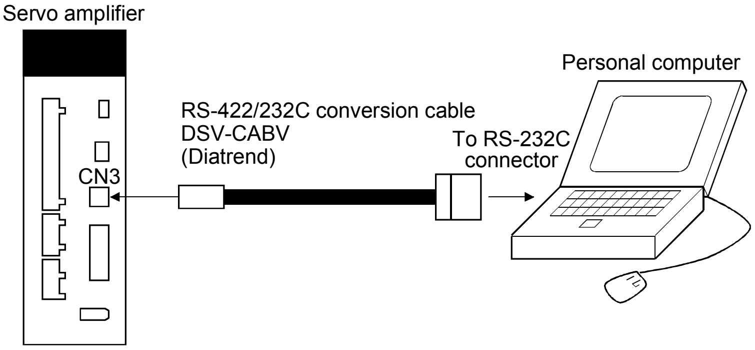
3. 64-bit Windows XP and 64-bit Windows Vista are not supported.

(b) Connection with servo amplifier

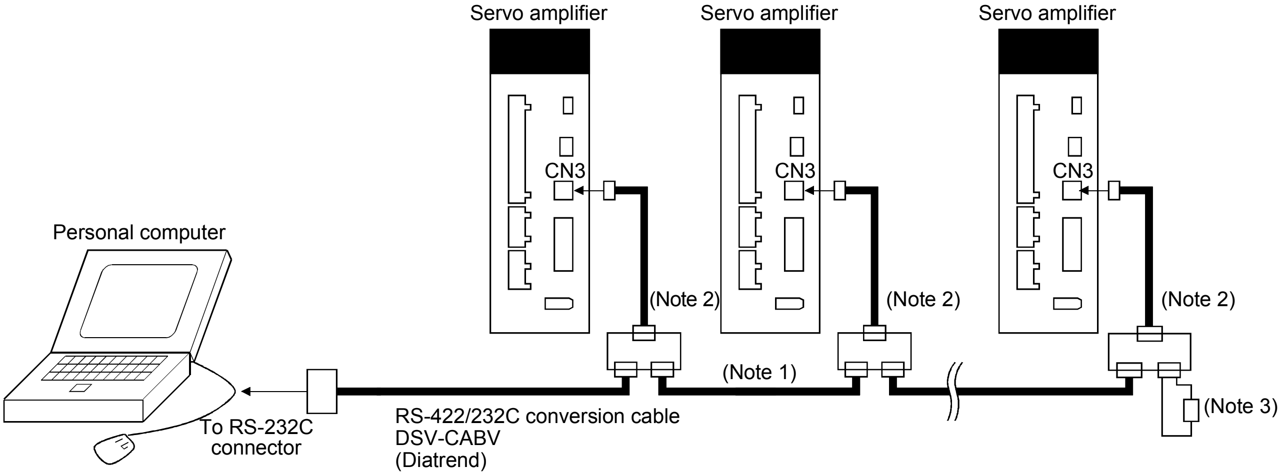
1) For use of USB



2) For use of RS-422



3) For use of RS-422 to make multidrop connection



Note 1. Refer to section 13.1 for cable wiring.

2. The BMJ-8 (Hakko Electric Machine Works) is recommended as the branch connector.

3. The final axis must be terminated between RDP (pin No.3) and RDN (pin No.6) on the receiving side (servo amplifier) with a 150Ω resistor.

(c) To diagnose the trouble using diagnosis cable (MR-J3ACHECK)

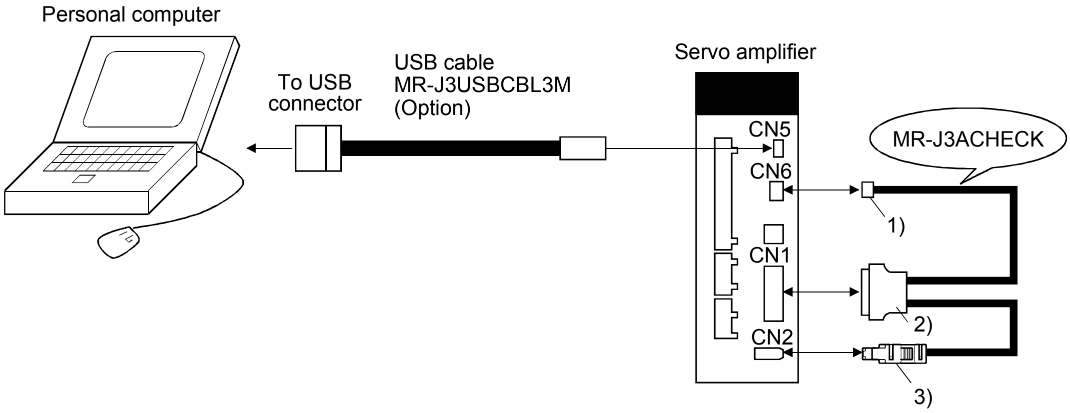
POINT

- The amplifier diagnosis function can be used with the following software versions of the servo amplifier.
  Servo amplifier: A1 or later
  MR Configurator: A1 or later
- Turn the power on after all connectors are connected.
  Do not connect or disconnect connectors after the power is turned on. Otherwise failure will be caused.

This cable is a diagnosis cable of the servo amplifier. The amplifier diagnosis function of MR Configurator can be used when this cable is used.

Cable model	Application
MR-J3ACHECK	Amplifier diagnosis cable for MR Configurator.

Connection between the servo amplifier and servo motor is shown in the figure below.



Cable model	1) For CN6 connector	2) For CN1 connector	3) For CN2 connector
MR-J3ACHECK	Housing: 51004-0300 Contact: 50011-8000 (Molex)	Plug: 10150-3000PE Shell kit: 10350-52F0-008 (3M)	Receptacle: 36210-0100PL Shell kit: 36310-3200-008 (3M or equivalent)

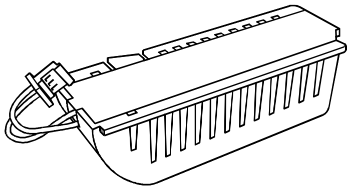
12.9 Battery unit MR-J3BAT

POINT

- Refer to appendix 7 and 8 for battery transportation and the new EU Battery Directive.

(1) Purpose of use for MR-J3BAT

This battery is used to construct an absolute position detection system. Refer to section 14.3 for the fitting method, etc.

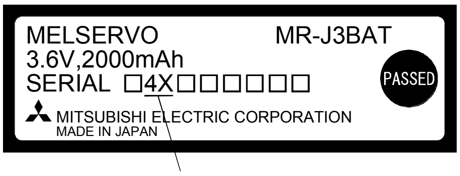


(2) Year and month when MR-J3BAT is manufactured

Production year and month of the MR-J3BAT are indicated in a serial number on the rating plate of the battery back face.

The year and month of manufacture are indicated by the last one digit of the year and 1 to 9, X(10), Y(11), Z(12).

For October 2004, the Serial No. is like, "SERIAL□4X□□□□□□".



MELSERVO MR-J3BAT
3.6V,2000mAh
SERIAL □4X□□□□□□
MITSUBISHI ELECTRIC CORPORATION
MADE IN JAPAN

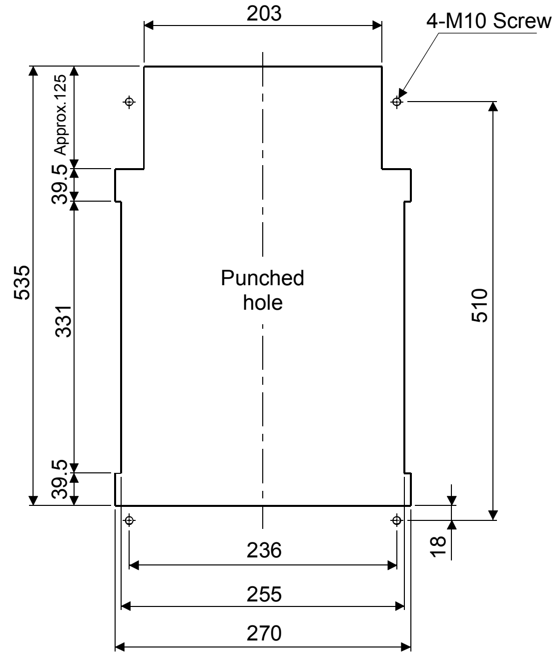
The year and month of manufacture

12.10 Heat sink outside mounting attachment (MR-J3ACN)

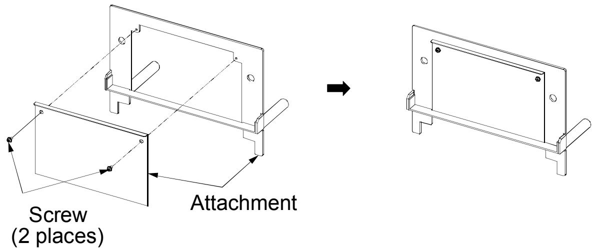
Use the heat sink outside mounting attachment to mount the heat generation area of the servo amplifier in the outside of the control box to dissipate servo amplifier-generated heat to the outside of the box and reduce the amount of heat generated in the box, thereby allowing a compact control box to be designed.
In the control box, machine a hole having the panel cut dimensions, fit the heat sink outside mounting attachment to the servo amplifier with the fitting screws (4 screws supplied), and install the servo amplifier to the control box.
The environment outside the control box when using the heat sink outside mounting attachment should be within the range of the servo amplifier operating environment conditions.
The heat sink outside mounting attachment of MR-J3ACN can be used for MR-J3-11KA(4) to MR-J3-22KA(4).

(1) Panel cut dimensions

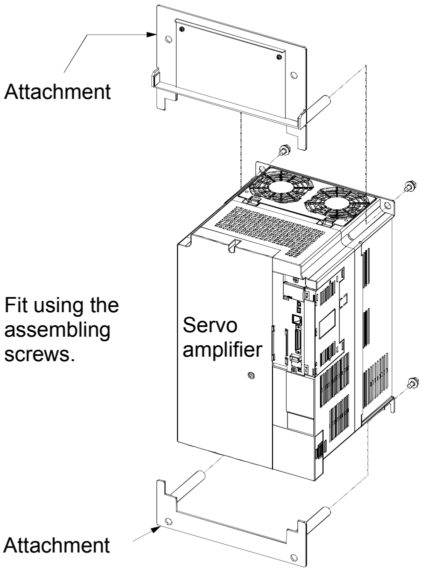
[Unit : mm]



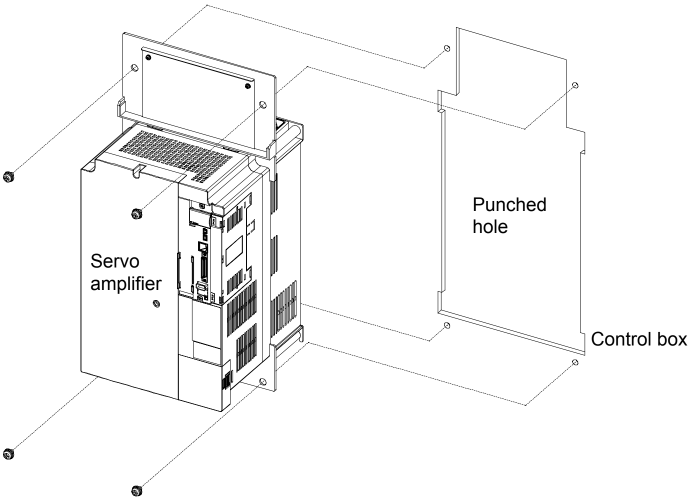
(2) How to assemble the attachment for a heat sink outside mounting attachment



(3) Fitting method



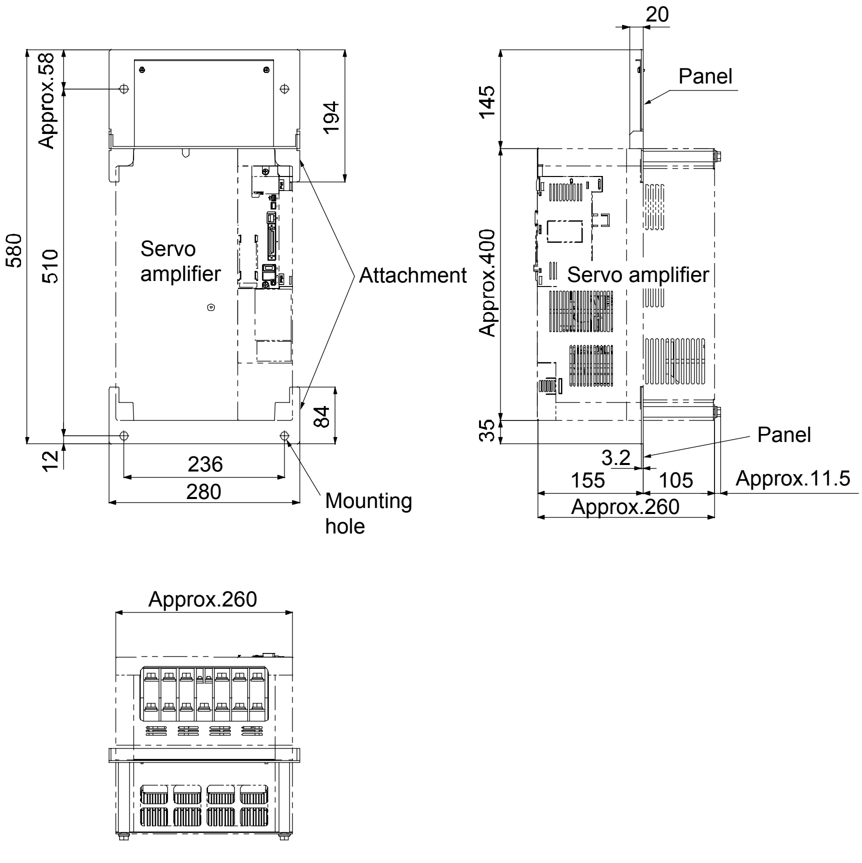
a. Assembling the heat sink outside mounting attachment



b. Installation to the control box

(4) Outline dimension drawing

[Unit: mm]



12.11 Selection example of wires

POINT

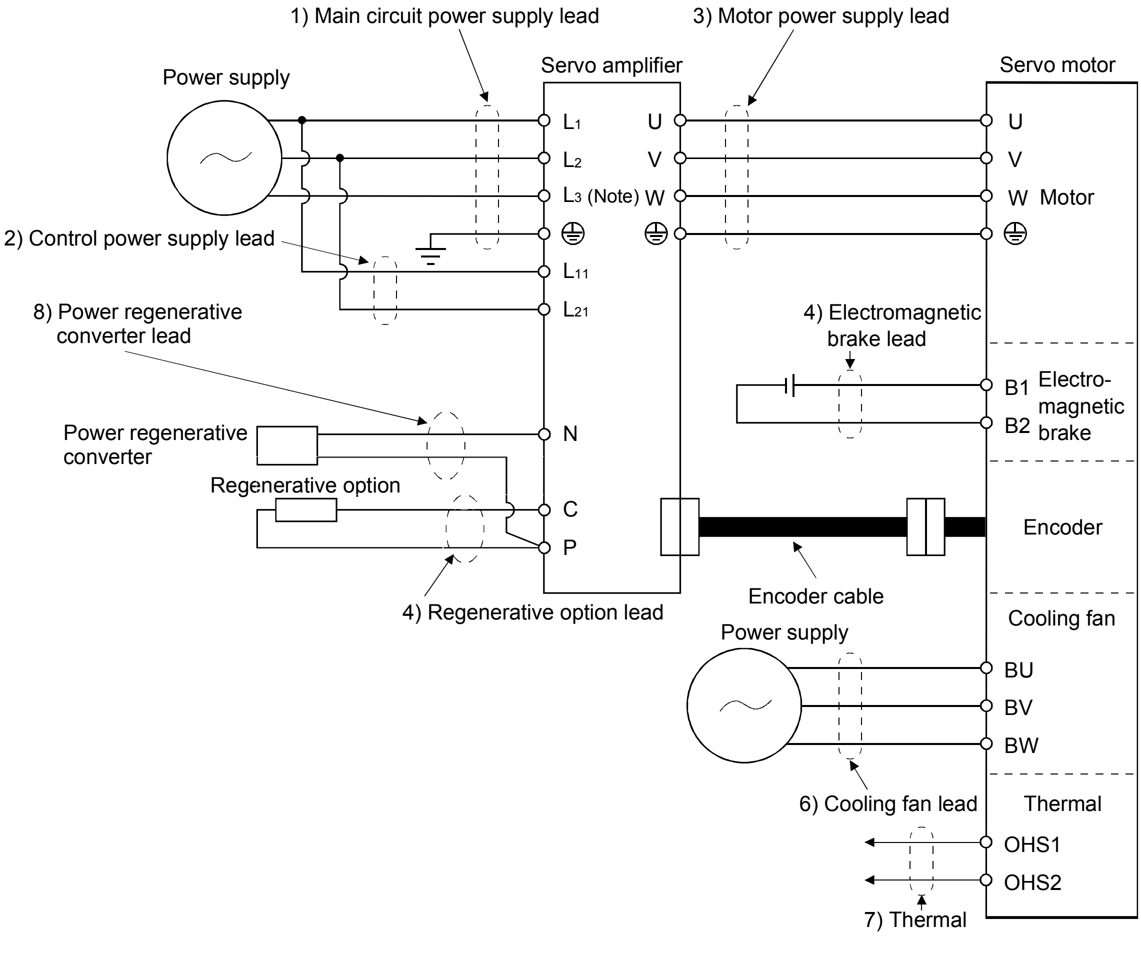
- Wires indicated in this section are separated wires. When using a cable for power line (U, V, and W) between the servo amplifier and servo motor, use a 600V grade EP rubber insulated chloroprene sheath cab-tire cable (2PNCT). For selection of cables, refer to appendix 6.
- To comply with the UL/CSA Standard, use the wires shown in appendix 10 for wiring. To comply with other standards, use a wire that is complied with each standard.
- Selection condition of wire size is as follows.
  Construction condition: One wire is constructed in the air
  Wire length: 30m or less

(1) Wires for power supply wiring

POINT

- Always use the 600V grade heat-resistant polyvinyl chloride insulated wire (HIV wire) when using the HF-JP series servo motor.

The following diagram shows the wires used for wiring. Use the wires given in this section or equivalent.



Note. There is no L_3 for 1-phase 100 to 120VAC power supply.

(a) When using the 600V Polyvinyl chloride insulated wire (IV wire)

Selection example of wire size when using IV wires is indicated below.

Table 12.1 Wire size selection example 1 (IV wire)

Servo amplifier	Wires [mm^2] (Note 1, 4)						
	1) L1・L2・L3・⏚	2) L11・L21	3) U・V・W・⏚	4) P・C	5) B1・B2	6) BU・BV・BW	7) OHS1・OHS2
MR-J3-10A(1)	2(AWG14)	1.25(AWG16)	1.25(AWG16)	2(AWG14)	1.25(AWG16)		
MR-J3-20A(1)							
MR-J3-40A(1)							
MR-J3-60A							
MR-J3-70A							
MR-J3-100A			2(AWG14)				
MR-J3-200A							
MR-J3-350A	3.5(AWG12)		3.5(AWG12)				
MR-J3-500A (Note 2)	5.5(AWG10): a	1.25(AWG16): h	5.5(AWG10): a	2(AWG14): g			
MR-J3-700A (Note 2)	8(AWG8): b		8(AWG8): b	3.5(AWG12): a		2(AWG14) (Note 3)	1.25(AWG16) (Note 3)
MR-J3-11KA (Note 2)	14(AWG6): c	1.25(AWG16): g	22(AWG4): d	5.5(AWG10): j		2(AWG14)	1.25(AWG16)
MR-J3-15KA (Note 2)	22(AWG4): d		30(AWG2): e				
MR-J3-22KA (Note 2)	50(AWG1/0): f		60(AWG2/0): f	5.5(AWG10): k			
MR-J3-60A4	2(AWG14)	1.25(AWG16)	1.25(AWG16)	2(AWG14)			
MR-J3-100A4							
MR-J3-200A4			2(AWG14)				
MR-J3-350A4	2(AWG14): g	1.25(AWG16): h	2(AWG14): g	2(AWG14): g			
MR-J3-500A4 (Note 2)	5.5(AWG10): a		5.5(AWG10): a				
MR-J3-700A4 (Note 2)						2(AWG14) (Note 3)	1.25(AWG16) (Note 3)
MR-J3-11KA4 (Note 2)	8(AWG8): l	1.25(AWG16): g	8(AWG8): l	3.5(AWG12): j		2(AWG14)	1.25(AWG16)
MR-J3-15KA4 (Note 2)	14(AWG6): c		22(AWG4): d	5.5(AWG10): j			
MR-J3-22KA4 (Note 2)	14(AWG6): m		22(AWG4): n	5.5(AWG10): k			

Note 1. Alphabets in the table indicate crimping tools. For crimping terminals and applicable tools, refer to (1) (c) in this section.

2. When connecting to the terminal block, be sure to use the screws which are provided with the terminal block.

3. For the servo motor with a cooling fan.

4. Wires are selected based on the highest rated current among combining servo motors.

Use wires 8) of the following sizes with the power regenerative converter (FR-RC-(H)).

Model	Wires [mm^2]
FR-RC-15K	14(AWG6)
FR-RC-30K	14(AWG6)
FR-RC-55K	22(AWG4)
FR-RC-H15K	14(AWG6)
FR-RC-H30K	14(AWG6)
FR-RC-H55K	14(AWG6)

(b) When using the 600V Grade heat-resistant polyvinyl chloride insulated wire (HIV wire)

POINT

- Refer to the table 12.3 when using the HF-JP series servo motor of 0.5k to 5kW with the 400% maximum torque setting.

Selection example of wire size when using HIV wires is indicated below. For the wire (8)) for power regenerative converter (FR-RC-(H)), use the IV wire indicated in (1) (a) in this section.

Table 12.2 Wire size selection example 2 (HIV wire)

Servo amplifier	Wires [mm^2] (Note 1, 4)						
	1) L_1・L_2・L_3・⏚	2) L_{11}・L_{21}	3) U・V・W・⏚	4) P・C	5) B1・B2	6) BU・BV・BW	7) OHS1・OHS2
MR-J3-10A(1)	2(AWG14)	1.25(AWG16)	1.25(AWG16)	2(AWG14)	1.25(AWG16)		
MR-J3-20A(1)							
MR-J3-40A(1)							
MR-J3-60A							
MR-J3-70A							
MR-J3-100A			1.25(AWG16)				
MR-J3-200A			2(AWG14)				
MR-J3-350A	3.5(AWG12)		3.5(AWG12)				
MR-J3-500A (Note 2)	5.5(AWG10): a	1.25(AWG16): h	5.5(AWG10): a	2(AWG14): g			
MR-J3-700A (Note 2)	8(AWG8): b		8(AWG8): b	2(AWG14): g		1.25(AWG16) (Note 3)	1.25(AWG16) (Note 3)
MR-J3-11KA (Note 2)	14(AWG6): c	1.25(AWG16): g	14(AWG6): c	3.5(AWG12): j		1.25(AWG16)	1.25(AWG16)
MR-J3-15KA (Note 2)	22(AWG4): d		22(AWG4): d				
MR-J3-22KA (Note 2)	38(AWG1): p		38(AWG1): p	5.5(AWG10): k			
MR-J3-60A4	2(AWG14)	1.25(AWG16)	1.25(AWG16)	2(AWG14)			
MR-J3-100A4							
MR-J3-200A4			2(AWG14)				
MR-J3-350A4	2(AWG14): g	1.25(AWG16): h	2(AWG14): g	2(AWG14): g			
MR-J3-500A4 (Note 2)	3.5(AWG12): a		3.5(AWG12): a				
MR-J3-700A4 (Note 2)			5.5(AWG10): a			1.25(AWG16) (Note 3)	1.25(AWG16) (Note 3)
MR-J3-11KA4 (Note 2)	5.5(AWG10): j	1.25(AWG16): g	8(AWG8): l	2(AWG14): q		1.25(AWG16)	1.25(AWG16)
MR-J3-15KA4 (Note 2)	8(AWG8): l		14(AWG6): c	3.5(AWG12): j			
MR-J3-22KA4 (Note 2)	14(AWG6): m		14(AWG6): m	3.5(AWG12): k			

Note 1. Alphabets in the table indicate crimping tools. For crimping terminals and applicable tools, refer to (1) (c) in this section.

2. When connecting to the terminal block, be sure to use the screws which are provided with the terminal block.

3. For the servo motor with a cooling fan.

4. Wires are selected based on the highest rated current among combining servo motors.

Table 12.3 Wire size selection example 3 (HIV wire) for the HF-JP series with the 400% maximum torque setting

HF-JP☐ servo motor	Servo amplifier	Wire [mm^2] (Note 1)				
		1) L_1・L_2・L_3・⏚	2) L_{11}・L_{21}	3) U・V・W・⏚	4) P・C	5) B1・B2
53	MR-J3-100A	2(AWG14)	1.25(AWG16)	1.25(AWG16)	2(AWG14)	1.25(AWG16)
73	MR-J3-200A					
103						
153	MR-J3-350A	3.5(AWG12)		2(AWG14)		
203						
353	MR-J3-500A (Note 2)	5.5(AWG10): a	1.25(AWG16): h	3.5(AWG12): a	2(AWG14): g	
503	MR-J3-700A (Note 2)	8(AWG8): b		5.5(AWG10): a		
534	MR-J3-100A4	2(AWG14)	1.25(AWG16)	1.25(AWG16)	2(AWG14)	
734	MR-J3-200A4					
1034						
1534	MR-J3-350A4	2(AWG14): g		2(AWG14): g	2(AWG14): g	
2034						
3534	MR-J3-500A4 (Note 2)	3.5(AWG12): a	1.25(AWG16): h			
5034	MR-J3-700A4 (Note 2)			3.5(AWG12): a		

Note 1. Alphabets in the table indicate crimping tools. For crimping terminals and applicable tools, refer to (1) (c) in this section.

2. When connecting to the terminal block, be sure to use the screws which are provided with the terminal block.

(c) Selection example of crimping terminals

Selection example of crimping terminals for the servo amplifier terminal box when using the wires mentioned in (1) (a) and (b) in this section is indicated below.

Symbol	Servo amplifier side crimping terminals				
	(Note 2) Crimping terminal	Applicable tool			Manufacturer
		Body	Head	Dice	
a	FVD5.5-4	YNT-1210S			Japan Solderless Terminals
(Note 1)b	8-4NS	YHT-8S			
c	FVD14-6	YF-1・E-4	YNE-38	DH-122・DH-112	
d	FVD22-6			DH-123・DH-113	
(Note 1)e	38-6	YPT-60-21		TD-124・TD-112	
		YF-1・E-4	YET-60-1		
(Note 1) f	R60-8	YPT-60-21		TD-125・TD-113	
		YF-1・E-4	YET-60-1		
g	FVD2-4	YNT-1614			
h	FVD2-M3				
j	FVD5.5-6	YNT-1210S			
k	FVD5.5-8				
l	FVD8-6	YF-1・E-4	YNE-38	DH-121・DH-111	
m	FVD14-8			DH-122・DH-112	
n	FVD22-8			DH-123・DH-113	
(Note 1) p	R38-8	YPT-60-21		TD-124・TD-112	
		YF-1・E-4	YET-60-1		
q	FVD2-6	YNT-1614			

Note 1. Coat the part of crimping with the insulation tube.

2. Some crimping terminals may not be mounted depending on the size. Make sure to use the recommended ones or equivalent ones.

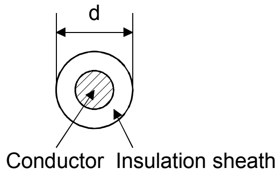
(2) Wires for cables

When fabricating a cable, use the wire models given in the following table or equivalent.

Table 12.3 Wires for option cables

TypeEncoder cable	Model	Length [m]	Core size [mm^2]	Number of Cores	Characteristics of one core			(Note 3) Finishing OD [mm]	Wire model
					Structure [Wires/mm]	Conductor resistance [Ω/mm]	Insulation coating OD d [mm] (Note 1)		
Encoder cable	MR-J3ENCBL□M-A1-L	2 to 10	AWG22	6 (3 pairs)	7/0.26	53 or less	1.2	7.1±0.3	(Note 3) VSVP 7/0.26 (AWG#22 or equivalent)-3P Ban-gi-shi-16823
	MR-J3ENCBL□M-A2-L								
	MR-J3ENCBL□M-A1-H	2 to 10	AWG22	6 (3 pairs)	70/0.08	56 or less	1.2	7.1±0.3	(Note 3) ETFE SVP 70/0.08 (AWG#22 or equivalent)-3P Ban-gi-shi-16824
	MR-J3ENCBL□M-A2-H								
	MR-J3JCBL03M-A1-L	0.3	AWG26	8 (4 pairs)	30/0.08	233 or less	1.2	7.1±0.3	(Note 5) T/2464-1061/II A-SB 4P × 26AWG
	MR-J3JCBL03M-A2-L								
	MR-EKCBL□M-L	2 to 10	0.3mm^2	4 (2 pairs)	12/0.18	65.7 or less	1.3	7.3	(Note 3) 20276 composite 4-pair shielded cable (A-TYPE)
			0.08mm^2	4 (2 pairs)	7/0.127	234 or less	0.67		
		20 ・ 30	0.3mm^2	12 (6 pairs)	12/0.18	63.6 or less	1.2	8.2	UL20276 AWG#23 6pair(BLACK)
	MR-EKCBL□M-H	20	0.2mm^2	12 (6 pairs)	40/0.08	105 or less	0.88	7.2	(Note 3) A14B2343 6P
		30 to 50	0.2mm^2	14 (7 pairs)	40/0.08	105 or less	0.88	8.0	(Note 3) J14B0238(0.2*7P)
	MR-J3JSCBL03M-A1-L	0.3	AWG26	8 (4 pairs)	7/0.16	146 or less	1.0	7.1±0.3	(Note 3) VSVP 7/0.16 (Equivalent to AWG#26)-4P Ban-gi-shi-16822
	MR-J3JSCBL03M-A2-L								
	MR-J3ENSCBL□M-L (-S06)	2 to 10	AWG22	6 (3 pairs)	7/0.26	53 or less	1.2	7.1±0.3	(Note 3) VSVP 7/0.26 (Equivalent to AWG#22)-3P Ban-gi-shi-16823
		20 ・ 30	AWG23	12 (6 pairs)	12/0.18	63.3 or less	1.2	8.2±0.3	(Note 3) 20276 VSVCAWG#23 × 6P Ban-gi-shi-15038
	MR-J3ENSCBL□M-H (-S06)	2 to 10	AWG22	6 (3 pairs)	70/0.08	56 or less	1.2	7.1±0.3	(Note 3) ETFE SVP 70/0.08 (Equivalent to AWG#22)-3P Ban-gi-shi-16824
		20 to 50	AWG24	12 (6 pairs)	40/0.08	105 or less	0.88	7.2	(Note 3) ETFE ・ SVP 40/0.08mm × 6P Ban-gi-shi-15266
	MR-ENECBL□M-H	2 to 10	0.2	8 (4 pairs)	40/0.08	105 or less	0.88	7.2	(Note 3) A14B2339 4P
		20	0.2	12 (6 pairs)	40/0.08	105 or less	0.88	7.2	(Note 3) A14B2343 6P
		30 to 50	0.2	14 (7 pairs)	40/0.08	105 or less	0.88	8.0	(Note 3) J14B0238(0.2*7P)
Motor power supply cable	MR-PWS1CBL□M-A1-L	2 to 10	AWG18	4	34/0.18	21.8 or less	1.71	62±0.3	HRZFEV-A(CL3) AWG18 4-cores
	MR-PWS1CBL□M-A2-L	2 to 10							
	MR-PWS1CBL□M-A1-H	2 to 10	(Note 6) AWG19 (0.75mm^2)	4	150/0.08	29.1 or less	1.63	5.7±0.5	(Note 4) RMFES-A(CL3X) AWG19 4-cores
	MR-PWS1CBL□M-A2-H	2 to 10							
	MR-PWS2CBL03M-A1-L	0.3	AWG19	4	30/0.18	25.8 or less	1.64	–	(Note 3, 7) J11B2330 UL 10125
	MR-PWS2CBL03M-A2-L	0.3							
Motor brake cable	MR-BKS1CBL□M-A1-L	2 to 10	AWG20	2	21/0.18	34.6 or less	1.35	4.7±0.1	(Note 4) HRZFEV-A(CL3) AWG20 2-cores
	MR-BKS1CBL□M-A2-L	2 to 10							
	MR-BKS1CBL□M-A1-H	2 to 10	(Note 6) AWG20 (0.75mm^2)	2	110/0.08	39.0 or less	1.37	4.5±0.3	RMFES-A(CL3X) AWG20 2-cores
	MR-BKS1CBL□M-A2-H	2 to 10							
	MR-BKS2CBL03M-A1-L	0.3	AWG20	2	19/0.203	32.0 or less	1.42	–	(Note 3, 7) J11B331 UL 10125
	MR-BKS2CBL03M-A2-L	0.3							

Note 1. d is as shown below.



2. Purchase from Toa Electric Industry
3. Standard OD. Max. OD is about 10% greater.
4. Purchase from Taisei
5. Taiyo Electric Wire and Cable
6. These wire sizes assume that the UL-compliant wires are used at the wiring length of 10m.
7. These models consist with solid wires. Specify the color, separately.

12.12 No-fuse breakers, fuses, magnetic contactors

Always use one no-fuse breaker and one magnetic contactor with one servo amplifier. When using a fuse instead of the no-fuse breaker, use the one having the specifications given in this section.

Servo amplifier	No-fuse breaker			Fuse			(Note 2) Magnetic contactor
	Current		Voltage AC	(Note 1) Class	Current [A]	Voltage AC [V]	
	Not using power factor improving reactor	Using power factor improving reactor					
MR-J3-10A(1)	30A frame 5A	30A frame 5A	240V	T	10	300	S-N10
MR-J3-20A	30A frame 5A	30A frame 5A			10		
MR-J3-20A1	30A frame 10A	30A frame 10A			15		
MR-J3-40A	30A frame 10A	30A frame 5A			15		
MR-J3-60A MR-J3-70A MR-J3-100A MR-J3-40A1	30A frame 15A	30A frame 10A			20		
MR-J3-200A	30A frame 20A	30A frame 15A			40		S-N18
MR-J3-350A	30A frame 30A	30A frame 30A			70		S-N20
MR-J3-500A	50A frame 50A	50A frame 40A			125		S-N35
MR-J3-700A	100A frame 75A	50A frame 50A			150		S-N50
MR-J3-11KA	100A frame 100A	100A frame 75A			200		S-N65
MR-J3-15KA	225A frame 125A	100A frame 100A			250		S-N95
MR-J3-22KA	225A frame 175A	225A frame 150A			350		S-N125
MR-J3-60A4	30A frame 5A	30A frame 5A	600Y/347V		10	600	S-N10
MR-J3-100A4	30A frame 10A	30A frame 10A			15		
MR-J3-200A4	30A frame 15A	30A frame 15A			25		
MR-J3-350A4	30A frame 20A	30A frame 20A			35		S-N18
MR-J3-500A4	30A frame 30A	30A frame 30A			50		
MR-J3-700A4	50A frame 40A	50A frame 30A			65		S-N20
MR-J3-11KA4	60A frame 60A	50A frame 50A			100		S-N25
MR-J3-15KA4	100A frame 75A	60A frame 60A			150		S-N35
MR-J3-22KA4	225A frame 125A	100A frame 100A			175		S-N65

Note 1. When not using the servo amplifier as a UL/CSA Standard compliant product, K5 class fuse can be used.

2. Be sure to use a magnetic contactor with an operation delay time of 80ms or less. The operation delay time is the time interval between current being applied to the coil until closure of contacts.

12.13 Power factor improving DC reactor

POINT

- For the 100VAC power supply type (MR-J3-□A1), the power factor improving DC reactor cannot be used.

The power factor improving DC reactor increases the form factor of the servo amplifier's input current to improve the power factor. It can decrease the power supply capacity. As compared to the power factor improving AC reactor (FR-BAL-(H)), it can decrease the loss. The input power factor is improved to about 95%.

It is also effective to reduce the input side harmonics.

When connecting the power factor improving DC reactor to the servo amplifier, always disconnect P_1 and P_2 (For 11k to 22kW, disconnect P_1 and P). If it remains connected, the effect of the power factor improving DC reactor is not produced.

When used, the power factor improving DC reactor generates heat. To release heat, therefore, leave a 10cm or more clearance at each of the top and bottom, and a 5cm or more clearance on each side.

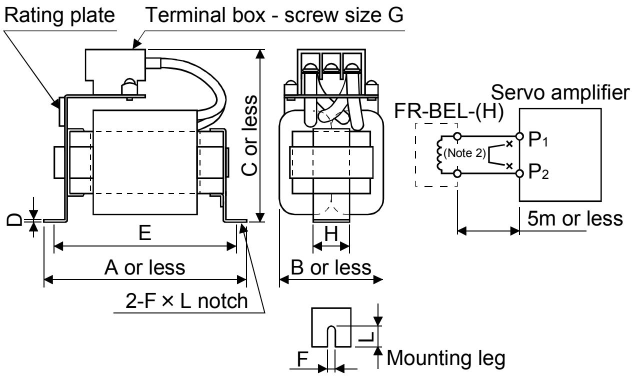


Fig. 12.1

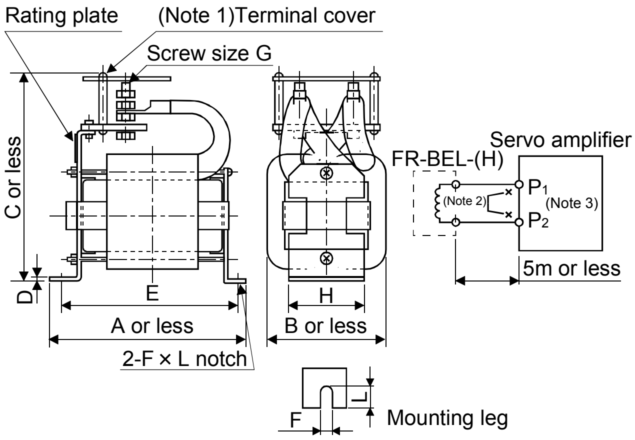


Fig. 12.2

Note 1. Since the terminal cover is supplied, attach it after connecting a wire.

2. When using power factor improving DC reactor, disconnect P_1 and P_2.

3. When 11k to 22kW, "P_2" becomes "P", respectively.

Servo amplifier	Power factor improving DC reactor	Outline drawing	Dimensions [mm]									Mounting screw size	Mass [kg(lb)]	Wire [mm^2] (Note)
			A	B	C	D	E	F	L	G	H			
MR-J3-10A・20A	FR-BEL-0.4K	Fug. 12.1	110	50	94	1.6	95	6	12	M3.5	25	M5	0.5(1.10)	2(AWG14)
MR-J3-40A	FR-BEL-0.75K		120	53	102	1.6	105	6	12	M4	25	M5	0.7(1.54)	
MR-J3-60A・70A	FR-BEL-1.5K		130	65	110	1.6	115	6	12	M4	30	M5	1.1(2.43)	
MR-J3-100A	FR-BEL-2.2K		130	65	110	1.6	115	6	12	M4	30	M5	1.2(2.65)	
MR-J3-200A	FR-BEL-3.7K		150	75	102	2.0	135	6	12	M4	40	M5	1.7(3.75)	
MR-J3-350A	FR-BEL-7.5K		150	75	126	2.0	135	6	12	M5	40	M5	2.3(5.07)	3.5(AWG12)
MR-J3-500A	FR-BEL-11K		170	93	132	2.3	155	6	14	M5	50	M5	3.1(6.83)	5.5(AWG10)
MR-J3-700A	FR-BEL-15K	Fig. 12.2	170	93	170	2.3	155	6	14	M8	56	M5	3.8(8.38)	8(AWG8)
MR-J3-11KA														22(AWG4)
MR-J3-15KA	FR-BEL-22K		185	119	182	2.6	165	7	15	M8	70	M6	5.4(11.91)	30(AWG2)
MR-J3-22KA	FR-BEL-30K		185	119	201	2.6	165	7	15	M8	70	M6	6.7(14.77)	60(AWG2/0)
MR-J3-60A4	FR-BEL-H1.5K	Fig. 12.1	130	63	89	1.6	115	6	12	M3.5	32	M5	0.9(1.98)	2(AWG14)
MR-J3-100A4	FR-BEL-H2.2K		130	63	101	1.6	115	6	12	M3.5	32	M5	1.1(2.43)	
MR-J3-200A4	FR-BEL-H3.7K		150	75	102	2	135	6	12	M4	40	M5	1.7(3.75)	
MR-J3-350A4	FR-BEL-H7.5K		150	75	124	2	135	6	12	M4	40	M5	2.3(5.07)	
MR-J3-500A4	FR-BEL-H11K		170	93	132	2.3	155	6	14	M5	50	M5	3.1(6.83)	5.5(AWG10)
MR-J3-700A4	FR-BEL-H15K	Fig. 12.2	170	93	160	2.3	155	6	14	M6	56	M5	3.7(8.16)	8(AWG8)
MR-J3-11KA4														
MR-J3-15KA4	FR-BEL-H22K		185	119	171	2.6	165	7	15	M6	70	M6	5.0(11.02)	22(AWG4)
MR-J3-22KA4	FR-BEL-H30K		185	119	189	2.6	165	7	15	M6	70	M6	6.7(14.77)	

Note. Selection condition of wire size is as follows.

Wire type: 600V Polyvinyl chloride insulated wire (IV wire)

Construction condition: One wire is constructed in the air

12.14 Power factor improving reactors

The power factor improving reactors improve the phase factor by increasing the form factor of servo amplifier's input current.

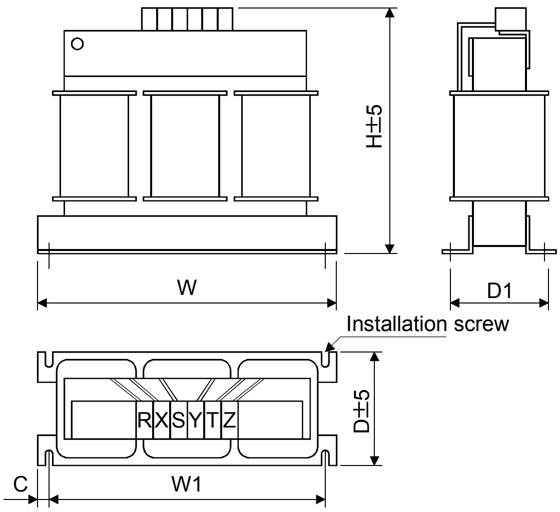
It can reduce the power capacity.

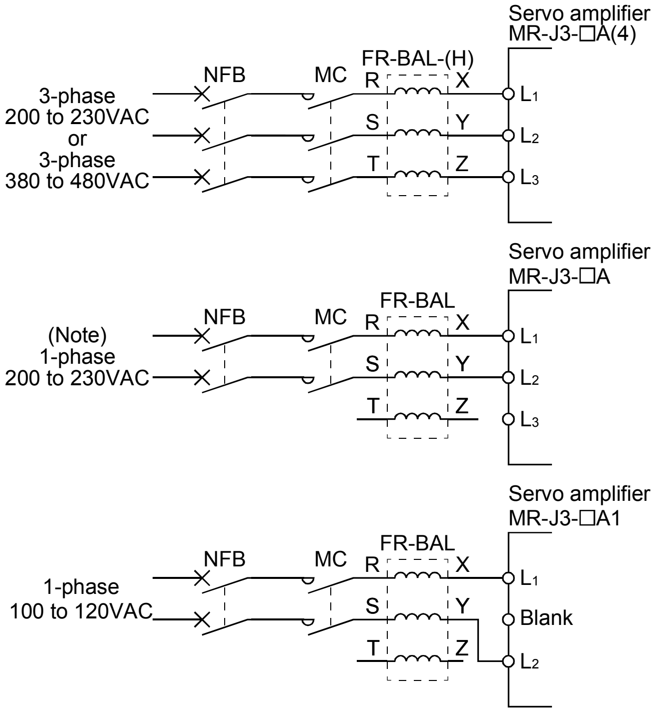
The input power factor is improved to be about 90%. For use with a 1-phase power supply, it may be slightly lower than 90%.

In addition, it reduces the higher harmonic of input side.

When using power factor improving AC reactors for two or more servo amplifiers, be sure to connect a power factor improving AC reactor to each servo amplifier.

If using only one power factor improving AC reactor, enough improvement effect of phase factor cannot be obtained unless all servo amplifiers are operated.





Note. For the 1-phase 200 to 230VAC power supply, Connect the power supply to L_1, L_2 and leave L_3 open.

Servo amplifier	Model	Dimensions [mm]						Mounting screw size	Terminal screw size	Mass [kg (lb)]
		W	W1	H	D	D1	C			
MR-J3-10A・20A・10A1	FR-BAL-0.4K	135	120	115	59	$45^{0}_{-2.5}$	7.5	M4	M3.5	2.0 (4.41)
MR-J3-40A・20A1	FR-BAL-0.75K	135	120	115	69	$57^{0}_{-2.5}$	7.5	M4	M3.5	2.8 (6.17)
MR-J3-60A・70A・40A1	FR-BAL-1.5K	160	145	140	71	$55^{0}_{-2.5}$	7.5	M4	M3.5	3.7 (8.16)
MR-J3-100A	FR-BAL-2.2K	160	145	140	91	$75^{0}_{-2.5}$	7.5	M4	M3.5	5.6 (12.35)
MR-J3-200A	FR-BAL-3.7K	220	200	192	90	$70^{0}_{-2.5}$	10	M5	M4	8.5 (18.74)
MR-J3-350A	FR-BAL-7.5K	220	200	194	120	$100^{0}_{-2.5}$	10	M5	M5	14.5 (31.97)
MR-J3-500A	FR-BAL-11K	280	255	220	135	$100^{0}_{-2.5}$	12.5	M6	M6	19 (41.89)
MR-J3-700A	FR-BAL-15K	295	270	275	133	$110^{0}_{-2.5}$	12.5	M6	M6	27 (59.53)
MR-J3-11KA										
MR-J3-15KA	FR-BAL-22K	290	240	301	199	170±5	25	M8	M8	35 (77.16)
MR-J3-22KA	FR-BAL-30K	290	240	301	219	190±5	25	M8	M8	43 (94.80)
MR-J3-60A4	FR-BAL-H1.5K	160	145	140	87	$70^{0}_{-2.5}$	7.5	M4	M3.5	5.3 (11.68)
MR-J3-100A4	FR-BAL-H2.2K	160	145	140	91	$75^{0}_{-2.5}$	7.5	M4	M3.5	5.9 (13.01)
MR-J3-200A4	FR-BAL-H3.7K	220	200	190	90	$70^{0}_{-2.5}$	10	M5	M3.5	8.5 (18.74)
MR-J3-350A4	FR-BAL-H7.5K	220	200	192	120	100±5	10	M5	M4	14 (30.87)
MR-J3-500A4	FR-BAL-H11K	280	255	226	130	100±5	12.5	M6	M5	18.5 (40.79)
MR-J3-700A4	FR-BAL-H15K	295	270	244	130	110±5	12.5	M6	M5	27 (59.53)
MR-J3-11KA4										
MR-J3-15KA4	FR-BAL-H22K	290	240	269	199	170±5	25	M8	M8	Approx.35 (Approx.77.16)
MR-J3-22KA4	FR-BAL-H30K	290	240	290	219	190±5	25	M8	M8	Approx.43 (Approx.94.80)

12.15 Relays (recommended)

The following relays should be used with the interfaces.

Interface	Selection example
Relay used for digital input command signals (interface DI-1)	To prevent defective contacts , use a relay for small signal (twin contacts). (Ex.) Omron : type G2A , MY
Relay used for digital output signals (interface DO-1)	Small relay with 12VDC or 24VDC of rated current 40mA or less (Ex.) Omron : type MY

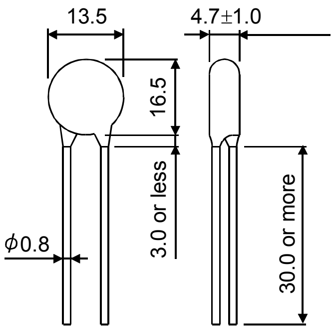
12.16 Surge absorbers (recommended)

A surge absorber is required for the electromagnetic brake. Use the following surge absorber or equivalent. When using the surge absorber, perform insulation beforehand to prevent short-circuit.

Maximum rating					Maximum limit voltage		Static capacity (reference value)	Varistor voltage rating (range) V1mA
Permissible circuit voltage		Surge immunity	Energy immunity	Rated power				
AC [Vma]	DC [V]	[A]	[J]	[W]	[A]	[V]	[pF]	[V]
140	180	(Note) 500/time	5	0.4	25	360	300	220 (198 to 242)

Note. 1 time = 8 × 20μs

[Unit: mm]



(Example) ERZV10D221 (Panasonic)
TNR-10V221K (Nippon chemi-con)
Outline drawing [mm]
(ERZ-C10DK221)

12.17 Noise reduction techniques

Noises are classified into external noises which enter the servo amplifier to cause it to malfunction and those radiated by the servo amplifier to cause peripheral devices to malfunction. Since the servo amplifier is an electronic device which handles small signals, the following general noise reduction techniques are required. Also, the servo amplifier can be a source of noise as its outputs are chopped by high carrier frequencies. If peripheral devices malfunction due to noises produced by the servo amplifier, noise suppression measures must be taken. The measures will vary slightly with the routes of noise transmission.

(1) Noise reduction techniques

(a) General reduction techniques

- Avoid laying power lines (input and output cables) and signal cables side by side or do not bundle them together. Separate power lines from signal cables.
- Use shielded, twisted pair cables for connection with the encoder and for control signal transmission, and connect the shield to the SD terminal.
- Ground the servo amplifier, servo motor, etc. together at one point (refer to section 3.12).

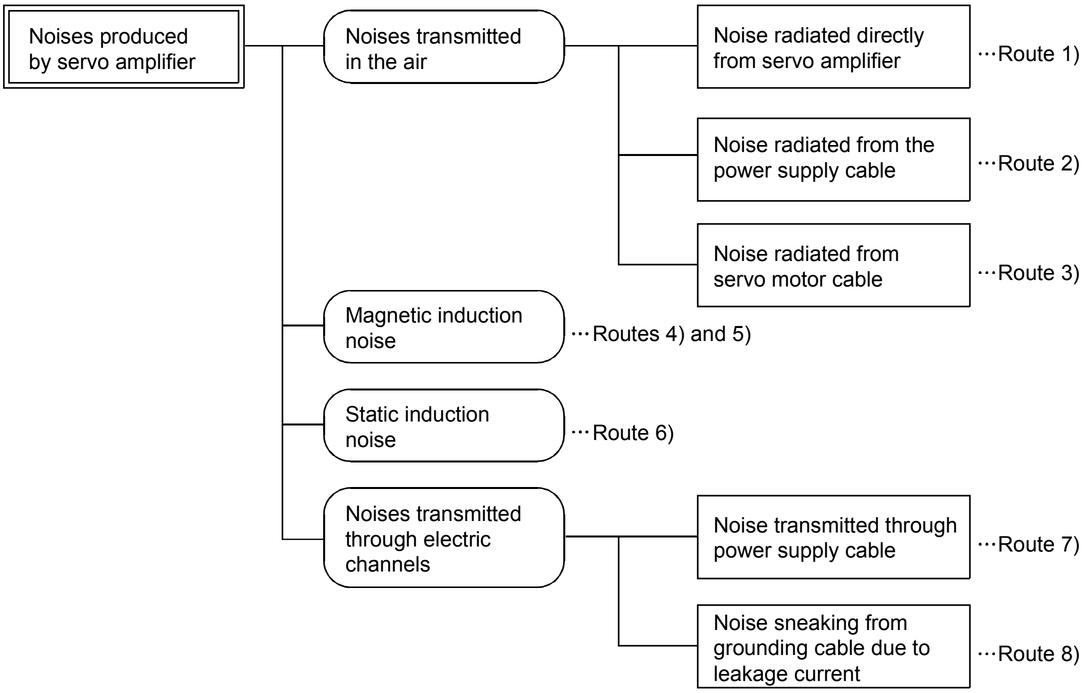
(b) Reduction techniques for external noises that cause the servo amplifier to malfunction

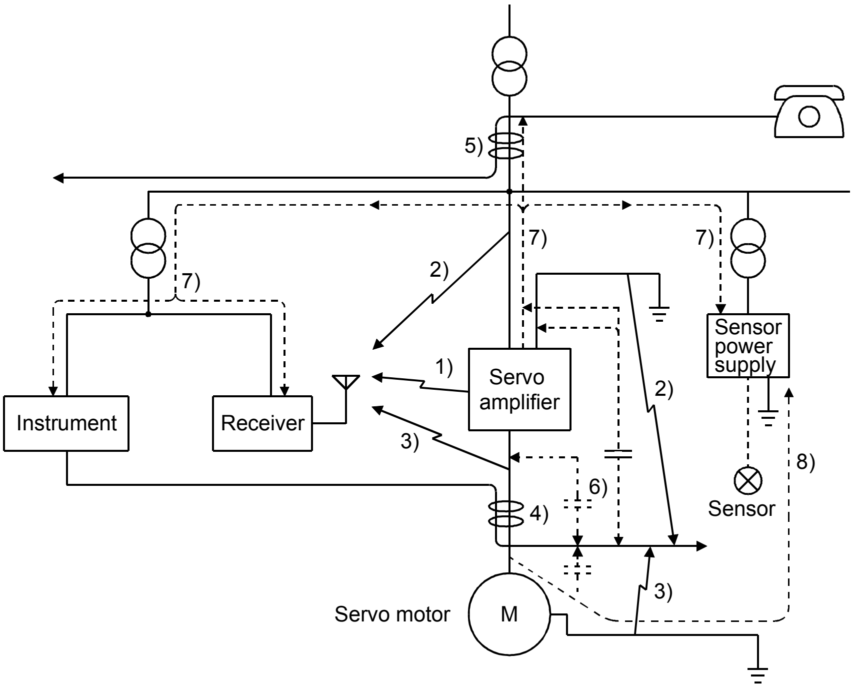
If there are noise sources (such as a magnetic contactor, an electromagnetic brake, and many relays which make a large amount of noise) near the servo amplifier and the servo amplifier may malfunction, the following countermeasures are required.

- Provide surge absorbers on the noise sources to suppress noises.
- Attach data line filters to the signal cables.
- Ground the shields of the encoder connecting cable and the control signal cables with cable clamp fittings.
- Although a surge absorber is built into the servo amplifier, to protect the servo amplifier and other equipment against large exogenous noise and lightning surge, attaching a varistor to the power input section of the equipment is recommended.

(c) Techniques for noises radiated by the servo amplifier that cause peripheral devices to malfunction

Noises produced by the servo amplifier are classified into those radiated from the cables connected to the servo amplifier and its main circuits (input and output circuits), those induced electromagnetically or statically by the signal cables of the peripheral devices located near the main circuit cables, and those transmitted through the power supply cables.





Noise transmission route	Suppression techniques
1) 2) 3)	When measuring instruments, receivers, sensors, etc. which handle weak signals and may malfunction due to noise and/or their signal cables are contained in a control box together with the servo amplifier or run near the servo amplifier, such devices may malfunction due to noises transmitted through the air. The following techniques are required. 1. Provide maximum clearance between easily affected devices and the servo amplifier. 2. Provide maximum clearance between easily affected signal cables and the I/O cables of the servo amplifier. 3. Avoid laying the power lines (Input cables of the servo amplifier) and signal cables side by side or bundling them together. 4. Insert a line noise filter to the I/O cables or a radio noise filter on the input line. 5. Use shielded wires for signal and power cables or put cables in separate metal conduits.
4) 5) 6)	When the power lines and the signal cables are laid side by side or bundled together, magnetic induction noise and static induction noise will be transmitted through the signal cables and malfunction may occur. The following techniques are required. 1. Provide maximum clearance between easily affected devices and the servo amplifier. 2. Provide maximum clearance between easily affected signal cables and the I/O cables of the servo amplifier. 3. Avoid laying the power lines (I/O cables of the servo amplifier) and signal cables side by side or bundling them together. 4. Use shielded wires for signal and power cables or put the cables in separate metal conduits.
7)	When the power supply of peripheral devices is connected to the power supply of the servo amplifier system, noises produced by the servo amplifier may be transmitted back through the power supply cable and the devices may malfunction. The following techniques are required. 1. Insert the radio noise filter (FR-BIF-(H)) on the power cables (Input cables) of the servo amplifier. 2. Insert the line noise filter (FR-BSF01・FR-BLF) on the power cables of the servo amplifier.
8)	When the cables of peripheral devices are connected to the servo amplifier to make a closed loop circuit, leakage current may flow to malfunction the peripheral devices. If so, malfunction may be prevented by disconnecting the grounding cable of the peripheral device.

(2) Noise reduction products

(a) Data line filter (Recommended)

Noise can be prevented by installing a data line filter onto the encoder cable, etc.

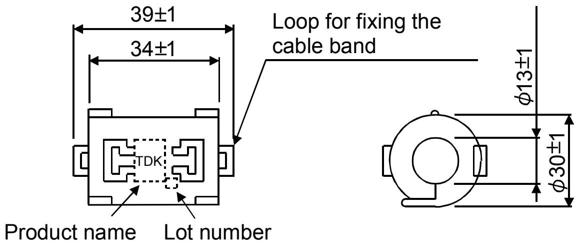
For example, the ZCAT3035-1330 of TDK and the ESD-SR-250 of NEC TOKIN make are available as data line filters.

As a reference example, the impedance specifications of the ZCAT3035-1330 (TDK) are indicated below.

This impedances is reference values and not guaranteed values.

Impedance [Ω]	
10 to 100MHz	100 to 500MHz
80	150

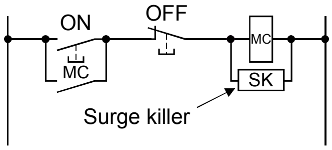
[Unit: mm]

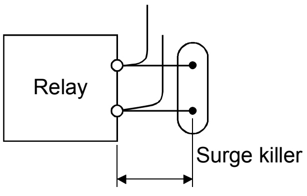


Outline drawing (ZCAT3035-1330)

(b) Surge killer

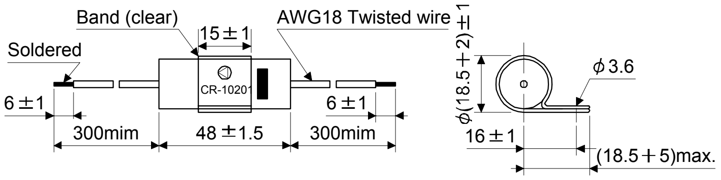
The recommended surge killer for installation to an AC relay, AC valve or the like near the servo amplifier is shown below. Use this product or equivalent.



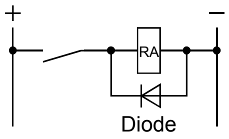


This distance should be short (within 20cm).

(Ex.) CR-50500
(OKAYA Electric Industries Co., Ltd.)

Rated voltage AC [V]	C [μF±20%]	R [Ω±30%]	Test voltage AC [V]	Outline drawing [Unit: mm]
250	0.5	50 (1/2W)	Between terminals: 625VAC 50/60Hz 60s Between terminal and case: 2,000VAC 50/60Hz 60s	

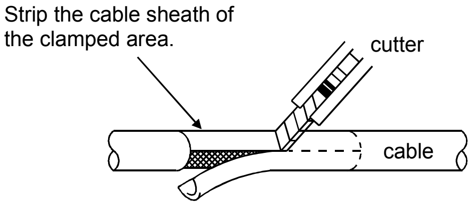
Note that a diode should be installed to a DC relay, DC valve or the like.
Maximum voltage: Not less than 4 times the drive voltage of the relay or the like
Maximum current: Not less than twice the drive current of the relay or the like

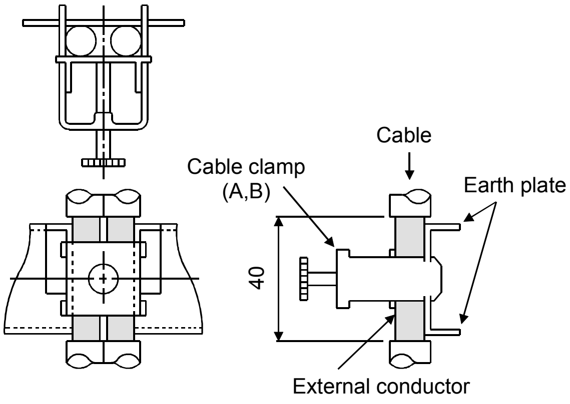


(c) Cable clamp fitting (AERSBAN-☐SET)

Generally, the earth of the shielded cable may only be connected to the connector's SD terminal. However, the effect can be increased by directly connecting the cable to an earth plate as shown below. Install the earth plate near the servo amplifier for the encoder cable. Peel part of the cable sheath to expose the external conductor, and press that part against the earth plate with the cable clamp. If the cable is thin, clamp several cables in a bunch.
The clamp comes as a set with the earth plate.

[Unit: mm]



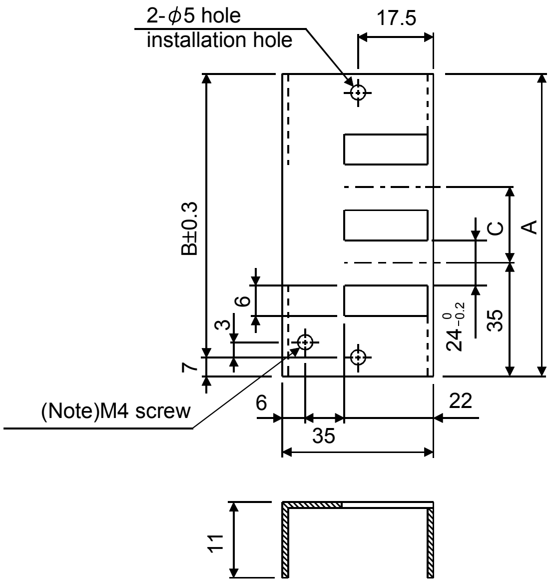


Clamp section diagram

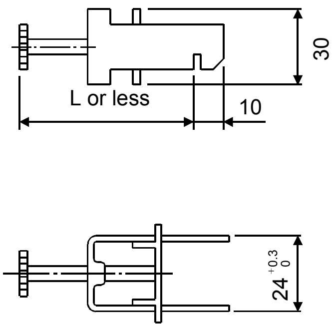
- Outline drawing

[Unit: mm]

Earth plate



Clamp section diagram



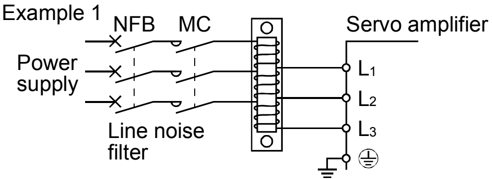
Note. Screw hole for grounding. Connect it to the earth plate of the control box.

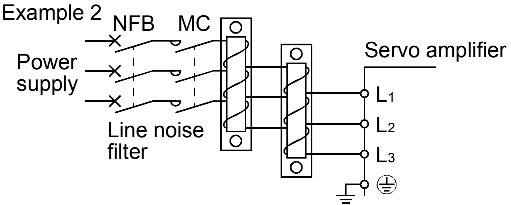
Type	A	B	C	Accessory fittings
AERSBAN-DSET	100	86	30	clamp A: 2pcs.
AERSBAN-ESET	70	56		clamp B: 1pc.

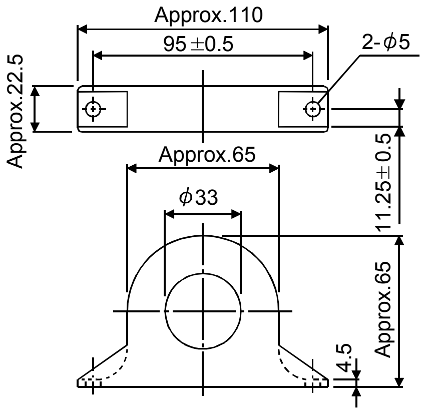
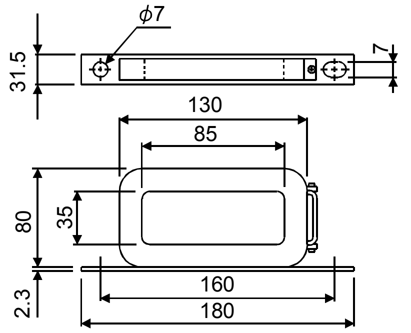
Clamp fitting	L
A	70
B	45

(d) Line noise filter (FR-BSF01, FR-BLF)

This filter is effective in suppressing noises radiated from the power supply side and output side of the servo amplifier and also in suppressing high-frequency leakage current (zero-phase current) especially within 0.5M to 5MHz band.

<table>
<tr><th>Connection diagram</th><th>Outline drawing [Unit: mm]</th></tr>
<tr><td rowspan="2">Use the line noise filters for wires of the main power supply (L_1 · L_2 · L_3) and of the servo motor power supply (U · V · W). Pass all wires through the line noise filter an equal number of times in the same direction. For the main power supply, the effect of the filter rises as the number of passes increases, but generally four passes would be appropriate. For the motor power supply, passes must be four times or less. Do not pass the grounding (earth) wire through the filter, or the effect of the filter will drop. Wind the wires by passing through the filter to satisfy the required number of passes as shown in Example 1. If the wires are too thick to wind, use two or more filters to have the required number of passes as shown in Example 2. Place the line noise filters as close to the servo amplifier as possible for their best performance.
Example 1


(Number of turns: 4)
Example 2


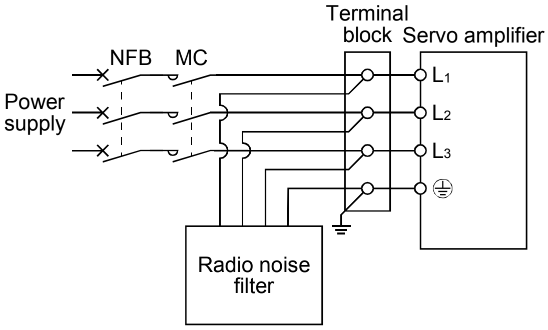
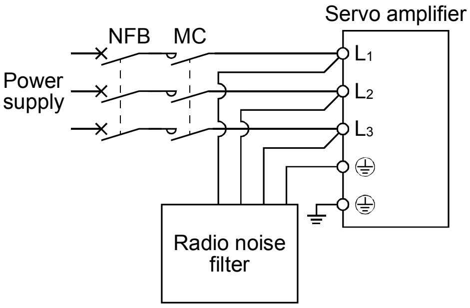
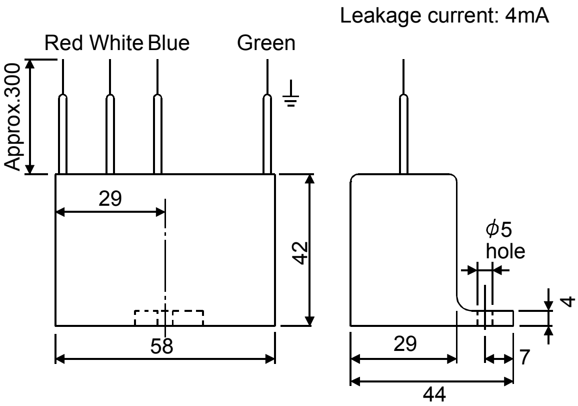
Two filters are used
(Total number of turns: 4)</td>
<td>FR-BSF01 (for wire size 3.5mm^2 (AWG12) or less)

 </td></tr>
<tr><td>FR-BLF(for wire size 5.5mm^2 (AWG10) or more)

 </td></tr>
</table>

(e) Radio noise filter (FR-BIF-(H))

This filter is effective in suppressing noises radiated from the power supply side of the servo amplifier especially in 10MHz and lower radio frequency bands. The FR-BIF-(H) is designed for the input only.

200V class: FR-BIF

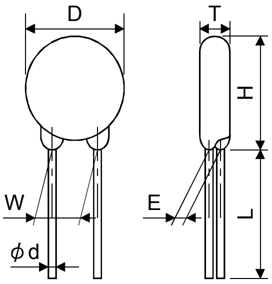
400V class: FR-BIF-H

Connection diagram	Outline drawing (Unit: mm)
Make the connection wires as short as possible. Grounding is always required. When using the FR-BIF with a single-phase power supply, always insulate the wires that are not used for wiring. ・MR-J3-350A or less, MR-J3-200A4 or less  ・MR-J3-500A or more, MR-J3-350A4 or more 	

(f) Varistors for input power supply (Recommended)

Varistors are effective to prevent exogenous noise and lightning surge from entering the servo amplifier. When using a varistor, connect it between each phase of the input power supply of the equipment. For varistors, the TND20V-431K, TND20V-471K and TND20V-102K, manufactured by NIPPON CHEMI-CON, are recommended. For detailed specification and usage of the varistors, refer to the manufacturer catalog.

Power supply voltage	Varistor	Maximum rating					Maximum limit voltage		Static capacity (reference value)	Varistor voltage rating (range) V1mA
		Permissible circuit voltage		Surge current immunity	Energy immunity	Rated pulse power				
		AC [V_{rms}]	DC [V]	8/20μs [A]	2ms [J]	[W]	[A]	[V]	[pF]	[V]
100V class	TND20V-431K	275	350	10000/1 time	195	1.0	100	710	1300	430(387 to 473)
200V class	TND20V-471K	300	385	7000/2 time	215			775	1200	470(423 to 517)
400V class	TND20V-102K	625	825	7500/1 time 6500/2 time	400			1650	500	1000(900 to 1100)



[Unit: mm]

Model	D Max.	H Max.	T Max.	E ±1.0	(Note)L min.	ϕd ±0.05	W ±1.0
TND20V-431K	21.5	24.5	6.4	3.3	20	0.8	10.0
TND20V-471K			6.6	3.5			
TND20V-102K	22.5	25.5	9.5	6.4			

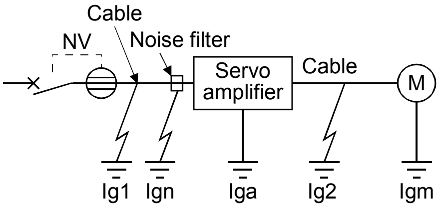
Note. For special purpose items for lead length (L), contact the manufacturer.

12.18 Leakage current breaker

(1) Selection method

High-frequency chopper currents controlled by pulse width modulation flow in the AC servo circuits.
Leakage currents containing harmonic contents are larger than those of the motor which is run with a commercial power supply.
Select a leakage current breaker according to the following formula, and ground the servo amplifier, servo motor, etc. securely.
Make the input and output cables as short as possible, and also make the grounding cable as long as possible (about 30cm) to minimize leakage currents.

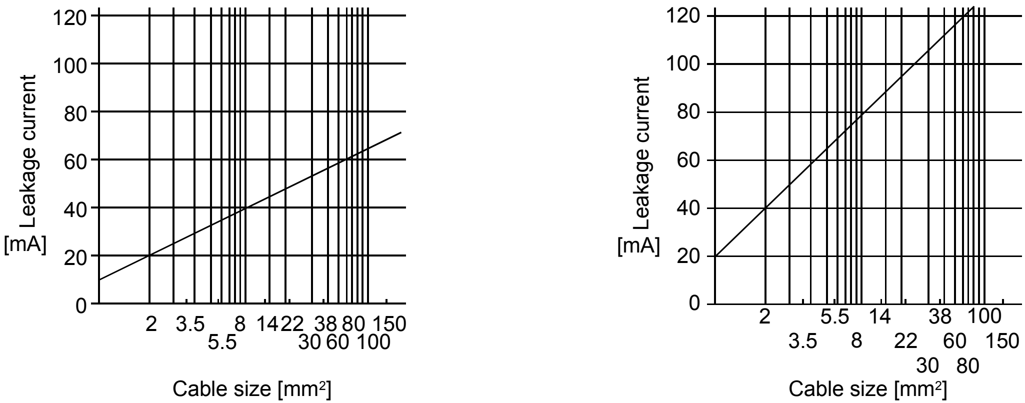
Rated sensitivity current $\geq 10 \cdot \{Ig1 + Ign + Iga + K \cdot (Ig2 + Igm)\}$ [mA] ....(12.1)



K: Constant considering the harmonic contents

Leakage current breaker		K
Type	Mitsubishi products	
Models provided with harmonic and surge reduction techniques	NV-SP NV-SW NV-CP NV-CW NV-L	1
General models	BV-C1 NFB NV-L	3

Ig1 : Leakage current on the electric channel from the leakage current breaker to the input terminals of the servo amplifier (Found from Fig. 12.3.)
Ig2 : Leakage current on the electric channel from the output terminals of the servo amplifier to the servo motor (Found from Fig. 12.3.)
Ign : Leakage current when a filter is connected to the input side (4.4mA per one FR-BIF-(H))
Iga : Leakage current of the servo amplifier (Found from Table 12.5.)
Igm : Leakage current of the servo motor (Found from Table 12.4.)



a. 200V class

b. 400V class

Fig. 12.3 Leakage current example (Ig1, Ig2) for CV cable run in metal conduit

Table 12.4 Servo motor's leakage current example (Igm)

Servo motor power [kW]	Leakage current [mA]
0.05 to 1	0.1
2	0.2
3.5	0.3
5	0.5
7	0.7
11	1.0
15	1.3
22	2.3

Table 12.5 Servo amplifier's leakage current example (Iga)

Servo amplifier capacity [kW]	Leakage current [mA]
0.1 to 0.6	0.1
0.75 to 3.5 (Note)	0.15
5・7	2
11・15	5.5
22	7

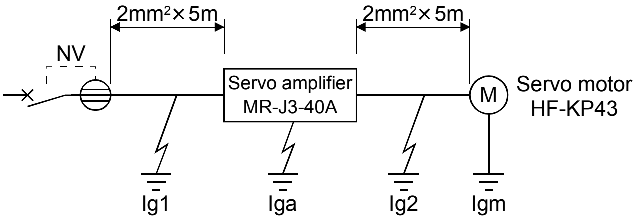
Note. For the 3.5kW of 400V class, leakage current is 2mA, which is the same as for 5kW and 7kW.

Table 12.6 Leakage circuit breaker selection example

Servo amplifier	Rated sensitivity current of leakage circuit breaker [mA]
MR-J3-10A to MR-J3-350A MR-J3-10A1 to MR-J3-40A1 MR-J3-60A4 to MR-J3-350A4	15
MR-J3-500A(4)	30
MR-J3-700A(4)	50
MR-J3-11KA(4) to MR-J3-22KA(4)	100

(2) Selection example

Indicated below is an example of selecting a leakage current breaker under the following conditions.



Use a leakage current breaker generally available.

Find the terms of Equation (12.1) from the diagram.

$$Ig1 = 20 \cdot \frac{5}{1000} = 0.1 \ [mA]$$

$$Ig2 = 20 \cdot \frac{5}{1000} = 0.1 \ [mA]$$

Ign＝0 (not used)

Iga＝0.1 [mA]

Igm＝0.1 [mA]

Insert these values in Equation (12.1).

$$Ig \geq 10 \cdot \{0.1+0+0.1+1 \cdot (0.1+0.1)\}$$

$$\geq 4.0 \ [mA]$$

According to the result of calculation, use a leakage current breaker having the rated sensitivity current (Ig) of 4.0[mA] or more. A leakage current breaker having Ig of 15[mA] is used with the NV-SP/SW/CP/CW/HW series.

12.19 EMC filter (recommended)

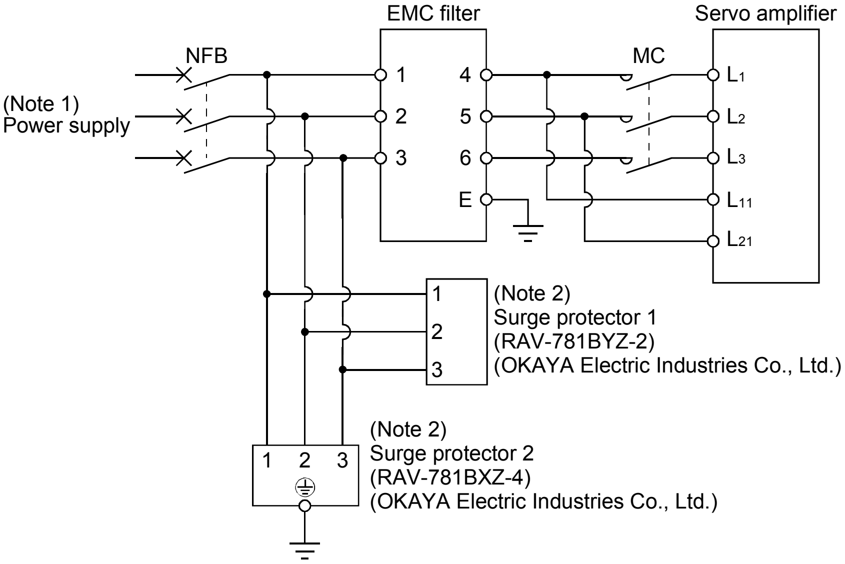
For compliance with the EMC directive of the IEC/EN Standard, it is recommended to use the following filter. Some EMC filters are large in leakage current.

(1) Combination with the servo amplifier

Servo amplifier	Recommended filter (Soshin Electric)		Mass [kg]([lb])
	Model	Leakage current [mA]	
MR-J3-10A to MR-J3-100A MR-J3-10A1 to MR-J3-40A1	(Note) HF3010A-UN	5	3 (6.61)
MR-J3-250A ▪ MR-J3-350A	(Note) HF3030A-UN		5.5 (12.13)
MR-J3-500A ▪ MR-J3-700A	(Note) HF3040A-UN	1.5	6.0 (13.23)
MR-J3-11KA to MR-J3-22KA	(Note) HF3100A-UN	6.5	15 (33.07)
MR-J3-60A4 to MR-J3-100A4	TF3005C-TX	5.5	6(13.23)
MR-J3-200A4 ▪ MR-J3-700A4	TF3020C-TX		
MR-J3-11KA4	TF3030C-TX		7.5(16.54)
MR-J3-15KA4	TF3040C-TX		12.5(27.56)
MR-J3-22KA4	TF3060C-TX		

Note. A surge protector is separately required to use any of these EMC filters.

(2) Connection example

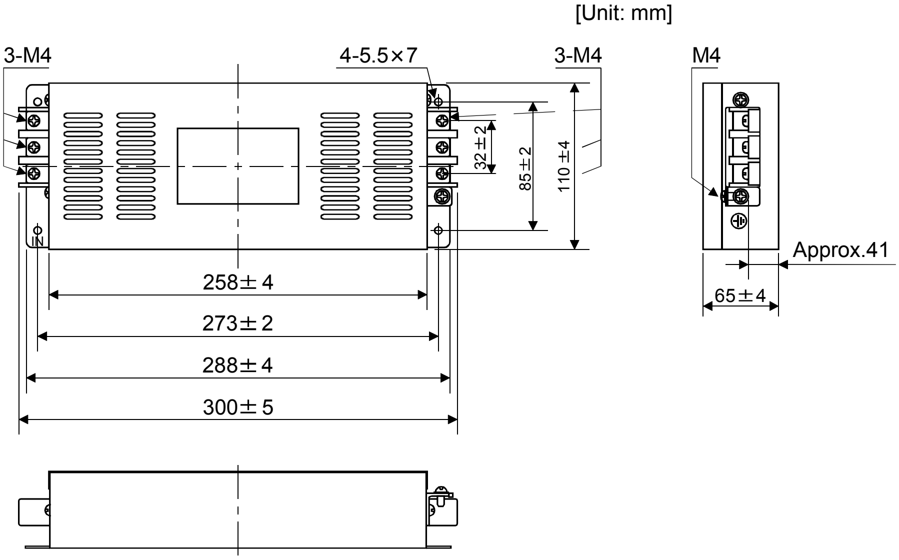


Note 1. For 1-phase 200 to 230VAC power supply, connect the power supply to L_1, L_2 and leave L_3 open.
There is no L_3 for 1-phase 100 to 120VAC power supply. Refer to section 1.3 for the power supply specification.
2. The example is when a surge protector is connected.

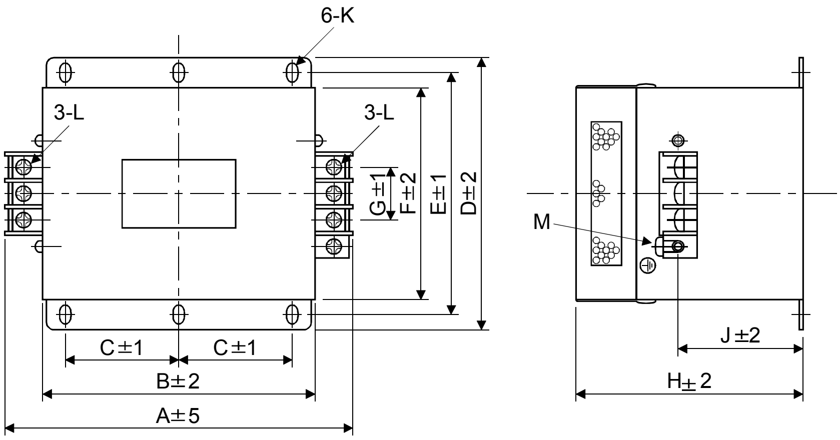
(3) Outline drawing

(a) EMC filter

HF3010A-UN

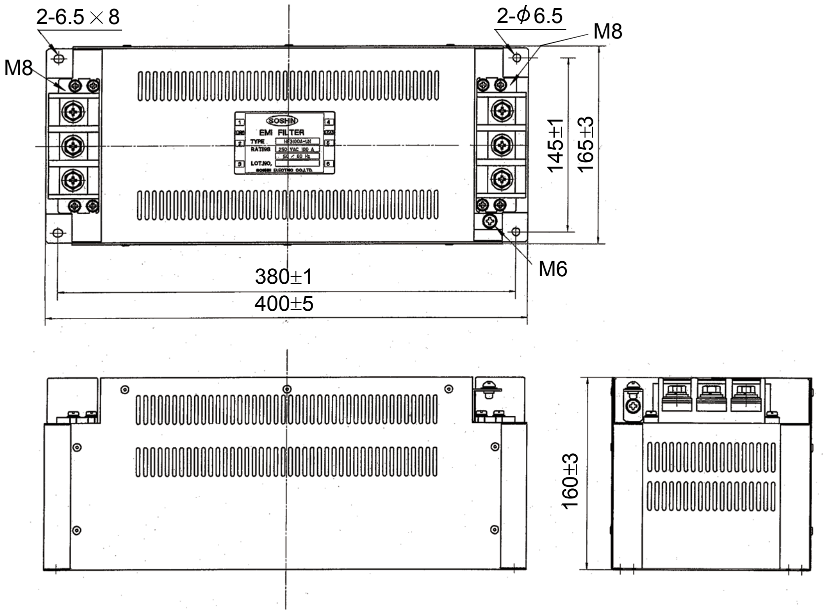


HF3030A-UN · HF-3040A-UN



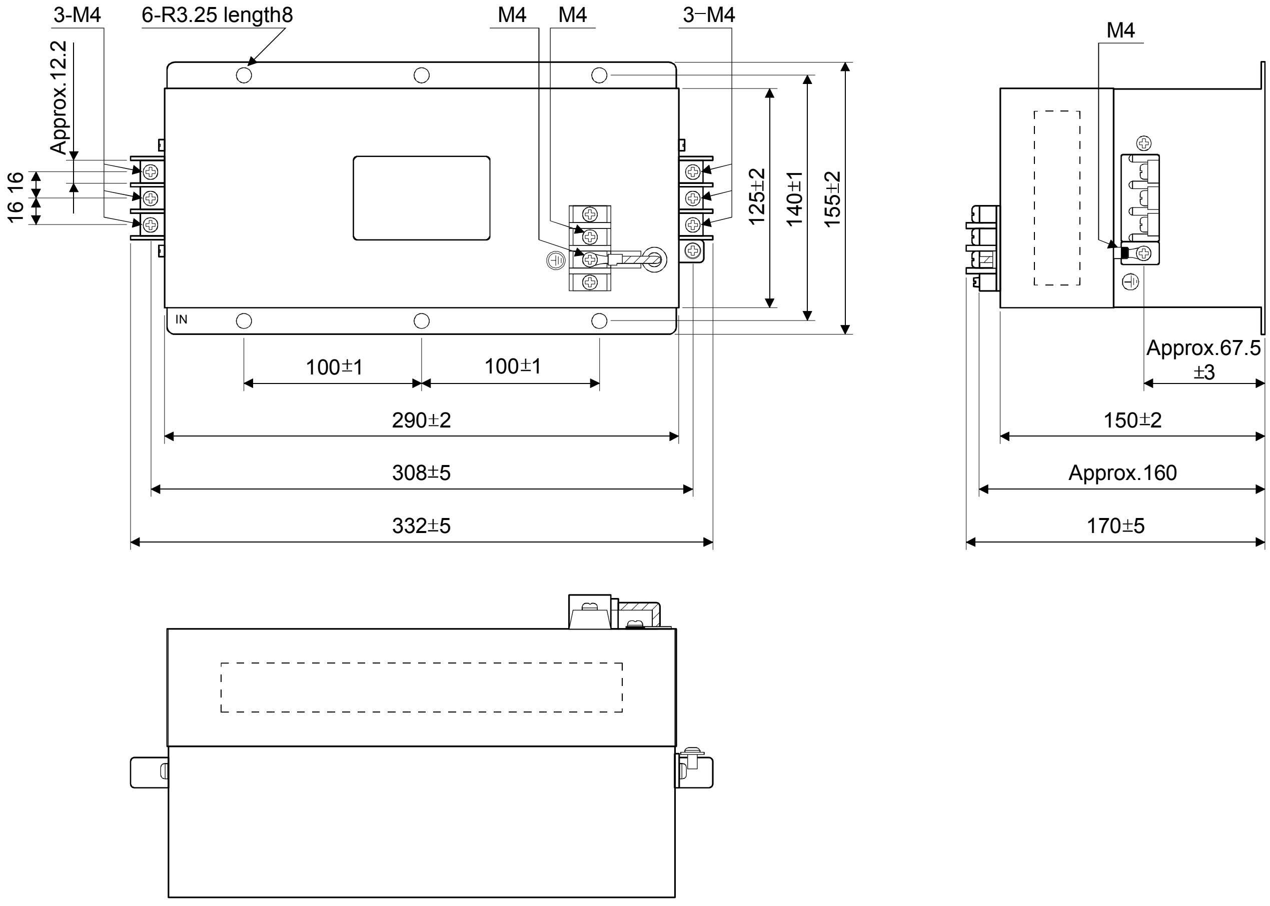
Model	Dimensions [mm]											
	A	B	C	D	E	F	G	H	J	K	L	M
HF3030A-UN	260	210	85	155	140	125	44	140	70	R3.25, length 8	M5	M4
HF3040A-UN	260	210	85	155	140	125	44	140	70		M5	M4

HF3100A-UN



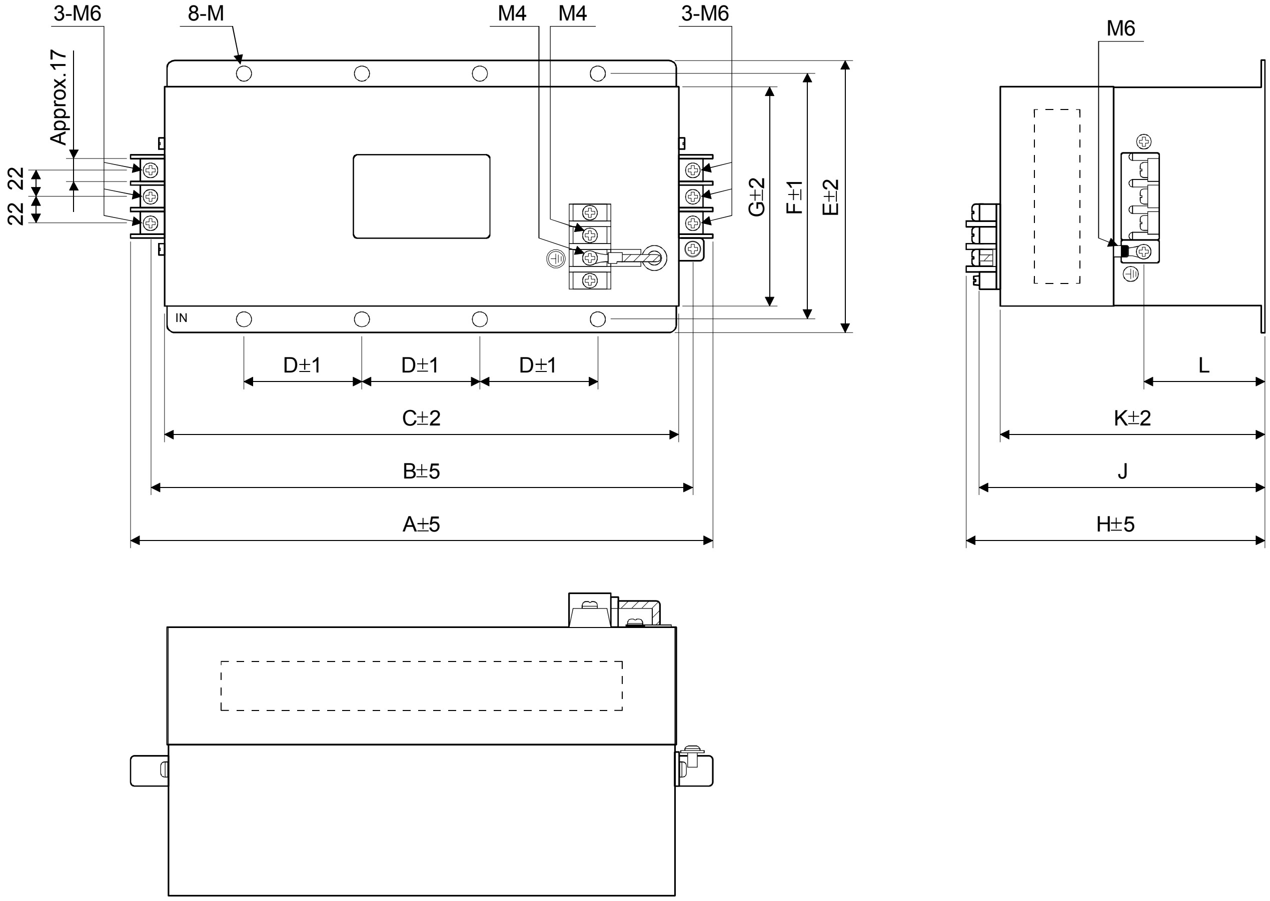
TF3005C-TX・TX3020C-TX・TF3030C-TX

[Unit: mm]



TF3040C-TX・TF3060C-TX

[Unit: mm]

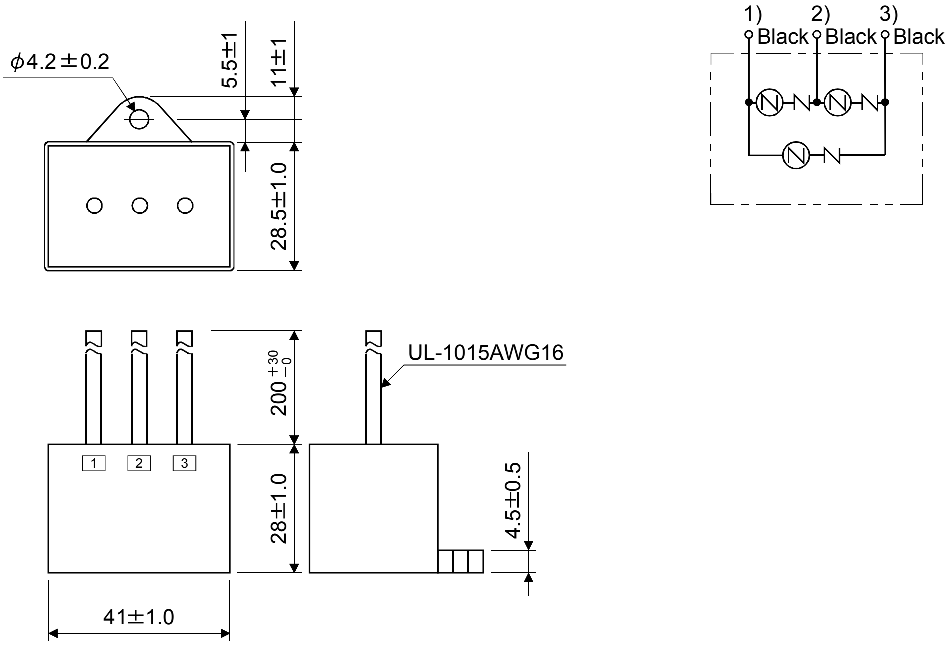


Model	Dimensions [mm]											
	A	B	C	D	E	F	G	H	J	K	L	M
TF3040C-TX	438	412	390	100	175	160	145	200	Approx.190	180	Approx.91.5	R3.25 length 8 (M6)
TF3060C-TX												

(b) Surge protector

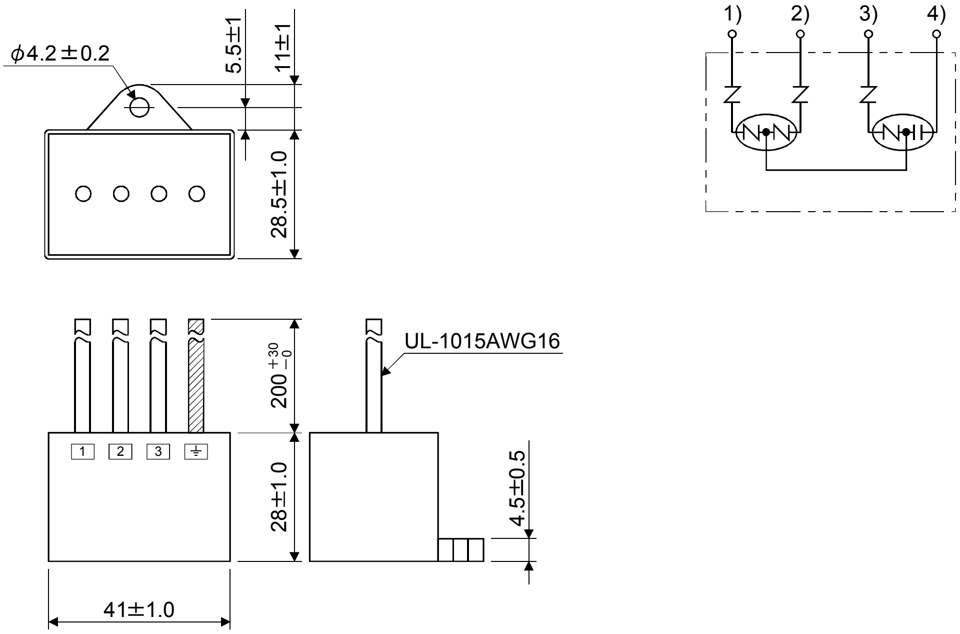
RAV-781BYZ-2

[Unit: mm]



RAV-781BXZ-4

[Unit: mm]



13. COMMUNICATION FUNCTION

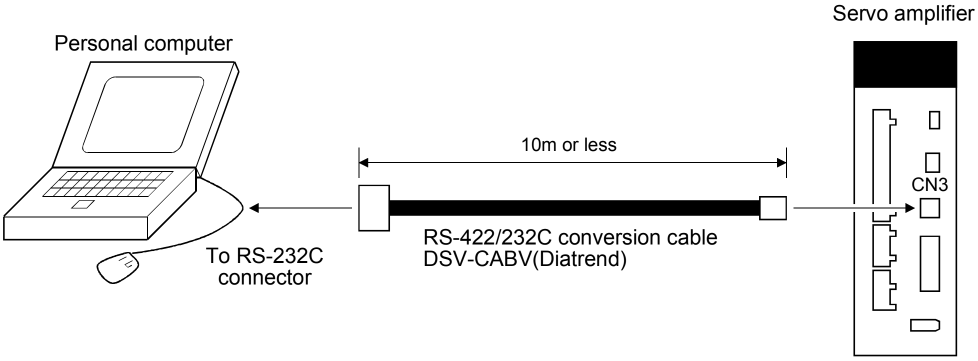
POINT
- The USB communication function (CN5 connector) and the RS-422 communication function (CN3 connector) are mutually exclusive functions. They cannot be used simultaneously.

Using the serial communication function of RS-422, this servo amplifier enables servo operation, parameter change, monitor function, etc.

13.1 Configuration

(1) Single axis

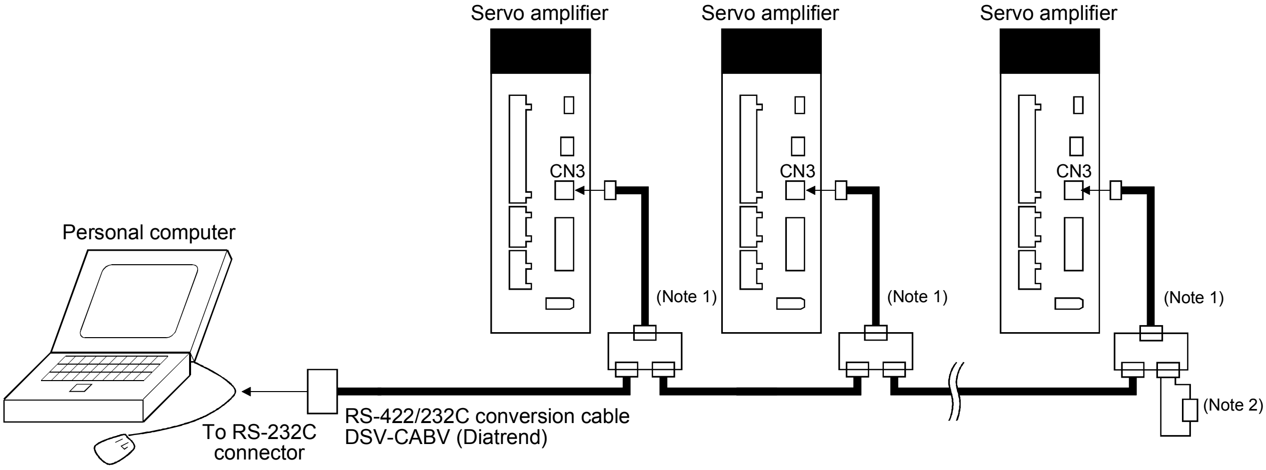
Operate the single-axis servo amplifier. It is recommended to use the following cable.



(2) Multidrop connection

(a) Diagrammatic sketch

Up to 32 axes of servo amplifiers from stations 0 to 31 can be operated on the same bus.

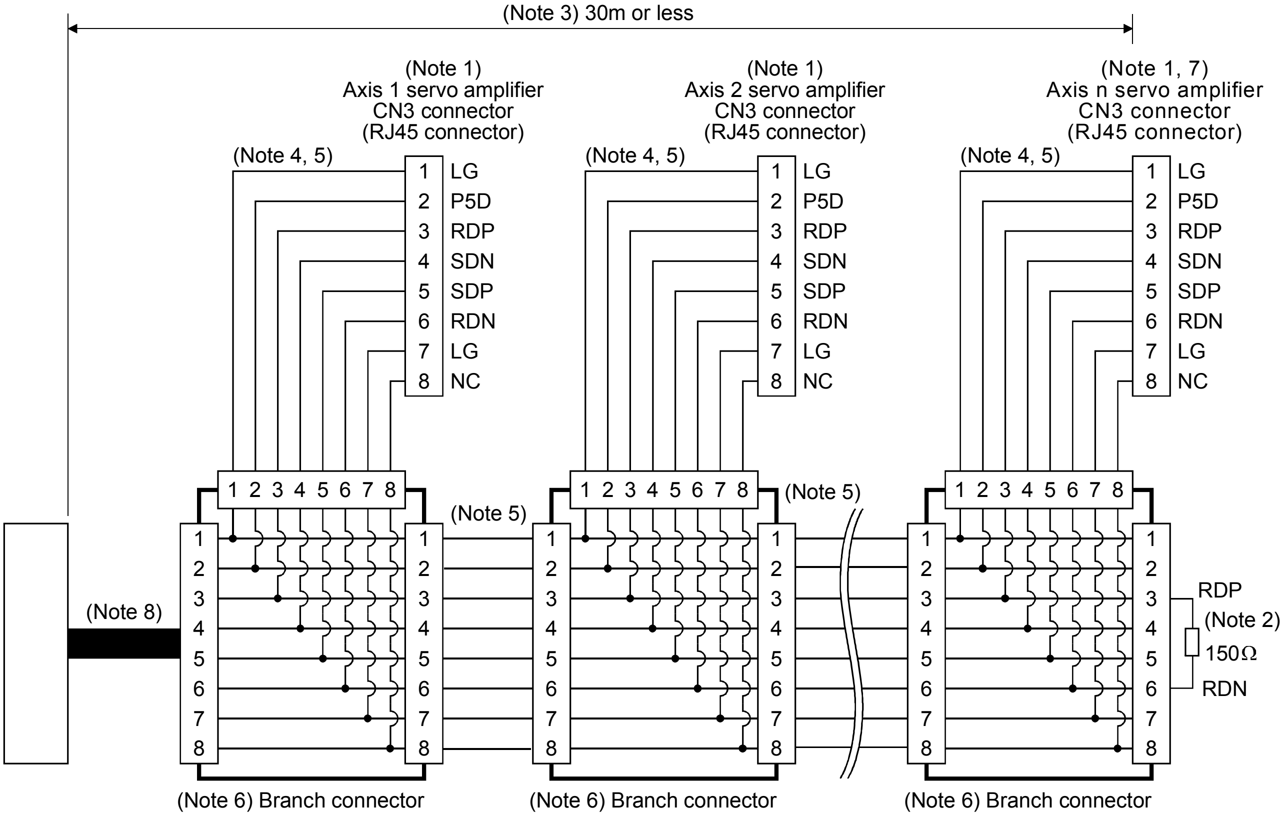


Note 1. The BMJ-8 (Hakko Electric Machine Works) is recommended as the branch connector.

2. The final axis must be terminated between RDP (pin No.3) and RDN (pin No.6) on the receiving side (servo amplifier) with a 150Ω resistor.

(b) Cable connection diagram

Wire the cables as shown below.



Note 1. Recommended connector (Hirose Electric)

Plug: TM10P-88P

Connection tool: CL250-0228-1

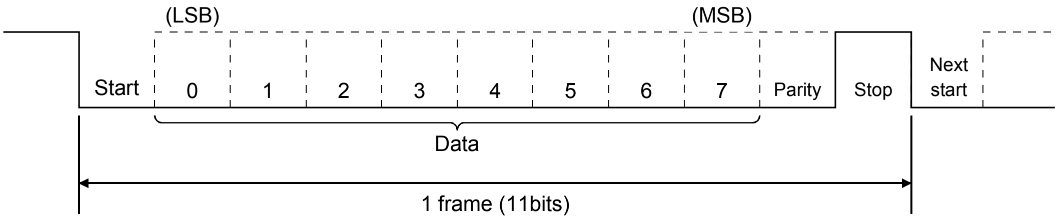
2. The final axis must be terminated between RDP (pin No.3) and RDN (pin No.6) on the receiving side (servo amplifier) with a 150Ω resistor.
3. The overall length is 30m or less in low-noise environment.
4. The wiring between the branch connector and servo amplifier should be as short as possible.
5. Use the EIA568-compliant cable (10BASE-T cable, etc.).
6. Recommended branch connector: BMJ-8 (Hakko Electric Machine Works)
7. n ≤ 32 (Up to 32 axes can be connected.)
8. RS-422/232C conversion cable DSV-CABV (Diatrend)

13.2 Communication specifications

13.2.1 Communication overview

This servo amplifier is designed to send a reply on receipt of an instruction. The device which gives this instruction (e.g. personal computer) is called a master station and the device which sends a reply in response to the instruction (servo amplifier) is called a slave station. When fetching data successively, the master station repeatedly commands the slave station to send data.

Item	Description
Baud rate	9600/19200/38400/57600/115200 asynchronous system
Transfer code	Start bit : 1 bit Data bit : 8 bits Parity bit : 1 bit (even) Stop bit : 1 bit
Transfer protocol	Character system, half-duplex communication system

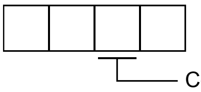


13.2.2 Parameter setting

When the USB/RS-422 communication function is used to operate the servo, set the communication specifications of the servo amplifier in the corresponding parameters.
After setting the values of these parameters, they are made valid by switching power off once, then on again.

(1) Serial communication baud rate
Choose the communication speed. Match this value to the communication speed of the sending end (master station).

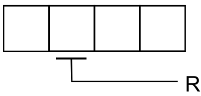
Parameter No.PC21



Communication baud rate
0: 9600[bps]
1: 19200[bps]
2: 38400[bps]
3: 57600[bps]
4: 115200[bps]

(2) RS-422 communication response delay time
Set the time from when the servo amplifier (slave station) receives communication data to when it sends back data. Set "0" to send back data in less than 800μs or "1" to send back data in 800μs or longer.

Parameter No.PC21



RS-422 communication response delay time
0: Invalid
1: Valid, reply sent in 800μs or longer

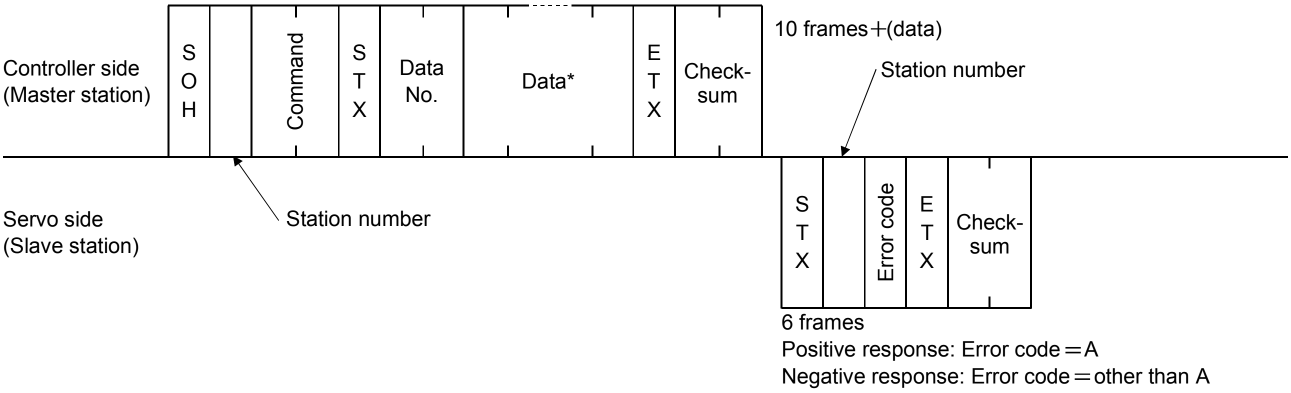
(3) Station number setting
Set the station number of the servo amplifier in parameter No.PC20. The setting range is station 0 to 31.

13.3 Protocol

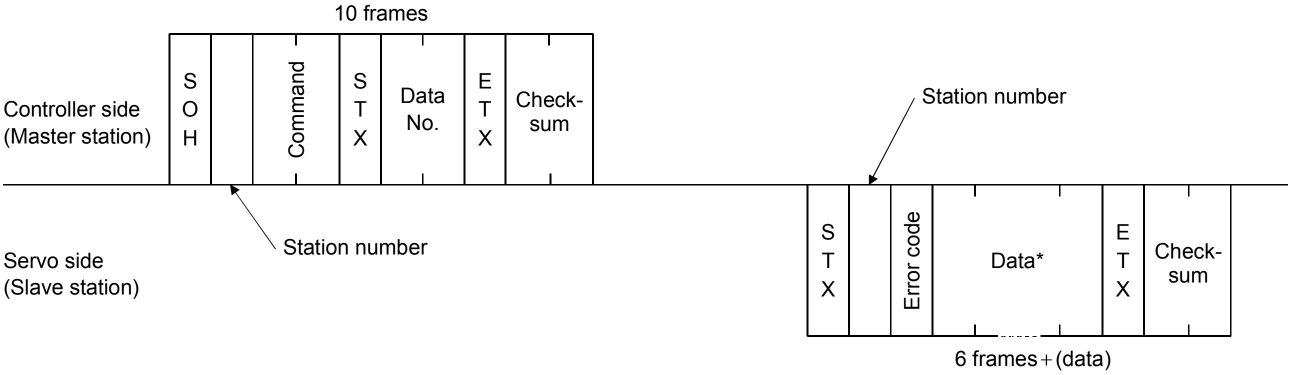
13.3.1 Transmission data configuration

Since up to 32 axes may be connected to the bus, add a station number to the command, data No., etc. to determine the destination servo amplifier of data communication. Set the station number to each servo amplifier using the parameter. Transmission data is valid for the servo amplifier of the specified station number. When "*" is set as the station number added to the transmission data, the transmission data is made valid for all servo amplifiers connected. However, when return data is required from the servo amplifier in response to the transmission data, set "0" to the station number of the servo amplifier which must provide the return data.

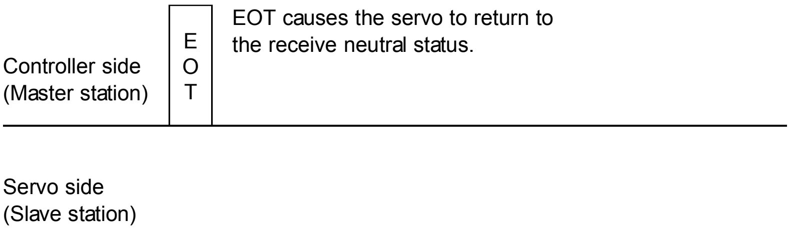
(1) Transmission of data from the controller to the servo



(2) Transmission of data request from the controller to the servo

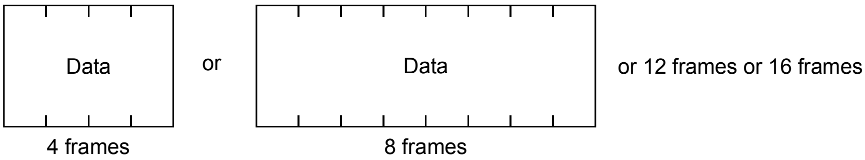


(3) Recovery of communication status by time-out



(4) Data frames

The data length depends on the command.



13.3.2 Character codes

(1) Control codes

Code name	Hexadecimal (ASCII code)	Description	Personal computer terminal key operation (General)
SOH	01H	start of head	ctrl＋A
STX	02H	start of text	ctrl＋B
ETX	03H	end of text	ctrl＋C
EOT	04H	end of transmission	ctrl＋D

(2) Codes for data

ASCII unit codes are used.

b_8	0	0	0	0	0	0	0	0
b_7	0	0	0	0	1	1	1	1
b_6	0	0	1	1	0	0	1	1
b_5	0	1	0	1	0	1	0	1

b_8 to b_5	b_4	b_3	b_2	b_1
	0	0	0	0
	0	0	0	1
	0	0	1	0
	0	0	1	1
	0	1	0	0
	0	1	0	1
	0	1	1	0
	0	1	1	1
	1	0	0	0
	1	0	0	1
	1	0	1	0
	1	0	1	1
	1	1	0	0
	1	1	0	1
	1	1	1	0
	1	1	1	1

C / R	0	1	2	3	4	5	6	7
0	NUL	DLE	Space	0	@	P	`	p
1	SOH	DC$_1$	!	1	A	Q	a	q
2	STX	DC$_2$	“	2	B	R	b	r
3	ETX	DC$_3$	#	3	C	S	c	s
4			$	4	D	T	d	t
5			%	5	E	U	e	u
6			&	6	F	V	f	v
7			‘	7	G	W	g	w
8			(	8	H	X	h	x
9			)	9	I	Y	i	y
10			＊	:	J	Z	j	z
11			+	;	K	[	k	{
12			,	<	L	¥	l	|
13			−	=	M	]	m	}
14			.	>	N	^	n	‾
15			/	?	O	–	o	DEL

(3) Station numbers

You may set 32 station numbers from station 0 to station 31 and the ASCII unit codes are used to specify the stations.

Station number	0	1	2	3	4	5	6	7	8	9	10	11	12	13	14	15
ASCII code	0	1	2	3	4	5	6	7	8	9	A	B	C	D	E	F

Station number	16	17	18	19	20	21	22	23	24	25	26	27	28	29	30	31
ASCII code	G	H	I	J	K	L	M	N	O	P	Q	R	S	T	U	V

For example, "30H" is transmitted in hexadecimal for the station number of "0" (axis 1).

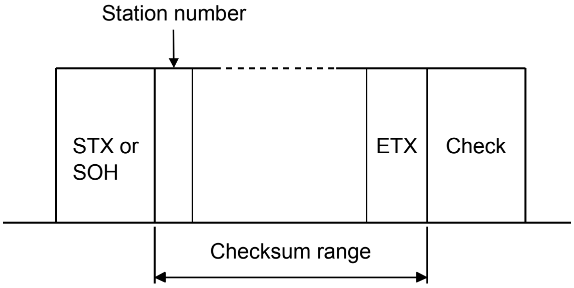
13.3.3 Error codes

Error codes are used in the following cases and an error code of single-code length is transmitted.
On receipt of data from the master station, the slave station sends the error code corresponding to that data to the master station.
The error code sent in upper case indicates that the servo is normal and the one in lower case indicates that an alarm occurred.

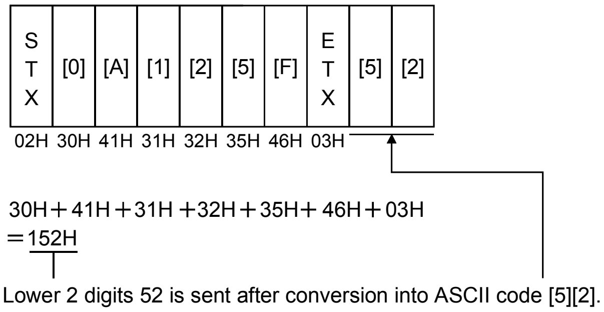
Error code		Error name	Description	Remarks
Servo normal	Servo alarm			
[A]	[a]	Normal	Data transmitted was processed properly.	Positive response
[B]	[b]	Parity error	Parity error occurred in the transmitted data.	Negative response
[C]	[c]	Checksum error	Checksum error occurred in the transmitted data.	
[D]	[d]	Character error	Character not existing in the specifications was transmitted.	
[E]	[e]	Command error	Command not existing in the specifications was transmitted.	
[F]	[f]	Data No. error	Data No. not existing in the specifications was transmitted.	

13.3.4 Checksum

The checksum is a ASCII-coded hexadecimal representing the lower two digits of the sum of ASCII-coded hexadecimal numbers up to ETX, with the exception of the first control code (STX or SOH).



(Example)

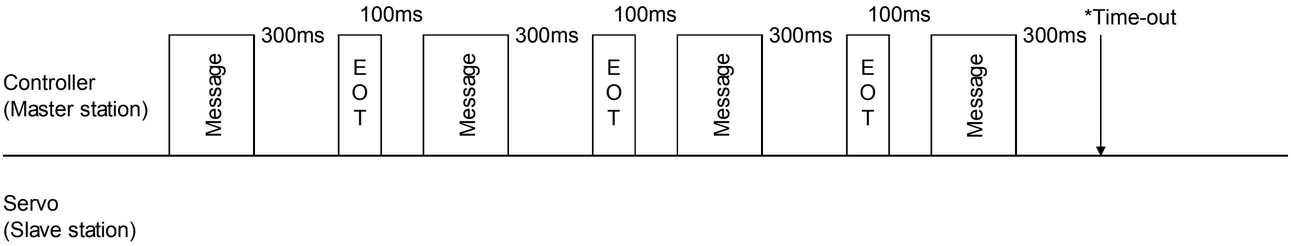


30H＋41H＋31H ＋32H＋35H＋ 46H＋03H
＝152H

Lower 2 digits 52 is sent after conversion into ASCII code [5][2].

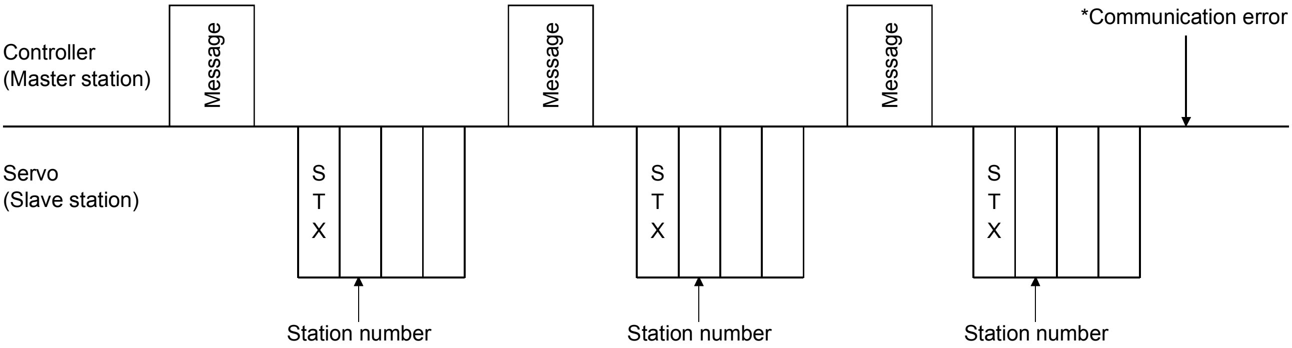
13.3.5 Time-out

The master station transmits EOT when the slave station does not start reply processing (STX is not received) 300[ms] after the master station has ended communication processing. 100[ms] after that, the master station retransmits the message. Time-out occurs if the slave station does not answer after the master station has performed the above communication processing three times. (Communication error)



13.3.6 Retry

When a fault occurs in communication between the master and slave stations, the error code in the response data from the slave station is a negative response code ([B] to [F], [b] to [f]). In this case, the master station retransmits the message which was sent at the occurrence of the fault (Retry processing). A communication error occurs if the above processing is repeated and results in the error three or more consecutive times.



Similarly, when the master station detects a fault (e.g. checksum, parity) in the response data from the slave station, the master station retransmits the message which was sent at the occurrence of the fault. A communication error occurs if the retry processing is performed three times.

13.3.7 Initialization

After the slave station is switched on, it cannot reply to communication until the internal initialization processing terminates. Hence, at power-on, ordinary communication should be started after.

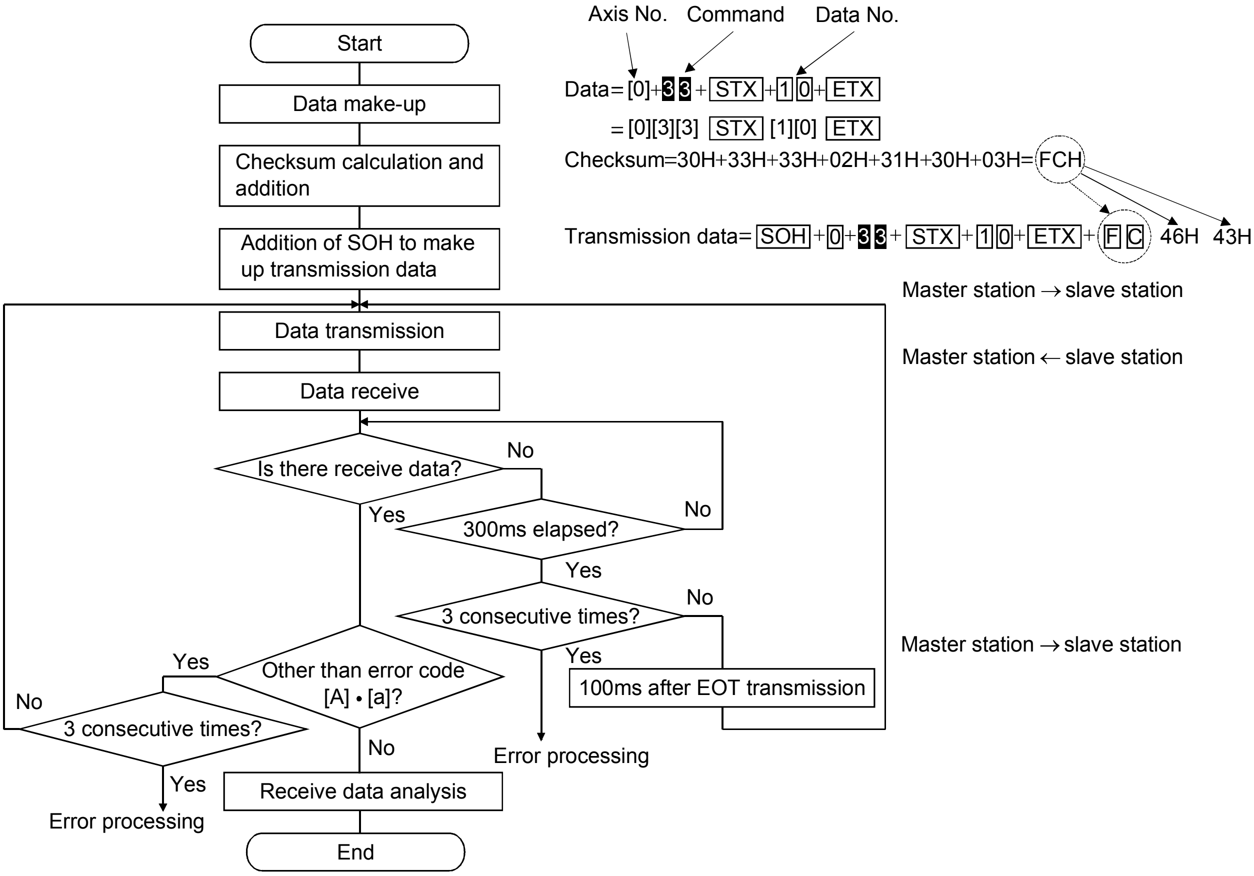
(1) 1s or longer time has elapsed after the slave station is switched on; and

(2) Making sure that normal communication can be made by reading the parameter or other data which does not pose any safety problems.

13.3.8 Communication procedure example

The following example reads the set value of alarm history (last alarm) from the servo amplifier of station 0.

Data item	Value	Description
Station number	0	Servo amplifier station 0
Command	33	Read command
Data No.	10	Alarm history (last alarm)



13.4 Command and data No. list

POINT

- If the command and data No. are the same, the description may be different from that of the servo amplifier.

13.4.1 Read commands

(1) Status display (Command [0][1])

Command	Data No.	Description	Display item	Frame length
[0][1]	[0][0]	Status display name and unit	Cumulative feedback pulse	16
	[0][1]		Servo motor speed	
	[0][2]		Droop pulse	
	[0][3]		Cumulative command pulse	
	[0][4]		Command pulse frequency	
	[0][5]		Analog speed command voltage Analog speed limit voltage	
	[0][6]		Analog torque command voltage Analog torque limit voltage	
	[0][7]		Regenerative load ratio	
	[0][8]		Effective load ratio	
	[0][9]		Peak load ratio	
	[0][A]		Instantaneous torque	
	[0][B]		Within one-revolution position	
	[0][C]		ABS counter	
	[0][D]		Load inertia moment ratio	
	[0][E]		Bus voltage	
	[8][0]	Status display data value and processing information	Cumulative feedback pulse	12
	[8][1]		Servo motor speed	
	[8][2]		Droop pulse	
	[8][3]		Cumulative command pulse	
	[8][4]		Command pulse frequency	
	[8][5]		Analog speed command voltage Analog speed limit voltage	
	[8][6]		Analog torque command voltage Analog torque limit voltage	
	[8][7]		Regenerative load ratio	
	[8][8]		Effective load ratio	
	[8][9]		Peak load ratio	
	[8][A]		Instantaneous torque	
	[8][B]		Within one-revolution position	
	[8][C]		ABS counter	
	[8][D]		Load inertia moment ratio	
	[8][E]		Bus voltage	

(2) Parameters (Command [0][4] ・ [0][5] ・ [0][6] ・ [0][7] ・ [0][8] ・ [0][9])

Command	Data No.	Description	Frame length
[0][4]	[0][1]	Parameter group read 0000: Basic setting parameter (No.PA□□) 0001: Gain filter parameter (No.PB□□) 0002: Extension setting parameter (No.PC□□) 0003: I/O setting parameter (No.PD□□)	4
[0][5]	[0][1] to [F][F]	Current values of parameters Reads the current values of the parameters in the parameter group specified with the command [8][5]＋data No.[0][0]. Before reading the current values, therefore, always specify the parameter group with the command [8][5]＋data No.[0][0]. The decimal equivalent of the data No. value (hexadecimal) corresponds to the parameter number.	8
[0][6]	[0][1] to [F][F]	Upper limit values of parameter setting ranges Reads the permissible upper limit values of the parameters in the parameter group specified with the command [8][5]＋data No.[0][0]. Before reading the upper limit values, therefore, always specify the parameter group with the command [8][5]＋data No.[0][0]. The decimal equivalent of the data No. value (hexadecimal) corresponds to the parameter number.	8
[0][7]	[0][1] to [F][F]	Lower limit values of parameter setting ranges Reads the permissible lower limit values of the parameters in the parameter group specified with the command [8][5]＋data No.[0][0]. Before reading the lower limit values, therefore, always specify the parameter group with the command [8][5]＋data No.[0][0]. The decimal equivalent of the data No. value (hexadecimal) corresponds to the parameter number.	8
[0][8]	[0][1] to [F][F]	Abbreviations of parameters Reads the abbreviations of the parameters in the parameter group specified with the command [8][5]＋data No.[0][0]. Before reading the abbreviations, therefore, always specify the parameter group with the command [8][5]＋data No.[0][0]. The decimal equivalent of the data No. value (hexadecimal) corresponds to the parameter number.	12
[0][9]	[0][1] to [F][F]	Write enable/disable of parameters Reads write enable/disable of the parameters in the parameter group specified with the command [8][5]＋data No.[0][0]. Before reading write enable/disable, therefore, always specify the parameter group with the command [8][5]＋data No.[0][0]. 0000: Write enabled 0001: Write disabled	4

(3) External I/O signals (Command [1][2])

Command	Data No.	Description	Frame length
[1][2]	[0][0]	Input device status	8
	[4][0]	External input pin status	
	[6][0]	Status of input device turned ON by communication	
	[8][0]	Output device status	
	[C][0]	External output pin status	

(4) Alarm history (Command [3][3])

Command	Data No.	Description	Alarm occurrence sequence	Frame length
[3][3]	[1][0]	Alarm number in alarm history	most recent alarm	4
	[1][1]		first alarm in past	
	[1][2]		second alarm in past	
	[1][3]		third alarm in past	
	[1][4]		fourth alarm in past	
	[1][5]		fifth alarm in past	
	[2][0]	Alarm occurrence time in alarm history	most recent alarm	8
	[2][1]		first alarm in past	
	[2][2]		second alarm in past	
	[2][3]		third alarm in past	
	[2][4]		fourth alarm in past	
	[2][5]		fifth alarm in past	

(5) Current alarm (Command [0][2])

Command	Data No.	Description	Frame length
[0][2]	[0][0]	Current alarm number	4

Command	Data No.	Description	Display item	Frame length
[3][5]	[0][0]	Status display name and unit at alarm occurrence	Cumulative feedback pulse	16
	[0][1]		Servo motor speed	
	[0][2]		Droop pulse	
	[0][3]		Cumulative command pulse	
	[0][4]		Command pulse frequency	
	[0][5]		Analog speed command voltage Analog speed limit voltage	
	[0][6]		Analog torque command voltage Analog torque limit voltage	
	[0][7]		Regenerative load ratio	
	[0][8]		Effective load ratio	
	[0][9]		Peak load ratio	
	[0][A]		Instantaneous torque	
	[0][B]		Within one-revolution position	
	[0][C]		ABS counter	
	[0][D]		Load inertia moment ratio	
	[0][E]		Bus voltage	
	[8][0]	Status display data value and processing information at alarm occurrence	Cumulative feedback pulse	12
	[8][1]		Servo motor speed	
	[8][2]		Droop pulse	
	[8][3]		Cumulative command pulse	
	[8][4]		Command pulse frequency	
	[8][5]		Analog speed command voltage Analog speed limit voltage	
	[8][6]		Analog torque command voltage Analog torque limit voltage	
	[8][7]		Regenerative load ratio	
	[8][8]		Effective load ratio	
	[8][9]		Peak load ratio	
	[8][A]		Instantaneous torque	
	[8][B]		Within one-revolution position	
	[8][C]		ABS counter	
	[8][D]		Load inertia moment ratio	
	[8][E]		Bus voltage	

(6) Test operation mode (Command [0][0])

Command	Data No.	Description	Frame length
[0][0]	[1][2]	Test operation mode read 0000: Normal mode (not test operation mode) 0001: JOG operation 0002: Positioning operation 0003: Motorless operation 0004: Output signal (DO) forced output	4

(7) Others

Command	Data No.	Description	Frame length
[0][2]	[9][0]	Servo motor end pulse unit absolute position	8
	[9][1]	Command unit absolute position	8
	[7][0]	Software version	16

13.4.2 Write commands

(1) Status display (Command [8][1])

Command	Data No.	Description	Setting range	Frame length
[8][1]	[0][0]	Status display data erasure	1EA5	4

(2) Parameters (Command [8][4] ･ [8][5])

Command	Data No.	Description	Setting range	Frame length
[8][4]	[0][1] to [F][F]	Write of parameters Writes the values of the parameters in the parameter group specified with the command [8][5]＋data No.[0][0]. Before writing the values, therefore, always specify the parameter group with the command [8][5]＋data No.[0][0]. The decimal equivalent of the data No. value (hexadecimal) corresponds to the parameter number.	Depending on the parameter	8
[8][5]	[0][0]	Parameter group write 0000: Basic setting parameter (No.PA□□) 0001: Gain filter parameter (No.PB□□) 0002: Extension setting parameter (No.PC□□) 0003: I/O setting parameter (No.PD□□)	0000 to 0003	4

(3) External I/O signal (Command [9][2])

Command	Data No.	Description	Setting range	Frame length
[9][2]	[6][0]	Communication input device signal	Refer to section 13.5.5	8

(4) Alarm history (Command [8][2])

Command	Data No.	Description	Setting range	Frame length
[8][2]	[2][0]	Alarm history erasure	1EA5	4

(5) Current alarm (Command [8][2])

Command	Data No.	Description	Setting range	Frame length
[8][2]	[0][0]	Alarm erasure	1EA5	4

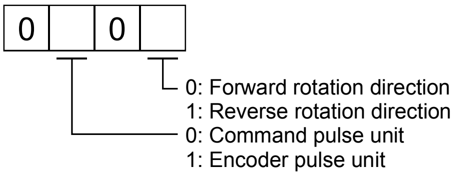
(6) I/O device prohibition (Command [9][0])

Command	Data No.	Description	Setting range	Frame length
[9][0]	[0][0]	Turns OFF the input device, external analog input signal or pulse train input, except EMG, LSP and LSN, independently of the external ON/OFF status.	1EA5	4
	[0][3]	Disables all output devices (DO).	1EA5	4
	[1][0]	Cancels the prohibition of the input device, external analog input signal or pulse train input, except EMG, LSP and LSN.	1EA5	4
	[1][3]	Cancels the prohibition of the output device.	1EA5	4

(7) Operation mode selection (Command [8][B])

Command	Data No.	Description	Setting range	Frame length
[8][B]	[0][0]	Operation mode switching 0000: Test operation mode cancel 0001: JOG operation 0002: Positioning operation 0003: Motorless operation 0004: Output signal (DO) forced output	0000 to 0004	4

(8) Test operation mode data (Command [9][2] ･ [A][0])

Command	Data No.	Description	Setting range	Frame length
[9][2]	[0][0]	Input signal for test operation	Refer to section 13.5.7.	8
	[A][0]	Forced output of signal pin	Refer to section 13.5.9.	8
[A][0]	[1][0]	Writes the speed in the test operation mode (JOG operation, positioning operation).	0000 to 7FFF	4
	[1][1]	Writes the acceleration/deceleration time constant in the test operation mode (JOG operation, positioning operation).	00000000 to 7FFFFFFF	8
	[2][0]	Sets the moving distance in the test operation mode (JOG operation, positioning operation).	00000000 to 7FFFFFFF	8
	[2][1]	Selects the positioning direction of test operation (positioning operation). 	0000 to 0001	4
	[4][0]	Test operation (positioning operation) start command.	1EA5	4
	[4][1]	Used to make a temporary stop during test operation (positioning operation). ☐ in the data indicates a blank. STOP: Temporary stop GO☐☐: Restart for remaining distance CLR☐: Remaining distance clear.	STOP GO☐☐ CLR☐	4

13.5 Detailed explanations of commands

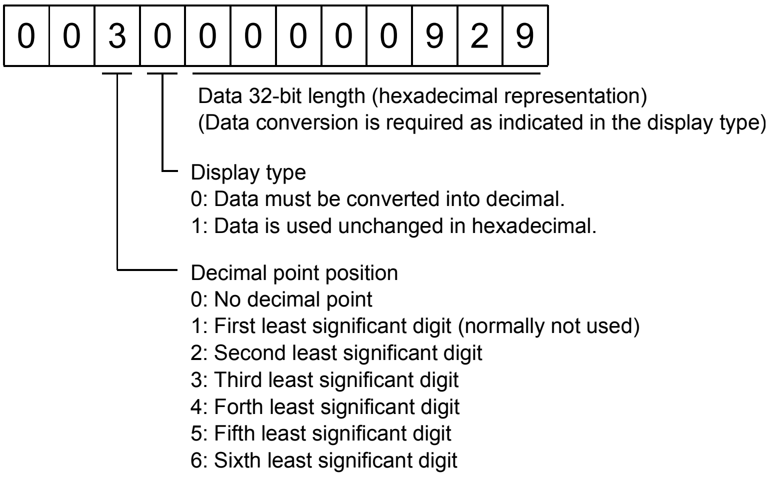
13.5.1 Data processing

When the master station transmits a command＋data No. or a command＋data No.＋data to a slave station, the servo amplifier returns a reply or data according to the purpose.
When numerical values are represented in these send data and receive data, they are represented in decimal, hexadecimal, etc.
Therefore, data must be processed according to the application.
Since whether data must be processed or not and how to process data depend on the monitoring, parameters, etc., follow the detailed explanation of the corresponding command.
The following methods are how to process send and receive data when reading and writing data.

(1) Processing the read data

When the display type is 0, the eight-character data is converted from hexadecimal to decimal and a decimal point is placed according to the decimal point position information.
When the display type is 1, the eight-character data is used unchanged.

The following example indicates how to process the receive data "003000000929" given to show.
The receive data is as follows.



Data 32-bit length (hexadecimal representation)
(Data conversion is required as indicated in the display type)

Display type
0: Data must be converted into decimal.
1: Data is used unchanged in hexadecimal.

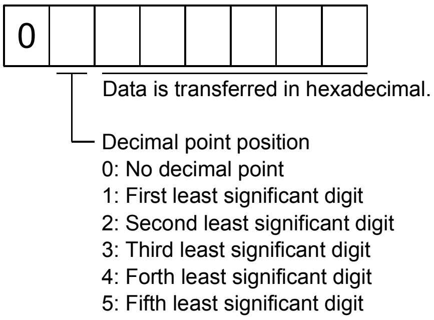
Decimal point position
0: No decimal point
1: First least significant digit (normally not used)
2: Second least significant digit
3: Third least significant digit
4: Forth least significant digit
5: Fifth least significant digit
6: Sixth least significant digit

Since the display type is "0" in this case, the hexadecimal data is converted into decimal.
00000929H→2345
As the decimal point position is "3", a decimal point is placed in the third least significant digit.
Hence, "23.45" is displayed.

(2) Writing the processed data

When the data to be written is handled as decimal, the decimal point position must be specified. If it is not specified, the data cannot be written. When the data is handled as hexadecimal, specify "0" as the decimal point position.

The data to be sent is the following value.



By way of example, here is described how to process the set data when a value of "15.5" is sent.

Since the decimal point position is the second digit, the decimal point position data is "2".

As the data to be sent is hexadecimal, the decimal data is converted into hexadecimal.

155→9B

Hence, "0200009B" is transmitted.

13.5.2 Status display

(1) Reading the status display name and unit

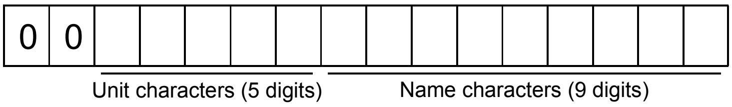
Read the status display name and unit.

(a) Transmission

Transmit command [0][1] and the data No. corresponding to the status display item to be read, [0][0] to [0][E]. (Refer to section 13.4.1.)

(b) Reply

The slave station sends back the status display name and unit requested.



(2) Status display data read

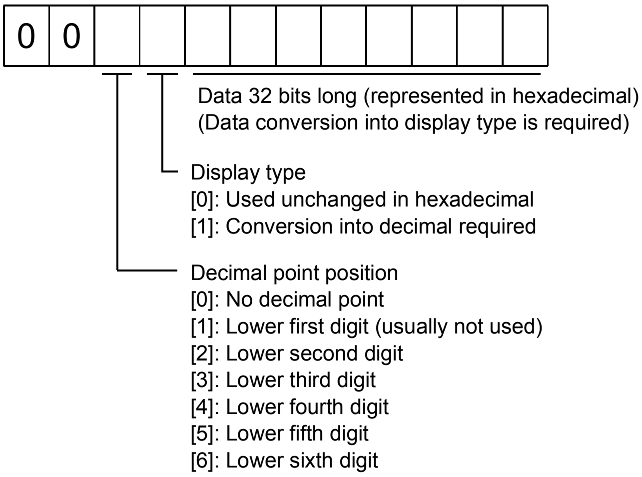
Read the status display data and processing information.

(a) Transmission

Transmit command [0][1] and the data No. corresponding to the status display item to be read. Refer to section 13.4.1.

(b) Reply

The slave station sends back the status display data requested.



(3) Status display data clear

The cumulative feedback pulse data of the status display is cleared. Send this command immediately after reading the status display item. The data of the status display item transmitted is cleared to zero.

Command	Data No.	Data
[8][1]	[0][0]	[1][E][A][5]

For example, after sending command [0][1] and data No.[8][0] and receiving the status display data, send command [8][1], data No.[0][0] and data [1EA5] to clear the cumulative feedback pulse value to zero.

13.5.3 Parameters

(1) Specify the parameter group

The group of the parameters to be operated must be specified in advance to read or write the parameter settings, etc. Write data to the servo amplifier as described below to specify the parameter group to be operated.

Command	Data No.	Transmission data	Parameter group
[8][5]	[0][0]	0000	Basic setting parameter (No.PA□□)
		0001	Gain filter parameter (No.PB□□)
		0002	Extension setting parameter (No.PC□□)
		0003	I/O setting parameter (No.PD□□)

(2) Reading the parameter group

Read the parameter group.

(a) Transmission

Send command [0][4] and data No.[0][1].

Command	Data No.
[0][4]	[0][1]

(b) Reply

The slave station sends back the preset parameter group.

0	0	0	

Parameter group
0: Basic setting parameter (No.PA□□)
1: Gain filter parameter (No.PB□□)
2: Extension setting parameter (No.PC□□)
3: I/O setting parameter (No.PD□□)

(3) Reading the symbol

Read the parameter name. Specify the parameter group in advance (refer to (1) in this section).

(a) Transmission

Transmit command [0][8] and the data No. corresponding to the parameter No., [0][1] to [F][F]. (Refer to section 13.4.1.)

The data No. is expressed in hexadecimal. The decimal equivalent of the data No. value corresponds to the parameter number.

(b) Reply

The slave station sends back the name of the parameter No. requested.

0	0	0									

Name characters (9 digits)

(4) Reading the setting

Read the parameter setting. Specify the parameter group in advance (refer to (1) in this section).

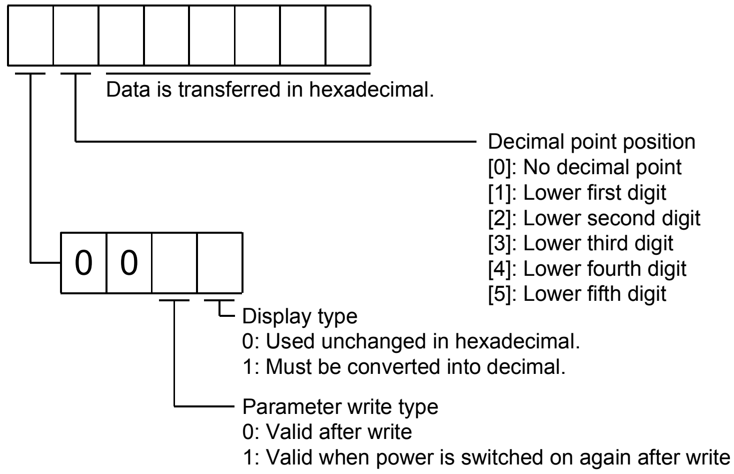
(a) Transmission

Transmit command [0][5] and the data No. corresponding to the parameter No., [0][1] to [F][F]. (Refer to section 13.4.1.)

The data No. is expressed in hexadecimal. The decimal equivalent of the data No. value corresponds to the parameter number.

(b) Reply

The slave station sends back the data and processing information of the parameter No. requested.



For example, data "1200270F" means 999.9 (decimal display format) and data "0003ABC" means 3ABC (hexadecimal display format).

When the display type is "0" (hexadecimal) and the decimal point position is other than 0, the display type is a special hexadecimal display format and "F" of the data value is handled as a blank. Data "01FFF053" means 053 (special hexadecimal display format).

"000000" is transferred when the parameter that was read is the one inaccessible for write/reference in the parameter write disable setting of parameter No.PA19.

(5) Reading the setting range

Read the parameter setting range. Specify the parameter group in advance (refer to (1) in this section).

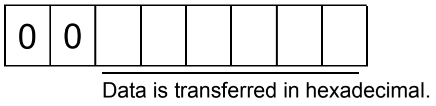
(a) Transmission

When reading the upper limit value, transmit command [0][6] and the data No. corresponding to the parameter No., [0][0] to [F][F]. When reading the lower limit value, transmit command [0][7] and the data No. corresponding to the parameter No., [0][0] to [F][F]. (Refer to section 13.4.1.)

The data No. is expressed in hexadecimal. The decimal equivalent of the data No. value corresponds to the parameter number.

(b) Reply

The slave station sends back the data and processing information of the parameter No. requested.



For example, data "10FFFFEC" means -20.

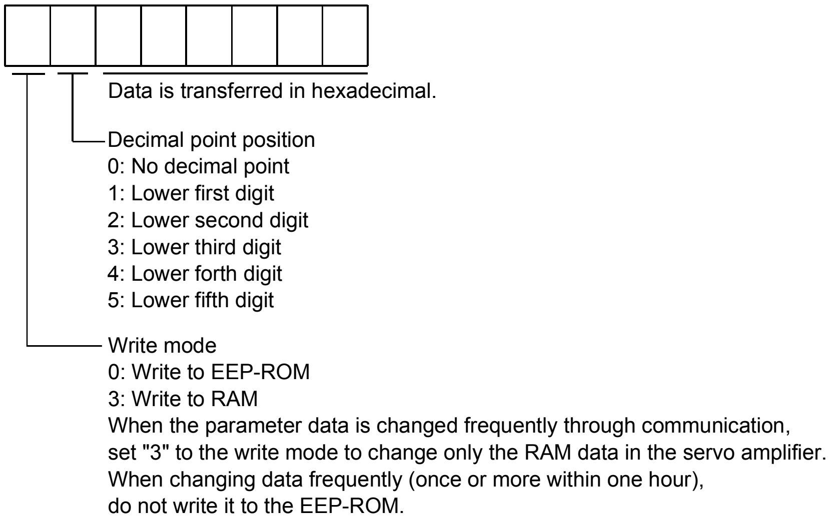
(6) Parameter write

POINT

- If setting values need to be changed with a high frequency (i.e. one time or more per one hour), write the setting values to the RAM, not the EEP-ROM. The EEP-ROM has a limitation in the number of write times and exceeding this limitation causes the servo amplifier to malfunction. Note that the number of write times to the EEP-ROM is limited to approximately 100, 000.

Write the parameter setting into EEP-ROM of the servo amplifier. Specify the parameter group in advance (refer to (1) in this section).
Write the value within the setting enabled range. For the setting enabled range, refer to chapter 5 or read the setting range by performing operation in (3) in this section.
Transmit command [8][4], the data No. , and the set data.
The data No. is expressed in hexadecimal. The decimal equivalent of the data No. value corresponds to the parameter number.
When the data to be written is handled as decimal, the decimal point position must be specified. If it is not specified, data cannot be written. When the data is handled as hexadecimal, specify 0 as the decimal point position.
Write the data after making sure that it is within the upper/lower limit value range.
Read the parameter data to be written, confirm the decimal point position, and create transmission data to prevent error occurrence. On completion of write, read the same parameter data to verify that data has been written correctly.

Command	Data No.	Set data
[8][4]	[0][0] to [F][F]	See below.



When the parameter data is changed frequently through communication, set "3" to the write mode to change only the RAM data in the servo amplifier. When changing data frequently (once or more within one hour), do not write it to the EEP-ROM.

13.5.4 External I/O signal statuses (DIO diagnosis)

(1) Reading of input device statuses

Read the statuses of the input devices.

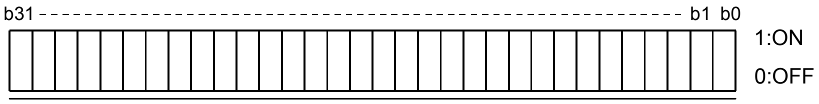
(a) Transmission

Transmit command [1][2] and data No.[0][0].

Command	Data No.
[1][2]	[0][0]

(b) Reply

The slave station sends back the statuses of the input pins.



Command of each bit is transmitted to the master station as hexadecimal data.

bit	Abbreviation	bit	Abbreviation	bit	Abbreviation	bit	Abbreviation
0	SON	8	SP1	16		24	
1	LSP	9	SP2	17		25	
2	LSN	10	SP3	18		26	
3	TL	11	ST1	19		27	CDP
4	TL1	12	ST2	20	STAB2	28	
5	PC	13	CM1	21		29	
6	RES	14	CM2	22		30	
7	CR	15	LOP	23		31	

(2) External input pin status read

Read the ON/OFF statuses of the external output pins.

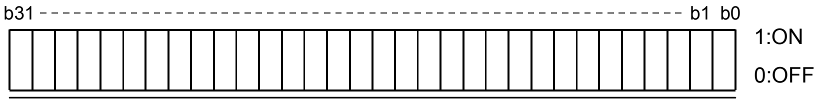
(a) Transmission

Transmit command [1][2] and data No.[4][0].

Command	Data No.
[1][2]	[4][0]

(b) Reply

The ON/OFF statuses of the input pins are sent back.



Command of each bit is transmitted to the master station as hexadecimal data.

bit	CN1 connector pin	bit	CN1 connector pin	bit	CN1 connector pin	bit	CN1 connector pin
0	43	8	18	16		24	
1	44	9	45	17		25	
2	42	10		18		26	
3	15	11		19		27	
4	19	12		20		28	
5	41	13		21		29	
6	16	14		22		30	
7	17	15		23		31	

(3) Read of the statuses of input devices switched on through communication

Read the ON/OFF statuses of the input devices switched on through communication.

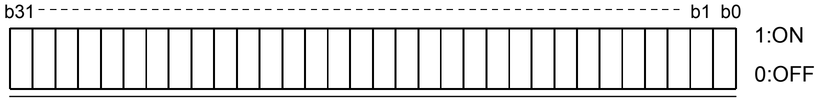
(a) Transmission

Transmit command [1][2] and data No.[6][0].

Command	Data No.
[1][2]	[6][0]

(b) Reply

The slave station sends back the statuses of the input pins.



Command of each bit is transmitted to the master station as hexadecimal data.

bit	Abbreviation	bit	Abbreviation	bit	Abbreviation	bit	Abbreviation
0	SON	8	SP1	16		24	
1	LSP	9	SP2	17		25	
2	LSN	10	SP3	18		26	
3	TL	11	ST1	19		27	CDP
4	TL1	12	ST2	20	STAB2	28	
5	PC	13	CM1	21		29	
6	RES	14	CM2	22		30	
7	CR	15	LOP	23		31	

(4) External output pin status read

Read the ON/OFF statuses of the external output pins.

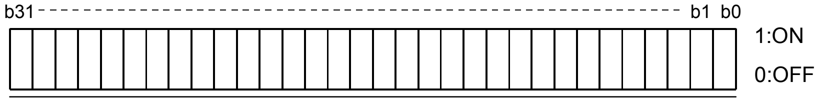
(a) Transmission

Transmit command [1][2] and data No.[C][0].

Command	Data No.
[1][2]	[C][0]

(b) Reply

The slave station sends back the ON/OFF statuses of the output pins.



Command of each bit is transmitted to the master station as hexadecimal data.

bit	CN1 connector pin
0	49
1	24
2	23
3	25
4	22
5	48
6	33
7	

bit	CN1 connector pin
8	
9	
10	
11	
12	
13	
14	
15	

bit	CN1 connector pin
16	
17	
18	
19	
20	
21	
22	
23	

bit	CN1 connector pin
24	
25	
26	
27	
28	
29	
30	
31	

(5) Read of the statuses of output devices

Read the ON/OFF statuses of the output devices.

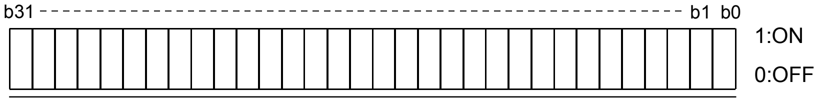
(a) Transmission

Transmit command [1][2] and data No.[8][0].

Command	Data No.
[1][2]	[8][0]

(b) Reply

The slave station sends back the statuses of the output devices.



Command of each bit is transmitted to the master station as hexadecimal data.

bit	Abbreviation
0	RD
1	SA
2	ZSP
3	TLC
4	VLC
5	INP
6	
7	WNG

bit	Abbreviation
8	ALM
9	OP
10	MBR
11	
12	ACD0
13	ACD1
14	ACD2
15	BWNG

bit	Abbreviation
16	
17	
18	
19	
20	
21	
22	
23	

bit	Abbreviation
24	
25	CDPS
26	
27	ABSV
28	
29	
30	
31	

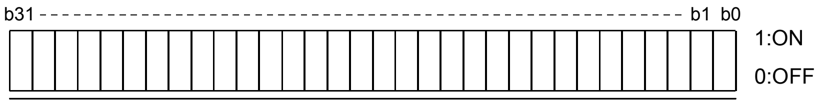
13.5.5 Input device ON/OFF

POINT

- The ON/OFF states of all devices in the servo amplifier are the states of the data received last. Hence, when there is a device which must be kept ON, send data which turns that device ON every time.

Each input device can be switched on/off. However, when the device to be switched off exists in the external input signal, also switch off that input signal.
Send command [9][2], data No.[6][0] and data.

Command	Data No.	Set data
[9][2]	[6][0]	See below.



Command of each bit is transmitted to the slave station as hexadecimal data.

bit	Abbreviation
0	SON
1	LSP
2	LSN
3	TL
4	TL1
5	PC
6	RES
7	CR

bit	Abbreviation
8	SP1
9	SP2
10	SP3
11	ST1
12	ST2
13	CM1
14	CM2
15	LOP

bit	Abbreviation
16	
17	
18	
19	
20	STAB2
21	
22	
23	

bit	Abbreviation
24	
25	
26	
27	CDP
28	
29	
30	
31	

13.5.6 Disable/enable of I/O devices (DIO)

Inputs can be disabled independently of the I/O devices ON/OFF. When inputs are disabled, the input signals (devices) are recognized as follows. Among the input devices, EMG, LSP and LSN cannot be disabled.

Signal	Status
Input devices (DI)	OFF
External analog input signals	0V
Pulse train inputs	None

(1) Disabling/enabling the input devices (DI), external analog input signals and pulse train inputs with the exception of EMG, LSP and LSN.
Transmit the following communication commands.

(a) Disable

Command	Data No.	Data
[9][0]	[0][0]	1EA5

(b) Enable

Command	Data No.	Data
[9][0]	[1][0]	1EA5

(2) Disabling/enabling the output devices (DO)
Transmit the following communication commands.

(a) Disable

Command	Data No.	Data
[9][0]	[0][3]	1EA5

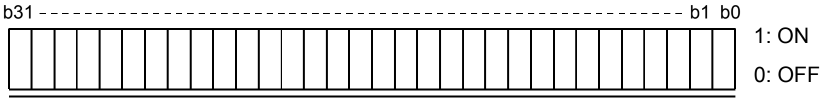
(b) Enable

Command	Data No.	Data
[9][0]	[1][3]	1EA5

13.5.7 Input devices ON/OFF (test operation)

Each input devices can be turned on/off for test operation. when the device to be switched off exists in the external input signal, also switch off that input signal.
Send command [9] [2], data No.[0] [0] and data.

Command	Data No.	Set data
[9][2]	[0][0]	See below



Command of each bit is transmitted to the slave station as hexadecimal data.

bit	Abbreviation
0	SON
1	LSP
2	LSN
3	TL
4	TL1
5	PC
6	RES
7	CR

bit	Abbreviation
8	SP1
9	SP2
10	SP3
11	ST1
12	ST2
13	CM1
14	CM2
15	LOP

bit	Abbreviation
16	
17	
18	
19	
20	STAB2
21	
22	
23	

bit	Abbreviation
24	
25	
26	
27	CDP
28	
29	
30	
31	

13.5.8 Test operation mode

POINT

- The test operation mode is used to confirm operation. Do not use it for actual operation.
- If communication stops for longer than 0.5s during test operation, the servo amplifier decelerates to a stop, resulting in servo lock. To prevent this, continue communication all the time, e.g. monitor the status display.
- Even during operation, the servo amplifier can be put in the test operation mode. In this case, as soon as the test operation mode is selected, the base circuit is shut off, coasting the servo amplifier.

(1) Preparation and cancel of test operation mode

(a) Preparation of test operation mode

Set the test operation mode type in the following procedure.

1) Selection of test operation mode

Send the command [8][B]＋data No.[0][0] to select the test operation mode.

Command	Data No.	Transmission data	Test operation mode selection
[8][B]	[0][0]	0001	JOG operation
		0002	Positioning operation
		0003	Motorless operation
		0004	DO forced output (Note)

Note. Refer to section 13.5.9 for DO forced output.

2) Confirmation of test operation mode

Read the test operation mode set for the slave station, and confirm that it is set correctly.

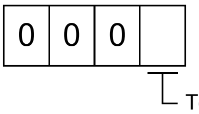
a. Transmission

Send the command [0][0]＋data No.[1][2].

Command	Data No.
[0][0]	[1][2]

b. Return

The slave station returns the set test operation mode.



Test operation mode read
0: Normal mode (not test operation mode)
1: JOG operation
2: Positioning operation
3: Motorless operation
4: DO forced output

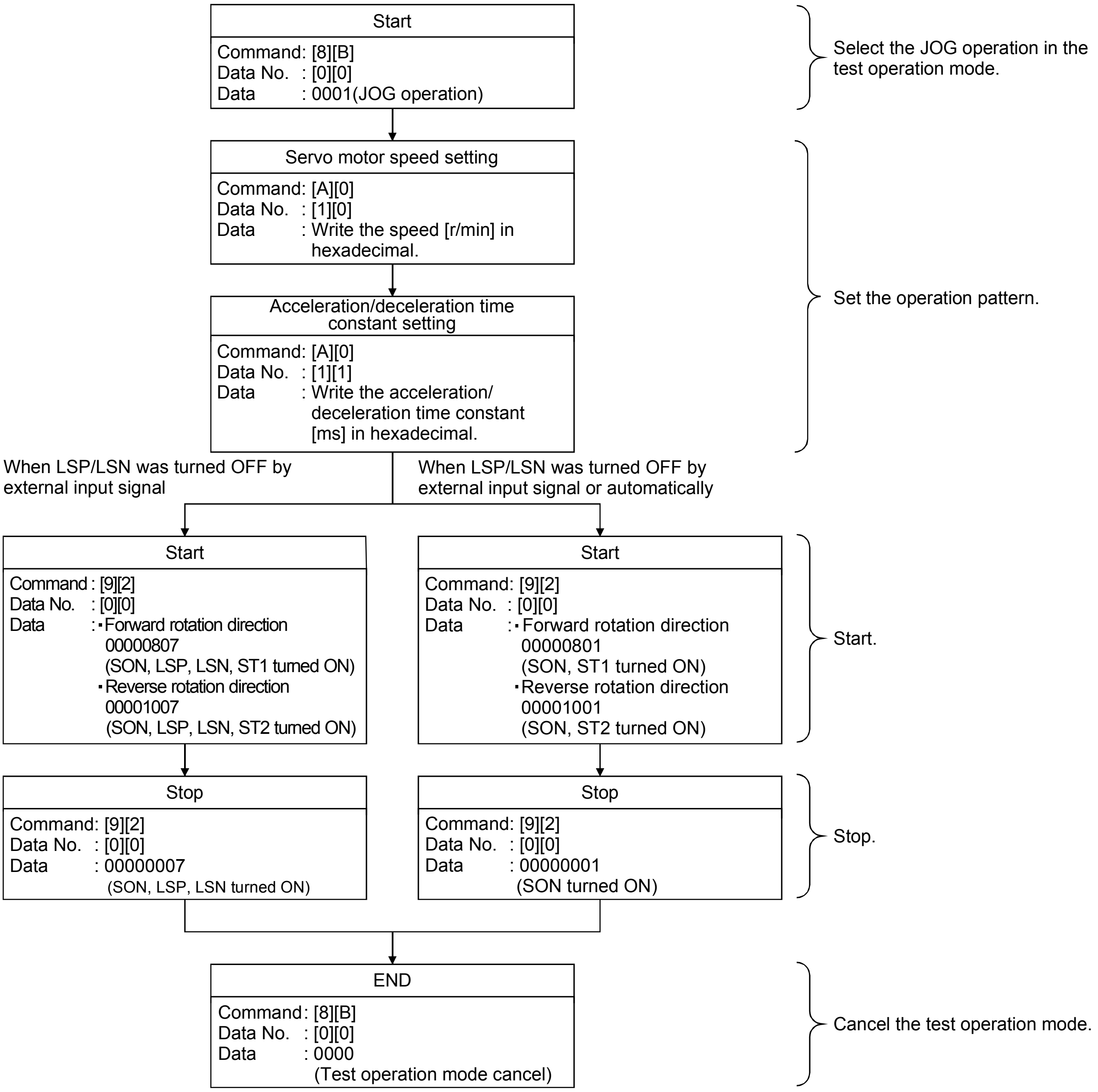
(b) Cancel of test operation mode

To terminate the test operation mode, send the command [8][B]＋data No.[0][0]＋data.

Command	Data No.	Transmission data	Test operation mode selection
[8][B]	[0][0]	0000	Test operation mode cancel

(2) JOG operation

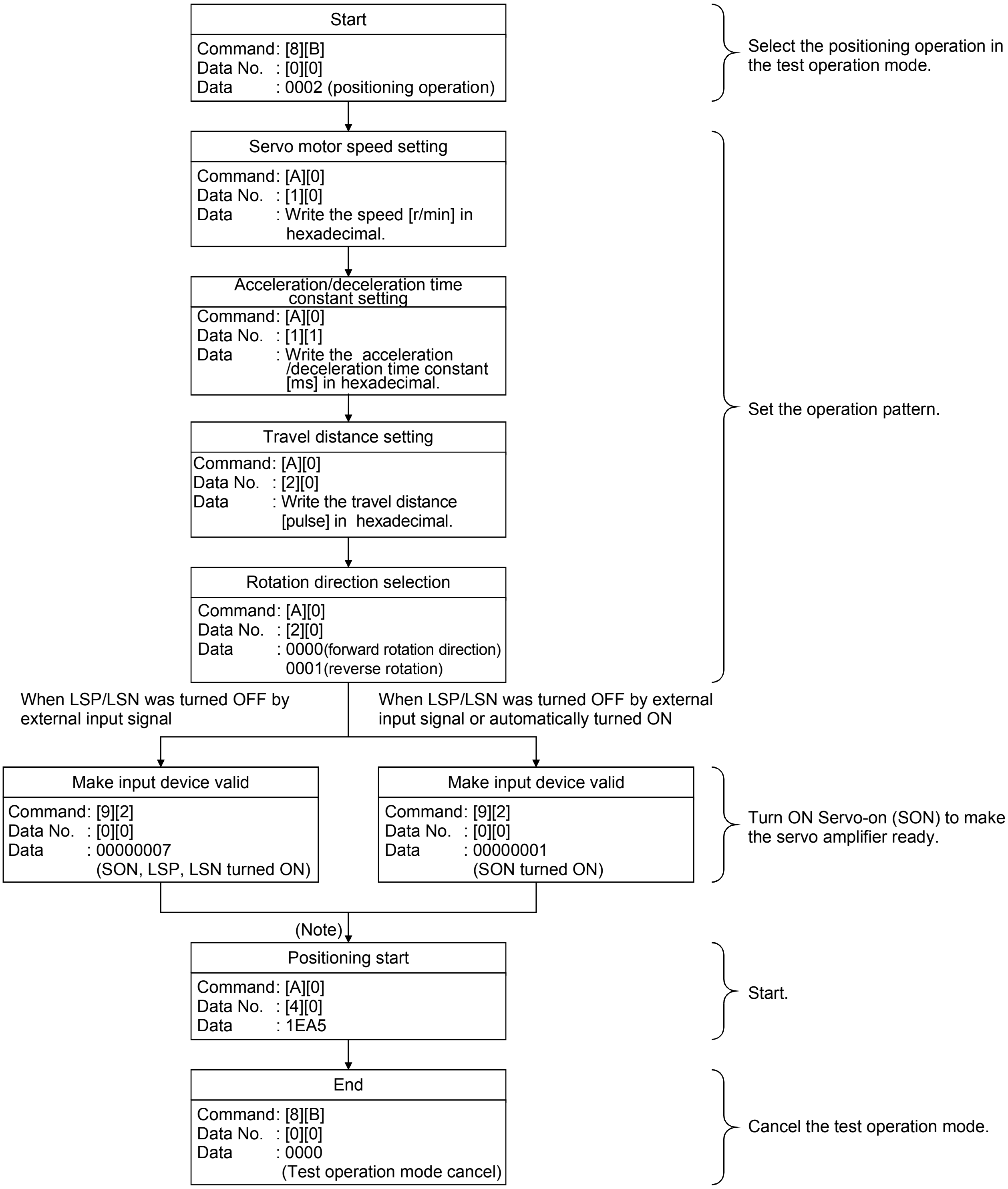
Send the command, data No. and data as indicated below to execute JOG operation.



(3) Positioning operation

(a) Operation procedure

Send the command, data No. and data as indicated below to execute positioning operation.



Start
Command: [8][B]
Data No. : [0][0]
Data : 0002 (positioning operation)

Select the positioning operation in the test operation mode.

Servo motor speed setting
Command: [A][0]
Data No. : [1][0]
Data : Write the speed [r/min] in hexadecimal.

Acceleration/deceleration time constant setting
Command: [A][0]
Data No. : [1][1]
Data : Write the acceleration /deceleration time constant [ms] in hexadecimal.

Travel distance setting
Command: [A][0]
Data No. : [2][0]
Data : Write the travel distance [pulse] in hexadecimal.

Rotation direction selection
Command: [A][0]
Data No. : [2][0]
Data : 0000(forward rotation direction)
0001(reverse rotation)

Set the operation pattern.

When LSP/LSN was turned OFF by external input signal

Make input device valid
Command: [9][2]
Data No. : [0][0]
Data : 00000007
(SON, LSP, LSN turned ON)

When LSP/LSN was turned OFF by external input signal or automatically turned ON

Make input device valid
Command: [9][2]
Data No. : [0][0]
Data : 00000001
(SON turned ON)

Turn ON Servo-on (SON) to make the servo amplifier ready.

(Note)

Positioning start
Command: [A][0]
Data No. : [4][0]
Data : 1EA5

Start.

End
Command: [8][B]
Data No. : [0][0]
Data : 0000
(Test operation mode cancel)

Cancel the test operation mode.

Note. There is a 100ms delay.

(b) Temporary stop/restart/remaining distance clear

Send the following command, data No. and data during positioning operation to make deceleration to a stop.

Command	Data No.	Data
[A][0]	[4][1]	STOP

Send the following command, data No. and data during a temporary stop to make a restart.

Command	Data No.	(Note) Data
[A][0]	[4][1]	GO☐☐

Note. ☐ indicates a blank.

Send the following command, data No. and data during a temporary stop to stop positioning operation and erase the remaining travel distance.

Command	Data No.	(Note) Data
[A][0]	[4][1]	CLR☐

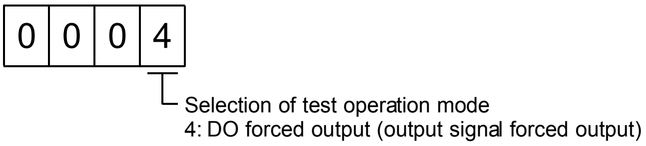
Note. ☐ indicates a blank.

13.5.9 Output signal pin ON/OFF output signal (DO) forced output

In the test operation mode, the output signal pins can be turned on/off independently of the servo status. Using command [9][0], disable the output signals in advance.

(1) Choosing DO forced output in test operation mode

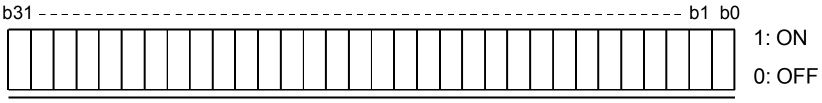
Transmit command [8][B]＋data No.[0][0]＋data "0004" to choose DO forced output.



(2) External output signal ON/OFF

Transmit the following communication commands.

Command	Data No.	Setting data
[9][2]	[A][0]	See below.



Command of each bit is sent to the slave station in hexadecimal.

bit	CN1 connector pin
0	49
1	24
2	23
3	25
4	22
5	48
6	33
7	

bit	CN1 connector pin
8	
9	
10	
11	
12	
13	
14	
15	

bit	CN1 connector pin
16	
17	
18	
19	
20	
21	
22	
23	

bit	CN1 connector pin
24	
25	
26	
27	
28	
29	
30	
31	

(3) DO forced output

Transmit command [8][B]＋data No.[0][0]＋data to choose DO forced output.

Command	Data No.	Transmission data	Test operation mode selection
[8][B]	[0][0]	0000	Test operation mode cancel

13.5.10 Alarm history

(1) Alarm No. read

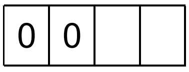
Read the alarm No. which occurred in the past. The alarm numbers and occurrence times of No.0 (last alarm) to No.5 (sixth alarm in the past) are read.

(a) Transmission

Send command [3][3] and data No.[1][0] to [1][5]. Refer to section 13.4.1.

(b) Reply

The alarm No. corresponding to the data No. is provided.



Alarm No. is transferred in hexadecimal.

For example, "0032" means AL.32 and "00FF" means AL._ (no alarm).

(2) Alarm occurrence time read

Read the occurrence time of alarm which occurred in the past.

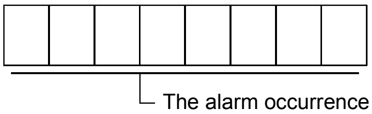
The alarm occurrence time corresponding to the data No. is provided in terms of the total time beginning with operation start, with the minute unit omitted.

(a) Transmission

Send command [3][3] and data No.[2][0] to [2][5].

Refer to section 13.4.1.

(b) Reply



The alarm occurrence time is transferred in hexadecimal.
Hexadecimal must be converted into decimal.

For example, data "01F5" means that the alarm occurred in 501 hours after start of operation.

(3) Alarm history clear

Erase the alarm history.

Send command [8][2] and data No. [2][0].

Command	Data No.	Data
[8][2]	[2][0]	1EA5

13.5.11 Current alarm

(1) Current alarm read

Read the alarm No. which is occurring currently.

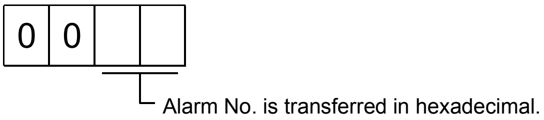
(a) Transmission

Send command [0][2] and data No.[0][0].

Command	Data No.
[0][2]	[0][0]

(b) Reply

The slave station sends back the alarm currently occurring.



For example, "0032" means AL.32 and "00FF" means AL._ (no alarm).

(2) Read of the status display at alarm occurrence

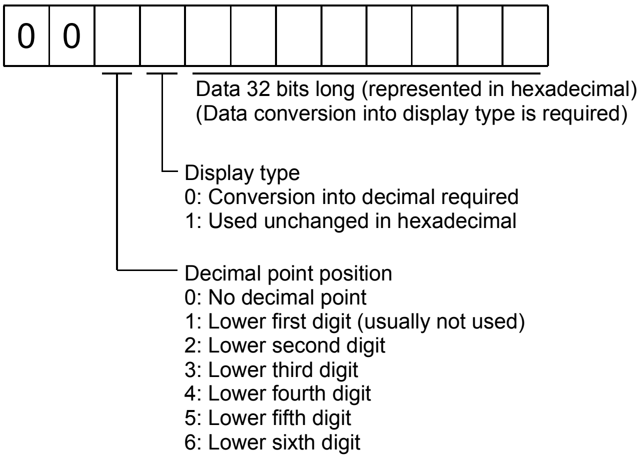
Read the status display data at alarm occurrence. When the data No. corresponding to the status display item is transmitted, the data value and data processing information are sent back.

(a) Transmission

Send command [3][5] and any of data No.[8][0] to [8][E] corresponding to the status display item to be read. Refer to section 13.4.1.

(b) Reply

The slave station sends back the requested status display data at alarm occurrence.



(3) Current alarm clear

As by the reset (RES) on, reset the servo amplifier alarm to make the servo amplifier ready to operate. After removing the cause of the alarm, reset the alarm with no command entered.

Command	Data No.	Data
[8][2]	[0][0]	1EA5

13.5.12 Other commands

(1) Servo motor side pulse unit absolute position

Read the absolute position in the servo motor side pulse unit.

Note that overflow will occur in the position of 8192 or more revolutions from the home position.

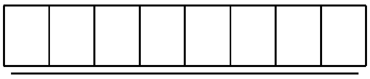
(a) Transmission

Send command [0][2] and data No.[9][0].

Command	Data No.
[0][2]	[9][0]

(b) Reply

The slave station sends back the requested servo motor side pulses.



Absolute position is sent back in hexadecimal in the servo motor side pulse unit.
(Must be converted into decimal)

For example, data "000186A0" is 100000 [pulse] in the motor side pulse unit.

(2) Command unit absolute position

Read the absolute position in the command unit.

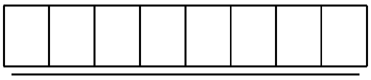
(a) Transmission

Send command [0][2] and data No.[9][1].

Command	Data No.
[0][2]	[9][1]

(b) Reply

The slave station sends back the requested command pulses.



Absolute position is sent back in hexadecimal in the command unit.
(Must be converted into decimal)

For example, data "000186A0" is 100000 [pulse] in the command unit.

(3) Software version

Reads the software version of the servo amplifier.

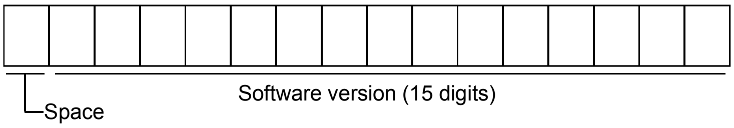
(a) Transmission

Send command [0][2] and data No.[7][0].

Command	Data No.
[0][2]	[7][0]

(b) Reply

The slave station returns the software version requested.



14. ABSOLUTE POSITION DETECTION SYSTEM

CAUTION

- If an absolute position erase (AL.25) or absolute position counter warning (AL.E3) has occurred, always perform home position setting again. Not doing so can cause runaway. Not doing so may cause unexpected operation.

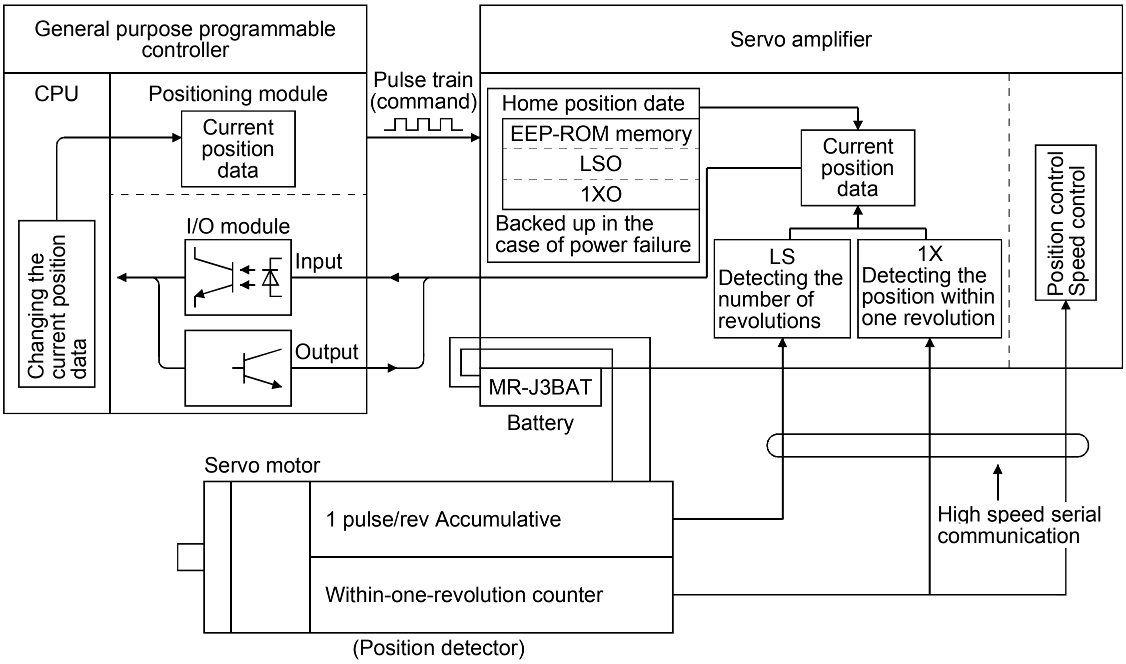
POINT

- If the encoder cable is disconnected, absolute position data will be lost in the following servo motor series. HF-MP, HF-KP, HF-SP, HC-RP, HC-UP, HC-LP, and HA-LP. After disconnecting the encoder cable, always execute home position setting and then positioning operation.
- When configuring an absolute position detection system using the QD75P/D PLC, refer to the Type QD75P/QD75D Positioning Module User's Manual (SH (NA) 080058).

14.1 Outline

14.1.1 Features

For normal operation, as shown below, the encoder consists of a detector designed to detect a position within one revolution and a cumulative revolution counter designed to detect the number of revolutions.
The absolute position detection system always detects the absolute position of the machine and keeps it battery-backed, independently of whether the general-purpose programming controller power is on or off. Therefore, once the home position is defined at the time of machine installation, home position return is not needed when power is switched on thereafter. If a power failure or a fault occurs, restoration is easy.



14.1.2 Restrictions

The absolute position detection system cannot be configured under the following conditions. Test operation cannot be performed in the absolute position detection system, either. To perform test operation, choose incremental in parameter No.PA03.

(1) Speed control mode, torque control mode.

(2) Control switch-over mode (position/speed, speed/torque, torque/position).

(3) Stroke-less coordinate system, e.g. rotary shaft, infinitely long positioning.

(4) Changing of electronic gear after home position setting.

(5) Use of alarm code output.

14.2 Specifications

(1) Specification list

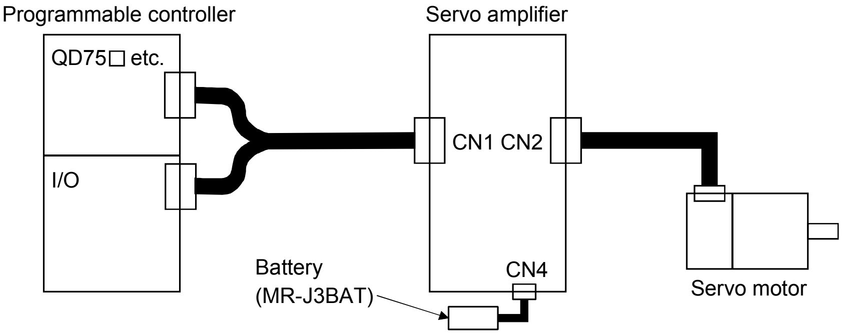
Item	Description
System	Electronic battery backup system
Battery	1 piece of lithium battery (primary battery, nominal＋3.6V) Type: MR-J3BAT
Maximum revolution range	Home position±32767 rev.
(Note 1) Maximum speed at power failure	3000r/min
(Note 2) Battery backup time	Approx. 10,000 hours (battery life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

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

2. Time to hold data by a battery with power off. Replace battery within three years since the operation start whether power is kept on/off. If the battery is used out of specification, the absolute position erase (AL.25) may occur.
3. Quality of battery degrades by the storage condition. It is recommended to connect and use battery in the servo amplifier within two years from the production date. The life of battery is five years from the production date regardless of the connection.

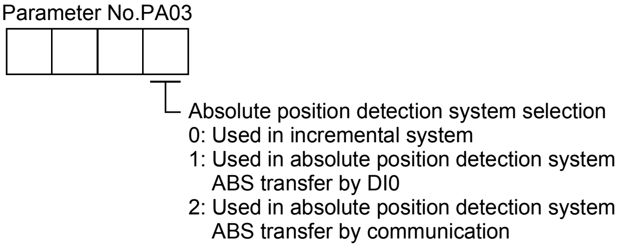
(2) Configuration

Positioning module	I/O module
QD75□	QX40・41・42 QY40・41・42・50
A1SD75□	AX40・41・42 AY40・41・42
FX_{2N}-1GP・FX_{2N}-10PG・FX_{2N}-10GM・FX_{2N}-20GM	$FX_{2N(c)}$ series・$FX_{3U(c)}$ series



(3) Parameter setting

Set "□□□1" in parameter No.PA03 to make the absolute position detection system valid. Set "□□□2" when using the communication-based ABS transfer system. Refer to section 14.12 for the communication-based ABS transfer system.



14.3 Battery replacement procedure

WARNING

- Before replacement a battery, turn off the main circuit power and wait for 15 minutes or longer (20 minutes for 30kW or higher) until the charge lamp turns off. Then, check the voltage between P(＋) and N(－) with a voltage tester or others. Otherwise, an electric shock may occur. In addition, always confirm from the front of the servo amplifier whether the charge lamp is off or not.

POINT

- The internal circuits of the servo amplifier may be damaged by static electricity. Always take the following precautions.
  - Ground human body and work bench.
  - Do not touch the conductive areas, such as connector pins and electrical parts, directly by hand.

14.3.1 When replacing battery with the control circuit power ON

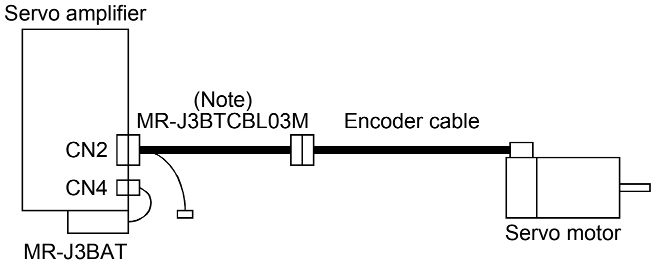
POINT

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

Replacing battery with the control circuit power ON will not erase the absolute position data. Refer to section 14.4 for installation procedure of battery to the servo amplifier. To replace battery with the control circuit power OFF, refer to section 14.3.2.

14.3.2 When replacing battery with the control circuit power OFF

Replacing battery with the control circuit power OFF will erase the absolute position data, but battery can be replaced without erasing the absolute position data in the following procedure. In this procedure, MR-J3BTCBL03M battery connection cable is required. MR-J3BTCBL03M cannot be added after home position is set. Make sure to connect MR-J3BTCBL03M between the servo amplifier and the encoder cable when setting up the encoder cable. Refer to section 14.5 for the replacement procedure of the battery.

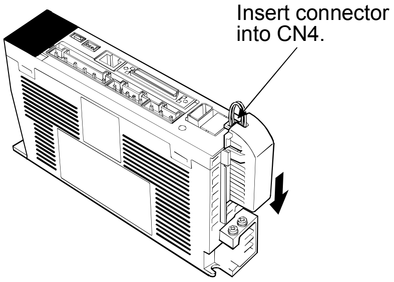


Note. Make sure to install MR-J3BTCBL03M when setting up the encoder cable.

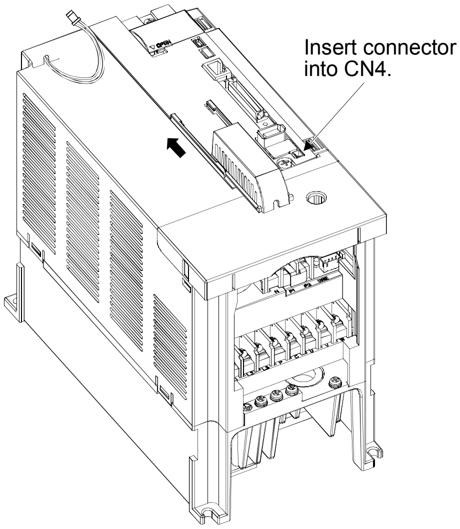
14.4 Battery installation procedure

POINT

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



For MR-J3-350A or less · MR-J3-200A4 or less



For MR-J3-500A or more · MR-J3-350A4 or more

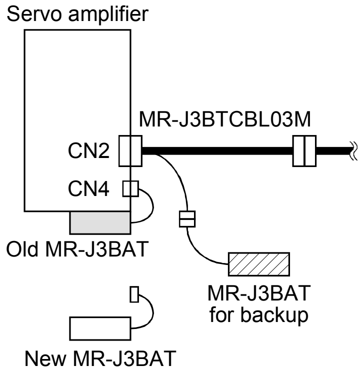
14.5 Procedure to replace battery with the control circuit power OFF

14.5.1 Preparation for battery replacement

For the battery replacement, battery for backup is required separately from the battery to be replaced. Prepare the following batteries.

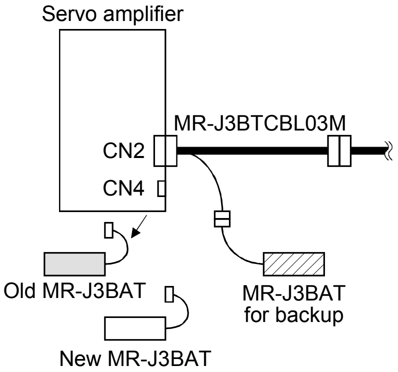
Product	Number and Use	Remarks
MR-J3BAT	1 for backup	Battery within two years from the production date.
	1 for replacement	

14.5.2 Replacement procedure



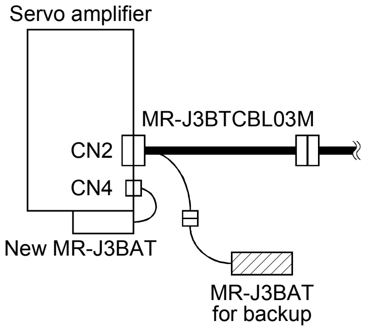
Step 1

Connect MR-J3BAT for backup to the battery connector of MR-J3BTCBL03M.



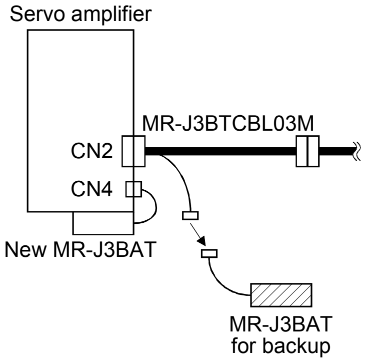
Step 2

Remove old MR-J3BAT from the servo amplifier.



Step 3

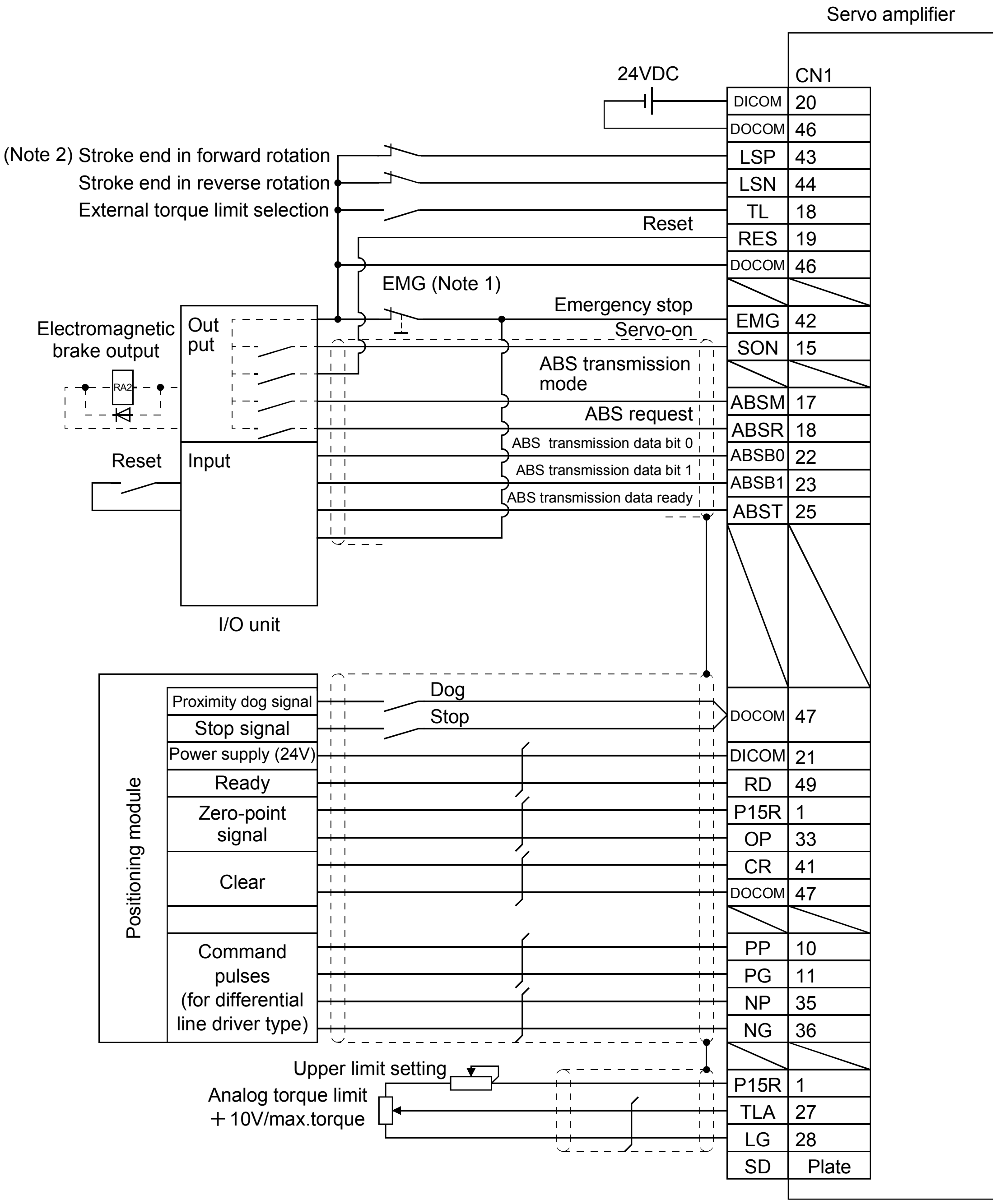
Install new MR-J3BAT to the servo amplifier. Then, connect the lead wire plug of new MR-J3BAT to the C4 connector of the servo amplifier.



Step 4

Remove the MR-J3BAT for backup from the battery connector of MR-J3BTCBL03M, and the procedure is completed.

14.6 Standard connection diagram



Note 1. Always install the emergency stop switch.

2. For operation, always turn on forward rotation stroke end (LSP)/reverse rotation stroke end (LSN).

14.7 Signal explanation

When the absolute position data is transferred, the signals of connector CN1 change as described in this section. They return to the previous status on completion of data transfer. The other signals are as described in section 3.5.

For the I/O interfaces (symbols in the I/O Category column in the table), refer to section 3.8.2.

Signal name	Code	CN1 Pin No.	Function/Application	I/O category	Control mode
ABS transfer mode	ABSM	(Note) 17	While ABSM is on, the servo amplifier is in the ABS transfer mode, and the functions of ZSP, TLC, and D01 are as indicated in this table.	DI-1	P (Position control)
ABS request	ABSR	(Note) 18	Turn on ABSR to request the ABS data in the ABS transfer mode.	DI-1	
ABS transmission data bit 0	ABSB0	22	Indicates the lower bit of the ABS data (2 bits) which is sent from the servo to the programmable controller in the ABS transfer mode. If there is a signal, D01 turns on.	DO-1	
ABS transmission data bit 1	ABSB1	23	Indicates the upper bit of the ABS data (2 bits) which is sent from the servo to the programmable controller in the ABS transfer mode. If there is a signal, ZSP turns on.	DO-1	
ABS transmission data ready	ABST	25	Indicates that the data to be sent is being prepared in the ABS transfer mode. At the completion of the ready state, TLC turns on.	DO-1	
Home position setting	CR	41	When CR is turned on, the position control counter is cleared and the home position data is stored into the non-volatile memory (backup memory).	DI-1	

Note. When "Used in absolute position detection system" is selected in parameter No.PA03, pin 17 acts as the ABS transfer mode (ABSM) and pin 18 as the ABS request (ABSR). They do not return to the original signals if data transfer ends.

14.8 Startup procedure

(1) Battery installation.
Refer to section 14.3.

(2) Parameter setting
Set "□□□1"in parameter No.PA03 of the servo amplifier and switch power off, then on.

(3) Resetting of absolute position erase (AL.25)
After connecting the encoder cable, the absolute position erase (AL.25) occurs at first power-on. Leave the alarm as it is for a few minutes, then switch power off, then on to reset the alarm.

(4) Confirmation of absolute position data transfer
When the servo-on (SON) is turned on, the absolute position data is transferred to the programmable controller. When the ABS data is transferred properly.

(a) The ready output (RD) turns on.

(b) The programmable controller/ABS data ready contact turns on.

(c) The MR Configurator ABS data display window (refer to section 14.13) and programmable controller side ABS data registers show the same value (at the home position address of 0).
If any warning such as ABS time-out warning (AL.E5) or programmable controller side transfer error occurs, refer to section 14.11 or chapter 9 and take corrective action.

(5) Home position setting
The home position must be set if.

(a) System set-up is performed;

(b) The servo amplifier has been changed;

(c) The servo motor has been changed; or

(d) The absolute position erase (AL.25) occurred.

In the absolute position detection system, the absolute position coordinates are made up by making home position setting at the time of system set-up.
The motor shaft may operate unexpectedly if positioning operation is performed without home position setting.
Always make home position setting before starting operation.
For the home position setting method and types, refer to section 14.9.3.

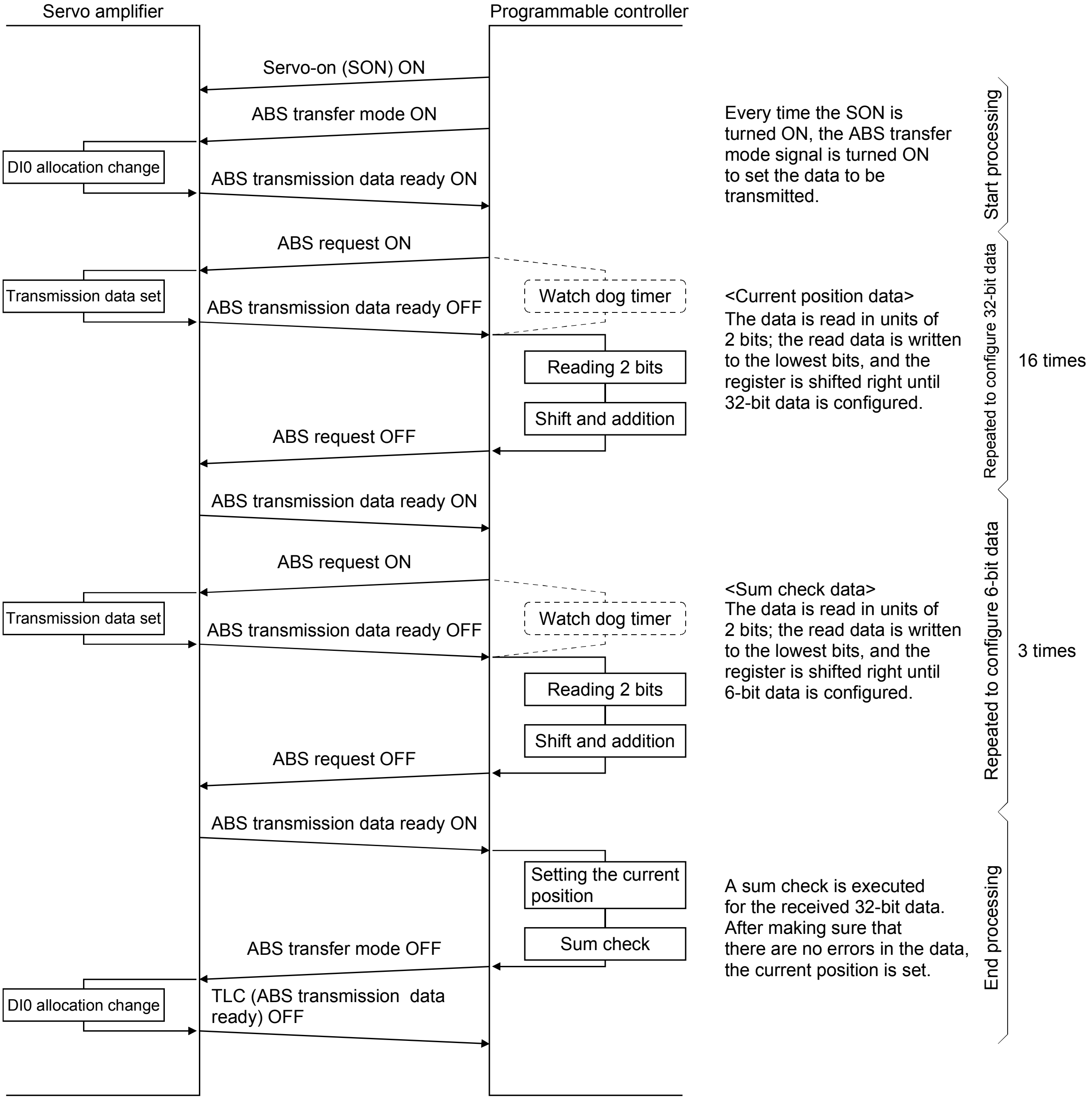
14.9 Absolute position data transfer protocol

POINT

- After switching on the ABS transfer mode (ABSM), turn on the servo-on signal (SON). When the ABS transfer mode is off, turning on the servo-on signal (SON) does not switch on the base circuit.

14.9.1 Data transfer procedure

Each time the servo-on (SON) is turned ON (when the power is switched ON for example), the programmable controller reads the position data (present position) of the servo amplifier.
Time-out monitoring is performed by the programmable controller.

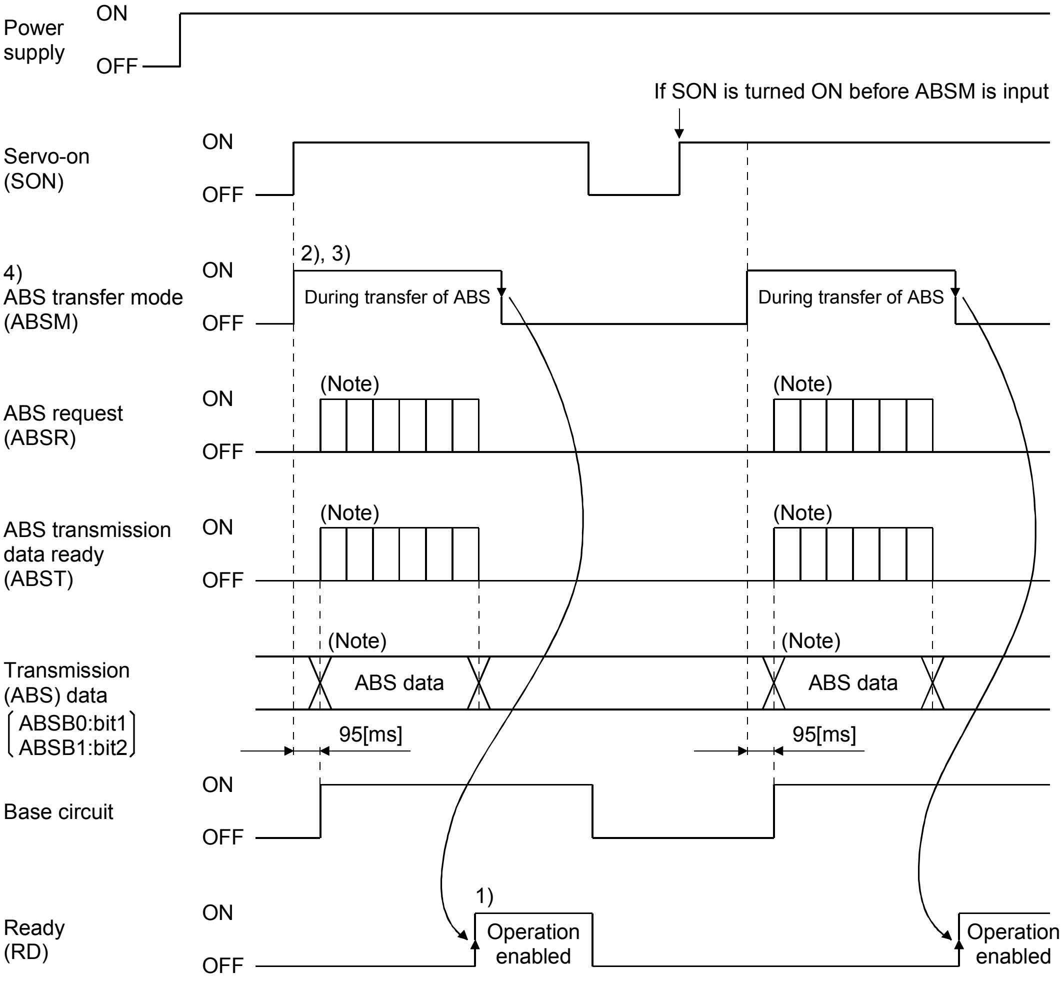


14.9.2 Transfer method

The sequence in which the base circuit is turned ON (servo-on) when it is in the OFF state due to the servo-on (SON) going OFF, an emergency stop (EMG), or alarm (ALM), is explained below. In the absolute position detection system, every time the servo-on (SON) is turned on, the ABS transfer mode (ABSM) should always be turned on to read the current position in the servo amplifier to the controller. The servo amplifier transmits to the controller the current position latched when the ABS transfer mode (ABSM) switches from OFF to ON. At the same time, this data is set as a position command value inside the servo amplifier. Unless the ABS transfer mode (ABSM) is turned ON, the base circuit cannot be turned ON.

(1) At power-on

(a) Timing chart



Note. For details, refer to (1) (b) of this section.

1) The ready (RD) is turned ON when the ABS transfer mode (ABSM) is turned OFF after transmission of the ABS data.
   While the ready (RD) is ON, the ABS transfer mode (ABSM) input is not accepted.

2) Even if the servo-on (SON) is turned ON before the ABS transfer mode (ABSM) is turned ON, the base circuit is not turned ON until the ABS transfer mode (ABSM) is turned ON.
   If a servo alarm has occurred, the ABS transfer mode (ABSM) is not received.
   The ABS transfer mode (ABSM) allows data transmission even while a servo warning is occurring.

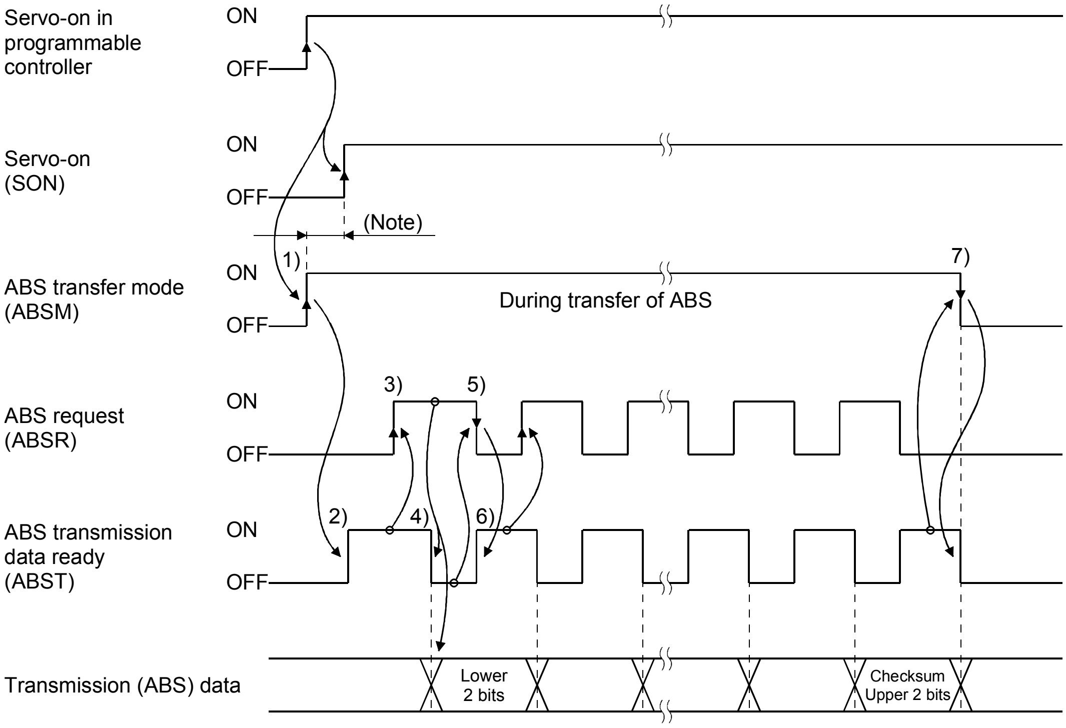
3) If the ABS transfer mode (ABSM) is turned OFF during the ABS transfer mode, the ABS transfer mode is interrupted and the time-out error (AL.E5) occurs.
   If the servo-on (SON) is turned OFF, the reset (RES) is turned ON, and the emergency stop (EMG) is turned OFF during the ABS transfer mode, the ABS time-out warning (AL.E5) occurs.

4) The functions of output signals such as ABST, ABSB0, and ABSB1 change depending on the ON/OFF state of the ABS transfer mode (ABSM).
   Note that if the ABS transfer mode (ABSM) is turned ON for a purpose other than ABS data transmission, the output signals will be assigned the functions of ABS data transmission.

CN1 Pin No.	Output signal	
	ABS transfer mode (ABSM): OFF	ABS transfer mode (ABSM): ON
22	Positioning completion	ABS transmission data bit 0
23	Zero speed detection	ABS transmission data bit 1
25	During torque limit control	ABS transmission data ready

5) The ABS transfer mode (ABSM) is not accepted while the base circuit is ON.
   For re-transferring, turn OFF the servo-on (SON) signal and keep the base circuit in the off state for 20ms or longer.

(b) Detailed description of absolute position data transfer



Note. If the servo-on (SON) is not turned ON within 1 second after the ABS transfer mode (ABSM) is turned ON, an SON time-out warning (AL.EA) occurs. This warning, however, does not interrupt data transmission. It is automatically cleared when the servo-on (SON) is turned ON.

1) The programmable controller turns ON the ABS transfer mode (ABSM) and servo-on (SON) at the leading edge of the internal servo-on (SON).

2) In response to the ABS transfer mode (ABSM), the servo detects and calculates the absolute position and turns ON the ABS transmission data ready (ABST) to notify the programmable controller that the servo is ready for data transmission.

3) After acknowledging that the ready to send (ABST) has been turned ON, the programmable controller turns ABS request (ABSR) ON.

4) In response to ABS request (ABSR), the servo outputs the lower 2 bits of the ABS data and the ABS transmission data ready (ABST) in the OFF state.

5) After acknowledging that the ABS transmission data ready (ABST) has been turned OFF, which implies that 2 bits of the ABS data have been transmitted, the programmable controller reads the lower 2 bits of the ABS data and then turns OFF the ABS request (ABSR).

6) The servo turns ON the ABS transmission data ready (ABST) so that it can respond to the next request.
Steps 3) to 6) are repeated until 32-bit data and the 6-bit checksum have been transmitted.

7) After receiving of the checksum, the programmable controller confirms that the 19th ABS transmission data ready (ABST) is turned ON, and then turns OFF the ABS transfer mode (ABSM). If the ABS transfer mode (ABSM) is turned OFF during data transmission, the ABS transfer mode (ABSM) is interrupted and the ABS time-out warning (AL.E5) occurs.

(c) Checksum

The checksum is the code which is used by the programmable controller to check for errors in the received ABS data. The 6-bit checksum is transmitted following the 32-bit ABS data.

At the programmable controller, calculate the sum of the received ABS data using the ladder program and compare it with the checksum code sent from the servo.

The method of calculating the checksum is shown. Every time the programmable controller receives 2 bits of ABS data, it adds the data to obtain the sum of the received data. The checksum is 6-bit data.

Example: ABS data: −10 (FFFFFFF6H)

$$\begin{array}{r} 10^{b}\\ 01^{b}\\ 11^{b}\\ 11^{b}\\ 11^{b}\\ 11^{b}\\ 11^{b}\\ 11^{b}\\ 11^{b}\\ 11^{b}\\ 11^{b}\\ 11^{b}\\ 11^{b}\\ 11^{b}\\ 11^{b}\\ +)\quad 11^{b}\\ \hline 101101^{b} \end{array}$$

<Appendix>

Decimal −10

↓

Hexadecimal FFFF FFF6

↓

Binary 1111 1111 1111··········0110

When the binary data of each 2bits of the ABS data is added up, "10 1101^{b} " is obtained.

Therefore, the checksum of "−10" (ABS data) is "2D^{b}"

(2) Transmission error

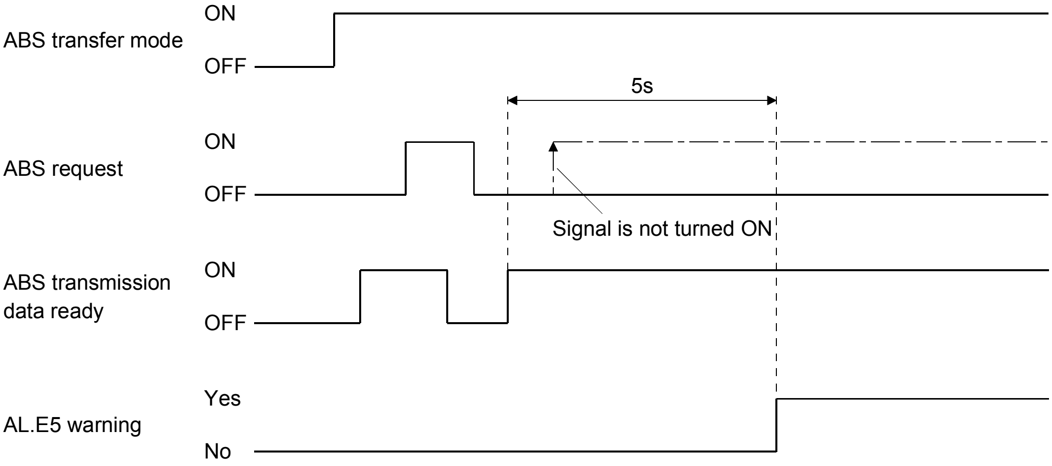
(a) Time-out warning(AL.E5)

In the ABS transfer mode, the time-out processing shown below is executed at the servo. If a time-out error occurs, an ABS time-out warning (AL.E5) is output.

The ABS time-out warning (AL.E5) is cleared when the ABS transfer mode (ABSM) changes from OFF to ON.

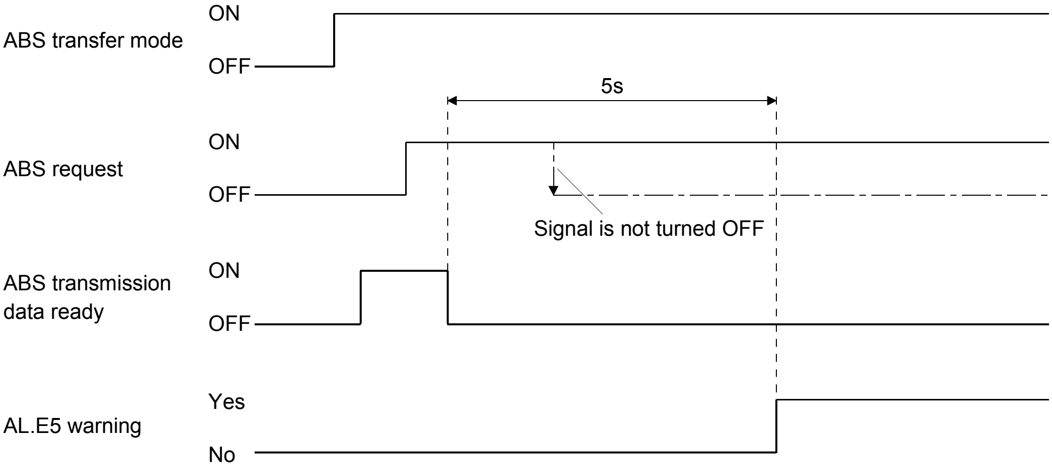
1) ABS request OFF-time time-out check (applied to 32-bit ABS data in 2-bit units + checksum)

If the ABS request signal is not turned ON by the programmable controller within 5s after the ABS transmission data ready (ABST) is turned ON, this is regarded as a transmission error and the ABS time-out warning (AL.E5) is output.



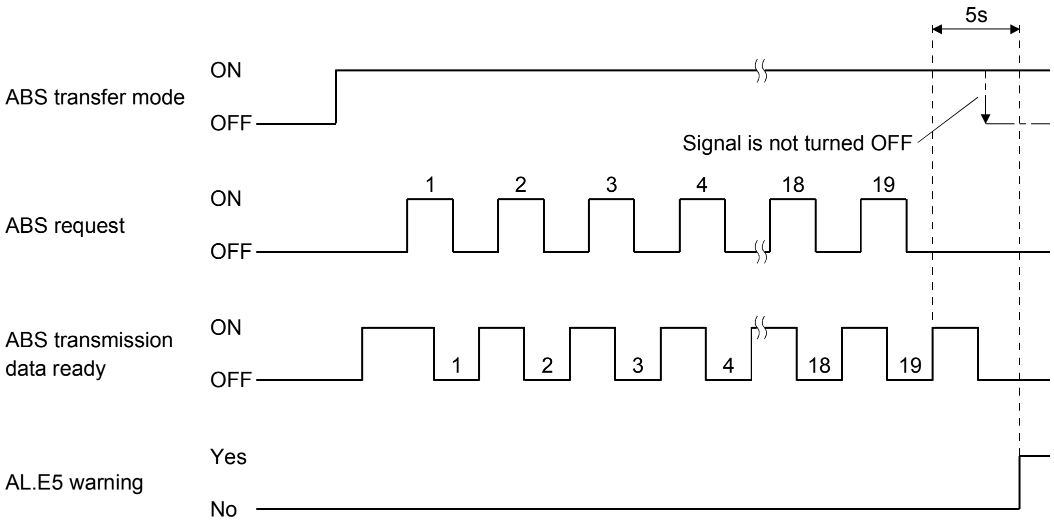
2) ABS request ON-time time-out check (applied to 32-bit ABS data in 2-bit units + checksum)

If the ABS request signal is not turned OFF by the programmable controller within 5s after the ABS transmission data ready (ABST) is turned OFF, this is regarded as the transmission error and the ABS time-out warning (AL.E5) is output.



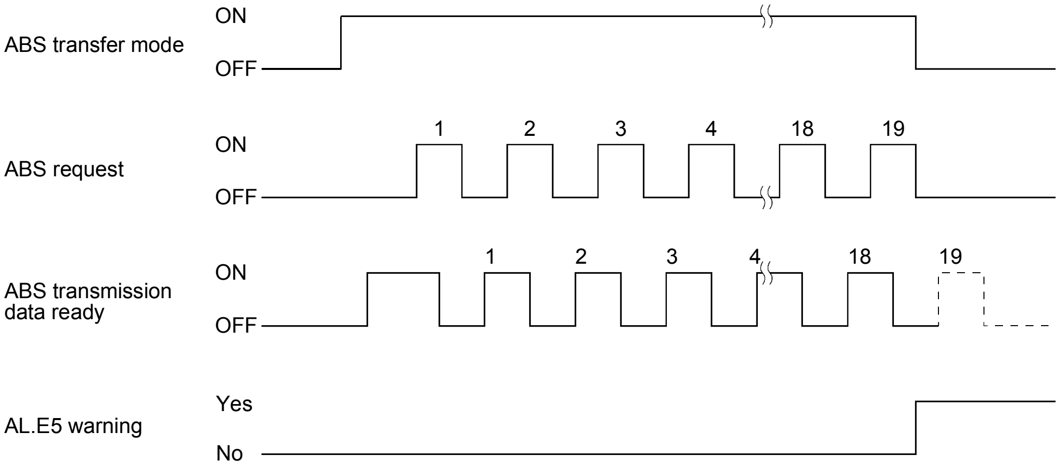
3) ABS transfer mode finish-time time-out check

If the ABS transfer mode (ABSM) is not turned OFF within 5s after the last ABS transmission data ready (19th signal for ABS data transmission) is turned ON, it is regarded as the transmission error and the ABS time-out warning (AL.E5) is output.

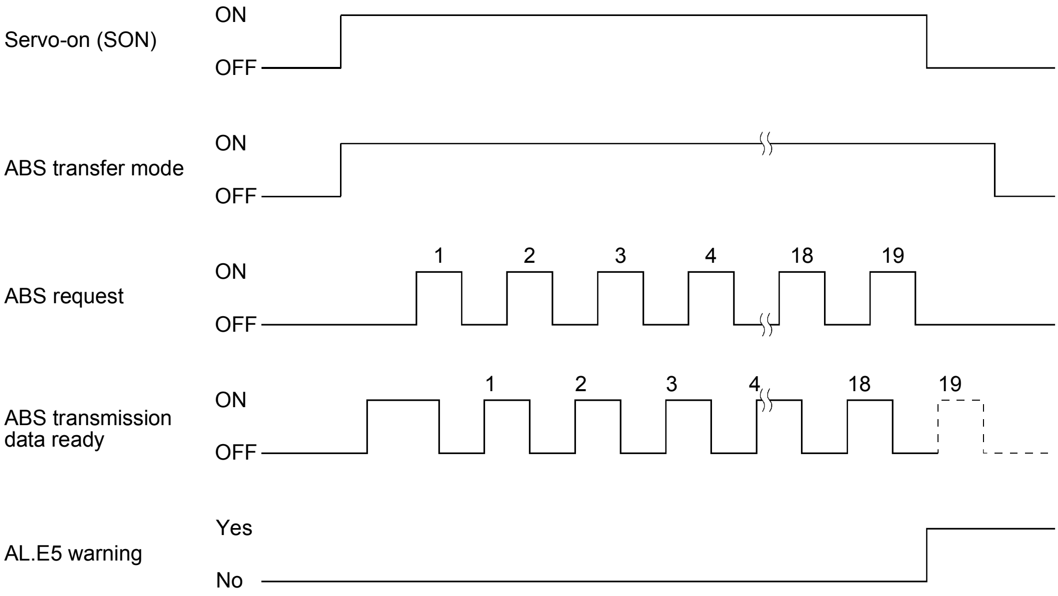


4) ABS transfer mode (ABSM) OFF check during the ABS transfer

When the ABS transfer mode is turned ON to start transferring and then the ABS transfer mode is turned OFF before the 19th ABS transmission data ready is turned ON, the ABS time-out warning (AL.E5) occurs, regarding it as a transfer error.



5) Servo-on (SON) OFF, Reset (RES) ON, Emergency stop (EMG) OFF check during the ABS transfer
   When the ABS transfer mode is turned ON to start transferring and then the servo-on (SON) is turned OFF, the reset (RES) is turned ON, or the emergency stop (EMG) is turned ON before the 19th ABS transmission data ready signal is turned ON, the ABS time-out warning (AL.E5) occurs, regarding it as a transfer error.

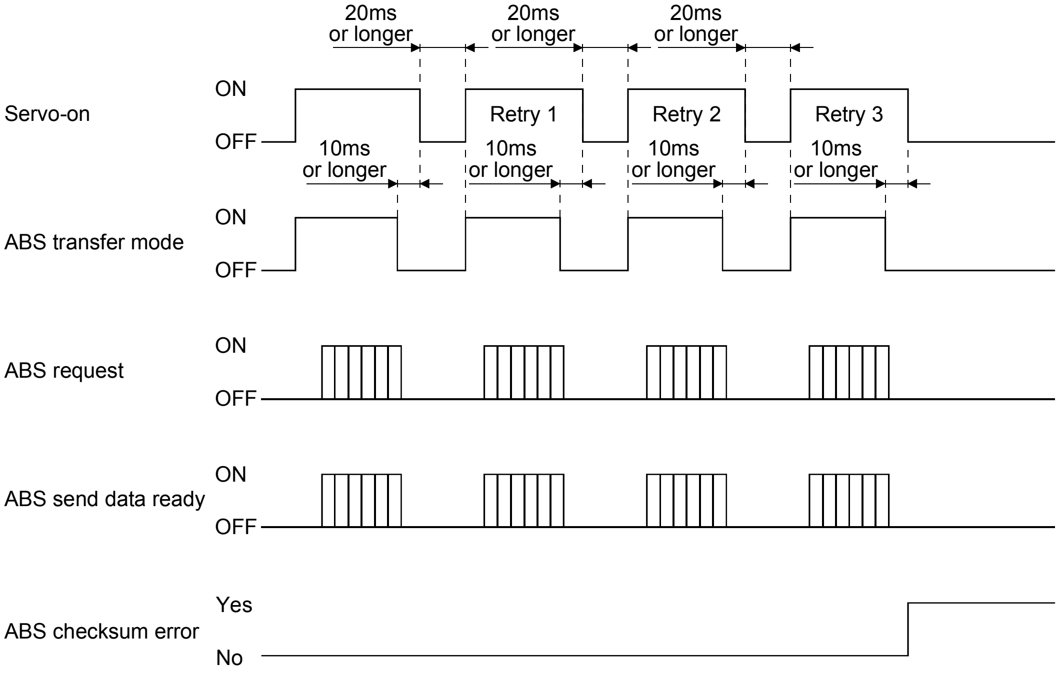


(b) Checksum error

If the checksum error occurs, the programmable controller should retry transmission of the ABS data. Using the ladder check program of the programmable controller, turn OFF the ABS transfer mode (ABSM). After a lapse of 10ms or longer, turn OFF the servo-on (SON) (OFF time should be longer than 20ms) and then turn it ON again.

If the ABS data transmission fails to end normally even after retry, regard this situation as an ABS checksum error and execute error processing.

The start command should be interlocked with the ABS data ready signal to disable positioning operation when an checksum error occurs.

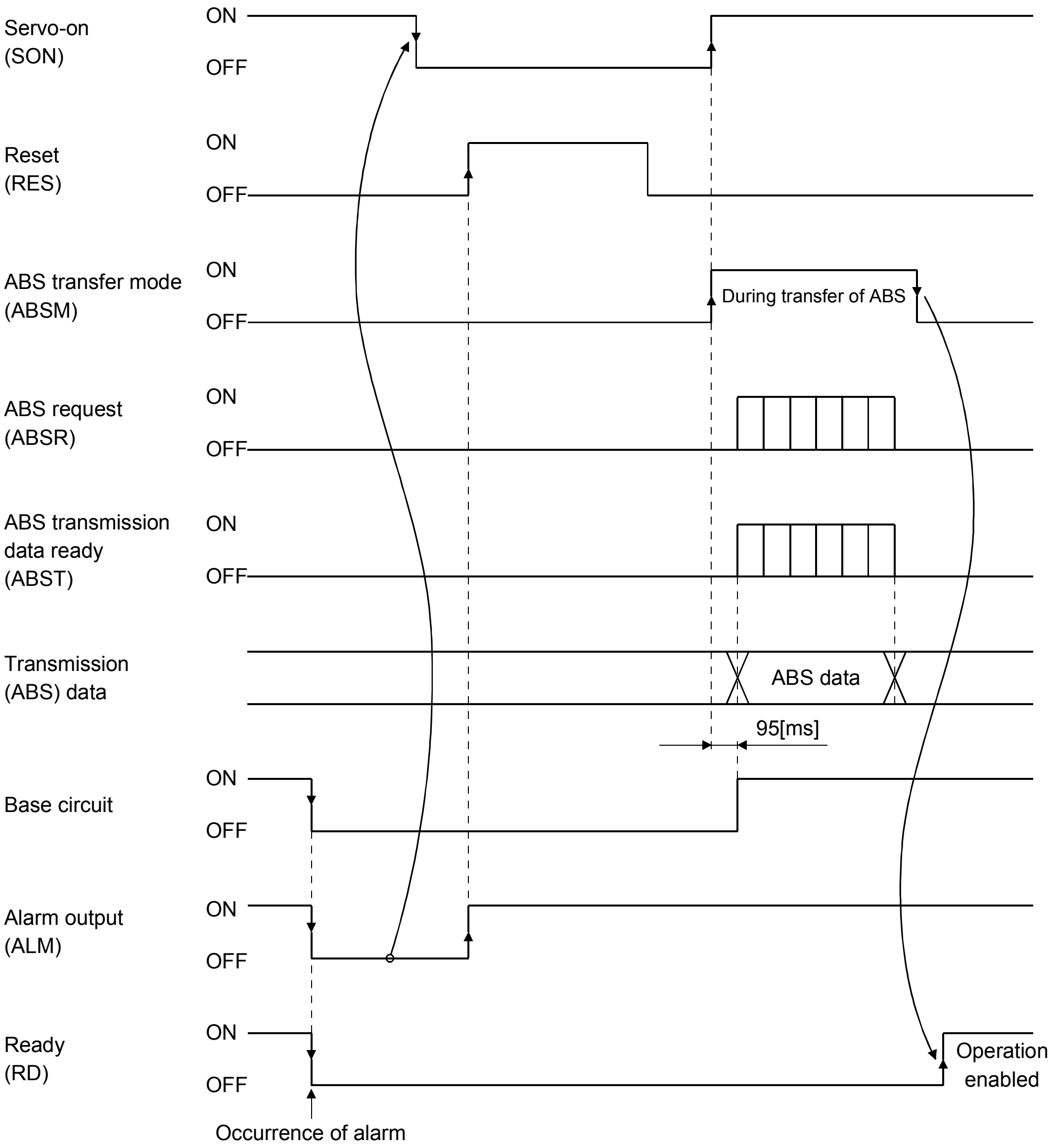


(3) At the time of alarm reset

If an alarm occurs, turn OFF the servo-on (SON) by detecting the alarm output (ALM).

If an alarm has occurred, the ABS transfer mode (ABSM) cannot be accepted.

In the reset state, the ABS transfer mode (ABSM) can be input.



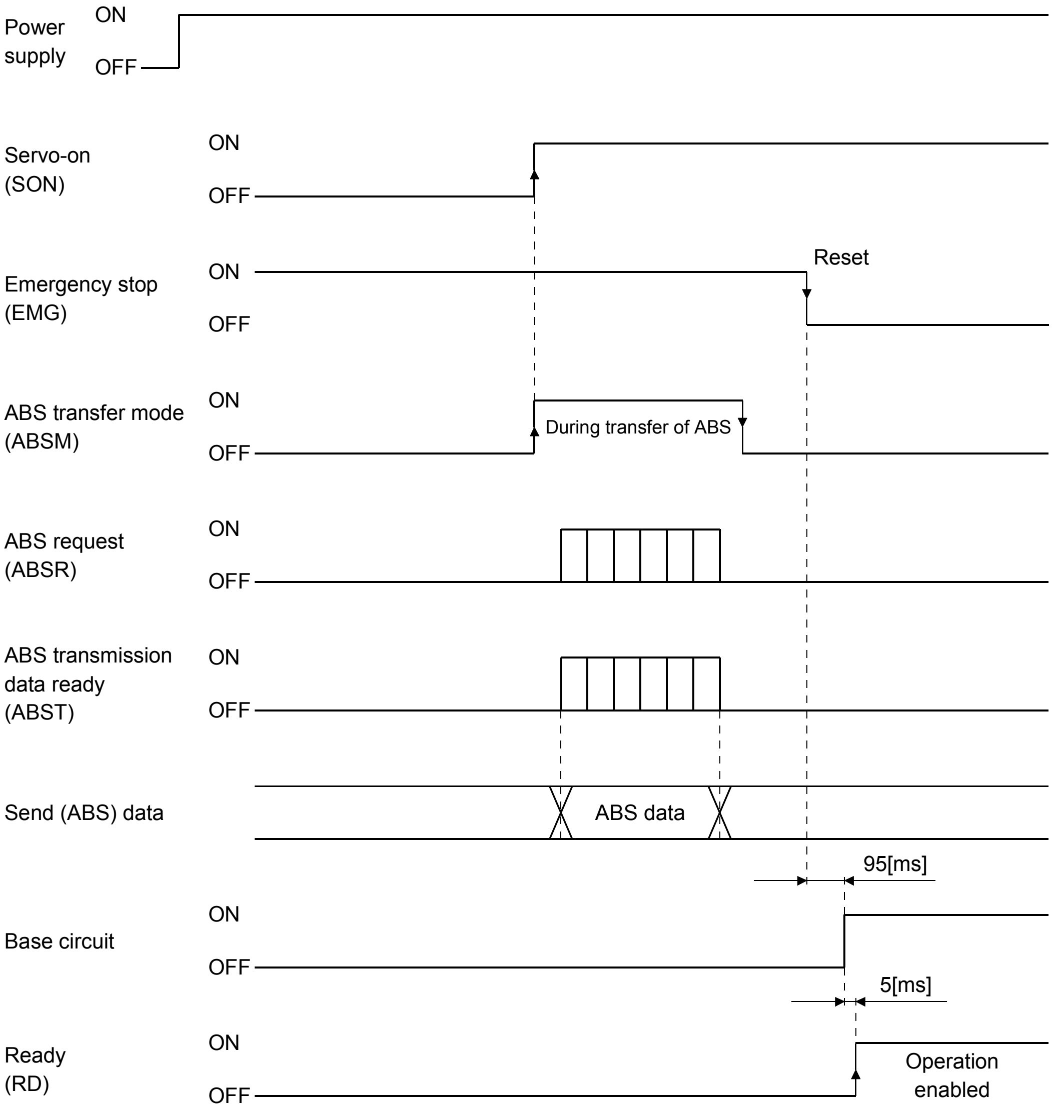
(4) At the time of emergency stop reset

(a) If the power is switched ON in the emergency stop state

The emergency stop state can be reset while the ABS data is being transferred.

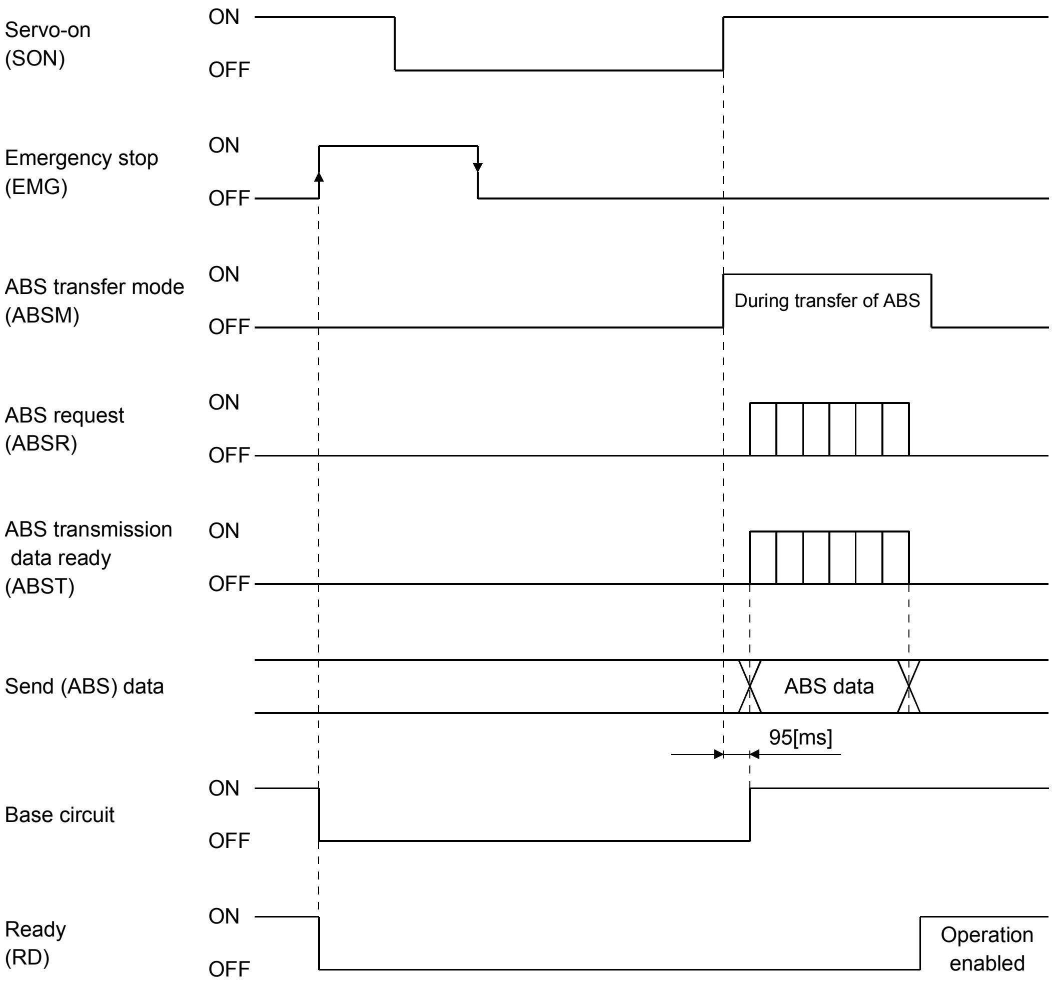
If the emergency stop state is reset while the ABS data is transmitted, the base circuit is turned ON 95[ms] after resetting. If the ABS transfer mode (ABSM) is OFF when the base circuit is turned ON, the ready (RD) is turned ON 5[ms] after the turning ON of the base circuit. If the ABS transfer mode (ABSM) is ON when the base circuit is turned ON, it is turned OFF and then the ready (RD) is turned ON. The ABS data can be transmitted after the emergency stop state is reset.

The current position in the servo amplifier is updated even during an emergency stop. When servo-on (SON) and ABS transfer mode (ABSM) are turned ON during an emergency stop as shown below, the servo amplifier transmits to the controller the current position latched when the ABS transfer mode (ABSM) switches from OFF to ON, and at the same time, the servo amplifier sets this data as a position command value. However, since the base circuit is OFF during an emergency stop, the servo-lock status is not encountered. Therefore, if the servo motor is rotated by external force or the like after the ABS transfer mode (ABSM) is turned ON, this travel distance is accumulated in the servo amplifier as droop pulses. If the emergency stop is cleared in this status, the base circuit turns ON and the motor returns to the original position rapidly to compensate for the droop pulses. To avoid this status, reread the ABS data before clearing the emergency stop.



(b) If emergency stop is activated during servo-on

The ABS transfer mode (ABSM) is permissible while in the emergency stop state. In this case, the base circuit and the ready (RD) are turned ON after the emergency stop state is reset.



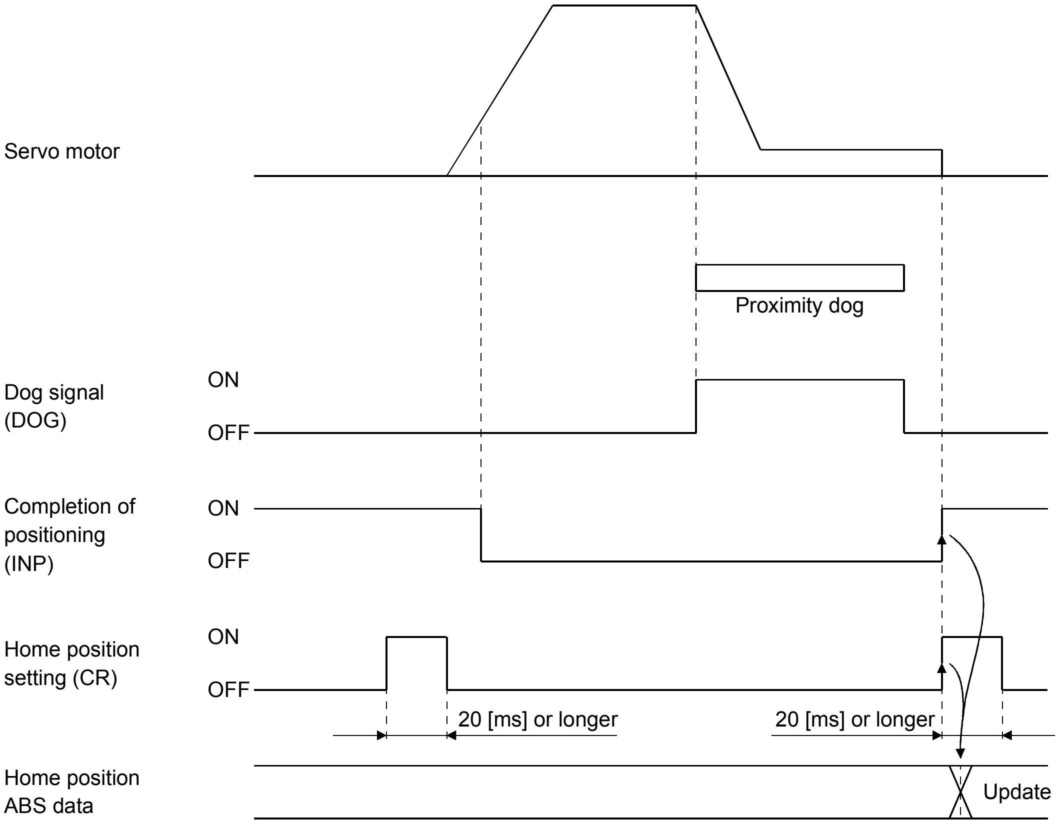
14.9.3 Home position setting

(1) Dog type home position return

Preset a home position return creep speed at which the machine will not be given impact. On detection of a zero pulse, the home position setting (CR) is turned from off to on. At the same time, the servo amplifier clears the droop pulses, comes to a sudden stop, and stores the stop position into the non-volatile memory as the home position ABS data.

The home position setting (CR) should be turned on after it has been confirmed that the in-position (INP) is on. If this condition is not satisfied, the home position setting warning (AL.96) will occur, but that warning will be reset automatically by making home position return correctly.

The number of home position setting times is limited to 1,000,000 times.



(2) Data set type home position return

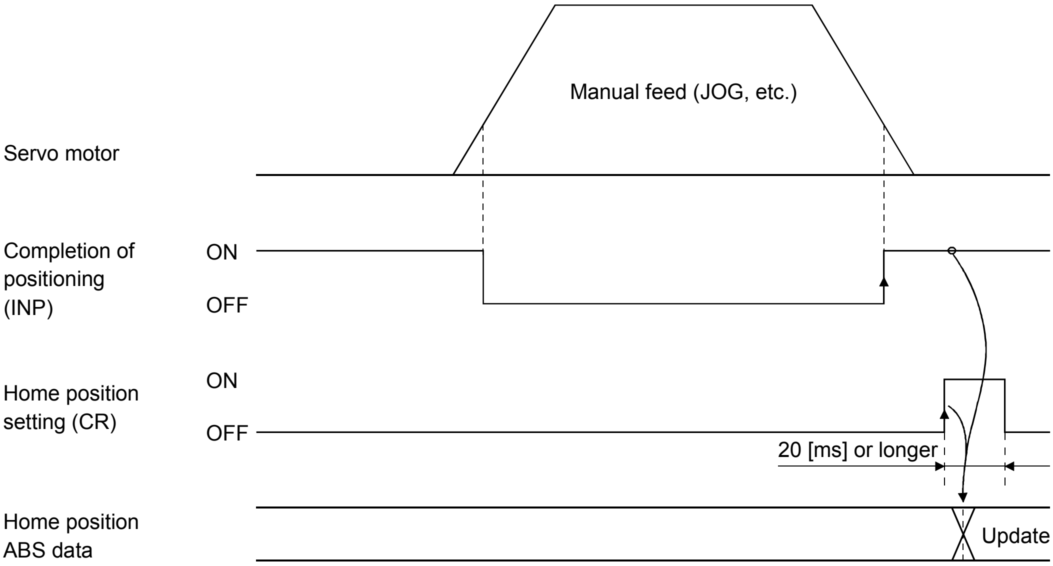
POINT

- Never make home position setting during command operation or servo motor rotation. It may cause home position sift.
- It is possible to execute data set type home position return when the servo off.

Move the machine to the position where the home position is to be set by performing manual operation such as JOG operation. When the home position setting (CR) is on for longer than 20ms, the stop position is stored into the non-volatile memory as the home position ABS data.

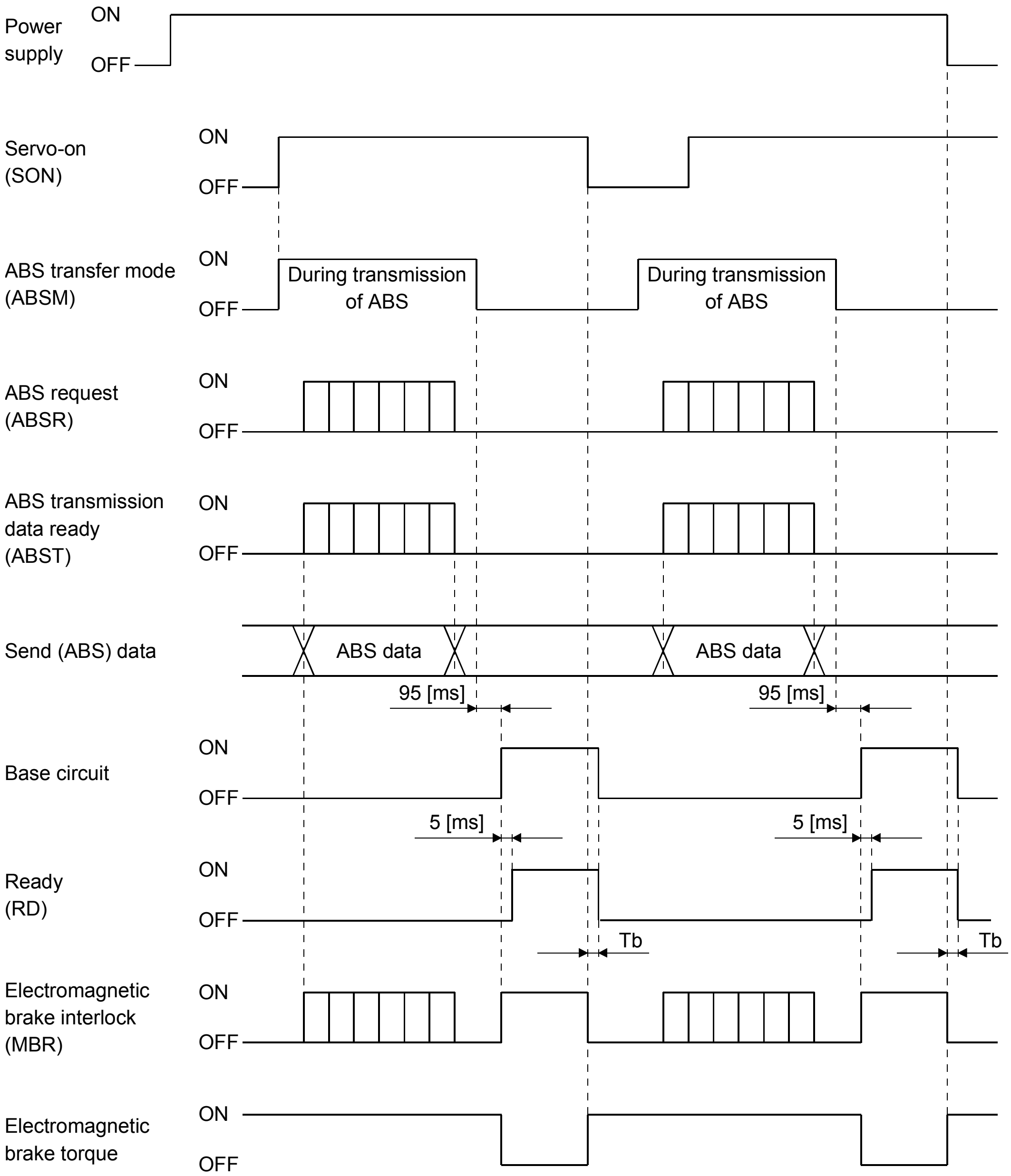
When the servo on, set home position setting (CR) to ON after confirming that the in-position (INP) is ON. If this condition is not satisfied, the home position setting warning (AL.96) will occur, but that warning will be reset automatically by making home position return correctly.

The number of home position setting times is limited to 1,000,000 times.



14.9.4 Use of servo motor with an electromagnetic brake

The timing charts at power on/off and servo-on (SON) on/off are given below.
Preset parameter No.PA04/PD13 to PD16/PD18 of the servo amplifier to make the electromagnetic brake interlock (MBR) valid. When the ABS transfer mode is ON, the electromagnetic brake interlock (MBR) set in parameter No.PA04 is used as the ABS data bit 1.
Hence, make up an external sequence which will cause the electromagnetic brake torque to be generated by the ABS mode (ABSM) and electromagnetic brake interlock (MBR).



14.9.5 How to process the absolute position data at detection of stroke end

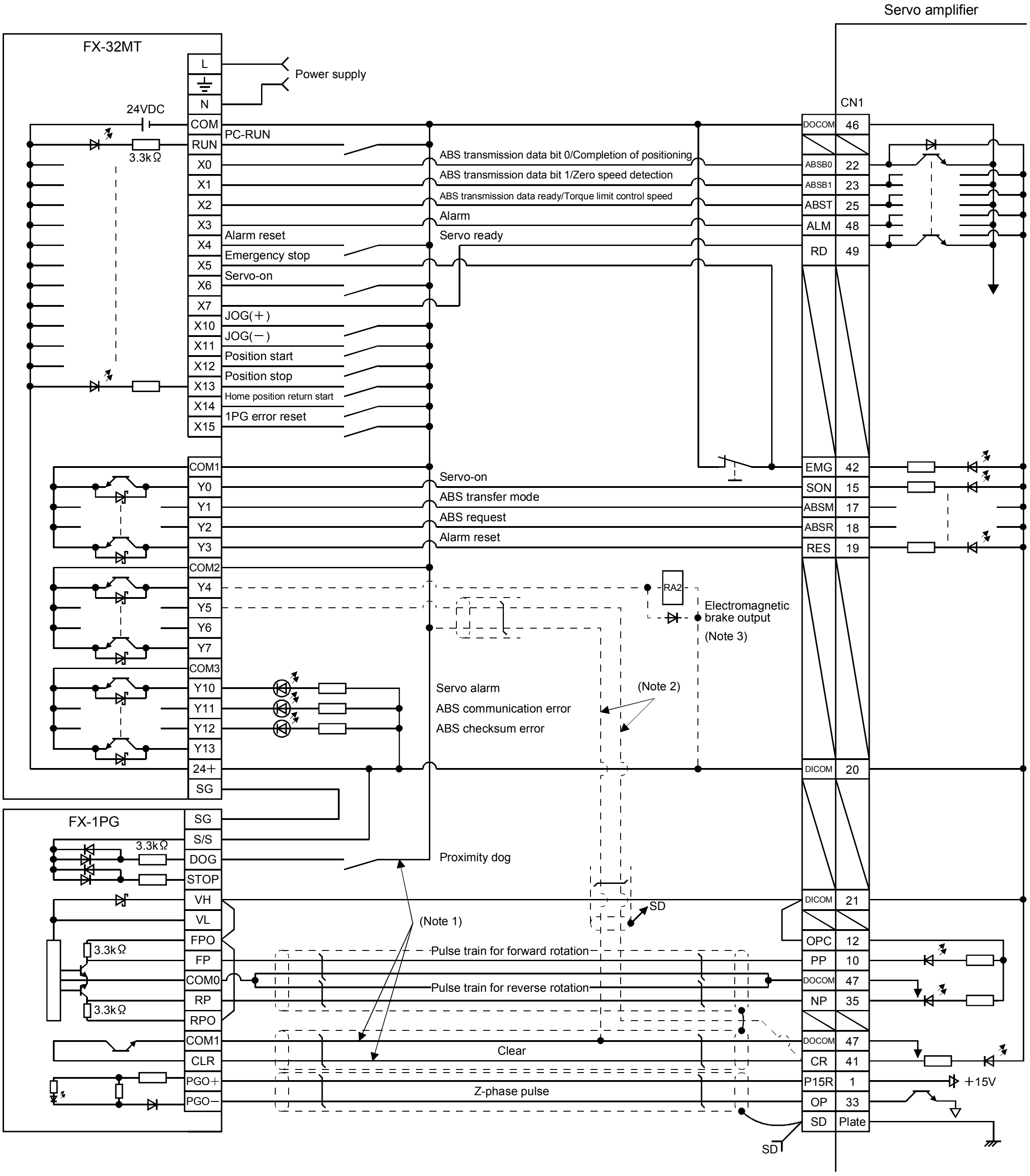
The servo amplifier stops the acceptance of the command pulse when stroke end (LSP・LSN) is detected, clears the droop pulses to 0 at the same time, and stops the servo motor rapidly.
At this time, the programmable controller keeps outputting the command pulse. Since this causes a discrepancy between the absolute position data of the servo amplifier and the programmable controller, a difference will occur between the position data of the servo amplifier and that of the programmable controller.
To prevent this difference in position data from occurring, do as described below. When the servo amplifier has detected the stroke end, perform JOG operation or the like to clear the stroke end. After that, switch the servo-on (SON) off once, then on again, or switch the power off once, then on again. This causes the absolute position data of the servo amplifier to be transferred to the programmable controller, restoring the normal data.

14.10 Examples of use

14.10.1 MELSEC FX(2N)-32MT (FX(2N)-1PG)

(1) Connection diagram

(a) FX-32MT (FX-1PG)

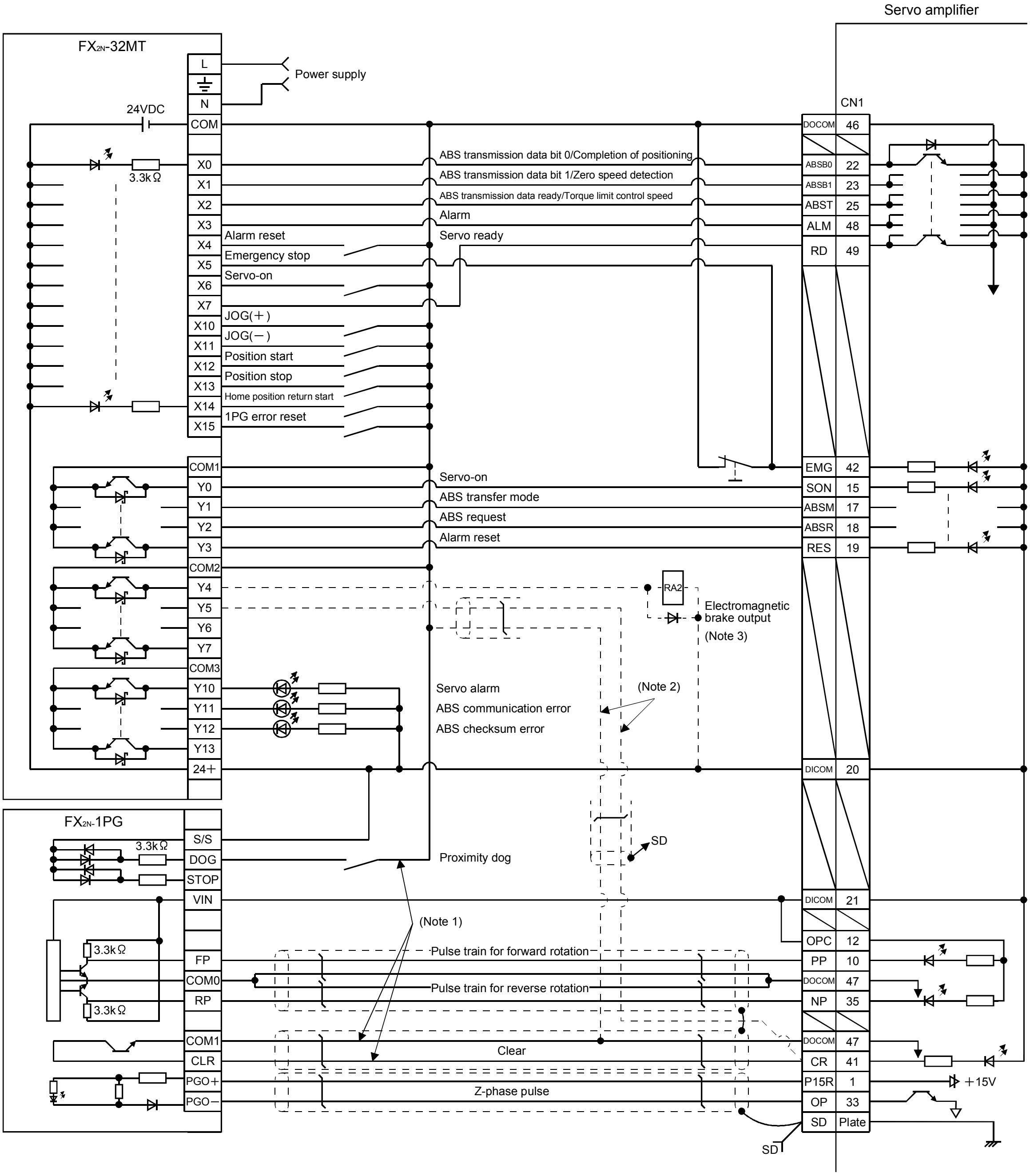


Note 1. To be connected for the dog type home position setting. At this time, do not connect the portions marked (Note 2).

2. To be connected for the data set type home position setting. At this time, do not connect the portions marked (Note 1).

3. The electromagnetic brake interlock (MBR) should be controlled by connecting the programmable controller output to a relay.

(b) FX2N-32MT (FX2N-1PG)



Note 1. To be connected for the dog type home position setting. At this time, do not connect the portions marked (Note 2).

2. To be connected for the data set type home position setting. At this time, do not connect the portions marked (Note 1).

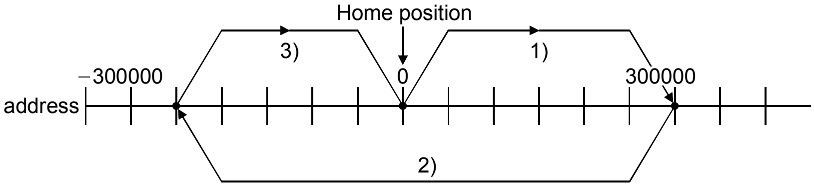
3. The electromagnetic brake interlock (MBR) should be controlled by connecting the programmable controller output to a relay.

(2) Sequence program example

(a) Conditions

1) Operation pattern

ABS data transfer is made as soon as the servo-on switch is turned on. After that, positioning operation is performed as shown below.



After the completion of ABS data transmission, JOG operation is possible using the JOG+ or JOG− switch, and dog type home position return is possible using the home position return switch.

2) Buffer memory assignment

For BFM#26 and later, refer to the FX2(N)-1PG User's Manual.

BMF No.		Name and symbol		Set value	Remark
Upper 16 bits	Lower 16 bits				
-	#0	Pulse rate	A	2000	
#2	#1	Feed rate	B	1000	
-	#3	Parameter		H0000	Command unit: Pulses
#5	#4	Max. speed	Vmax	100000PPS	
-	#6	Bias speed	Vbia	0PPS	
#8	#7	JOG operation	Vjog	10000PPS	
#10	#9	Home position return speed (high speed)	V_{RT}	50000PPS	
-	#11	Home position return speed (creep)	V_{CL}	1000PPS	
-	#12	Home position return zero-point signal count	N	2 pulses	Initial value: 10
#14	#13	Home position address	HP	0	
-	#15	Acceleration/deceleration time	Ta	200ms	Initial value: 100
-	#16	Not usable			
#18	#17	Target address (I)	P(I)	0	
#20	#19	Operation speed (I)	V(I)	100000	Initial value: 10
#22	#21	Target address (II)	P(II)	0	
#24	#23	Operation speed (II)	V(II)	10	
-	#25	Operation command		H0000	

3) Instructions

When the servo-on switch and the COM of the power supply are shorted, the ABS data is transmitted when the servo amplifier power is turned ON, or at the leading edge of the RUN signal after a PC reset operation (PC-RESET). The ABS data is also transmitted when an alarm is reset, or when the emergency stop state is reset.

If checksum discrepancy is detected in the transmitted data, the ABS data transmission is retried up to three times. If the checksum discrepancy is still detected after retrying, the ABS checksum error is generated (Y12 ON).

The following time periods are measured and if the ON/OFF state does not change within the specified time, the ABS communication error is generated (Y11 ON).

ON period of ABS transfer mode (Y1)

ON period of ABS request (Y2)

OFF period of ready to send the ABS data (X2).

(b) Device list

X input contact	
X0	Transmission data bit 0 / completion of positioning
X1	Transmission data bit 1 / zero speed detection
X2	Send ABS transmission data ready/ torque limit control
X3	Servo alarm
X4	Alarm reset switch
X5	Servo emergency stop
X6	Servo-on switch
X7	Servo ready
X10	JOG (+) switch
X11	JOG (−) switch
X12	Position start switch
X13	Position stop switch
X14	Home position return start switch
X15	1PG error reset

Y output contact	
Y0	Servo-on
Y1	ABS transfer mode
Y2	ABS request
Y3	Alarm reset
Y4 (Note 2)	Electromagnetic brake output
Y5 (Note 1)	Clear
Y10	Servo alarm
Y11	ABS communication error
Y12	ABS checksum error

D register	
D0	ABS data: Lower 16 bits
D1	ABS data: Upper 16 bits
D2	Checksum addition counter
D3	Check data in case of checksum error
D4	Transmission retry count in checksum discrepancy
D24	Home position address: Lower 16 bits
D25	Home position address: Upper 16 bits
D106	1PG present position address: Lower 16 bits
D107	1PG present position address: Upper 16 bits

M contact	
M0	Error flag
M1	ABS data transmission start
M2	Retry command
M3	ABS data read
M4	Servo-on request reset permission
M5	Servo-on request
M6	Retry flag
M10	ABS data 2 bit receiving buffer
M11	
M12	
M13	
M20	ABS data 32 bit buffer
↓	
M51	
M52	Checksum 6 bit buffer
↓	
M57	
M58	For checksum comparison
M59	
M62	Sum check discrepancy (greater) >
M63	Sum check discrepancy =
M64	Sum check discrepancy (less) <
M70 (Note 1)	Clear (CR) ON timer request
M71 (Note 1)	Data set type home position return request
M99	ABS data ready

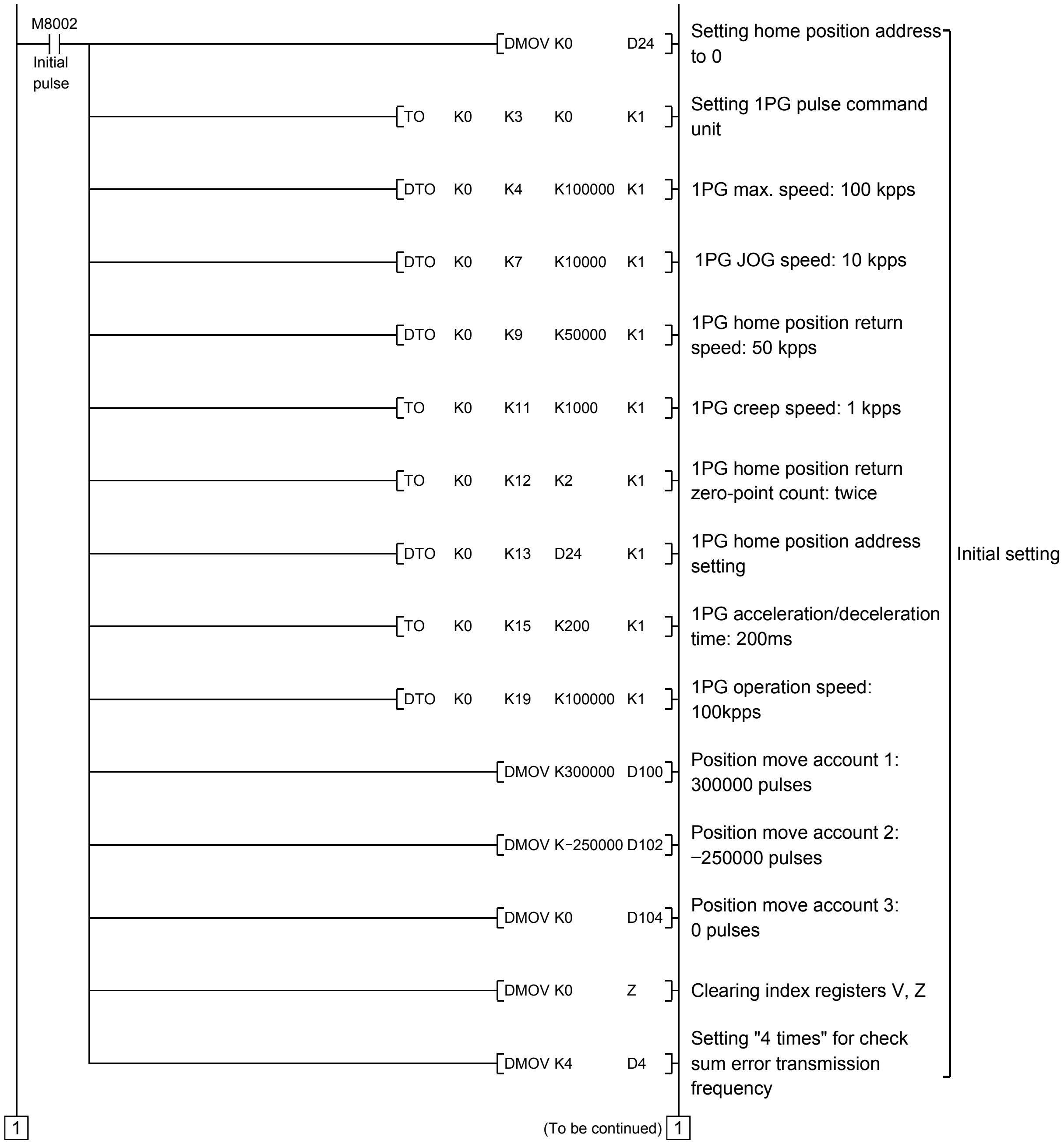
T timer	
T200	Retry wait timer
T201	ABS transfer mode timer
T202	ABS request response timer
T203	Ready to send response timer
T204	ABS data waiting timer
T210 (Note 1)	Clear (CR) ON timer
T211	Retry ABS transfer mode OFF wait timer 20ms set

C counter	
C0	All data reception frequency counter (19 times)
C1	Checksum reception frequency counter
C2	ABS data reception frequency counter (16 times)

Note 1. Necessary when data set type home position return is executed.

2. Necessary in the event of electromagnetic brake output.

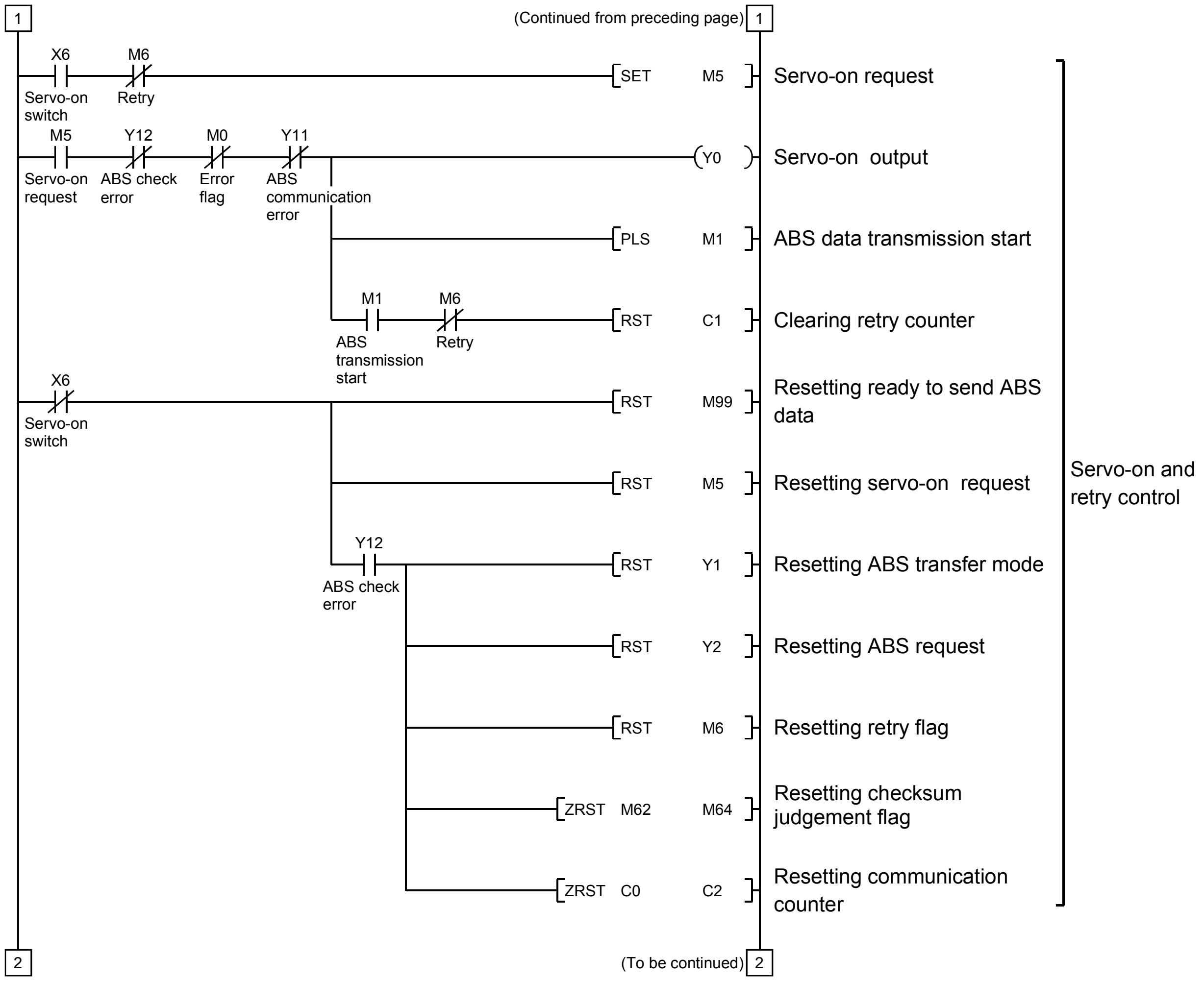
(c) ABS data transfer program for X-axis

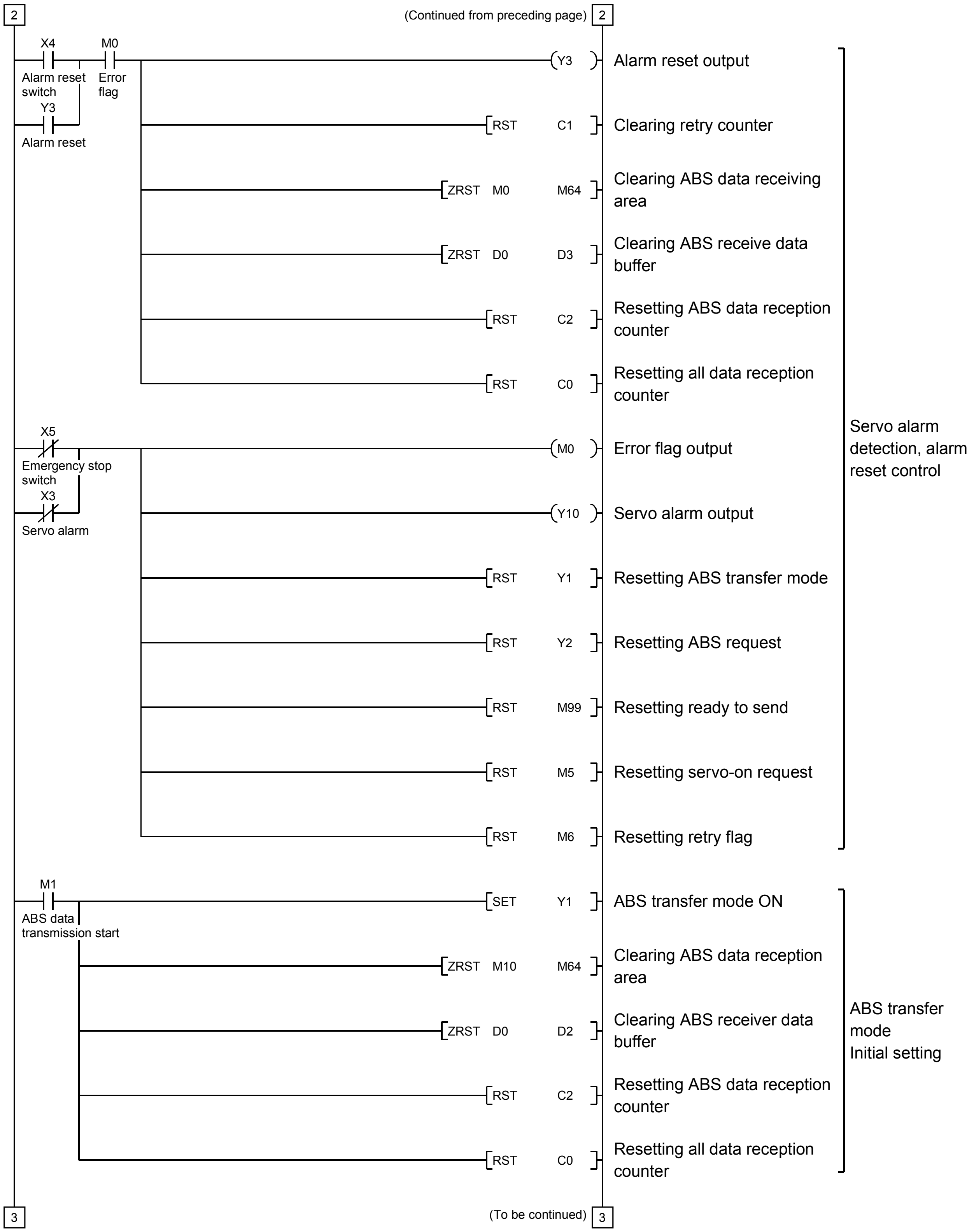


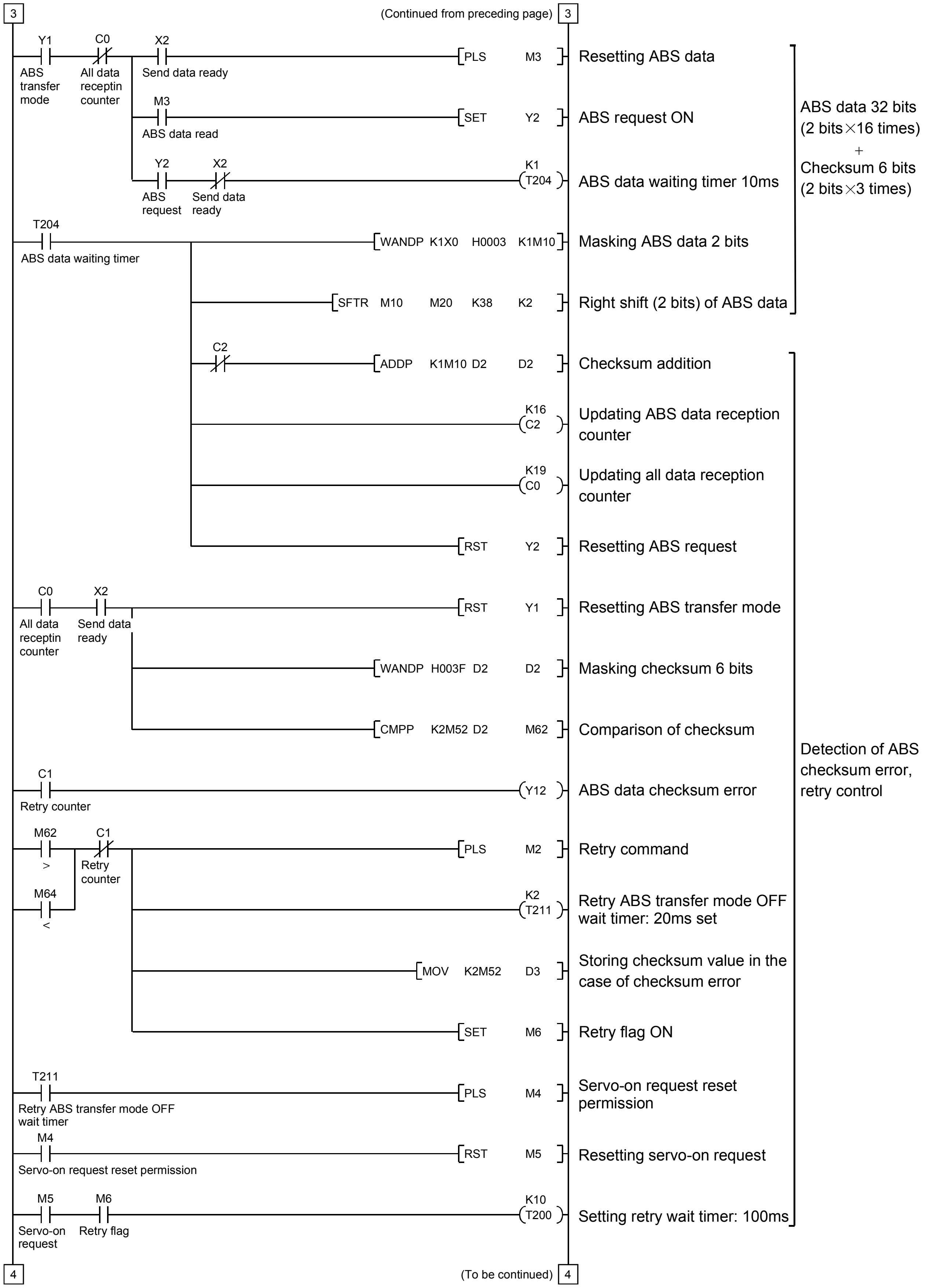
DMOV K0 D24	Setting home position address to 0
TO K0 K3 K0 K1	Setting 1PG pulse command unit
DTO K0 K4 K100000 K1	1PG max. speed: 100 kpps
DTO K0 K7 K10000 K1	1PG JOG speed: 10 kpps
DTO K0 K9 K50000 K1	1PG home position return speed: 50 kpps
TO K0 K11 K1000 K1	1PG creep speed: 1 kpps
TO K0 K12 K2 K1	1PG home position return zero-point count: twice
DTO K0 K13 D24 K1	1PG home position address setting
TO K0 K15 K200 K1	1PG acceleration/deceleration time: 200ms
DTO K0 K19 K100000 K1	1PG operation speed: 100kpps
DMOV K300000 D100	Position move account 1: 300000 pulses
DMOV K−250000 D102	Position move account 2: −250000 pulses
DMOV K0 D104	Position move account 3: 0 pulses
DMOV K0 Z	Clearing index registers V, Z
DMOV K4 D4	Setting "4 times" for check sum error transmission frequency

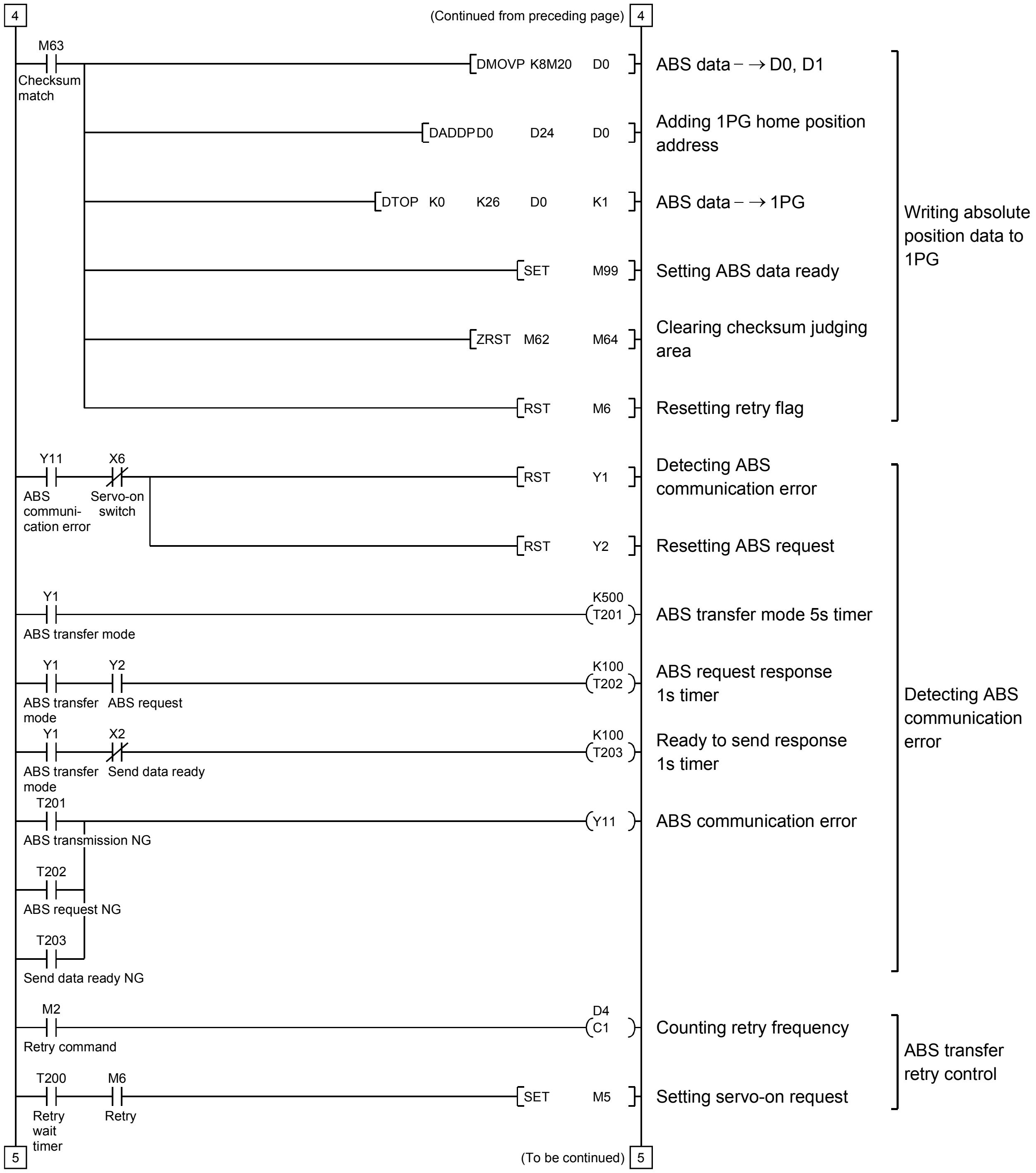
Initial setting

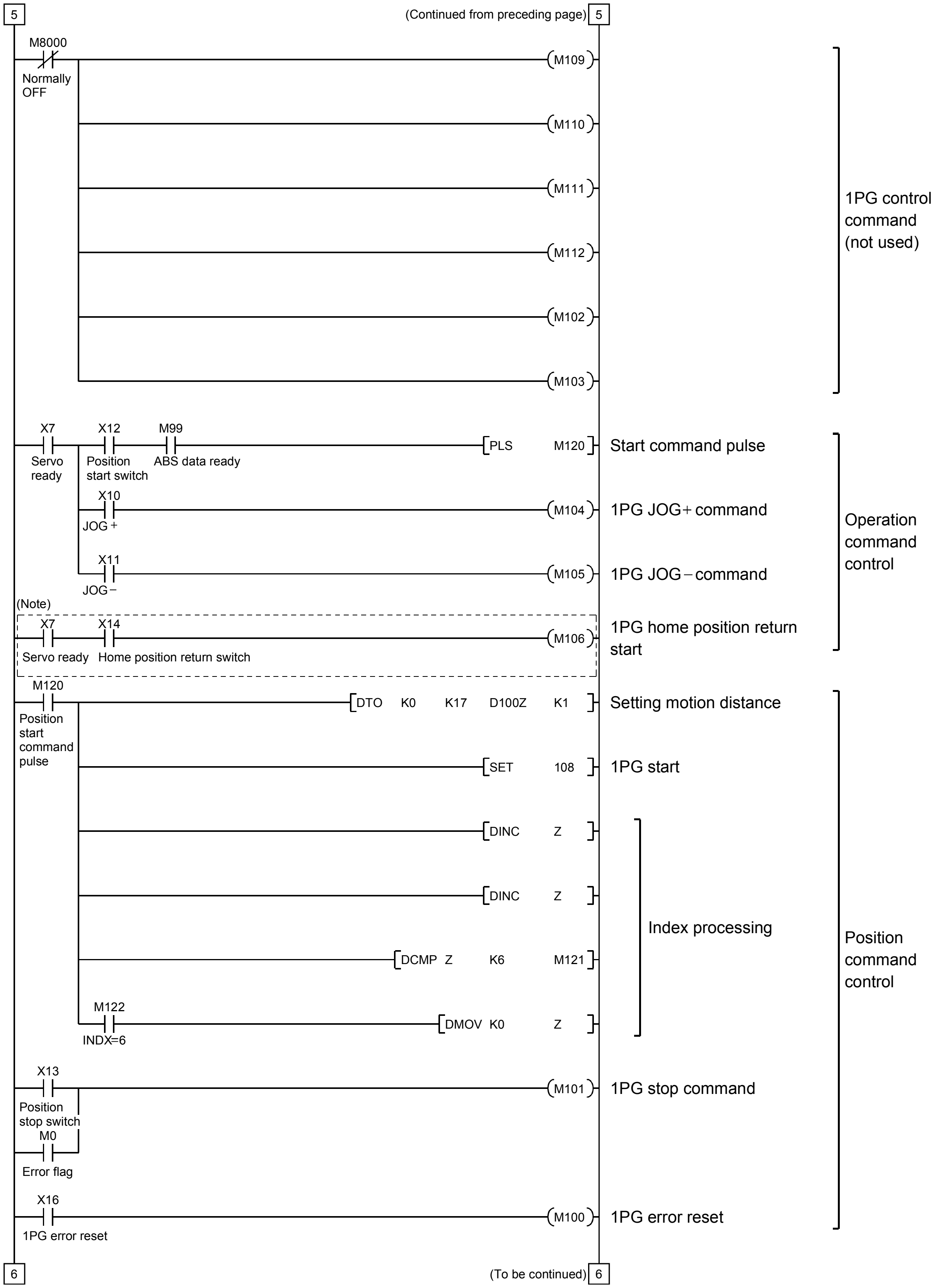
(To be continued)


1
(Continued from preceding page)
1
X6
M6
Servo-on switch
Retry
SET M5
Servo-on request
M5
Y12
M0
Y11
Servo-on request
ABS check error
Error flag
ABS communication error
Y0
Servo-on output
PLS M1
ABS data transmission start
M1
M6
ABS transmission start
Retry
RST C1
Clearing retry counter
X6
Servo-on switch
RST M99
Resetting ready to send ABS data
RST M5
Resetting servo-on request
Y12
ABS check error
RST Y1
Resetting ABS transfer mode
RST Y2
Resetting ABS request
RST M6
Resetting retry flag
ZRST M62 M64
Resetting checksum judgement flag
ZRST C0 C2
Resetting communication counter
Servo-on and retry control
2
(To be continued)
2

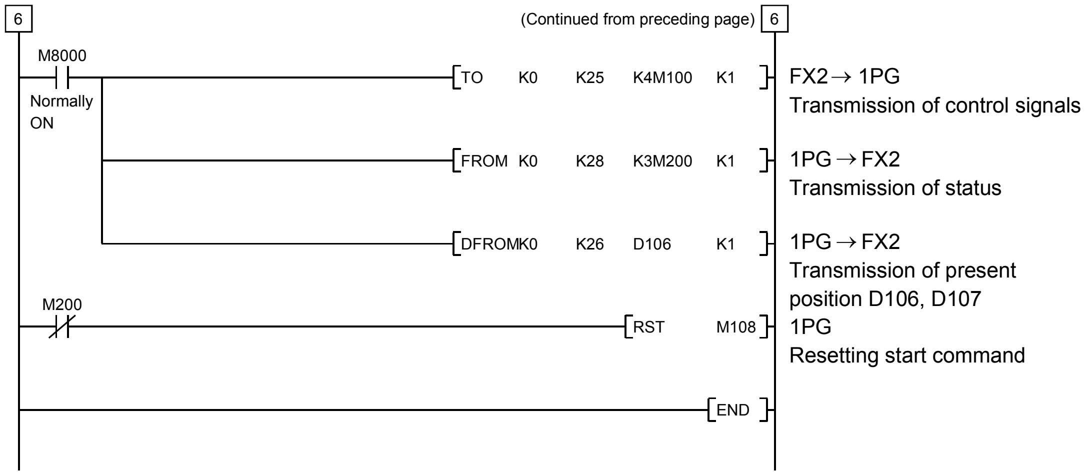

2
(Continued from preceding page)
2
X4
M0
Alarm reset switch
Error flag
Y3
Alarm reset
Y3
Alarm reset output
RST C1
Clearing retry counter
ZRST M0 M64
Clearing ABS data receiving area
ZRST D0 D3
Clearing ABS receive data buffer
RST C2
Resetting ABS data reception counter
RST C0
Resetting all data reception counter
X5
Emergency stop switch
X3
Servo alarm
M0
Error flag output
Y10
Servo alarm output
RST Y1
Resetting ABS transfer mode
RST Y2
Resetting ABS request
RST M99
Resetting ready to send
RST M5
Resetting servo-on request
RST M6
Resetting retry flag
Servo alarm detection, alarm reset control
M1
ABS data transmission start
SET Y1
ABS transfer mode ON
ZRST M10 M64
Clearing ABS data reception area
ZRST D0 D2
Clearing ABS receiver data buffer
RST C2
Resetting ABS data reception counter
RST C0
Resetting all data reception counter
ABS transfer mode Initial setting
3
(To be continued)
3


3
(Continued from preceding page)
3
Y1
C0
X2
PLS M3
Resetting ABS data
ABS transfer mode
All data receptin counter
Send data ready
M3
SET Y2
ABS request ON
ABS data read
Y2
X2
K1
T204
ABS data waiting timer 10ms
ABS request
Send data ready
ABS data 32 bits (2 bits×16 times) + Checksum 6 bits (2 bits×3 times)
T204
WANDP K1X0 H0003 K1M10
Masking ABS data 2 bits
ABS data waiting timer
SFTR M10 M20 K38 K2
Right shift (2 bits) of ABS data
C2
ADDP K1M10 D2 D2
Checksum addition
K16
C2
Updating ABS data reception counter
K19
C0
Updating all data reception counter
RST Y2
Resetting ABS request
C0
X2
RST Y1
Resetting ABS transfer mode
All data receptin counter
Send data ready
WANDP H003F D2 D2
Masking checksum 6 bits
CMPP K2M52 D2 M62
Comparison of checksum
Detection of ABS checksum error, retry control
C1
Y12
ABS data checksum error
Retry counter
M62
C1
PLS M2
Retry command
>
Retry counter
M64
K2
T211
Retry ABS transfer mode OFF wait timer: 20ms set
<
MOV K2M52 D3
Storing checksum value in the case of checksum error
SET M6
Retry flag ON
T211
PLS M4
Servo-on request reset permission
Retry ABS transfer mode OFF wait timer
M4
RST M5
Resetting servo-on request
Servo-on request reset permission
M5
M6
K10
T200
Setting retry wait timer: 100ms
Servo-on request
Retry flag
4
(To be continued)
4


4
(Continued from preceding page)
4
M63
Checksum match
DMOVP K8M20 D0
ABS data – → D0, D1
DADDP D0 D24 D0
Adding 1PG home position address
DTOP K0 K26 D0 K1
ABS data – → 1PG
SET M99
Setting ABS data ready
ZRST M62 M64
Clearing checksum judging area
RST M6
Resetting retry flag
Writing absolute position data to 1PG
Y11
ABS communi-cation error
X6
Servo-on switch
RST Y1
Detecting ABS communication error
RST Y2
Resetting ABS request
Y1
ABS transfer mode
K500
T201
ABS transfer mode 5s timer
Y1
ABS transfer mode
Y2
ABS request
K100
T202
ABS request response 1s timer
Y1
ABS transfer mode
X2
Send data ready
K100
T203
Ready to send response 1s timer
T201
ABS transmission NG
Y11
ABS communication error
T202
ABS request NG
T203
Send data ready NG
Detecting ABS communication error
M2
Retry command
D4
C1
Counting retry frequency
T200
Retry wait timer
M6
Retry
SET M5
Setting servo-on request
ABS transfer retry control
5
(To be continued)
5

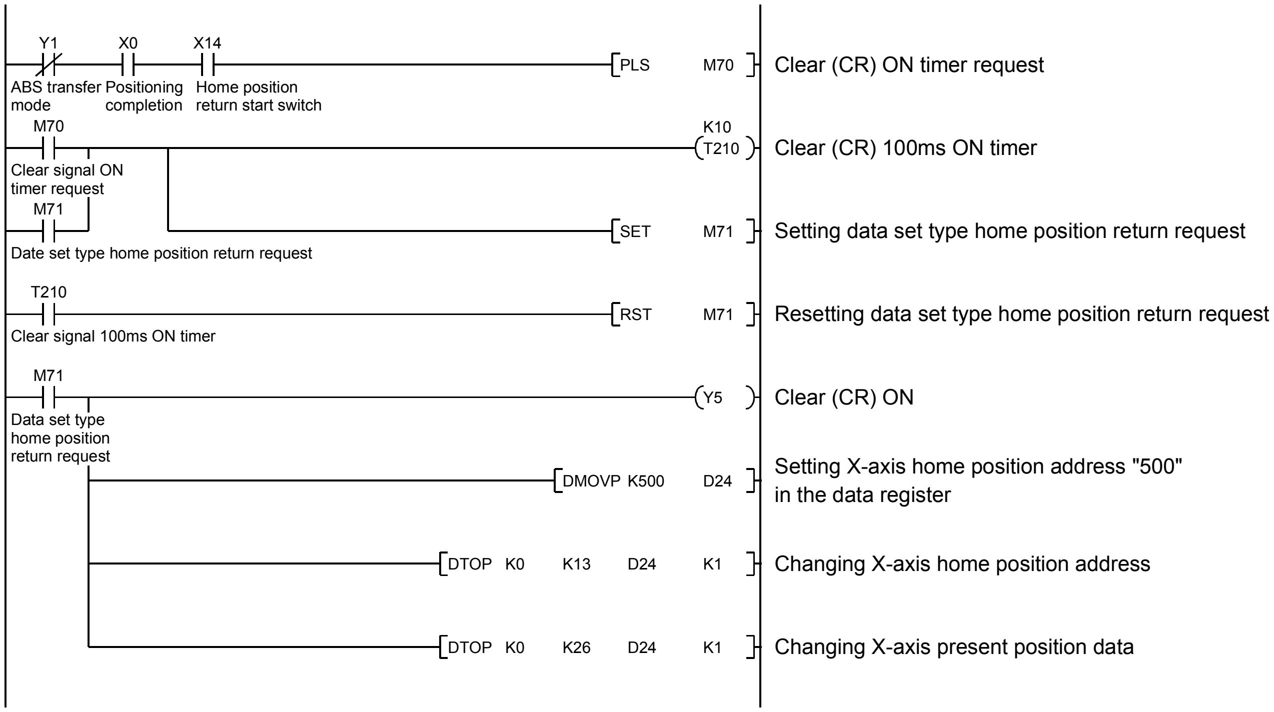


Note. Program example for the dog type home position return. For the data set type home position return, refer to the program example in (2), (d) of this section.



(d) Data set type home position return

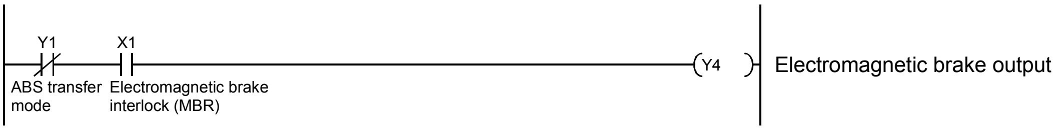
After jogging the machine to the position where the home position (e.g.500) is to be set, choose the home position return mode set the home position with the home position return start switch (X14) ON. After switching power on, rotate the servo motor more than 1 revolution before starting home position return. Do not turn ON the clear (CR) (Y5) for an operation other than home position return. Turning it ON in other circumstances will cause position shift.



(e) Electromagnetic brake output

During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the servo motor must be at a stop.

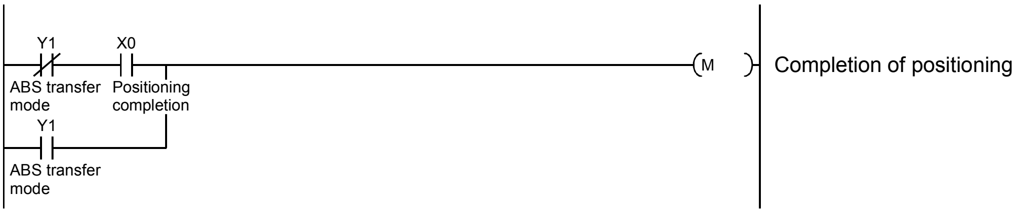
Set "□□□1" in parameter No.PA04 of the servo amplifier to make the electromagnetic brake interlock (MBR) valid.



(f) Positioning completion

To create the status information for positioning completion.

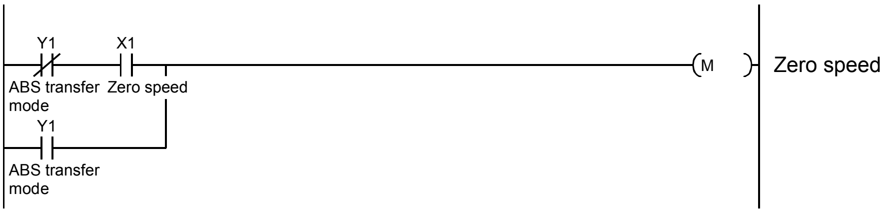
During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the servo motor must be at a stop.



(g) Zero speed

To create the status information for zero speed.

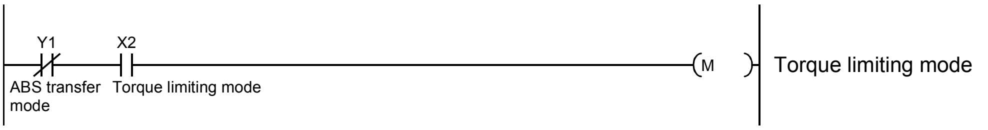
During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the servo motor must be at a stop.



(h) Torque limiting

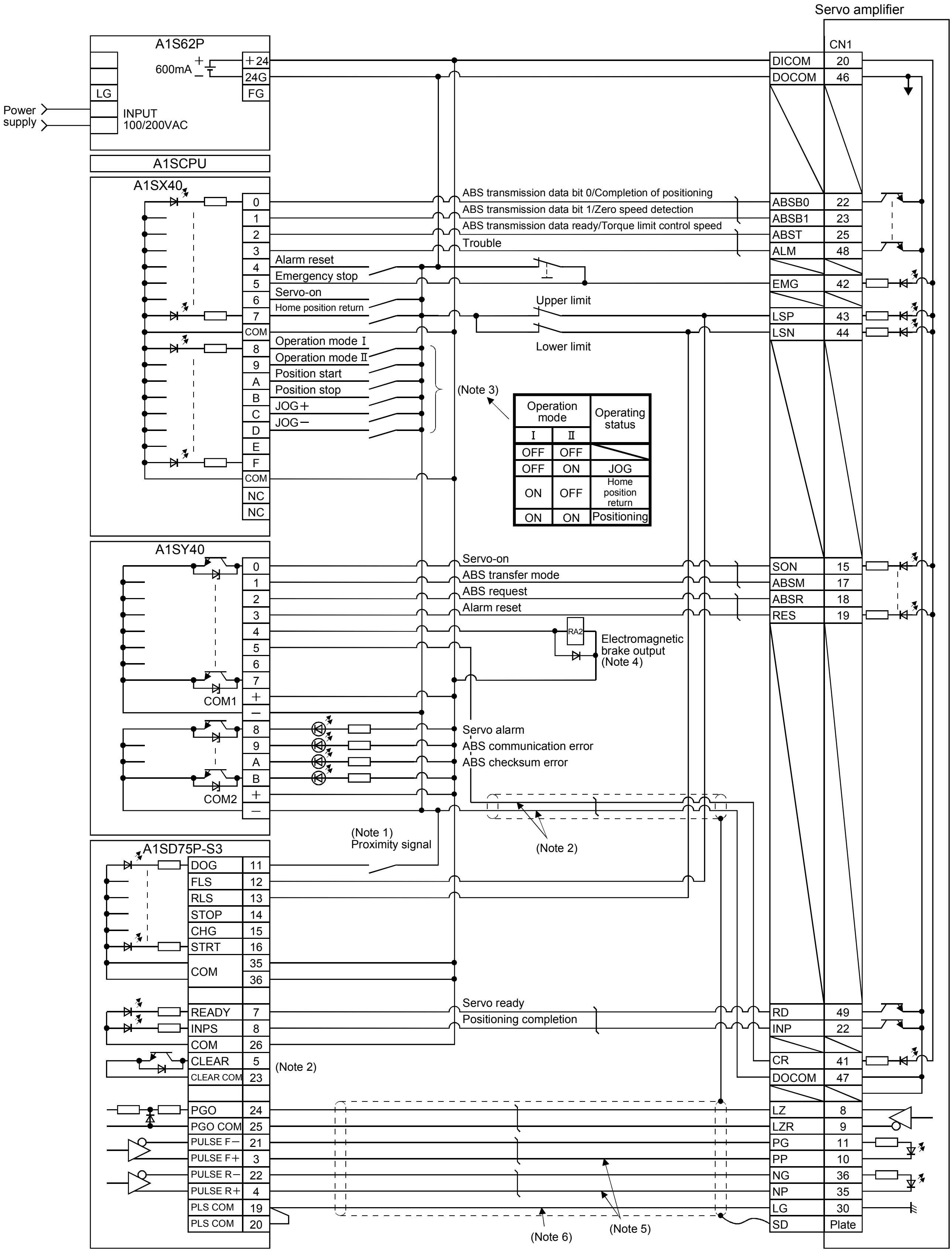
To create the status information for the torque limiting mode.

During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the torque limiting must be off.



14.10.2 MELSEC A1SD75

(1) Connection diagram



Operation mode		Operating status
I	II	
OFF	OFF	
OFF	ON	JOG
ON	OFF	Home position return
ON	ON	Positioning

Note 1. For the dog type home position return. Need not be connected for the data set type home position return.
2. If the servo motor provided with the zero point signal is started, the A1SD75 will output the deviation counter clear (CR). Therefore, do not connect the clear (CR) of the MR-J3-A to the A1SD75 but connect it to the output module of the programmable controller.
3. This circuit is provided for your reference.
4. The electromagnetic brake output should be controlled via a relay connected to the programmable controller output.
5. This connection diagram applies to the differential line driver system as a pulse input system. Refer to section 3.8.2 (3)(b) and A1SD75P☐-S3 Positioning Module User's Manual (IB(NA)66716) for the open collector system.
6. To enhance noise immunity, connect LG and pulse output COM.

(2) Sequence program example

(a) Conditions

The ABS data is transmitted using the leading edge of the servo-on switch as a trigger.

1) When the servo-on switch and power supply GND are shorted, the ABS data is transmitted at power-on of the servo amplifier or on the leading edge of the RUN signal after a PC reset operation (PC-RESET). The ABS data is also transmitted when an alarm is reset or when an emergency stop is reset.
Before starting the ABS data transfer, confirm that it is the servo-on (SON) ON state (refer to section 3.3.2).

2) If a checksum mismatch is detected in the transmitted data, data transmission is retried up to three times. If the checksum mismatch still persists after the retries, the ABS checksum error occurs (Y3A ON).

3) The following time periods are measured. If the ON/OFF state does not change within the specified time, the ABS communication error occurs change within the specified time, the ABS communication error occurs (Y3A ON).
ON period of ABS transfer mode (Y31)
ON period of ABS request (Y32)
OFF period of reading to send ABS data (X22)

(b) Device list

X input contact	
X20	ABS Transmission data bit 0 / positioning completion
X21	ABS Transmission data bit 1 / zero speed detection
X22	Reading to send ABS data / limiting torque
X23	Servo alarm
X24	Alarm reset switch
X25	Servo emergency stop
X26	Servo-on switch
X27	Home position return start switch
X28	Operation mode I
X29	Operation mode II

D register	
D0	ABS data transmission counter
D1	Checksum transmission counter
D2	Checksum addition register
D3	ABS data: Lower 16 bits
D4	ABS data: Upper 16 bits
D5	ABS data 2-bit receiving buffer
D6	Check data in case of checksum error
D7	Number of retries
D8	Forward rotation direction
D9	Home position address: Lower 16 bits
D10	Home position address: Upper 16 bits
D11	Drive unit ready data
D12	Home position return completion data
D110	Received shift data: Lower 16 bits
D111	Received shift data: Upper 16 bits

T timer	
T0	ABS transmission mode timer
T1	ABS request response timer
T2	Retry wait timer
T3	ABS data send reading response timer
T10 (Note 1)	Clear (CR) ON timer
T200	Transmitted data read 10ms delay timer
T211	Retry ABS transfer mode OFF wait timer 20ms set

Y output contact	
Y30	Servo-on
Y31	ABS transfer mode
Y32	ABS request
Y33	Alarm reset
Y34 (Note 2)	Electromagnetic brake output
Y35 (Note 1)	Clear
Y38	Servo alarm
Y39	ABS communication error
Y3A	ABS checksum error

M contact	
M5	ABS data transmission start
M6	Sum check completion
M7	Sum check mismatch
M8	ABS data ready
M9	Transmission data read enabled
M10	Checksum 2 bits read completion
M11	ABS 2 bits read completion
M12	ABS 2 bits request
M13	Servo-on request
M14	Servo alarm
M15	ABS data transfer retry start flag set
M16	Retry flag set
M17	Retry flag reset
M18	PLS processing command
M20 (Note 1)	Clear (CR) ON timer request
M21 (Note 1)	Data set type home position return request
M22	Home position return processing instruction
M23	Current position change processing instruction
M24	Current position change flag
M26	ABS transfer mode OFF permission

C counter	
C0	ABS data receive times counter
C1	Checksum receive times counter
C2	Retry counter

Note 1. Required for data set type home position return.

2. Required for electromagnetic brake output.

(c) ABS data transfer program for X axis

This sequence program example assumes the following conditions.

- Parameters of the A1SD75P1-S3 positioning module
  1) Unit setting :3 = pulse (PLS)
  2) Travel per pulse :1 = 1 pulse

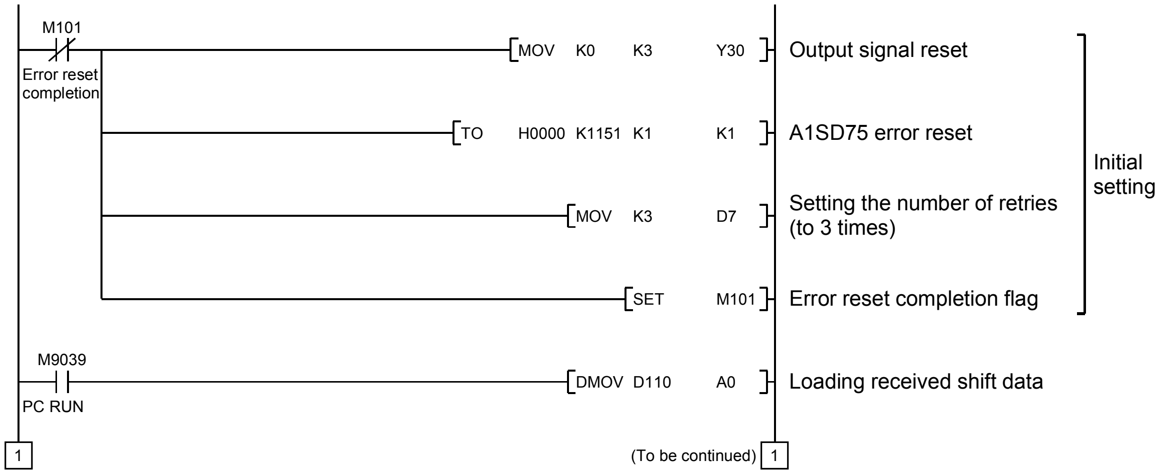
To select the unit other than the pulse, conversion into the unit of the feed value per pulse is required. Hence, add the following program to the area marked (Note) in the sequence program.

<Additional program>

[D * P K□□ D3 D3]

Item	mm				inch				degree				pulse
Unit setting	0				1				2				3
Travel per pulse	0.1 to	1 to	10 to	100	0.00001 to	0.0001 to	0.001 to	0.01 to	0.00001 to	0.0001 to	0.001 to	0.01 to	
Unit of travel	μm/PLS				inch/PLS				degree/PLS				PLS
Constant K for conversion into unit of travel	1 to	10 to	100 to	1000	1 to	10 to	100 to	1000	1 to	10 to	100 to	1000	None

Reference
- For 1μm/PLS, set constant K to 10
- For 5μm/PLS, set constant K to 50
- The additional program is not required for the unit setting is PLS.



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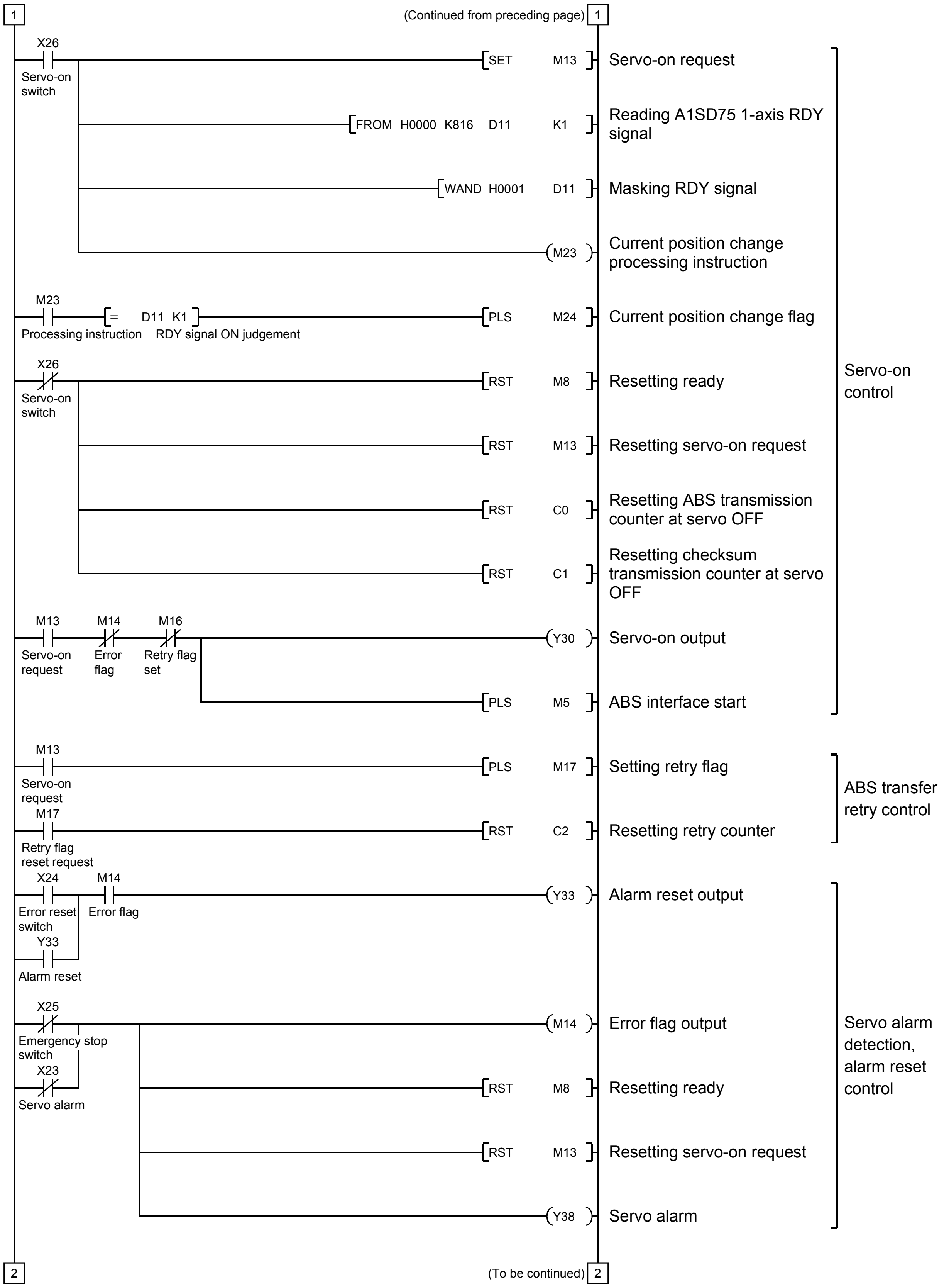
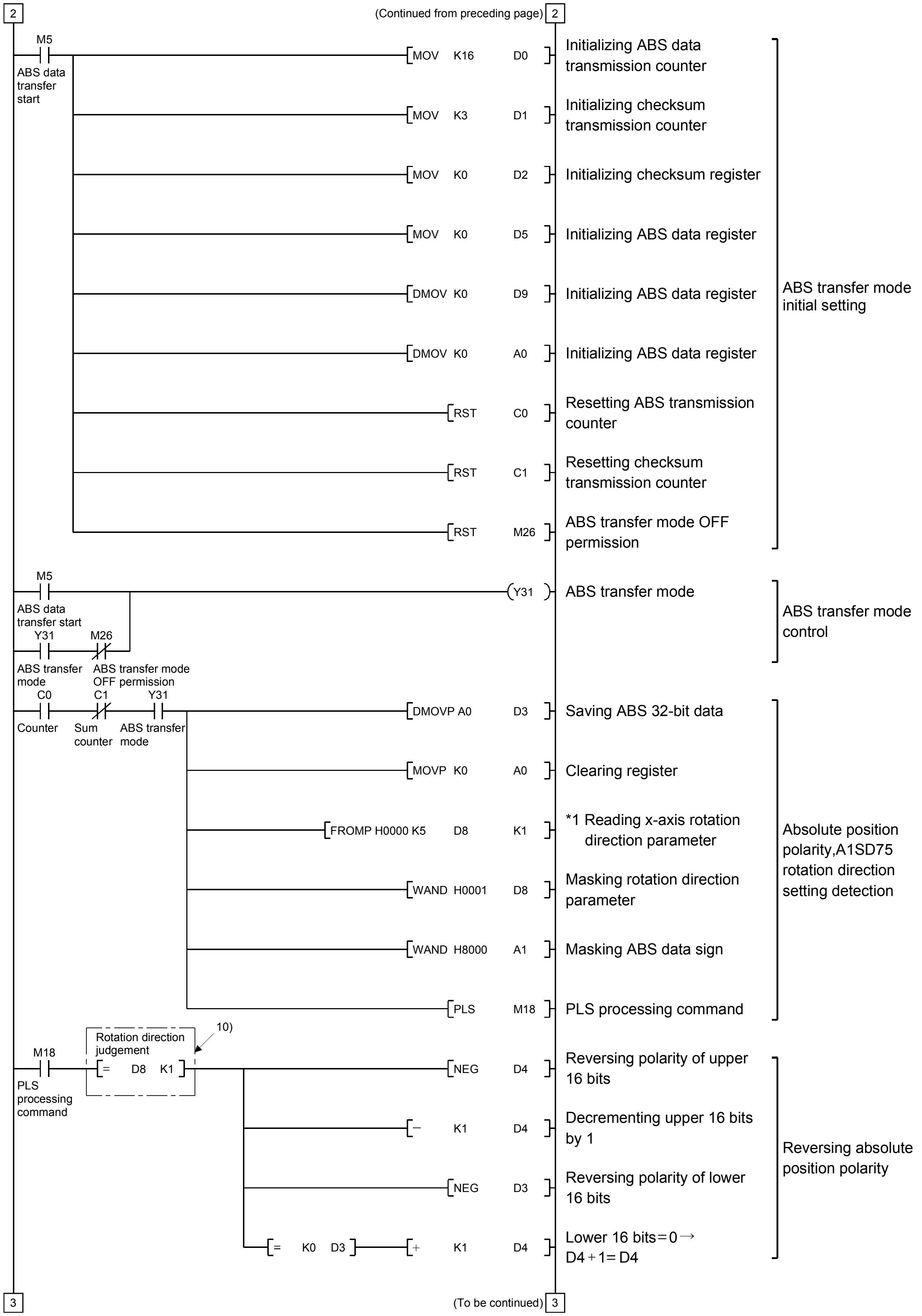
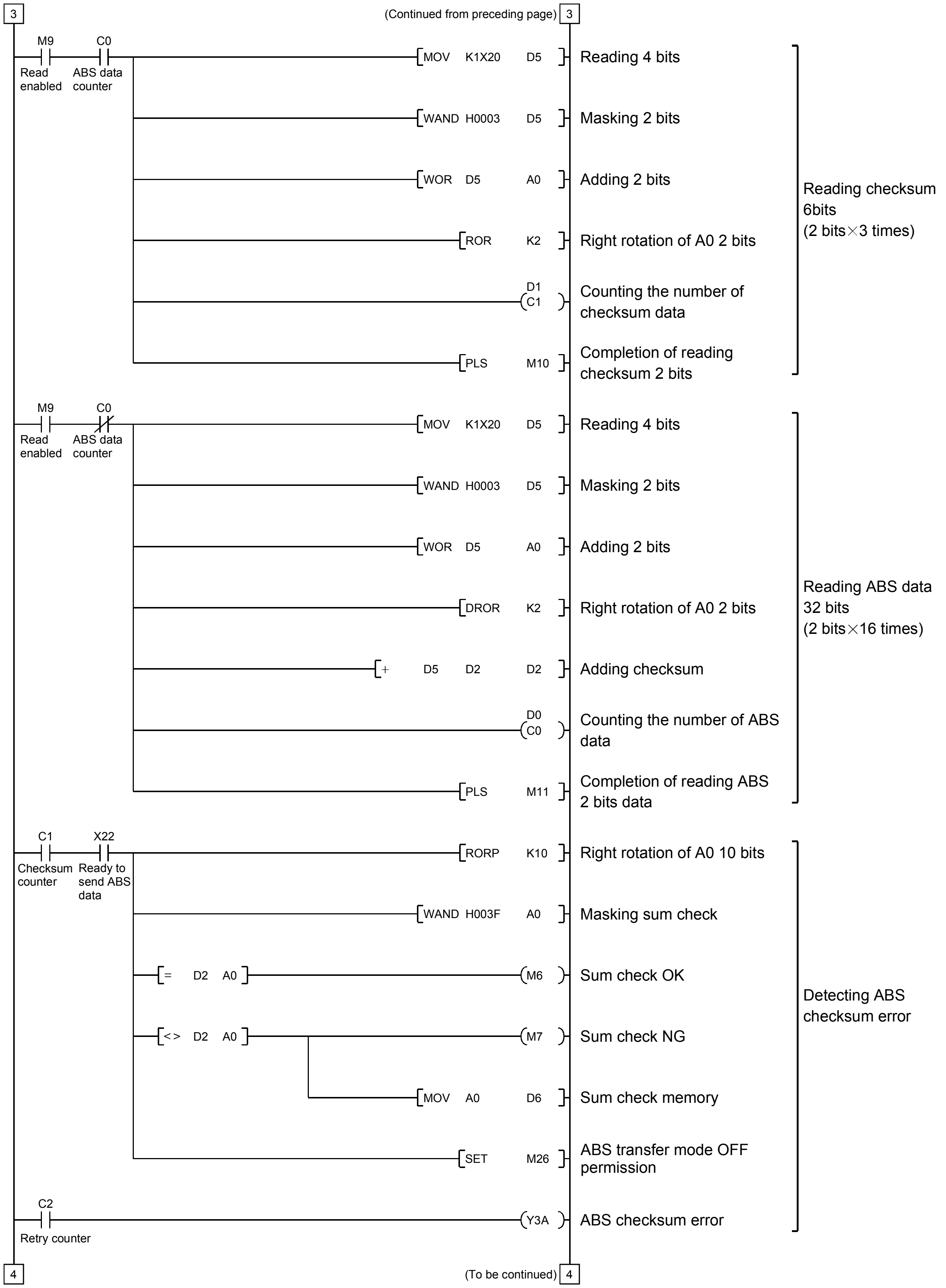
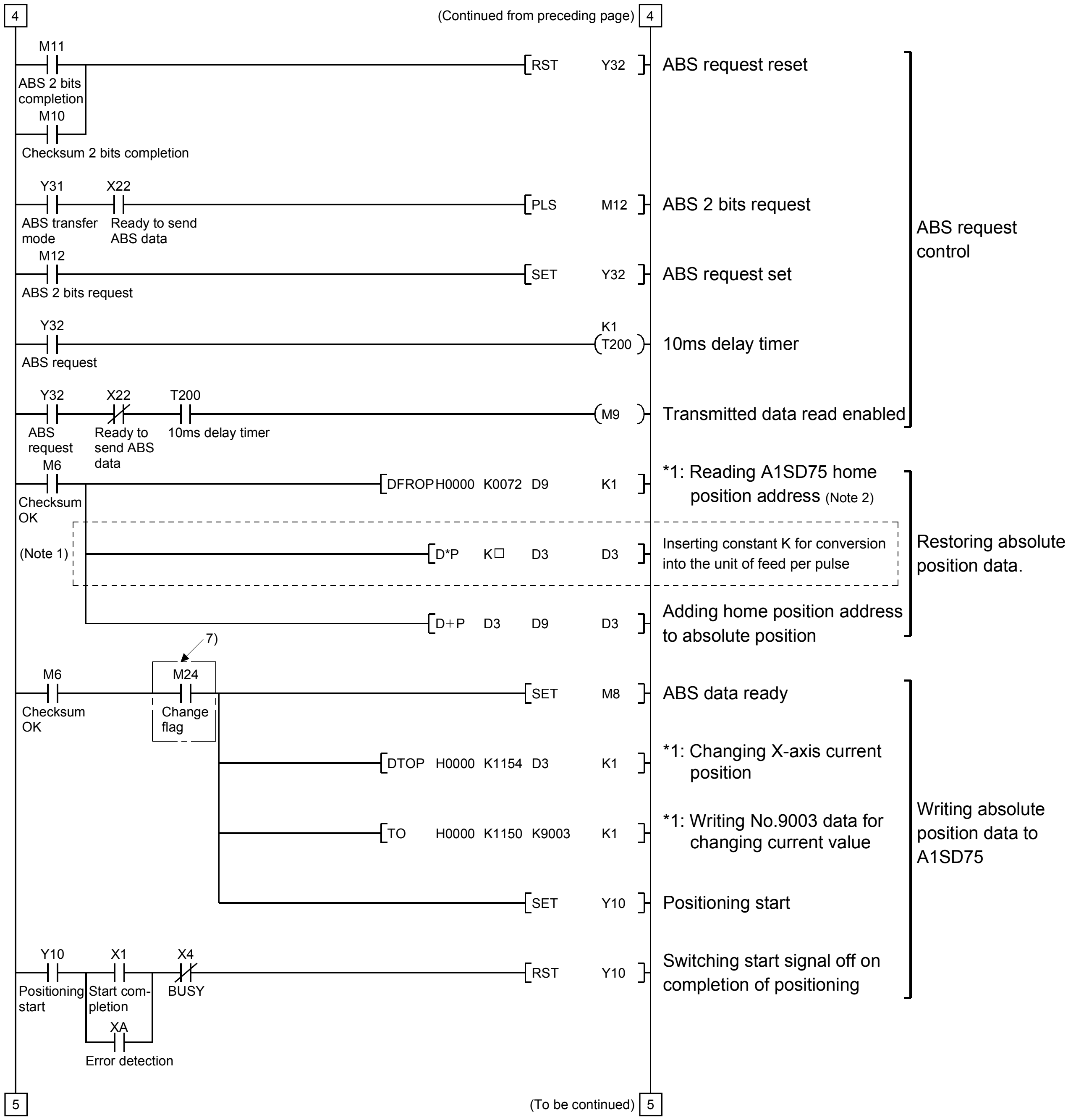


(To be continued)

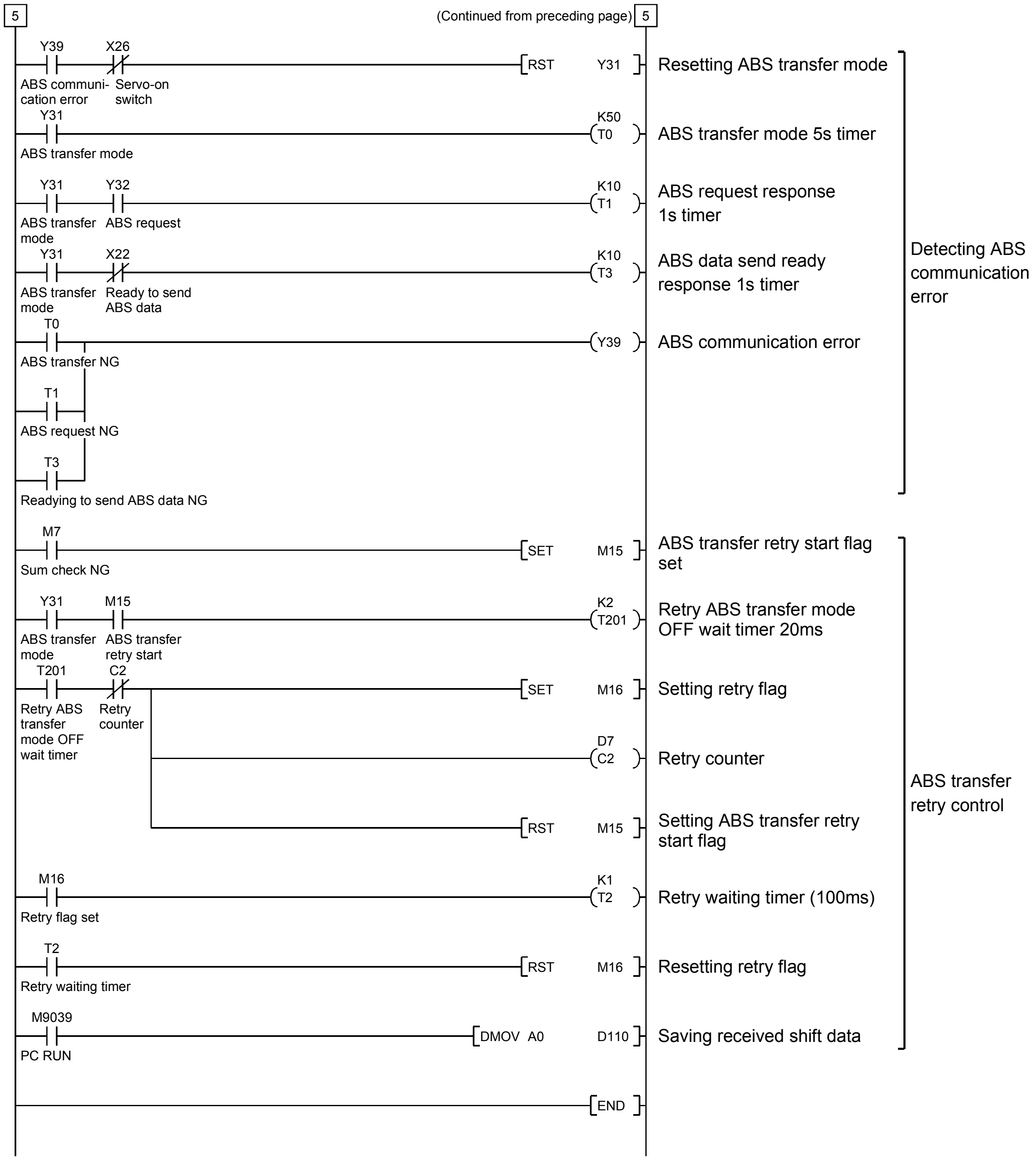

2
(Continued from preceding page) 2
M5
ABS data transfer start
MOV K16 D0
Initializing ABS data transmission counter
MOV K3 D1
Initializing checksum transmission counter
MOV K0 D2
Initializing checksum register
MOV K0 D5
Initializing ABS data register
DMOV K0 D9
Initializing ABS data register
DMOV K0 A0
Initializing ABS data register
RST C0
Resetting ABS transmission counter
RST C1
Resetting checksum transmission counter
RST M26
ABS transfer mode OFF permission
ABS transfer mode initial setting
M5
ABS data transfer start
Y31
ABS transfer mode
M26
ABS transfer mode OFF permission
Y31
ABS transfer mode
ABS transfer mode control
C0
Counter
C1
Sum counter
Y31
ABS transfer mode
DMOVP A0 D3
Saving ABS 32-bit data
MOVP K0 A0
Clearing register
FROMP H0000 K5 D8 K1
*1 Reading x-axis rotation direction parameter
WAND H0001 D8
Masking rotation direction parameter
WAND H8000 A1
Masking ABS data sign
PLS M18
PLS processing command
Absolute position polarity,A1SD75 rotation direction setting detection
M18
PLS processing command
Rotation direction judgement
= D8 K1
10)
NEG D4
Reversing polarity of upper 16 bits
– K1 D4
Decrementing upper 16 bits by 1
NEG D3
Reversing polarity of lower 16 bits
= K0 D3
+ K1 D4
Lower 16 bits=0→ D4+1=D4
Reversing absolute position polarity
3
(To be continued) 3


3
(Continued from preceding page)
3
M9
C0
Read enabled
ABS data counter
MOV K1X20 D5
Reading 4 bits
WAND H0003 D5
Masking 2 bits
WOR D5 A0
Adding 2 bits
ROR K2
Right rotation of A0 2 bits
D1
C1
Counting the number of checksum data
PLS M10
Completion of reading checksum 2 bits
Reading checksum 6bits (2 bits×3 times)
M9
C0
Read enabled
ABS data counter
MOV K1X20 D5
Reading 4 bits
WAND H0003 D5
Masking 2 bits
WOR D5 A0
Adding 2 bits
DROR K2
Right rotation of A0 2 bits
+ D5 D2 D2
Adding checksum
D0
C0
Counting the number of ABS data
PLS M11
Completion of reading ABS 2 bits data
Reading ABS data 32 bits (2 bits×16 times)
C1
X22
Checksum counter
Ready to send ABS data
RORP K10
Right rotation of A0 10 bits
WAND H003F A0
Masking sum check
= D2 A0
M6
Sum check OK
<> D2 A0
M7
Sum check NG
MOV A0 D6
Sum check memory
SET M26
ABS transfer mode OFF permission
C2
Retry counter
Y3A
ABS checksum error
Detecting ABS checksum error
4
(To be continued)
4



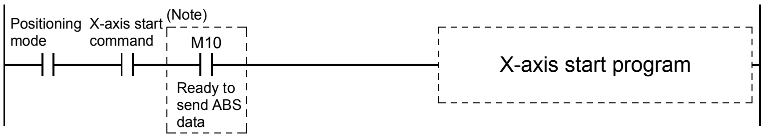
Note 1. When the unit setting parameter value of the A1SD75 positioning module is changed from "3" (pulse) to "0" (mm), the unit is × 0.1μm for the input value. To set the unit to × 1μm, add this program to multiple the feed value by 10.

2. The home position address loaded from flash ROM of normal positioning module can be obtained.
For updating the home position address by the home position setting, refer to (2) (f) Data set type home position return in this Section.


5
(Continued from preceding page)
5
Y39
X26
RST Y31
Resetting ABS transfer mode
ABS communi- cation error
Servo-on switch
Y31
K50
T0
ABS transfer mode 5s timer
ABS transfer mode
Y31
Y32
K10
T1
ABS request response 1s timer
ABS transfer mode
ABS request
Y31
X22
K10
T3
ABS data send ready response 1s timer
ABS transfer mode
Ready to send ABS data
Detecting ABS communication error
T0
Y39
ABS communication error
ABS transfer NG
T1
ABS request NG
T3
Readying to send ABS data NG
M7
SET M15
ABS transfer retry start flag set
Sum check NG
Y31
M15
K2
T201
Retry ABS transfer mode OFF wait timer 20ms
ABS transfer mode
ABS transfer retry start
T201
C2
SET M16
Setting retry flag
Retry ABS transfer mode OFF wait timer
Retry counter
D7
C2
Retry counter
ABS transfer retry control
RST M15
Setting ABS transfer retry start flag
M16
K1
T2
Retry waiting timer (100ms)
Retry flag set
T2
RST M16
Resetting retry flag
Retry waiting timer
M9039
DMOV A0 D110
Saving received shift data
PC RUN
END

(d) X-axis program

Do not execute the X-axis program while the ABS ready (M8) is off.



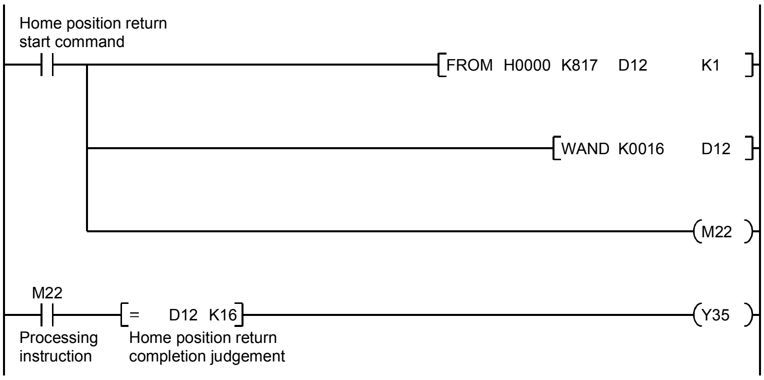
When "M10" (ready to send ABS data) switches on, the X-axis start program is executed by the X-axis start command.

(e) Dog type home position return

Refer to the home position return program in the A1SD75 User's Manual.

Note that this program requires a program which outputs the clear (CR) (Y35) after completion of home position return.

Add the following program.



Reading 1-axis home position return completion signal

Masking home position return completion

Home position return processing instruction

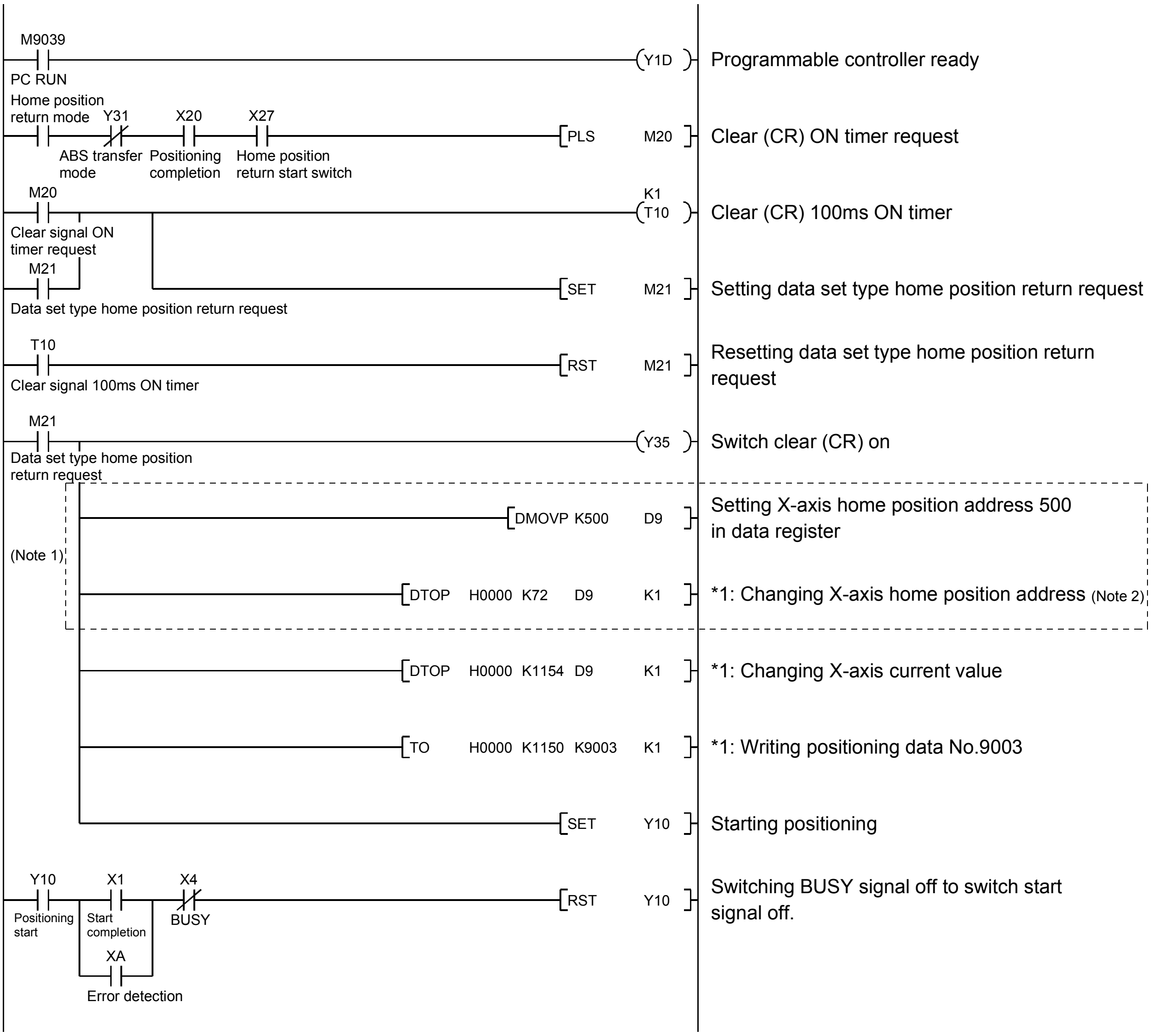
Switching clear (CR) on

(f) Data set type home position return

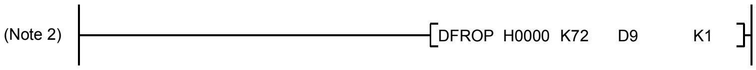
After jogging the machine to the position where the home position (e.g. 500) is to be set, choose the home position return mode and set the home position with the home position return start switch (X27) ON.

After switching power on, rotate the servo motor more than 1 revolution before starting home position return.

Do not turn ON the clear (CR) (Y35) for an operation other than home position return. Turning it on in other circumstances will cause position shift.



Note 1. When the data of the home position address parameter is not written from GX Developer or the like before starting the data set type home position return program, this sequence circuit is required.
When the home position address is written in the home position address parameter, change to the following circuit.

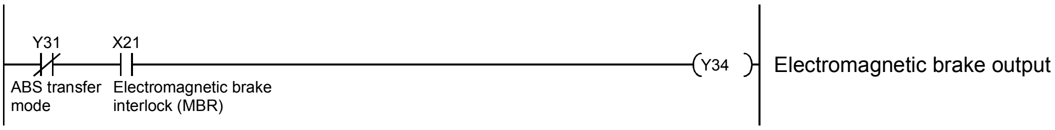


2. Changes are stored temporarily to buffer memory at this time. An additional processing is required when changes should be reflected to memory for OS or flash ROM. For details, refer to the positioning module user's manual.

(g) Electromagnetic brake output

During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the servo motor must be at a stop.

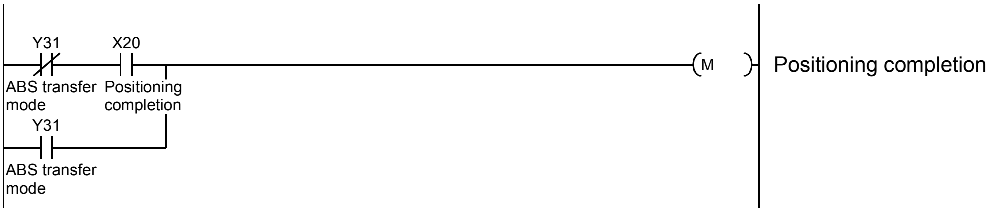
Set "□□□1" in parameter No.PA04 of the servo amplifier to make the electromagnetic brake interlock (MBR) valid.



(h) Positioning completion

To create the status information for positioning completion.

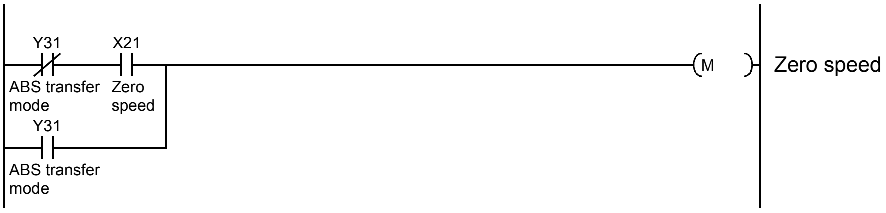
During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the servo motor must be at a stop.



(i) Zero speed

To create the status information for zero speed.

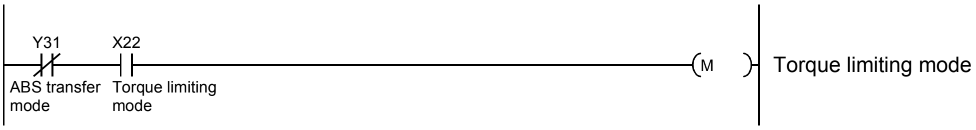
During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the servo motor must be at a stop.



(j) Torque limiting

To create the status information for the torque limiting mode.

During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the torque limiting must be off.



(3) Sequence program - 2-axis control

The following program is a reference example for creation of an ABS sequence program for the second axis (Y axis) using a single A1SD75 module. Create a program for the third axis in a similar manner.

(a) Y-axis program

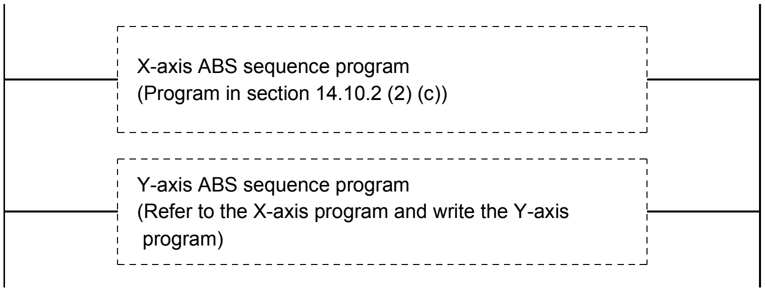
Refer to the X-axis ABS sequence program and create the Y-axis program.

Assign the X inputs, Y outputs, D registers, M contacts, T timers and C counters of the Y axis so that they do not overlap those of the X axis.

The buffer memory addresses of the A1SD75 differ between the X and Y axes. The instructions marked *1 in the program of section 14.10.2 (2) (c) should be changed as indicated below for use with the Y axis.

```
[FROMP  H0000  K5     D8     K1]  →  [FROMP  H0000  K155   D8     K1]
[DFROP  H0000  K0072  D9     K1]  →  [DFROP  H0000  K222   D9     K1]
[DTOP   H0000  K1154  D3     K1]  →  [DTOP   H0000  K1204  D3     K1]
[TO     H0000  K1150  K9003  K1]  →  [TO     H0000  K1200  K9003  K1]
```

[Program configuration]



(b) Data set type home position return

Arrange the data set type home position return programs given in section 14.10.2 (2) (f) in series to control two axes.

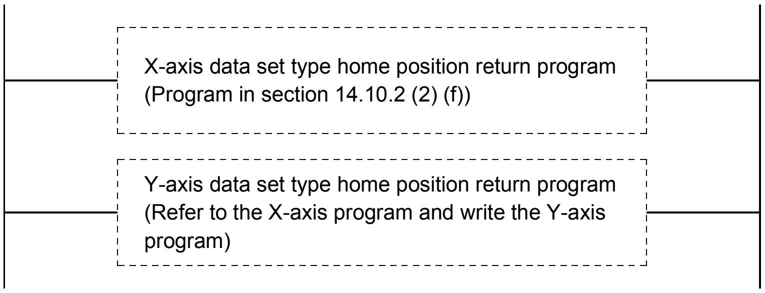
Refer to the X-axis data set type home position return program and create the Y-axis program.

Assign the X inputs, Y outputs, D registers, M contacts and T timers of the Y axis so that they do not overlap those of the X axis.

The buffer memory addresses of the A1SD75 differ between the X and Y axes. The instructions marked *1 in the program of section 14.10.2 (2) (f) should be changed as indicated below for use with the Y axis.

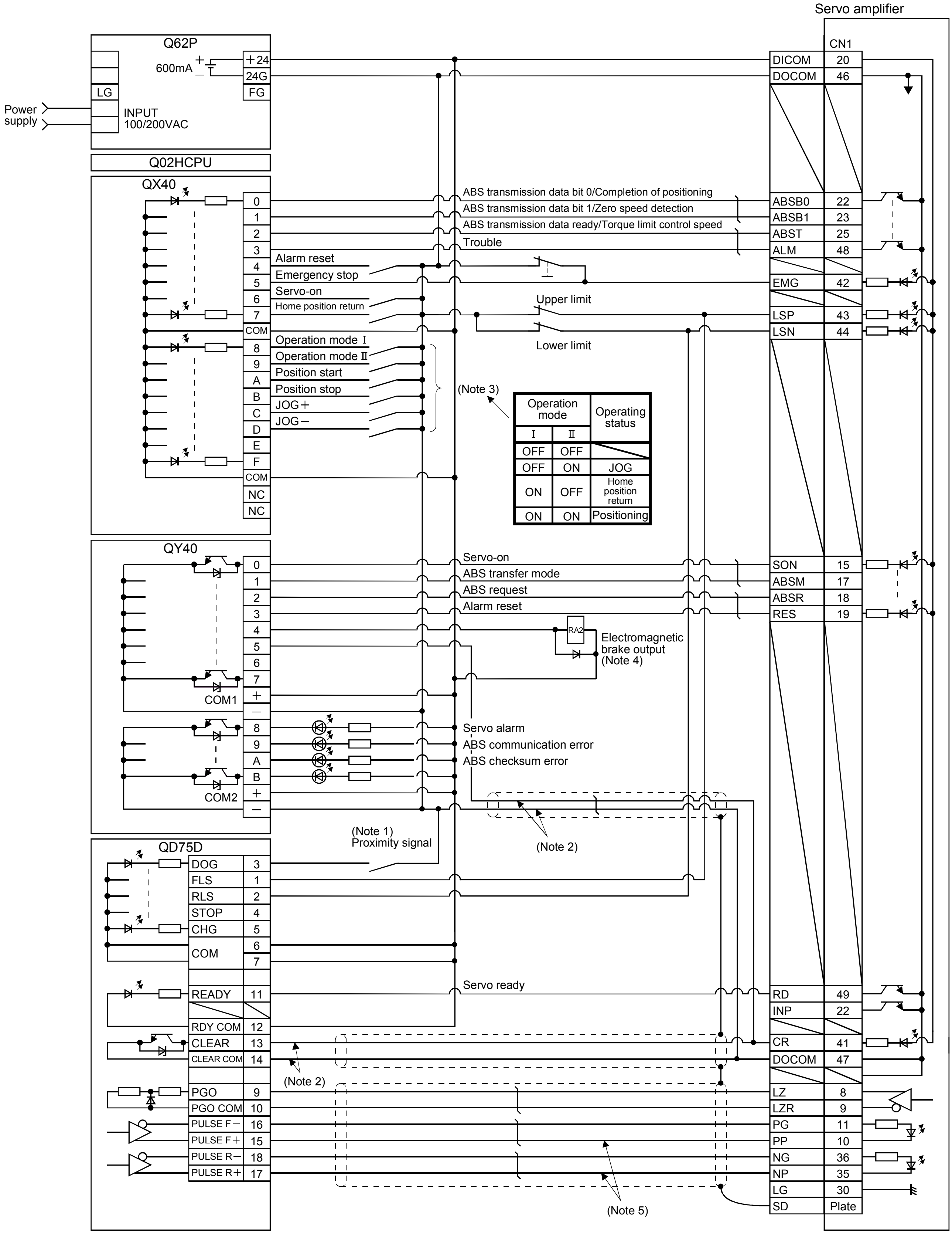
```
[DTOP  H0000  K72    D9     K1]  →  [DTOP  H0000  K222   D9     K1]
[DTOP  H0000  K1154  D9     K1]  →  [DTOP  H0000  K1204  D3     K1]
[TO    H0000  K1150  K9003  K1]  →  [TO    H0000  K1200  K9003  K1]
```

[Program configuration]



14.10.3 MELSEC QD75

(1) Connection diagram



Operation mode		Operating status
Ⅰ	Ⅱ	
OFF	OFF	
OFF	ON	JOG
ON	OFF	Home position return
ON	ON	Positioning

Note 1. For the dog type home position return. Need not be connected for the data set type home position return.
2. For the dog type home position return, connect a QD75 deviation counter clearing signal cable. For the data set type home position return, connect a cable to the output module of the programmable controller.
3. This circuit is provided for your reference.
4. The electromagnetic brake output should be controlled via a relay connected to the programmable controller output.
5. Refer to section 3.8.2 (3)(b) and Type QD75P/QD75D Positioning Module User's Manual when connecting to QD75P.

(2) Sequence program example

(a) Conditions

The ABS data is transmitted using the leading edge of the servo-on switch as a trigger.

1) When the servo-on switch and power supply GND are shorted, the ABS data is transmitted at power-on of the servo amplifier or on the leading edge of the RUN signal after a PC reset operation (PC-RESET). The ABS data is also transmitted when an alarm is reset or when an emergency stop is reset.

2) An ABS checksum error is caused (Y3AON) if checksum inconsistency is found in transferred data.

3) The following time periods are measured. If the ON/OFF state does not change within the specified time, the ABS communication error occurs change within the specified time, the ABS communication error occurs (Y3A ON).
ON period of ABS transfer mode (Y31)
ON period of ABS request (Y32)
OFF period of reading to send ABS data (X22)

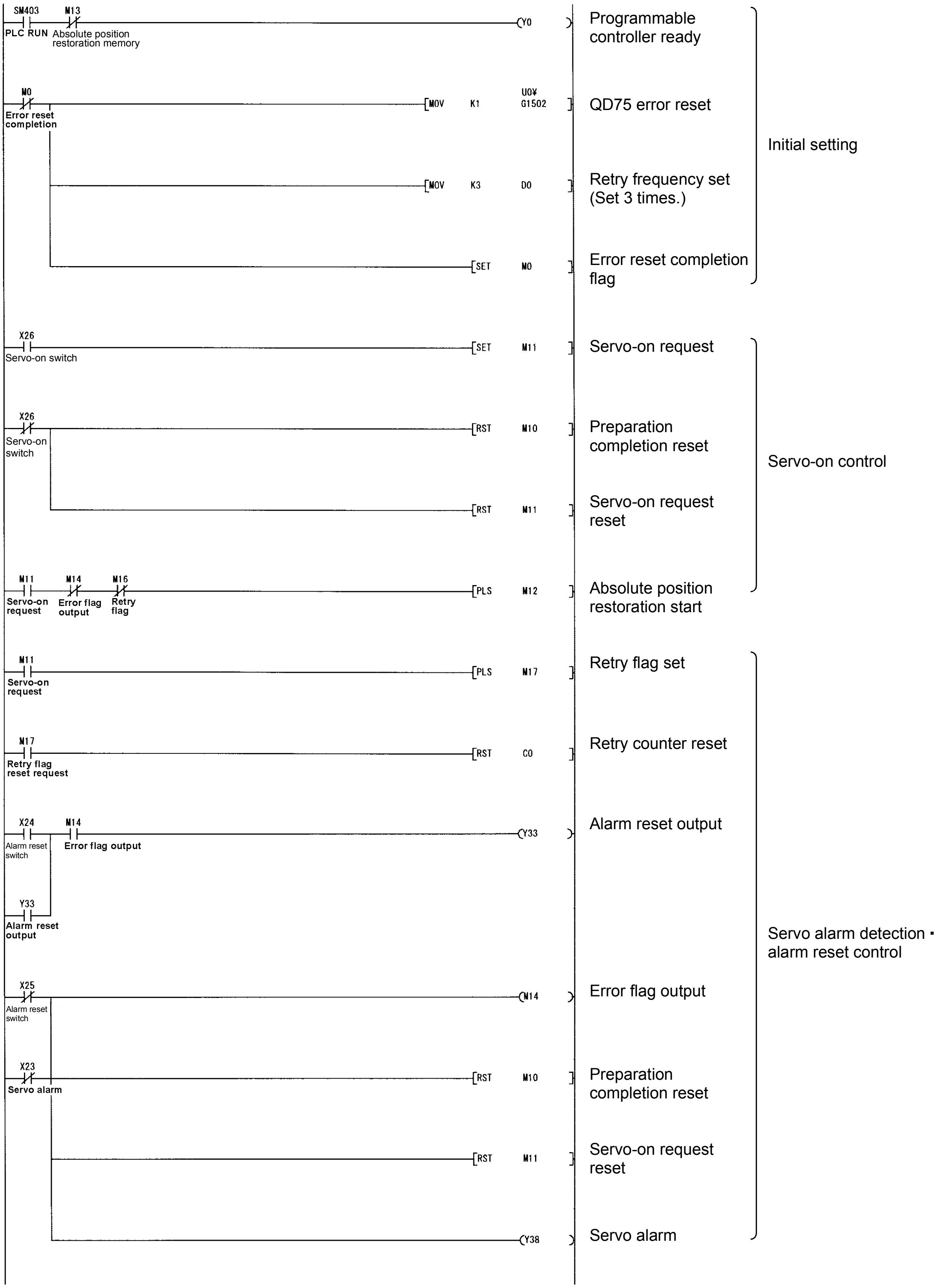
(b) Device list

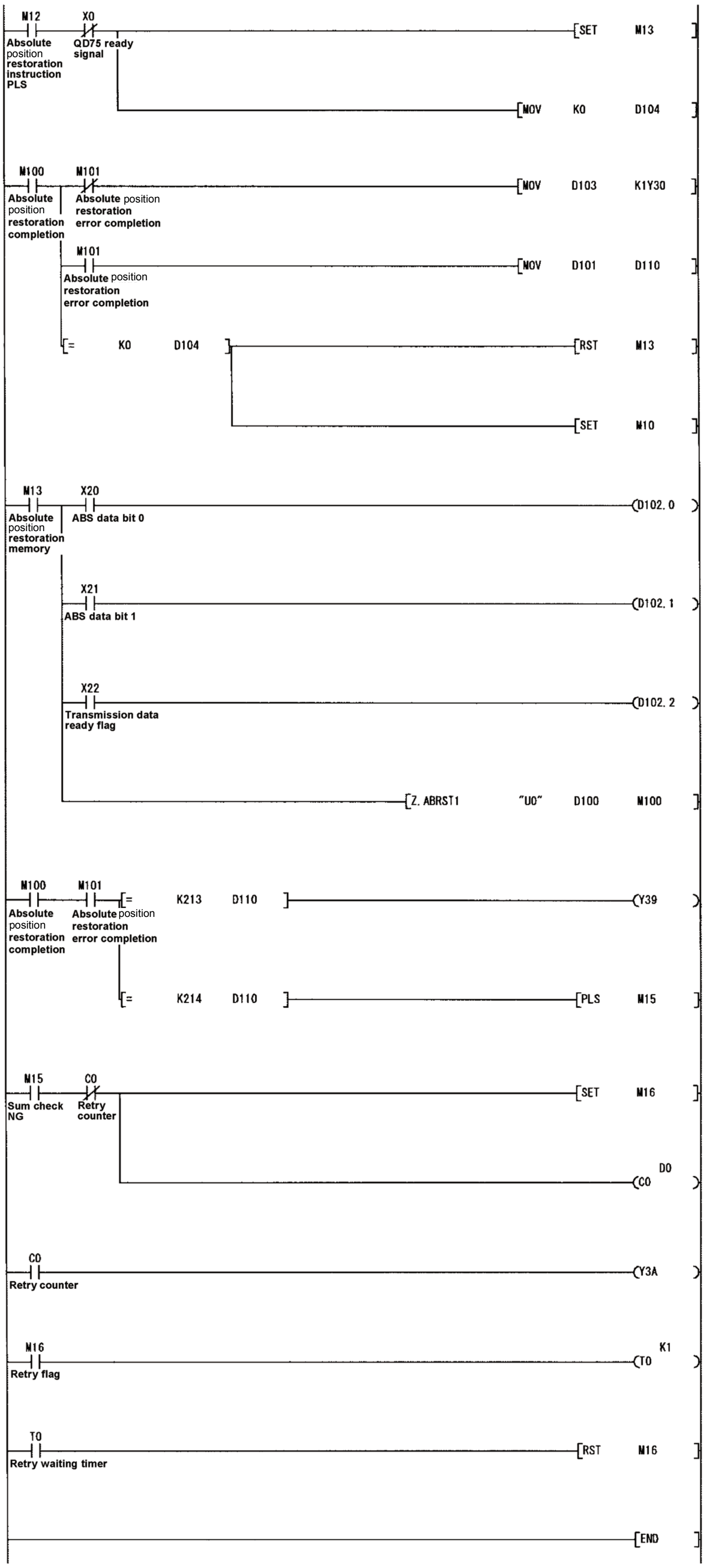
X input contact		Y output contact	
X20	ABS transmission data bit 0/Positioning completion	Y30	Servo-on
X21	ABS transmission data bit 1/zero speed detection	Y31	ABS transfer mode
X22	ABS transmission data ready/Torque limiting	Y32	ABS request
X23	Servo alarm	Y33	Alarm reset
X24	Alarm reset switch	Y34 (Note 2)	Electromagnetic brake output
X25	Servo emergency stop	Y35 (Note 1)	Clear
X26	Servo-on switch	Y38	Servo alarm
X27	Home position return start switch	Y39	ABS communication error
X28	Operation mode I	Y3A	ABS checksum error
X29	Operation mode II		

D register		M contact	
D0	Number of retries	M0	End of error reset
D9	Home position address: Lower 16 bits	M10	Preparation completion
D10	Home position address: Upper 16 bits	M11	Servo-on request
D100 to D104	For absolute position restoration dedicated instruction	M12	Absolute position restoration instruction PLS
		M13	Absolute position restoration memory
T timer		M14	Error flag output
T0	Retry wait timer	M15	Sum check NG
T10 (Note 1)	Clear (CR) ON timer	M16	Retry flag
		M17	Retry flag reset request
		M20 (Note 1)	Clear (CR) ON timer request
		M21 (Note 1)	Data set type home position return request
		M100 to M101	For absolute position restoration dedicated instruction
		C counter	
		C0	Retry counter

Note 1. Required for data set type home position return.
2. Required for electromagnetic brake output.

(c) ABS data transfer program for X axis





Absolute position restoration start flag

Absolute position restoration status reset

Absolute position restoration output

Error code storage

Absolute position restoration start flag reset

Preparation completion

Absolute position restoration data reception

Absolute position restoration data reception

Absolute position restoration data reception

Absolute position restoration dedicated instruction execution

Absolute position restoration

ABS communication error

Sum check error detection

Retry flag set

Retry counter

ABS checksum error

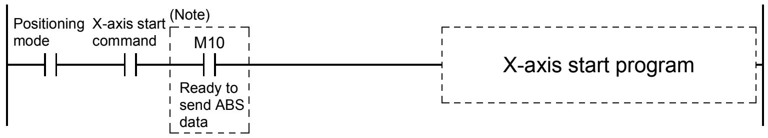
Retry wait timer

Retry flag reset

Error detection・retry control

(d) X-axis program

Do not execute the X-axis program while the ABS ready (M10) is off.



When "M10" (ready to send ABS data) switches on, the X-axis start program is executed by the X-axis start command.

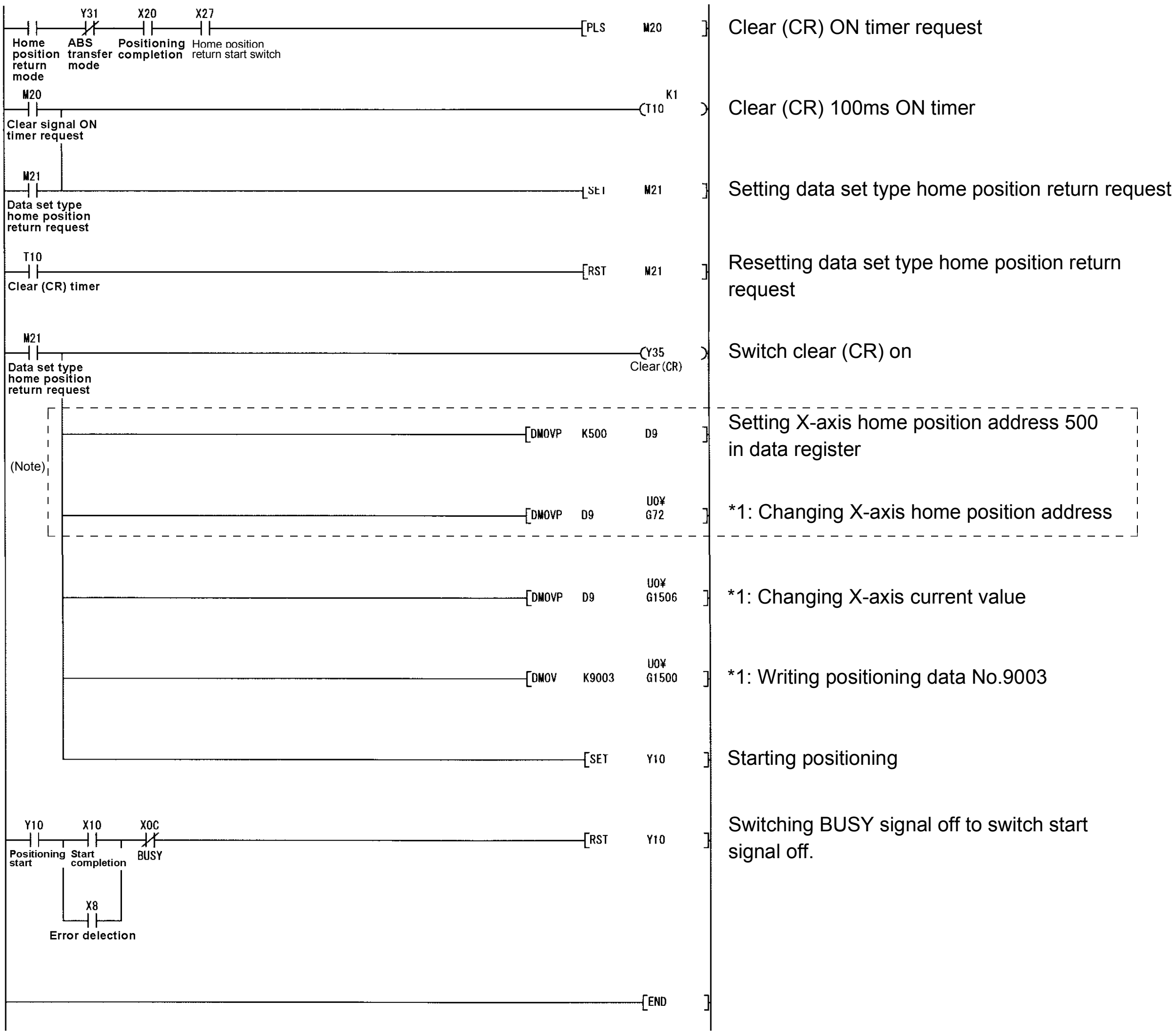
(e) Dog type home position return

Refer to the home position return program in the QD75 User's Manual.

(f) Data set type home position return

After jogging the machine to the position where the home position (e.g. 500) is to be set, choose the home position return mode and set the home position with the home position return start switch (X27) ON. After switching power on, rotate the servo motor more than 1 revolution before starting home position return.

Do not turn ON the clear (CR) (Y35) for an operation other than home position return. Turning it on in other circumstances will cause position shift.



Clear (CR) ON timer request

Clear (CR) 100ms ON timer

Setting data set type home position return request

Resetting data set type home position return request

Switch clear (CR) on

Setting X-axis home position address 500 in data register

*1: Changing X-axis home position address

*1: Changing X-axis current value

*1: Writing positioning data No.9003

Starting positioning

Switching BUSY signal off to switch start signal off.

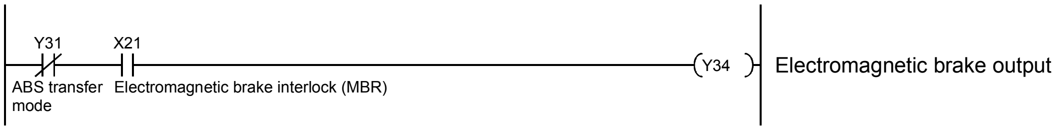
Note. When the data of the home position address parameter is not written from GX Developer or the like before starting the data set type home position return program, this sequence circuit is required.

When the home position address is written in the home position address parameter, change to the following circuit.

(g) Electromagnetic brake output

During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the servo motor must be at a stop.

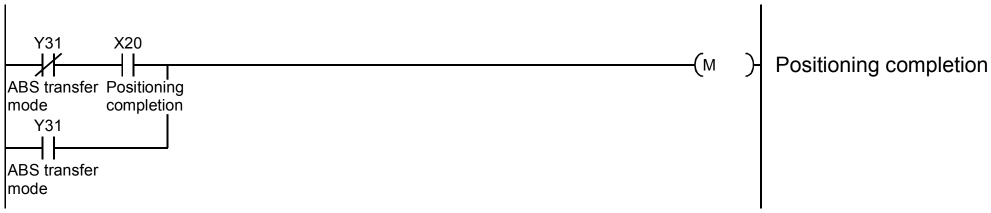
Set "□□□1" in parameter No.PA04 of the servo amplifier to make the electromagnetic brake interlock (MBR) valid.



(h) Positioning completion

To create the status information for positioning completion.

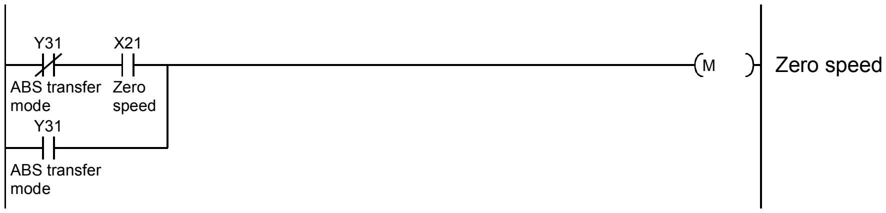
During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the servo motor must be at a stop.



(i) Zero speed

To create the status information for zero speed.

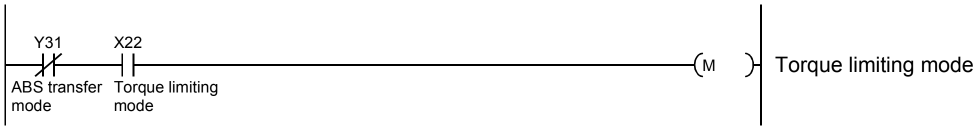
During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the servo motor must be at a stop.



(j) Torque limiting

To create the status information for the torque limiting mode.

During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the torque limiting must be off.



(3) Sequence program - 2-axis control

The following program is a reference example for creation of an ABS sequence program for the second axis (Y axis) using a single QD75 module. Create a program for the third axis in a similar manner.

(a) Y-axis program

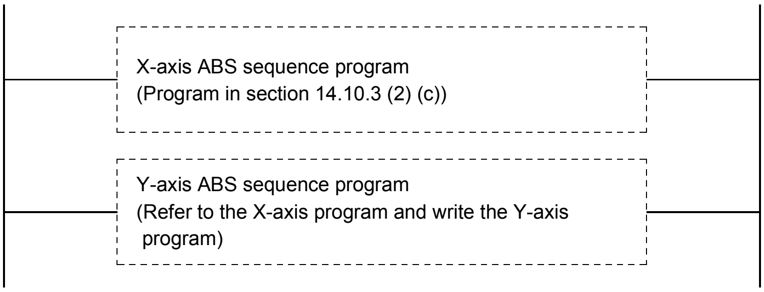
Refer to the X-axis ABS sequence program and create the Y-axis program.

Assign the X inputs, Y outputs, D registers, M contacts, T timers and C counters of the Y axis so that they do not overlap those of the X axis.

The buffer memory addresses of the QD75 differ between the X and Y axes. The instructions marked *1 in the program of section 14.10.3 (2) (c) should be changed as indicated below for use with the Y axis.

```
[Z. ABRST1   "U0"  D100  M100]  →  [Z. ABRST2   "U0"  D100  M100]
```

[Program configuration]



(b) Data set type home position return

Arrange the data set type home position return programs given in section 14.10.3 (2) (f) in series to control two axes.

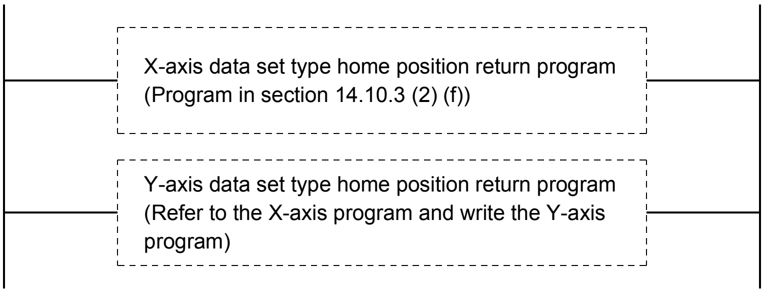
Refer to the X-axis data set type home position return program and create the Y-axis program.

Assign the X inputs, Y outputs, D registers, M contacts and T timers of the Y axis so that they do not overlap those of the X axis.

The buffer memory addresses of the QD75 differ between the X and Y axes. The instructions marked *1 in the program of section 14.10.2 (2) (f) should be changed as indicated below for use with the Y axis.

```
[DMOVP  D9      U0¥G72   ]  →  [DMOVP  D9       U0¥G222  ]
[DMOVP  U0¥G72   D9      ]  →  [DMOVP  U0¥G222   D9      ]
[DMOVP  D9      U0¥1506  ]  →  [DMOVP  D9       U0¥1606  ]
[DMOVP  K9003   U0¥1500  ]  →  [DMOVP  D9       U0¥1600  ]
```

[Program configuration]



14.11 Absolute position data transfer errors

14.11.1 Corrective actions

(1) Error list

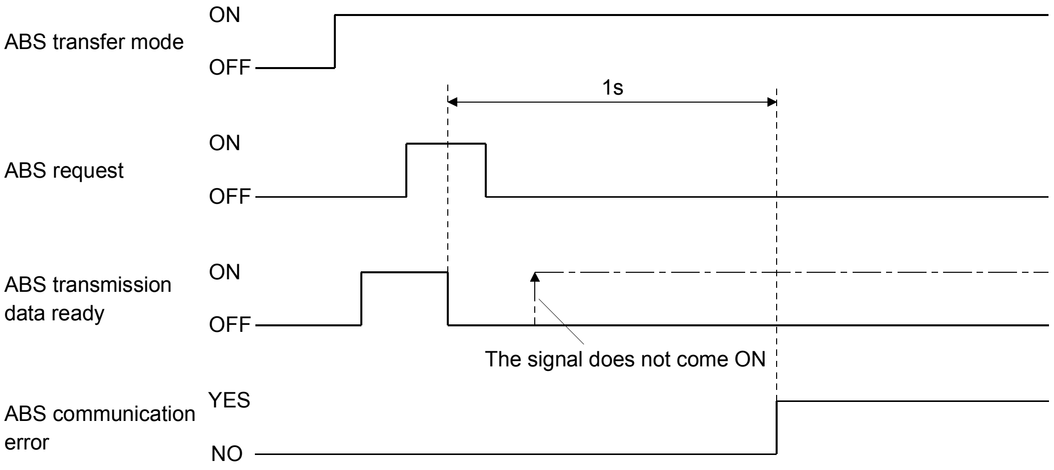
The number within parentheses in the table indicates the output coil or input contact number of the A1SD75.

Name	Output coil		Description	Cause	Action
	AD75	1PG			
(Note) ABS communication error	Y39	Y11	1. The ABS data transfer mode signal (Y41) is not completed within 5s. 2. The ready to send signal (X32) is not turned OFF within 1s after the ABS data request signal (Y42) is turned ON. 3. The ready to send signal (X32) remains OFF for longer than 1s.	1. Wiring for ABS transfer mode signal, ABS data request signal, or ready to send signal is disconnected or connected to the DOCOM terminal.	Correct the wiring.
				2. Programmable controller ladder program incorrect.	Correct the ladder.
				3. Faulty programmable controller output or input module.	Change the input or output module.
				4. Faulty printed board in the servo amplifier.	Change the amplifier
				5. Power supply to the servo amplifier is OFF.	Turn on the power to the servo amplifier.
ABS data checksum error	Y3A	Y12	・ABS data sumcheck resulted in mismatch four times consecutively.	1. Wiring for the ABS data signal (ABS bit 0 (PF), bit 1 (ZSP)) is disconnected or connected to the SG terminal.	Correct the wiring.
				2. Programmable controller ladder program incorrect.	Correct the ladder.
				3. Faulty Programmable controller input module.	Change the input module.
				4. Faulty printed board in the servo amplifier.	Change the amplifier.
Servo alarm	Y38	Y10	・Alarm occurred in the servo amplifier.	1. Emergency stop (EMG) of the servo amplifier was turned off.	After ensuring safety, turn EMG on.
				2. Trouble (ALM) of the servo amplifier was turned on.	Refer to chapter 9 and take action.

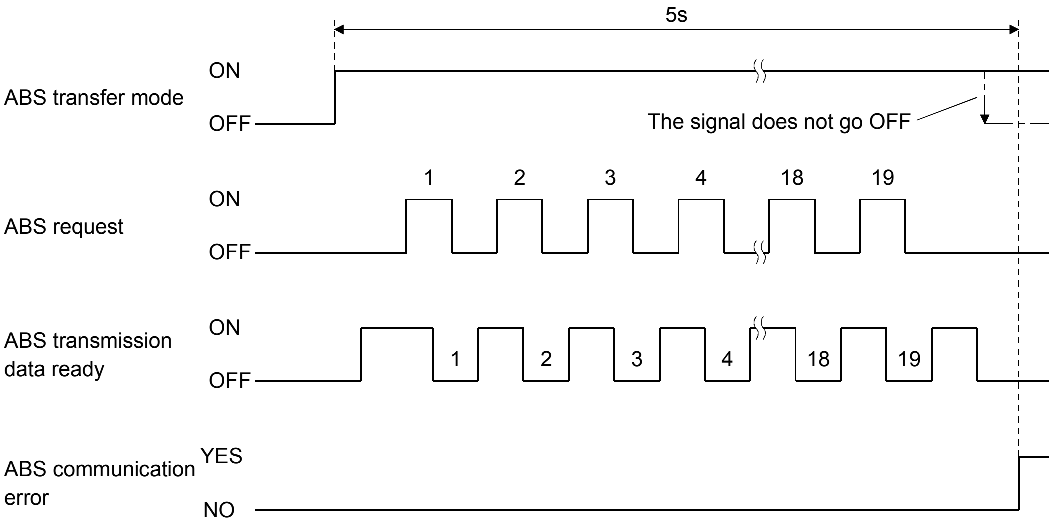
Note. Refer to (2) of this section for details of error occurrence definitions.

(2) ABS communication error

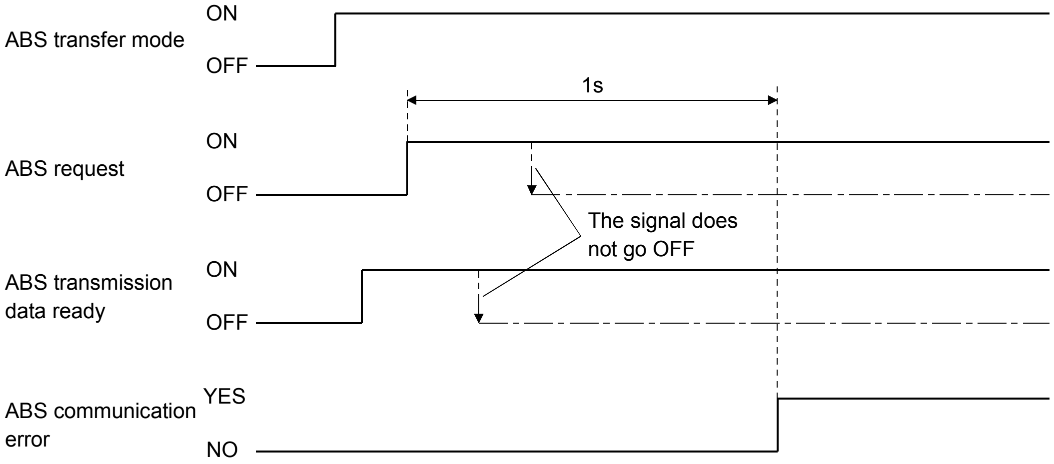
(a) The OFF period of the ABS transmission data ready signal output from the servo amplifier is checked.
If the OFF period is 1s or longer, this is regarded as a transfer fault and the ABS communication error is generated.
The ABS communication error occurs if the ABS time-out warning (AL.E5) is generated at the servo amplifier due to an ABS request ON time time-out.



(b) The time required for the ABS transfer mode signal to go OFF after it has been turned ON (ABS transfer time) is checked.
If the ABS transfer time is longer than 5s, this is communication error occurs if the ABS time-out warning (AL.E5) is generated at the servo amplifier due to an ABS transfer mode completion time time-out.



(c) To detect the ABS time-out warning (AL.E5) at the servo amplifier, the time required for the ABS request signal to go OFF after it has been turned ON (ABS request time) is checked. If the ABS request remains ON for longer than 1s, it is regarded that an fault relating to the ABS request signal or the ABS transmission data ready (ABST) has occurred, and the ABS communication error is generated.
The ABS communication error occurs if the ABS time-out warning (AL.E5) is generated at the servo amplifier due to an ABS request OFF time time-out.



14.11.2 Error resetting conditions

Always remove the cause of the error before resetting the error.

Name	Output coil		Servo status	Resetting condition
	A1SD75	1PG		
ABS communication error	Y39	Y11	Ready (RD) off	Reset when servo-on (SON) switch (X26) signal turns off.
ABS checksum error	Y3A	Y12	Ready (RD) on	For A1SD75 Reset when servo-on (SON) switch (X26) signal turns from off to on.
				For FX-1PG Reset when servo-on (SON) switch (X26) signal turns off.
Servo alarm	Y38	Y10	Ready (RD) on	Reset when alarm reset switch turns on or power switches from off to on.

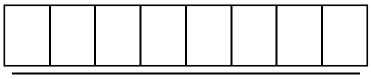
14.12 Communication-based ABS transfer system

14.12.1 Serial communication command

The following commands are available for reading absolute position data using the serial communication function. When reading data, take care to specify the correct station number of the drive unit from where the data will be read.
When the master station sends the data No. to the slave station (servo amplifier), the slave station returns the data value to the master station.

(1) Transmission
Transmit command [0][2] and data No. [9][1].

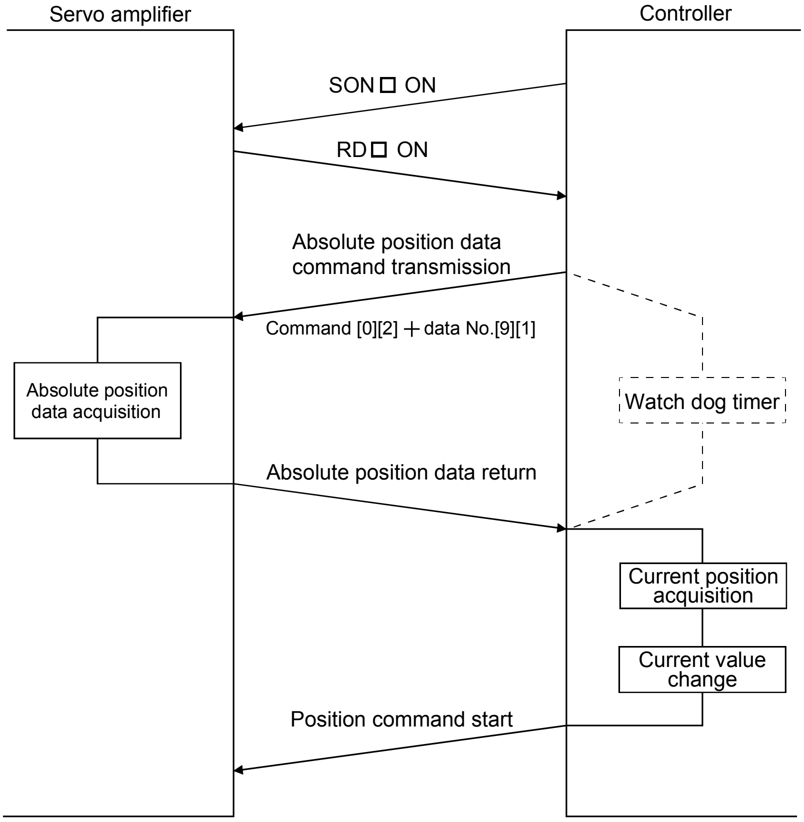
(2) Reply
The absolute position data in the command pulse unit is returned in hexadecimal.



Data 32-bit length (hexadecimal representation)

14.12.2 Absolute position data transfer protocol

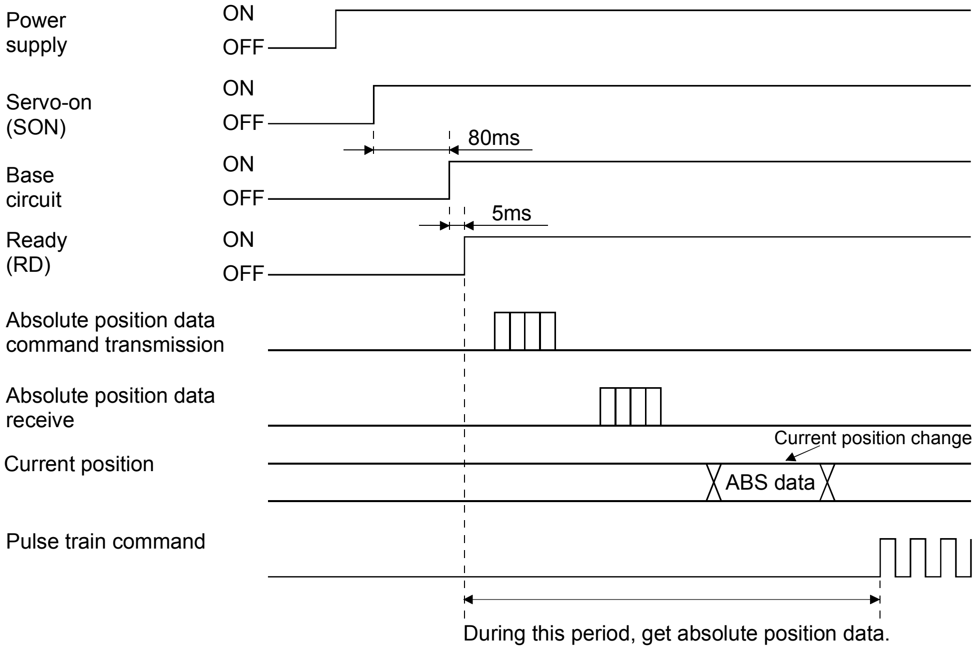
(1) Data transfer procedure
Every time the servo-on (SON) turns on at power-on or like, the controller must read the current position data in the servo amplifier. Not performing this operation will cause a position shift.
Time-out monitoring is performed by the controller.



(2) Transfer method

The sequence in which the base circuit is turned ON (servo-on) when it is in the OFF state due to the servo-on (SON) going OFF, an emergency stop, or alarm, is explained below. In the absolute position detection system, always give the serial communication command to read the current position in the servo amplifier to the controller every time the ready (RD) turns on. The servo amplifier sends the current position to the controller on receipt of the command. At the same time, this data is set as a position command value in the servo amplifier.

(a) Sequence processing at power-on



1) 95ms after the servo-on (SON) has turned on, the base circuit turns on.

2) After the base circuit has turned on, the ready (RD) turns on.

3) After the ready (RD) turned on and the controller acquired the absolute position data, give command pulses to the drive unit. Providing command pulses before the acquisition of the absolute position data can cause a position shift.

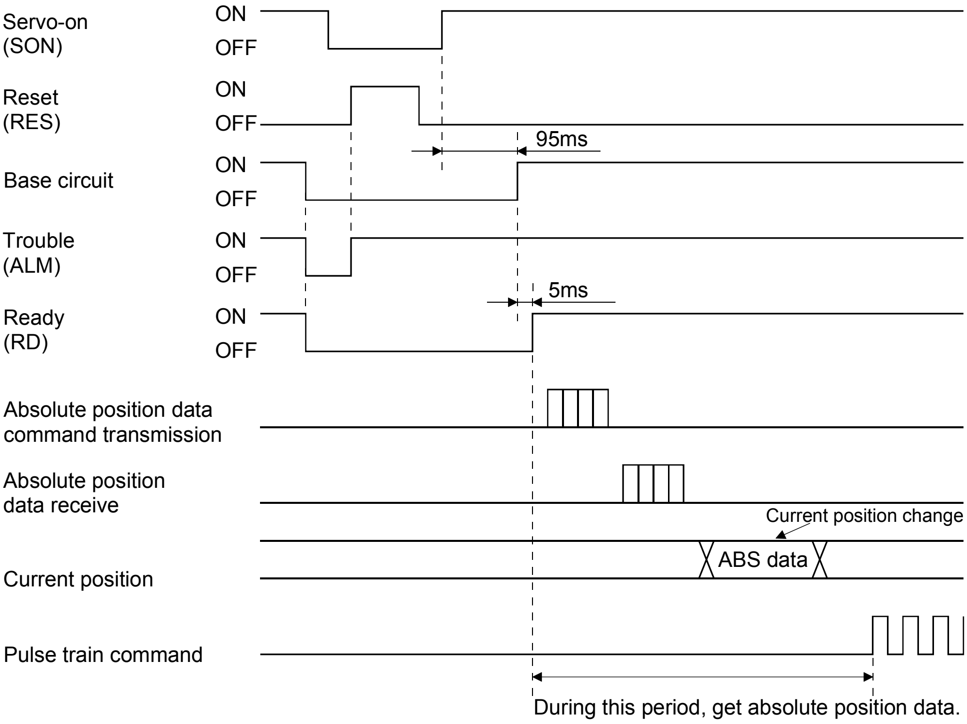
(b) Communication error

If a communication error occurs between the controller and servo amplifier, the servo amplifier sends the error code. The definition of the error code is the same as that of the communication function. Refer to section 13.3.3 for details.

If a communication error has occurred, perform retry operation. If several retries do not result in a normal termination, perform error processing.

(c) At the time of alarm reset

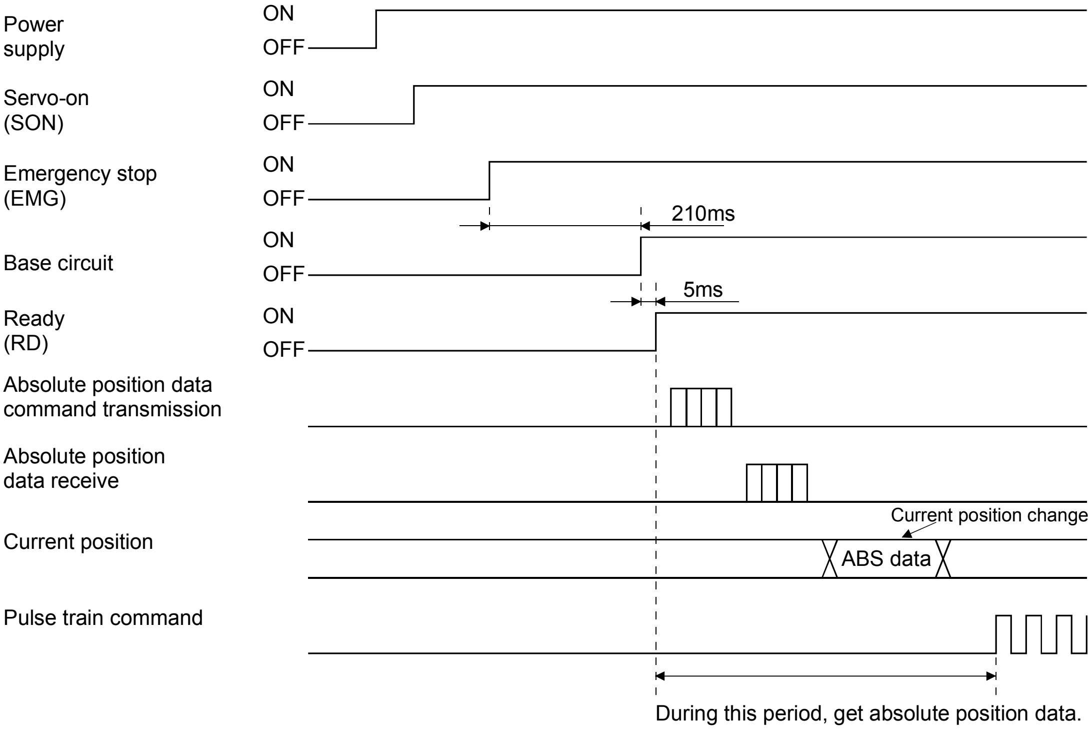
If an alarm has occurred, detect the trouble (ALM) and turn off the servo-on (SON). After removing the alarm occurrence factor and deactivating the alarm, get the absolute position data again from the servo amplifier in accordance with the procedure in (a) of this section.



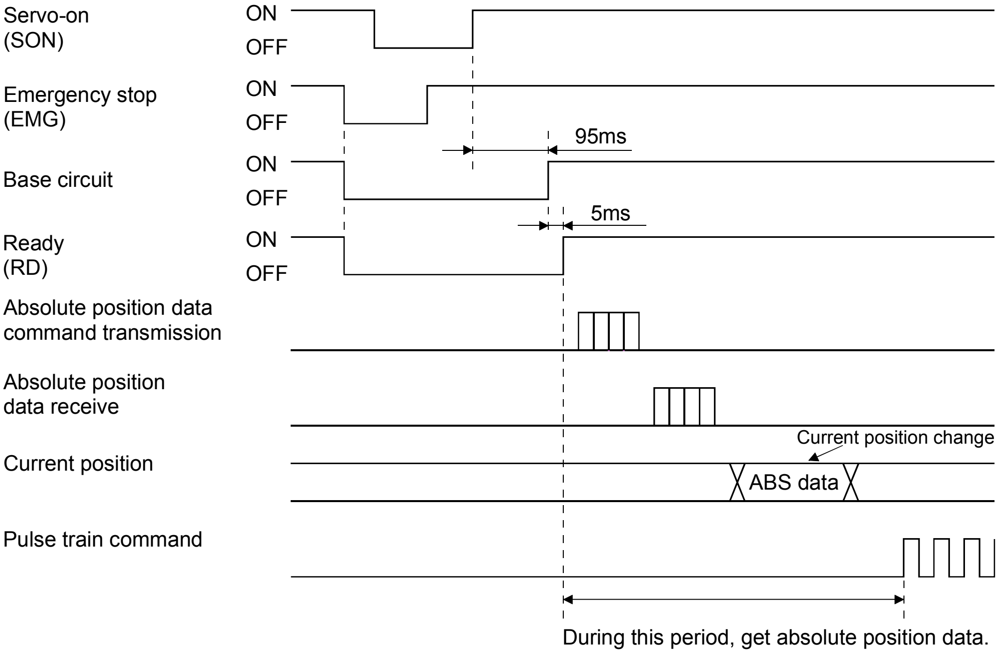
(d) At the time of forced stop reset

210ms after the forced stop is deactivated, the base circuit turns on, and further 5ms after that, the ready (RD) turns on. Always get the current position data from when the ready (RD) is triggered until before the position command is issued.

1) When power is switched on in a forced stop status



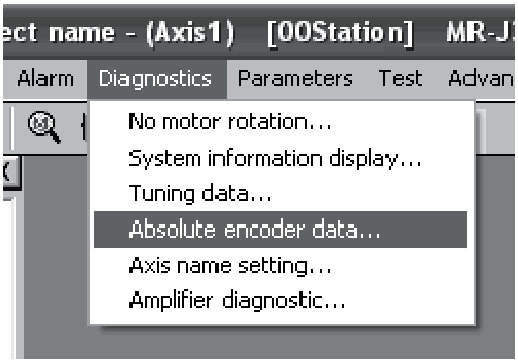
2) When a emergency stop is activated during servo on



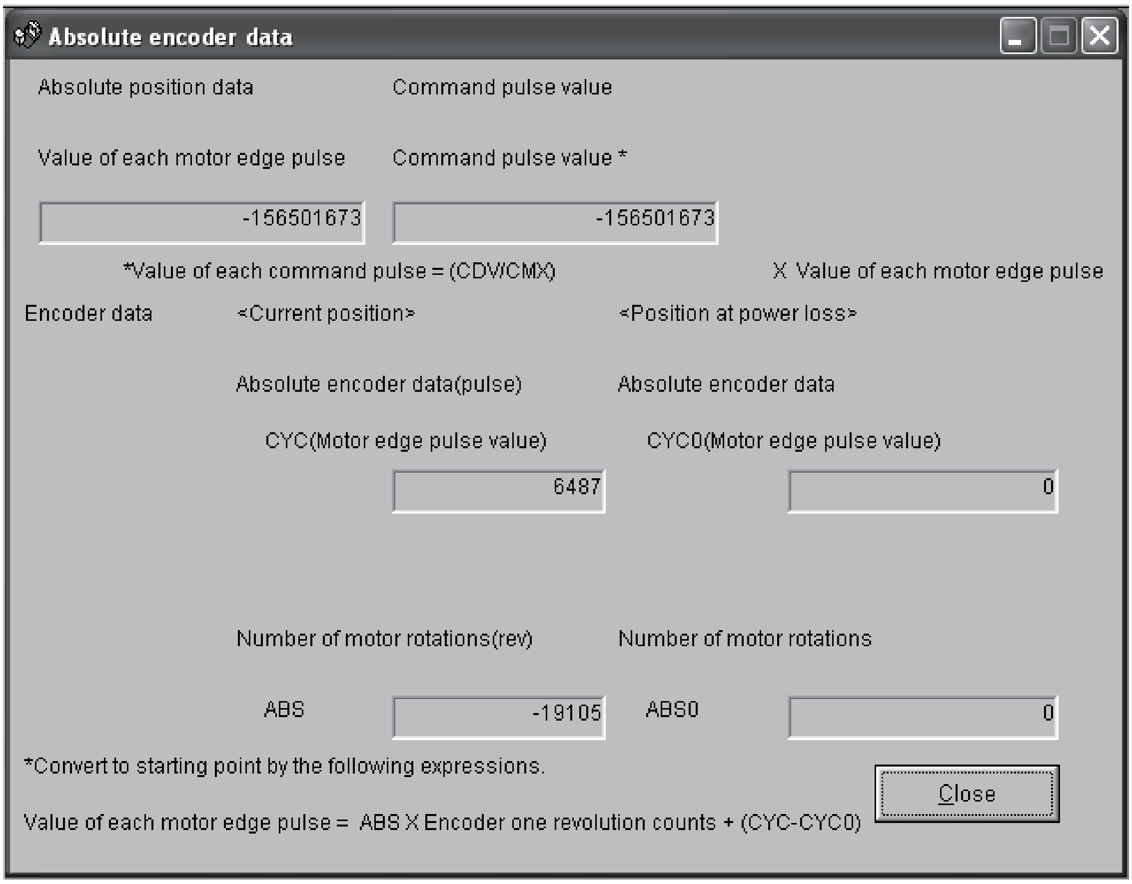
14.13 Confirmation of absolute position detection data

You can confirm the absolute position data with MR Configurator.
Choose "Diagnostics" and "Absolute Encoder Data" to open the absolute position data display screen.

(1) Choosing "Diagnostics" in the menu opens the sub-menu as shown below.



(2) By choosing "Absolute Encoder Data" in the sub-menu, the absolute encoder data display window appears.


Absolute encoder data

Absolute position data

Value of each motor edge pulse: -156501673

Command pulse value

Command pulse value *: -156501673

*Value of each command pulse = (CDV/CMX) X Value of each motor edge pulse

Encoder data

<Current position>

Absolute encoder data(pulse)

CYC(Motor edge pulse value): 6487

Number of motor rotations(rev)

ABS: -19105

<Position at power loss>

Absolute encoder data

CYC0(Motor edge pulse value): 0

Number of motor rotations

ABS0: 0

*Convert to starting point by the following expressions.

Value of each motor edge pulse = ABS X Encoder one revolution counts + (CYC-CYC0)

(3) Press the "Close" button to close the absolute encoder data display window.

15. SERVO AMPLIFIERS WITH A LARGE CAPACITY (30k TO 55kW)

This chapter explains the MELSERVO-J3-A series AC servo featuring a large capacity of 200V (30k to 37kW)/400V (30k to 55kW).
Explanation made in this chapter is exclusively for the MR-J3-CR☐(4) converter units and the MR-J3-DU☐A (4) drive units. Explanations on the following items are the same as those for servo amplifiers with 22kW or less. For such explanations, refer to the section indicated in the table.

Item	Reference
Startup	Chapter 4
Display and operation sections	Chapter 6
General gain adjustment	Chapter 7
Special adjustment functions	Chapter 8
Communication function	Chapter 13
Absolute position detection system	Chapter 14

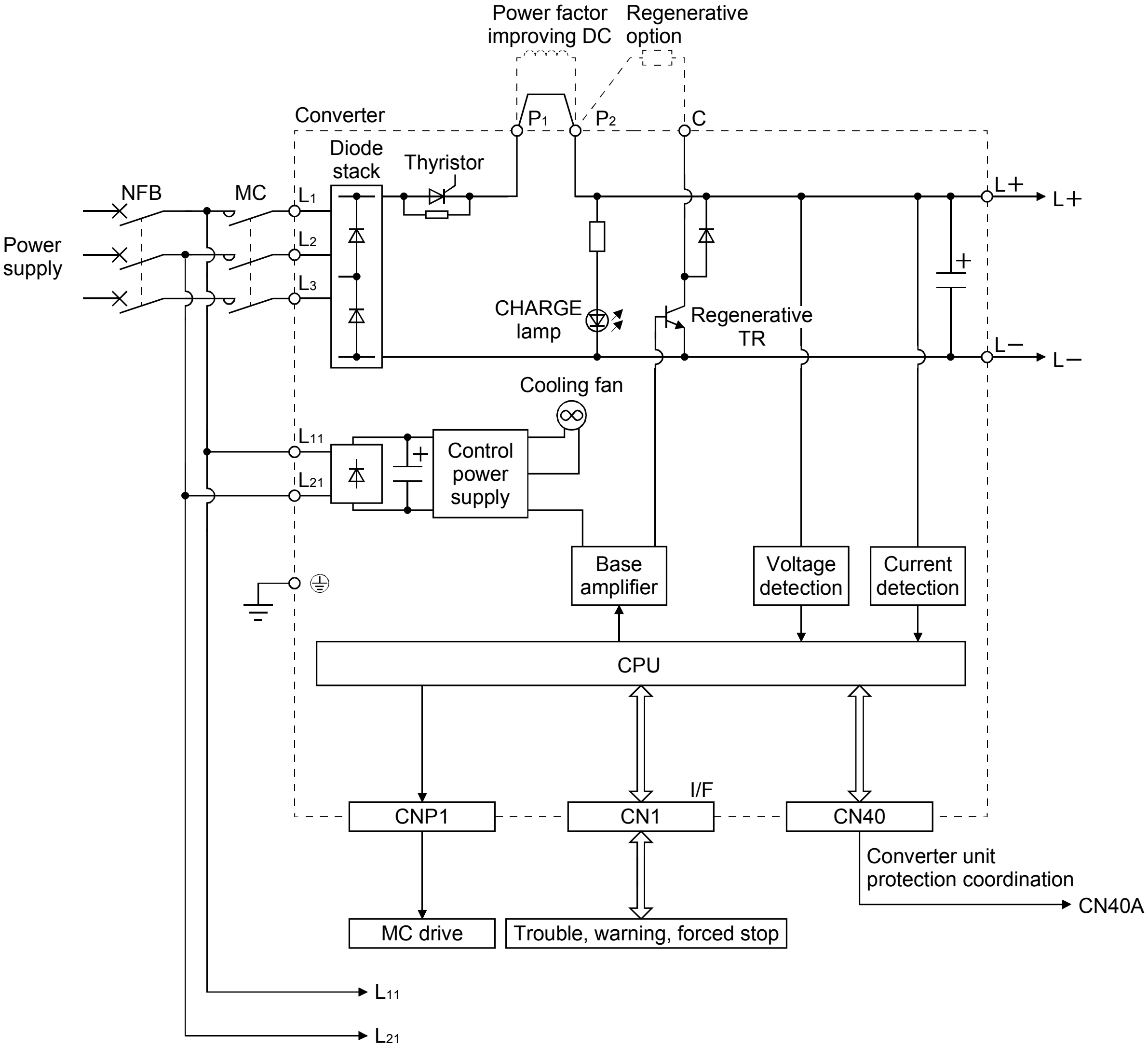
15.1. Functions and menus

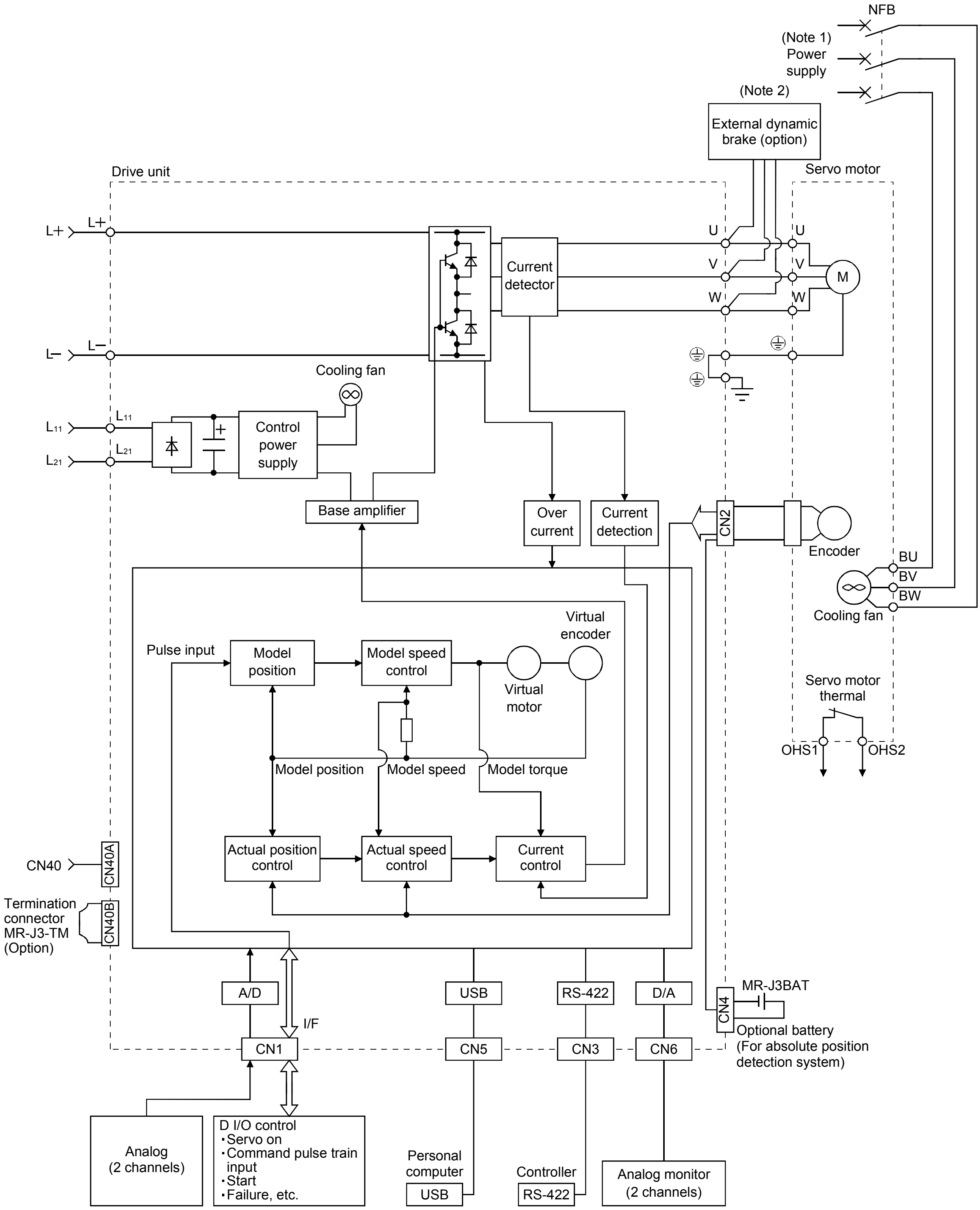
POINT

- Explanations on the following item are the same as those for servo amplifiers with 22kW or less. Refer to the section below for details.
  - Function list section 1.4

15.1.1 Function block diagram

The function block diagram of this servo is shown below.





Note 1. Refer to section 15.3.6 for the power supply specification of the servo motor cooling fan.

2. Use an external dynamic brake for the drive unit. Failure to do so will cause an accident because the servo motor does not stop immediately but coasts at an emergency stop and such conditions. Ensure the safety in the entire system.

15.1.2 Packing list

Unpack the product and check the rating plate to see if the converter unit, drive unit and servo motor are as you ordered.

(1) Converter unit

> POINT
>
> - Regenerative resistor and power factor improving DC reactors are option. Purchase them separately if required. (Refer to section 15.9.2, 15.9.6)

Model	Converter unit [units]	Eyebolt [pcs.]	Magnetic contactor wiring connector [pcs.] (Note)	Digital I/O connector [pcs.]	To Use The AC Servo Safely [manuals]
MR-J3-CR55K	1	2	1	1	1
MR-J3-CR55K4					

Note. Magnetic contactor control connector is mounted to CNP1 of the converter unit before shipping.

(2) Drive unit

Model	Drive unit [units]	Connection conductor [pcs.]	Eyebolt [pcs.]	To Use The AC Servo Safely [manuals]
MR-J3-DU30KA · MR-J3-DU37KA	1	2	2	1
MR-J3-DU30KA4 to MR-J3-DU55KA4				

(3) Servo motor

Model	Servo motor [units]	To Use The AC Servo Safely [manuals]
HA-LP30K1 · HA-LP37K1 HA-LP30K1M · HA-LP37K1M HA-LP30K2 · HA-LP37K2	1	1
HA-LP25K14 to HA-LP37K14 HA-LP30K1M4 to HA-LP50K1M4 HA-LP30K24 to HA-LP55K24		

15.1.3 Standard specifications

(1) Converter unit

Item			Converter unit	MR-J3-CR□	
				55K	55K4
Output	Rated voltage			283 to 326VDC	538 to 678VDC
	Rated current		[A]	215.9	113.8
Main circuit power supply	Voltage, frequency			3-phase 200 to 230VAC, 50/60Hz	3-phase 380 to 480VAC, 50/60Hz
	Rated current		[A]	251.1	132.2
	Permissible voltage fluctuation			3-phase 170 to 253VAC	3-phase 323 to 528VAC
	Permissible frequency fluctuation			Within±5%	
Control power supply	Voltage, frequency			1-phase 200 to 230VAC, 50/60Hz	1-phase 380 to 480VAC, 50/60Hz
	Rated current		[A]	0.3	0.2
	Permissible voltage fluctuation			1-phase 170 to 253VAC	1-phase 323 to 528VAC
	Permissible frequency fluctuation			Within±5%	
	Power consumption		[W]	45	
Interface power supply	Voltage			24VDC±10%	
	Power supply capacity		[A]	(Note) 0.13	
Rated output			[kW]	55	
Regenerative power (Using regenerative option)				One MR-RB139: 1300W Three MR-RB137: 3900W	One MR-RB136-4: 1300W Three MR-RB138-4: 3900W
Protective function				Regenerative overvoltage shutoff, overload shutoff (electronic thermal protector) Regenerative error protection, undervoltage, instantaneous power failure protection	
Compliance to standards				CE (LVD: IEC/EN 50178, EMC: IEC/EN 61800-3) UL (UL 508C)	
Structure				Force-cooling, open (IP rating: IP00)	
Environmental conditions	Ambient temperature	In operation	[℃]	0 to 55 (non-freezing)	
			[°F]	32 to 131 (non-freezing)	
		In storage	[℃]	−20 to 65 (non-freezing)	
			[°F]	−4 to 149 (non-freezing)	
	Ambient humidity	In operation		90%RH or less (non-condensing)	
		In storage			
	Ambient			Indoors (no direct sunlight) Free from corrosive gas, flammable gas, oil mist, dust and dirt	
	Altitude			Max. 1000m above sea level	
	Vibration			5.9 [m/s^2] or less at 10 to 55Hz (directions of X, Y and Z axes)	
Mass			[kg]	25	
			[lb]	55.1	

Note. 0.13A is the value applicable when all I/O signals are used. The current capacity can be decreased by reducing the number of I/O points.

(2) Drive unit

(a) 200V class

Drive unit Item				MR-J3-DU☐	
				30KA	37KA
Output	Rated voltage			3-phase 170VAC	
	Rated current		[A]	174	204
Control power supply	Voltage, frequency			1-phase 200 to 230VAC, 50/60Hz	
	Rated current		[A]	0.3	
	Permissible voltage fluctuation			1-phase 170 to 253VAC	
	Permissible frequency fluctuation			Within±5%	
	Power consumption		[W]	45	
Main circuit power supply				The main circuit power of the drive unit is supplied by the converter unit.	
Interface power supply	Voltage			24VDC±10%	
	Power supply capacity		[A]	(Note 1) 0.3	
Control system				Sine-wave PWM control, current control system	
Dynamic brake				External option (Note 2)	
Protective function				Overcurrent shut-off, overload shutoff (electronic thermal protector) Servo motor overheat protection, encoder error protection, undervoltage Instantaneous power failure protection, overspeed protection Excessive error protection	
Position control mode	Max. input pulse frequency			1Mpps (for differential receiver), 200kpps (for open collector)	
	Command pulse multiplying factor			Electronic gear A: 1 to 1048576, B: 1 to 1048576, 1/10 < A/B < 2000	
	In-position range setting			0 to ±10000 pulse (command pulse unit)	
	Error excessive			±3 revolutions	
	Torque limit			Set by parameter setting or external analog input (0 to +10VDC/maximum torque)	
Speed control mode	Speed control range			Analog speed command 1: 2000, internal speed command 1: 5000	
	Analog speed command input			0 to ±10VDC / Rated speed	
	Speed fluctuation ratio			±0.01% or less (load fluctuation 0 to 100%) 0% or less (power fluctuation ±10%) ±0.2% max.(ambient temperature 25±10°C) for external speed setting only	
	Torque limit			Set by parameter setting or external analog input (0 to +10VDC/maximum torque)	
Torque control mode	Analog torque command input			0 to ±8VDC / Maximum torque (input impedance 10 to 12kΩ)	
	Speed limit			Set by parameter setting or external analog input (0 to ±10VDC/Rated speed)	
Compliance to standards				CE (LVD: IEC/EN 50178, EMC: IEC/EN 61800-3) UL (UL 508C)	
Structure				Force-cooling, open (IP rating: IP00)	
Environmental conditions	Ambient temperature	In operation	[℃]	0 to 55 (non-freezing)	
			[°F]	32 to 131 (non-freezing)	
		In storage	[℃]	−20 to 65 (non-freezing)	
			[°F]	−4 to 149 (non-freezing)	
	Ambient humidity	In operation		90%RH or less (non-condensing)	
		In storage			
	Ambient			Indoors (no direct sunlight) Free from corrosive gas, flammable gas, oil mist, dust and dirt	
	Altitude			Max. 1000m above sea level	
	Vibration			5.9 [m/s^2] or less at 10 to 55Hz (directions of X, Y and Z axes)	
Mass			[kg]	26	
			[lb]	57.3	

Note 1. 0.3A is the value applicable when all I/O signals are used. The current capacity can be decreased by reducing the number of I/O points.

2. Use an external dynamic brake for the drive unit. Failure to do so will cause an accident because the servo motor does not stop immediately but coasts at an emergency stop and such conditions. Ensure the safety in the entire system.

(b) 400V class

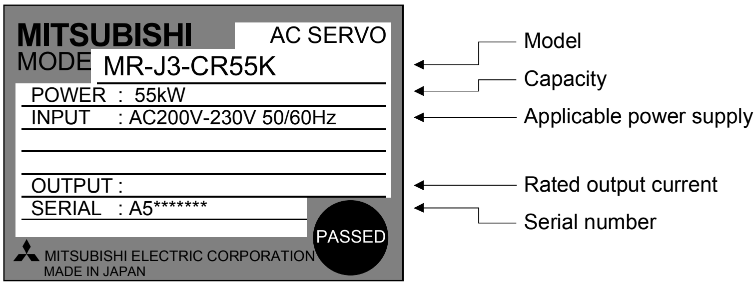
Item			Drive unit	MR-J3-DU□4			
				30KA	37KA	45KA	55KA
Output	Rated voltage			3-phase 323VAC			
	Rated current [A]			87	102	131	143
Control power supply	Voltage, frequency			1-phase 380 to 480VAC, 50/60Hz			
	Rated current [A]			0.2			
	Permissible voltage fluctuation			1-phase 323 to 528VAC			
	Permissible frequency fluctuation			Within±5%			
	Power consumption [W]			45			
Main circuit power supply				The main circuit power of the drive unit is supplied by the converter unit.			
Interface power supply	Voltage			24VDC±10%			
	Power supply capacity [A]			(Note 1) 0.3			
Control system				Sine-wave PWM control, current control system			
Dynamic brake				External option (Note 2)			
Protective function				Overcurrent shut-off, overload shutoff (electronic thermal protector) Servo motor overheat protection, encoder error protection, undervoltage Instantaneous power failure protection, overspeed protection Excessive error protection			
Position control mode	Max. input pulse frequency			1Mpps (for differential receiver), 200kpps (for open collector)			
	Command pulse multiplying factor			Electronic gear A: 1 to 1048576, B: 1 to 1048576, 1/10 < A/B < 2000			
	In-position range setting			0 to ±10000 pulse (command pulse unit)			
	Error excessive			±3 revolutions			
	Torque limit			Set by parameter setting or external analog input (0 to +10VDC/maximum torque)			
Speed control mode	Speed control range			Analog speed command 1: 2000, internal speed command 1: 5000			
	Analog speed command input			0 to ±10VDC / Rated speed			
	Speed fluctuation ratio			±0.01% or less (load fluctuation 0 to 100%) 0% or less (power fluctuation ±10%) ±0.2% max.(ambient temperature 25±10°C) for external speed setting only			
	Torque limit			Set by parameter setting or external analog input (0 to＋10VDC/maximum torque)			
Torque control mode	Analog torque command input			0 to ±8VDC / Maximum torque (input impedance 10 to 12kΩ)			
	Speed limit			Set by parameter setting or external analog input (0 to ±10VDC/Rated speed)			
Compliance to standards				CE (LVD: IEC/EN 50178, EMC: IEC/EN 61800-3) UL (UL 508C)			
Structure				Force-cooling, open(IP rating: IP00)			
Environmental conditions	Ambient temperature	In operation	[℃]	0 to 55 (non-freezing)			
			[°F]	32 to 131 (non-freezing)			
		In storage	[℃]	－20 to 65 (non-freezing)			
			[°F]	－4 to 149 (non-freezing)			
	Ambient humidity	In operation		90%RH or less (non-condensing)			
		In storage					
	Ambient			Indoors (no direct sunlight) Free from corrosive gas, flammable gas, oil mist, dust and dirt			
	Altitude			Max. 1000m above sea level			
	Vibration			5.9 [m/s^2] or less at 10 to 55Hz (directions of X, Y and Z axes)			
Mass			[kg]	18		26	
			[lb]	39.7		57.3	

Note 1. 0.3A is the value applicable when all I/O signals are used. The current capacity can be decreased by reducing the number of I/O points.

2. Use an external dynamic brake for the drive unit. Failure to do so will cause an accident because the servo motor does not stop immediately but coasts at an emergency stop and such conditions. Ensure the safety in the entire system.

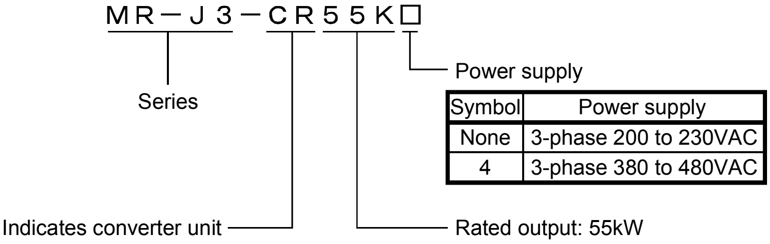
15.1.4 Model definition

(1) Rating plate



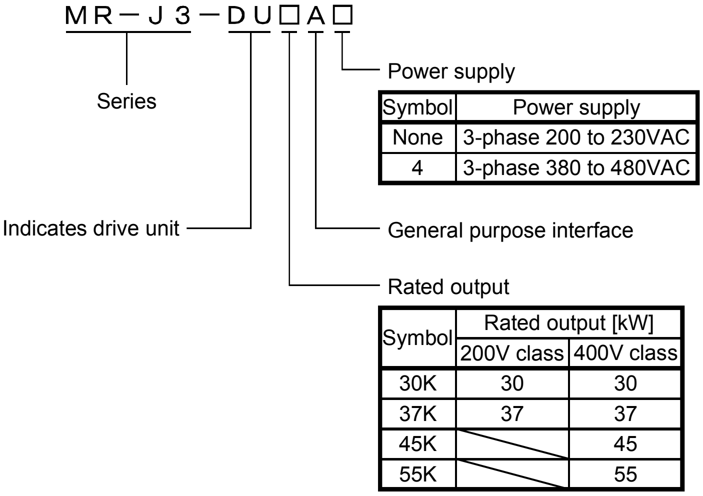
(2) Model

(a) Converter unit



Symbol	Power supply
None	3-phase 200 to 230VAC
4	3-phase 380 to 480VAC

(b) Drive unit



Symbol	Power supply
None	3-phase 200 to 230VAC
4	3-phase 380 to 480VAC

Symbol	Rated output [kW]	
	200V class	400V class
30K	30	30
37K	37	37
45K		45
55K		55

15.1.5 Combinations of converter units, drive unit and servo motors

The following tables indicate the combinations of the converter units, drive unit and servo motors.

(1) 200V class

Converter unit	Drive unit	Servo motor		
		HA-LP☐		
		1000r/min	1500r/min	2000r/min
MR-J3-CR55K	MR-J3-DU30KA	30K1	30K1M	30K2
	MR-J3-DU37KA	37K1	37K1M	37K2

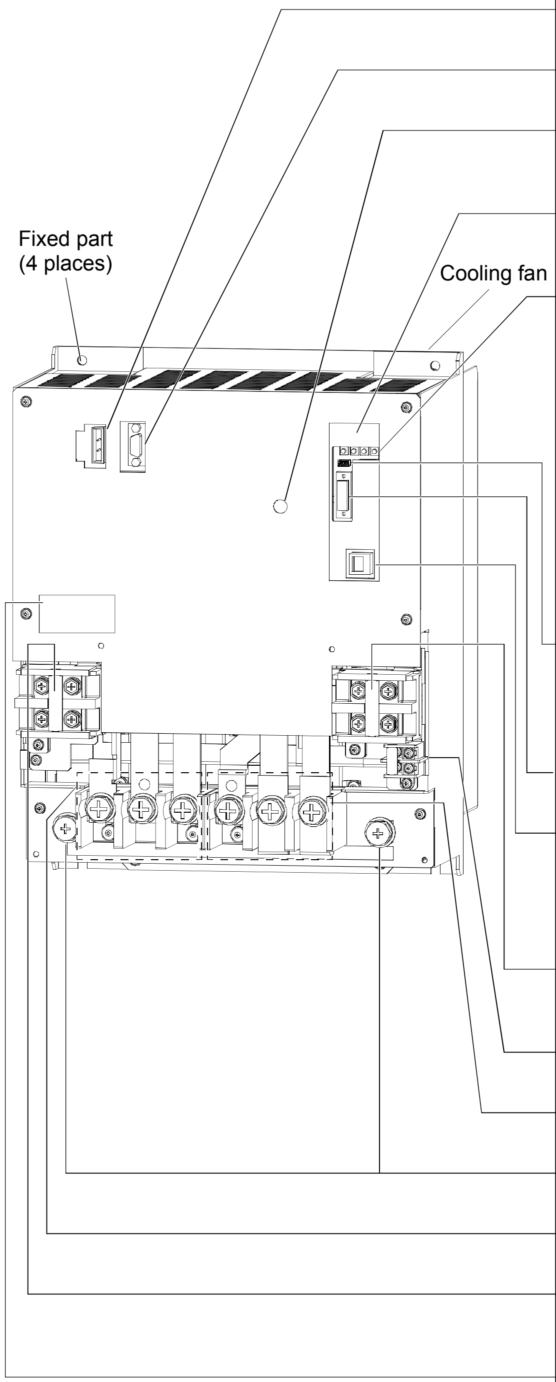
(2) 400V class

Converter unit	Drive unit	Servo motor		
		HA-LP☐		
		1000r/min	1500r/min	2000r/min
MR-J3-CR55K4	MR-J3-DU30KA4	25K14 30K14	30K1M4	30K24
	MR-J3-DU37KA4	37K14	37K1M4	37K24
	MR-J3-DU45KA4		45K1M4	45K24
	MR-J3-DU55KA4		50K1M4	55K24

15.1.6 Parts identification

(1) Converter unit (MR-J3-CR55K(4))

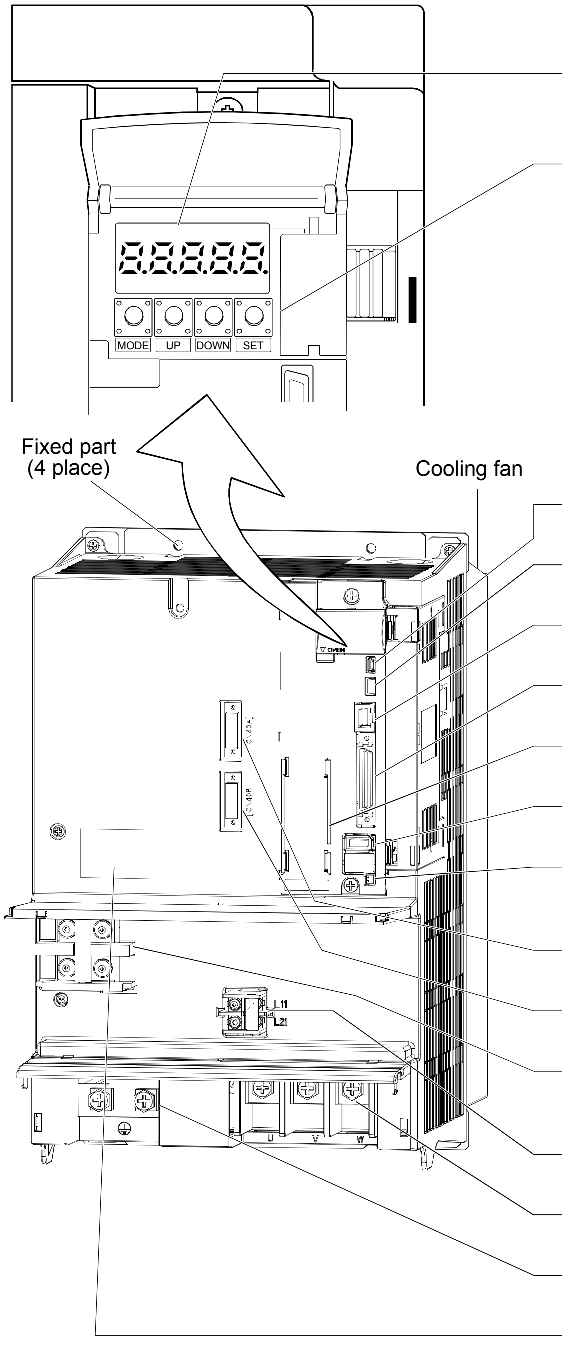
POINT
・The servo amplifier is shown with the terminal block cover removed. For removal of the front cover, refer to section 15.1.7.



Name/Application	Detailed explanation
Magnetic contactor control connector (CNP1) Connect to the operation coil of the magnetic contactor.	Section 15.3.1 Section 15.3.5
I/O signal connector (CN1) Used to connect digital I/O signals.	Section 15.3.5
Charge lamp Lit to indicate that the main circuit is charged. While this lamp is lit, do not reconnect the cables.	
Display The 3-digit, seven-segment LED shows the servo status and alarm number.	Section 15.4
Operation section Used to perform status display, diagnostic, alarm, parameter setting operations. ● MODE ● UP ● DOWN ● SET Used to set data. Used to change the display or data in each mode. Used to change the mode.	
For manufacturer setting connector (CN6) The connector is for manufacturer setting. Although the shape is similar to analog monitor connector (CN6) of the drive unit, do not connect anything including an analog monitor.	
Protection coordination connector (CN40) Connect to CN40A of the drive unit.	
For manufacturer setting connector (CN3) For manufacturer adjustment. Though the shape is similar to RS-422 communication connector (CN3), do not connect anything, including a personal computer and MR-PRU03 parameter unit.	
L＋ L－terminal (TE2-2) Used to connect to a drive unit using a connection conductor supplied with drive unit.	Section 15.3.3
Control circuit terminal L_{11}・L_{21}(TE3) Supply control circuit power.	
Regenerative option・Power factor improving DC reactor (TE1-2)	
Protective earth (PE) terminal (⏚) Ground terminal.	
Main circuit terminal block (TE1-1) Supply main circuit power.	
L＋L－terminal (TE2-1) When using brake unit, connect it to this terminal. Do not connect anything other than the brake unit.	Section 15.9.10
Rating plate	Section 15.1.4

(2) Drive unit (MR-J3-DU30KA4・MR-J3-DU37KA4)

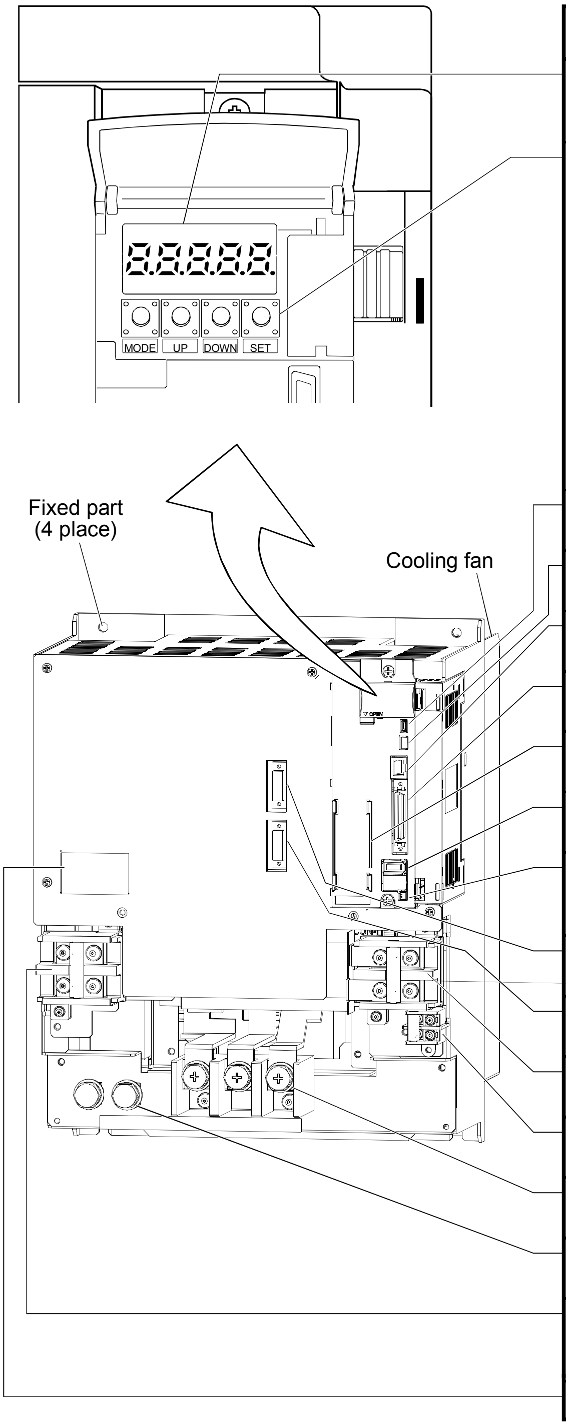
> POINT
>
> - The servo amplifier is shown with the terminal block cover removed. For removal of the front cover, refer to section 15.1.7.



Name/Application	Detailed explanation
Display The 5-digit, seven-segment LED shows the servo status and alarm number.	Chapter 6
Operation section Used to perform status display, diagnostic, alarm and parameter setting operations. ⊙ MODE ⊙ UP ⊙ DOWN ⊙ SET Used to set data. Used to change the display or data in each mode. Used to change the mode.	
USB communication connector (CN5) Connect the personal computer.	Section 12.8
Analog monitor connector (CN6) Outputs the analog monitor.	Section 3.2 Section 3.4
RS-422 communication connector (CN3) Connect the personal computer.	Section 12.8 Chapter 13
I/O signal connector (CN1) Used to connect digital I/O signals.	Section 3.2 Section 3.4
Battery holder Contains the battery for absolute position data backup.	Section 14.3
Encoder connector (CN2) Used to connect the servo motor encoder.	Section 3.4 Section 12.1
Battery connector (CN4) Used to connect the battery for absolute position data backup.	Section 12.9 Chapter 14
Converter unit connectors (CN40A) Connect to CN40 of the converter unit.	Section 15.3.2
Converter unit connectors (CN40B) Connect the termination connector (MR-J3-TM).	
L＋L－ terminals (TE2) Connect to the L＋L－ terminals of the converter unit using the connection conductors supplied.	Section 15.3.3
Control circuit terminal L_{11}・L_{21} (TE3) Supply control circuit power.	
Motor power supply terminals (TE1) Connect to U, V, W of the servo motor.	
Protective earth (PE) terminal (⏚) Ground terminal.	
Rating plate	Section 15.1.4

(3) Drive unit (MR-J3-DU30KA · MR-J3-DU37KA · MR-J3-DU45KA4 · MR-J3-DU55KA4)

> POINT
>
> - The servo amplifier is shown with the terminal block cover removed. For removal of the front cover, refer to section 15.1.7.



Name/Application	Detailed explanation
Display The 5-digit, seven-segment LED shows the servo status and alarm number.	Chapter 6
Operation section Used to perform status display, diagnostic, alarm and parameter setting operations. ⊙ MODE ⊙ UP ⊙ DOWN ⊙ SET Used to set data. Used to change the display or data in each mode. Used to change the mode.	
USB communication connector (CN5) Connect the personal computer.	Section 12.8
Analog monitor connector (CN6) Outputs the analog monitor.	Section 3.2 Section 3.4
RS-422 communication connector (CN3) Connect the personal computer.	Section 12.8 Chapter 13
I/O signal connector (CN1) Used to connect digital I/O signals.	Section 3.2 Section 3.4
Battery holder Contains the battery for absolute position data backup.	Section 14.3
Encoder connector (CN2) Used to connect the servo motor encoder.	Section 3.4 Section 12.1
Battery connector (CN4) Used to connect the battery for absolute position data backup.	Section 12.9 Chapter 14
Converter unit connectors (CN40A) Connect to CN40 of the converter unit.	Section 15.3.2
Converter unit connectors (CN40B) Connect the termination connector (MR-J3-TM).	
TE2-2 For manufacturer adjustment. Leave this open.	
Control circuit terminal L_{11} · L_{21} (TE3) Supply control circuit power.	Section 15.3.3
Motor power supply terminals (TE1) Connect to U, V, W of the servo motor.	
Protective earth (PE) terminal (⏚) Ground terminal.	
L＋L－ terminals (TE2) Connect to the L＋L－ terminals of the converter unit using the connection conductors supplied.	
Rating plate	Section 15.1.4

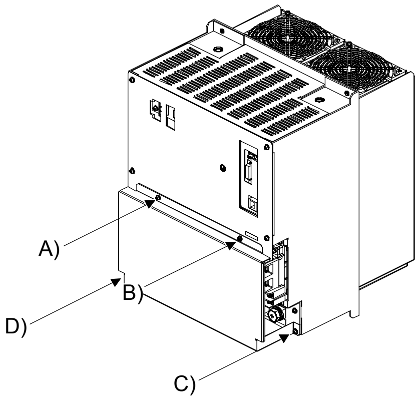
15.1.7 Removal and reinstallation of the terminal block cover

⚠ CAUTION	· Before removing or installing the front cover, turn off the power and wait for 20 minutes or longer until the charge lamp turns off. Then, confirm that the voltage between L+ and L− is safe with a voltage tester and others. Otherwise, an electric shock may occur. In addition, make sure to confirm from the front of the servo amplifier whether the charge lamp is off or not.

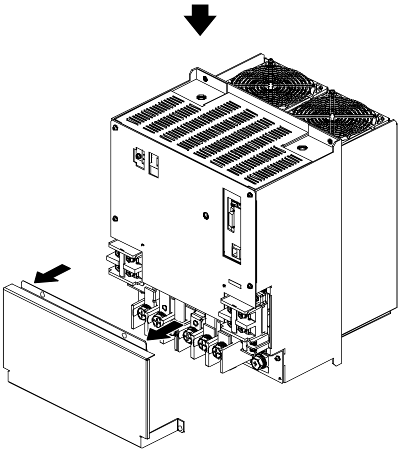
(1) MR-J3-CR55K(4), MR-J3-DU30KA, MR-J3-DU37KA, MR-J3-DU45KA4 or MR-J3-DU55KA4

Here, the method for removing and reinstalling the terminal block cover using the figure of converter unit as an example. For a drive unit, the shape of the main unit is different. However, the removal and reinstallation of the terminal block can be performed in the same procedure.

(a) How to remove the terminal block cover



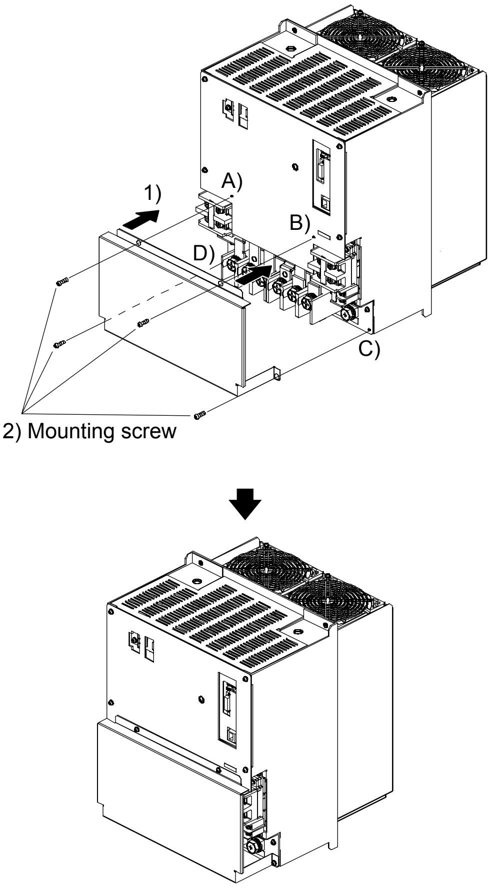
Remove the installation screws (A), B), C), D)) on the four corners of the terminal block cover.



Pull the terminal block cover toward you and remove it.

(b) How to reinstall the terminal block cover

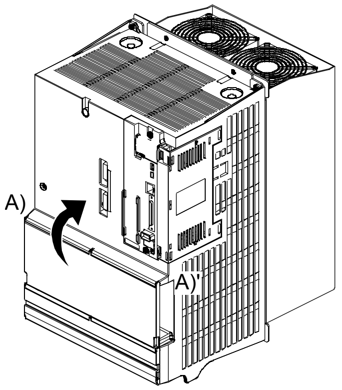
1) Put the terminal block cover on and match the screw holes of the cover fit with those of the main unit.
2) Install the installing screws into the screw holes (A), B), C), D)).



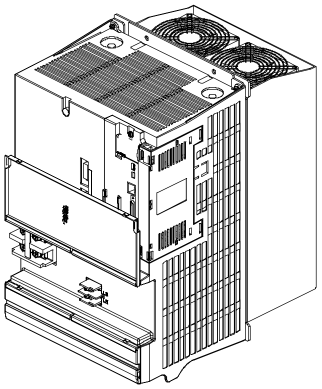
(2) MR-J3-DU30KA4 or MR-J3-DU37KA4

(a) Upper terminal block cover

1) How to open

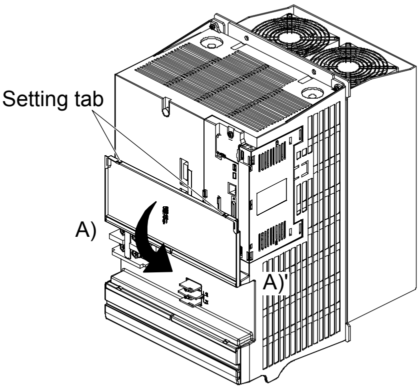


Pull up the cover using the axis A), A)' as a support.

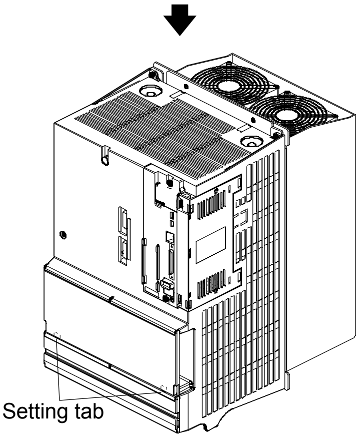


When pulled up to the top, the cover is fixed.

2) How to close



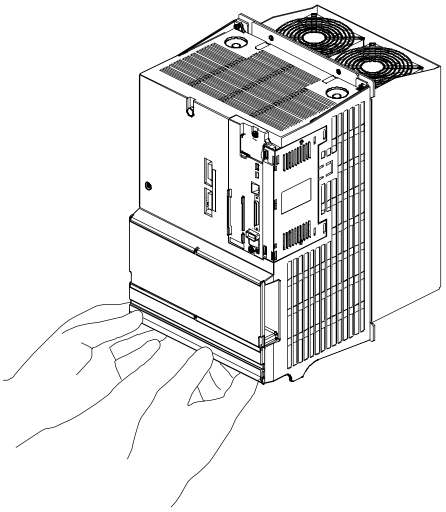
Close the cover using the axis A), A)' as a support.



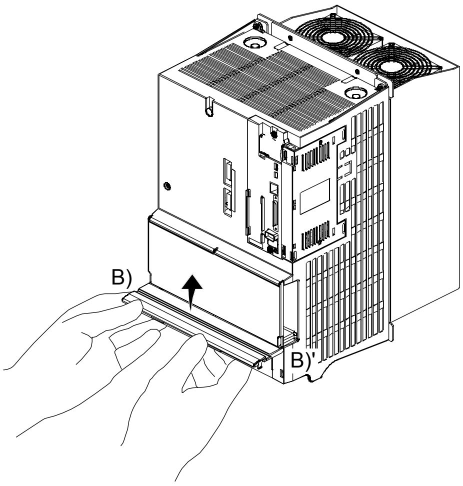
Press the cover against the terminal box until the installing knobs click.

(b) Lower terminal block cover

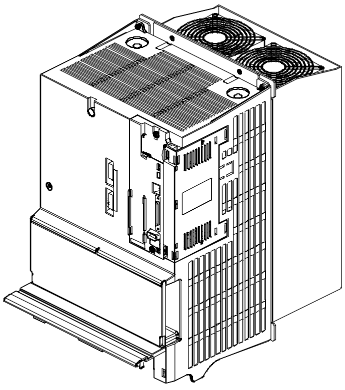
1) How to open



Hold the bottom of the terminal block cover with both hands.

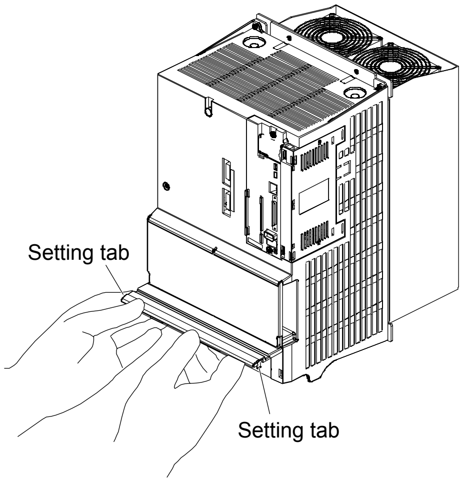


Pull up the cover using the axis B), B)' as a support.

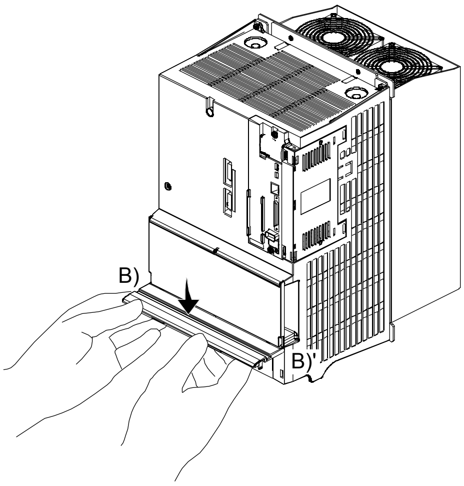


When pulled up to the top, the cover is fixed.

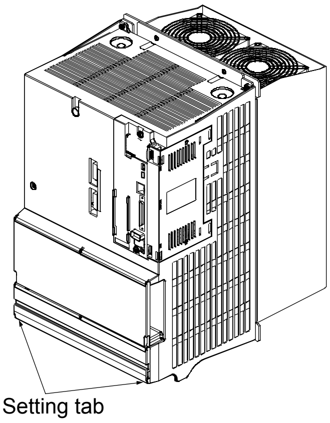
2) How to close



Hold the bottom of the terminal block cover with both hands.

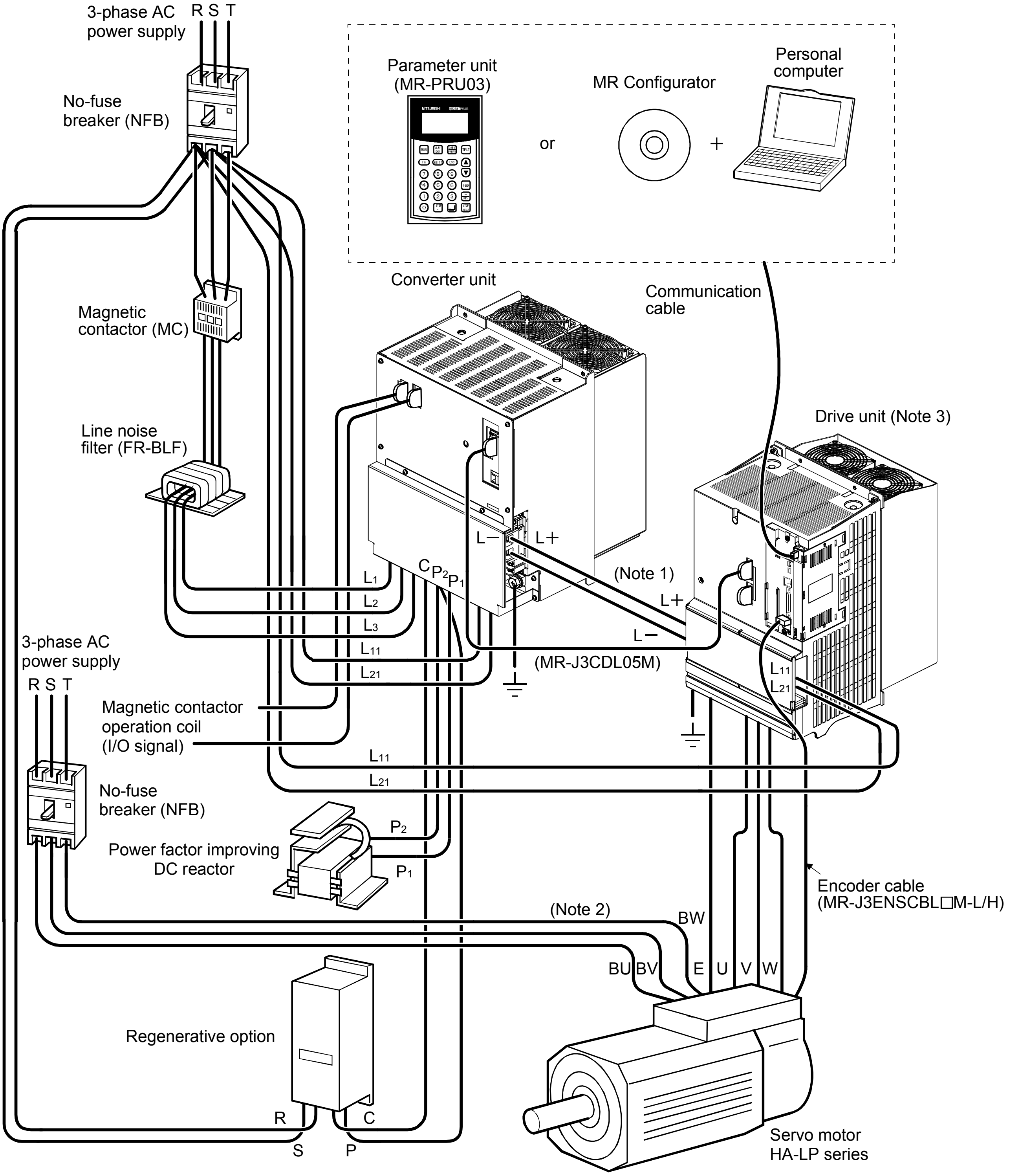


Close the cover using the axis B), B)' as a support.



Press the cover against the terminal box until the installing knobs click.

15.1.8 Servo system with auxiliary equipment



Note 1. The L+ and L− connection conductors used to connect a converter unit to a drive unit are standard accessories. The converter unit is attached to the drive unit actually. (Refer to section 15.2.1.)

2. The power supply of the servo motor cooling fan differs depending on the capacity of a servo motor. Refer to section 15.3.6.

3. For MR-J3-DU30KA4 or MR-J3-DU37KA4.

15.2 Installation

⚠WARNING	・To prevent electric shock, ground each equipment securely.

⚠CAUTION	・Stacking in excess of the limited number of products is not allowed. ・Install the equipment to incombustibles. Installing them directly or close to combustibles will led to a fire. ・Install the equipment in a load-bearing place in accordance with this Instruction Manual. ・Do not get on or put heavy load on the equipment to prevent injury. ・Use the equipment within the specified environmental condition range. (For the environmental conditions, refer to section 15.1.3.) ・Provide an adequate protection to prevent screws, metallic detritus and other conductive matter or oil and other combustible matter from entering the converter unit・drive unit. ・Do not block intake and exhaust areas of the converter unit and drive unit. Doing so may cause faults. ・Do not subject the converter unit・drive unit to drop impact or shock loads as they are precision equipment. ・Do not install or operate a faulty converter unit・drive unit. ・When the product has been stored for an extended period of time, contact your local sales office. ・When treating the converter unit・drive unit, be careful about the edged parts such as the corners of the converter unit・drive unit. ・The converter unit・drive unit must be installed in the metal cabinet (control box).

POINT

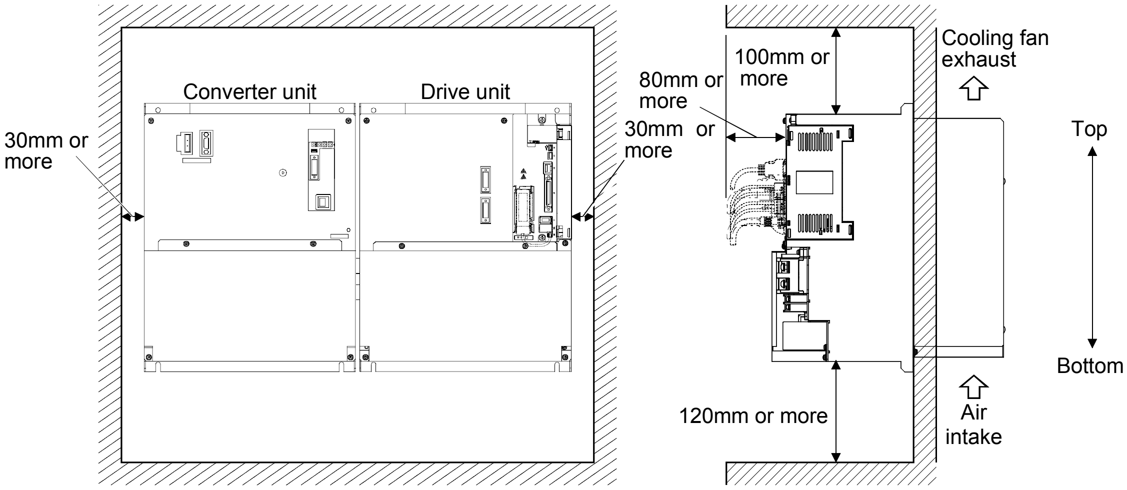
- Explanations on the following item are the same as those for servo amplifiers with 22kW or less. Refer to the section below for details.
  - Keep out foreign materials Refer to section 2.2.
  - Cable stress Refer to section 2.3.
  - Parts Having Service Lives Refer to section 2.6.

15.2.1 Installation direction and clearances

> ⚠ CAUTION
>
> - Install the equipment in the specified direction. Not doing so can cause a failure.
> - Leave the specified clearances between the converter unit/drive unit and the control box inside walls or other equipment. Not doing so can cause a failure.

(1) Installation

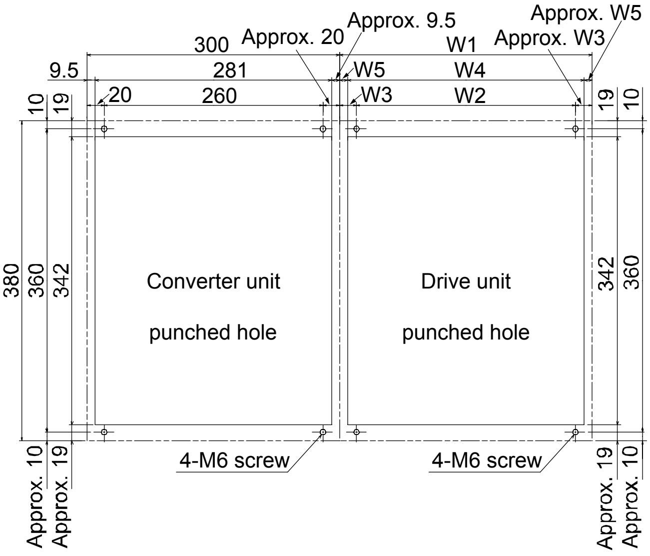
> **POINT**
>
> - Make sure to connect a drive unit to the right side of a converter unit as shown in the diagram.



Front view

Side view

(2) Mounting dimensional diagram



[Unit: mm]

Drive unit model	Dimensions					
	W1	W2	W3	W4	W5	A
MR-J3-DU30KA, 37KA, 45KA4, 55KA4	300	260	20	281	9.5	M6
MR-J3-DU30KA4, 37KA4	240	120	60	222	9	M5

(3) Others

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

Install the converter unit and drive unit on a perpendicular wall in the correct vertical direction.

15.2.2 Inspection

⚠WARNING	･Before starting maintenance and/or inspection, turn off the power and wait for 20 minutes or longer until the charge lamp turns off. Then, confirm that the voltage between L＋ and L－ is safe with a voltage tester and others. Otherwise, an electric shock may occur. In addition, always confirm from the front of the converter unit whether the charge lamp is off or not.

⚠CAUTION	･Any person who is involved in inspection should be fully competent to do the work. Otherwise, you may get an electric shock. For repair and parts replacement, contact your safes representative.

POINT

･Do not test the converter unit･drive unit with a megger (measure insulation resistance), or it may become faulty.

It is recommended to make the following checks periodically.

(1) Check for loose terminal block screws. Retighten any loose screws.

(2) Check the servo motor bearings, brake section, etc. for unusual noise.

(3) Check the cables and the like for scratches and cracks. Perform periodic inspection according to operating conditions.

(4) Check the servo motor shaft and coupling for misalignment.

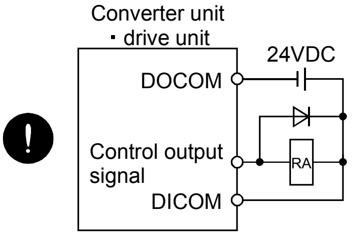
15.3 Signals and wiring

⚠ WARNING

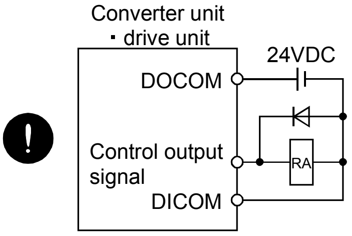
- Any person who is involved in wiring should be fully competent to do the work.
- Before wiring, turn off the power and wait for 20 minutes or longer until the charge lamp turns off. Then, confirm that the voltage between L＋ and L－ is safe with a voltage tester and others. Otherwise, an electric shock may occur. In addition, always confirm from the front of the converter unit whether the charge lamp is off or not.
- Ground the converter unit・drive unit and the servo motor securely.
- Do not attempt to wire the converter unit・drive unit and servo motor until they have been installed. Otherwise, you may get an electric shock.
- The cables should not be damaged, stressed excessively, loaded heavily, or pinched. Otherwise, you may get an electric shock.

⚠ CAUTION

- Wire the equipment correctly and securely. Otherwise, the servo motor may operate unexpected resulting in injury.
- Connect cables to correct terminals to prevent a burst, fault, etc.
- Ensure that polarity (＋, －) is correct. Otherwise, a burst, damage, etc. may occur.
- The surge absorbing diode installed to the DC relay for control output should be fitted in the specified direction.
  Otherwise, the emergency stop and other protective circuits may not operate.



For sink output interface



For source output interface

- Use a noise filter, etc. to minimize the influence of electromagnetic interference, which may be given to electronic equipment used near the converter unit・drive unit.
- Do not install a power capacitor, surge killer or radio noise filter (FR-BIF-(H) option) with the power line of the servo motor.
- When using the regenerative resistor, switch power off with the alarm signal. Otherwise, a transistor fault or the like may overheat the regenerative resistor, causing a fire.
- Do not modify the equipment.
- During power-on, do not open or close the motor power line. Otherwise, a malfunction or faulty may occur.

POINT

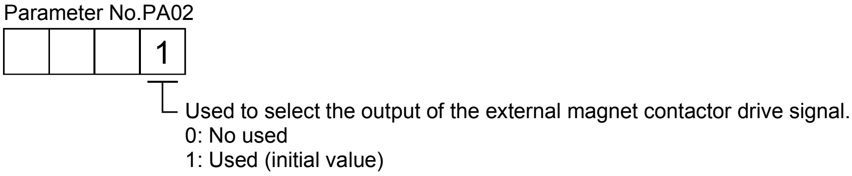
- Explanations on the following item are the same as those for servo amplifiers with 22kW or less. Refer to the section below for details.
  - I/O signal connection example Refer to section 3.2.
  - Signal (device) explanations Refer to section 3.5.
  - Detailed description of the signals Refer to section 3.6.
  - Interfaces Refer to section 3.8.
  - Treatment of cable shield external conductor Refer to section 3.9.
  - Grounding Refer to section 3.12.
- The pins with the same signal name are connected in the drive unit.

15.3.1 Magnetic contactor control connector (CNP1)

⚠WARNING

- Make sure to connect the magnetic contactor wiring connector to the converter unit. If the connector is not connected, an electric shock may occur since CNP1-1 and L_{11} are always conducting.

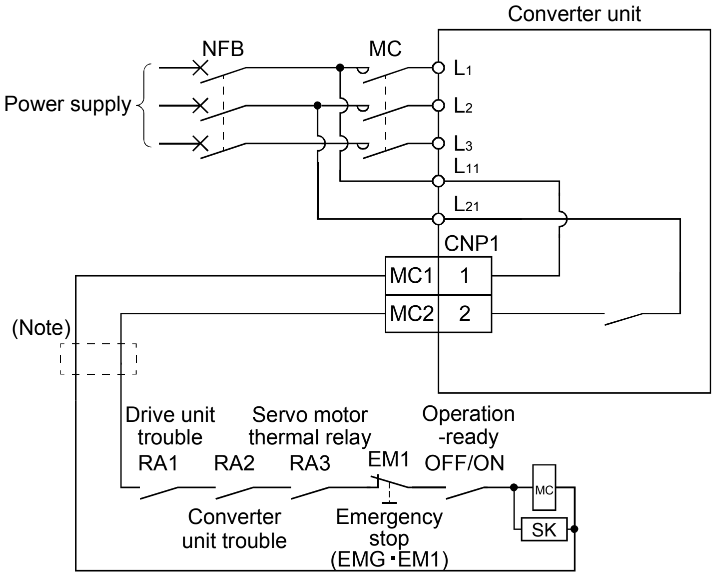
By enabling the control function of the magnetic contactor (parameter No.PA02＝□□□1 (initial value)), main circuit power supply can be shut off automatically when an alarm occurs on the converter unit or the drive unit.



Used to select the output of the external magnet contactor drive signal.
0: No used
1: Used (initial value)

(1) Enabling control function of magnetic contactor (parameter No.PA02=□□□1 (initial value))
Connecting the magnetic contactor control connector (CNP1) to the operating coil of the magnetic contactor enables to control the magnetic contactor.

Internal connection diagram of CNP1



Note. Stepdown transformer is required when coil voltage of the magnetic contactor is 200V class, and the converter unit and the drive unit are 400V class.

When the converter unit receives a start command from the drive unit while the magnetic contactor control connector (CNP1) is connected to the magnetic contactor (refer to section 15.3.2 (1)), CNP1-2 and L_{21} conduct in the converter unit. Then the control circuit power is supplied to turn ON the magnetic contactor and the main circuit power is supplied to the converter unit.
Either when an alarm occurs on the converter unit or the drive unit while the control function of the magnetic contactor is enabled, or when the forced stop (EM1) of the converter unit or the emergency stop (EMG) of the drive unit is turned OFF, the switch between CNP1-2 and L_{21} in the converter unit is disconnected and the main circuit power supply is automatically shut off.
To automatically shut off the main circuit power supply by alarm, enable the control function of the magnetic contactor.

(2) Disabling control function of magnetic contactor (parameter No.PA02=□□□0)
When not connecting the magnetic contactor control connector (CNP1) to the operating coil of the magnetic contactor, configure the circuit to shut off the main circuit power supply when detecting an alarm since the main circuit power supply is not automatically shut off even when an alarm occurs on the converter unit or the drive unit.

15.3.2 Input power supply circuit

⚠WARNING

- Insulate the connections of the power supply terminals. Not doing so can cause an electric shock.
- Magnetic contactor wiring connector on the converter unit CNP1. Unattached state may cause an electric shock.

⚠CAUTION

- Make sure to connect the magnetic contactor between the main circuit power supply and L_1, L_2, and L_3 of the converter unit, and configure to shut off the power supply on the side of the converter unit power supply. If the magnetic contactor is not connected, a large current keeps flowing and may cause a fire when the converter unit or the drive unit malfunctions.
- Use the trouble signal to switch power off. Otherwise, a regenerative transistor fault or the like may overheat the regenerative resistor, causing a fire.
- Connect the power supply phases (U, V, W) of the servo amplifier and servo motor correctly. Not doing so can cause the servo motor to run abnormally.
- Do not connect a 3-phase 200V power supply or a 3-phase 400V power supply directly to the servo motor. Doing so can cause a failure.
- Check the model and input the correct voltage for the power supply of the converter unit. When a voltage, which exceeds the maximum input voltage of the converter unit specifications, is input, the converter unit and drive unit malfunction.

POINT

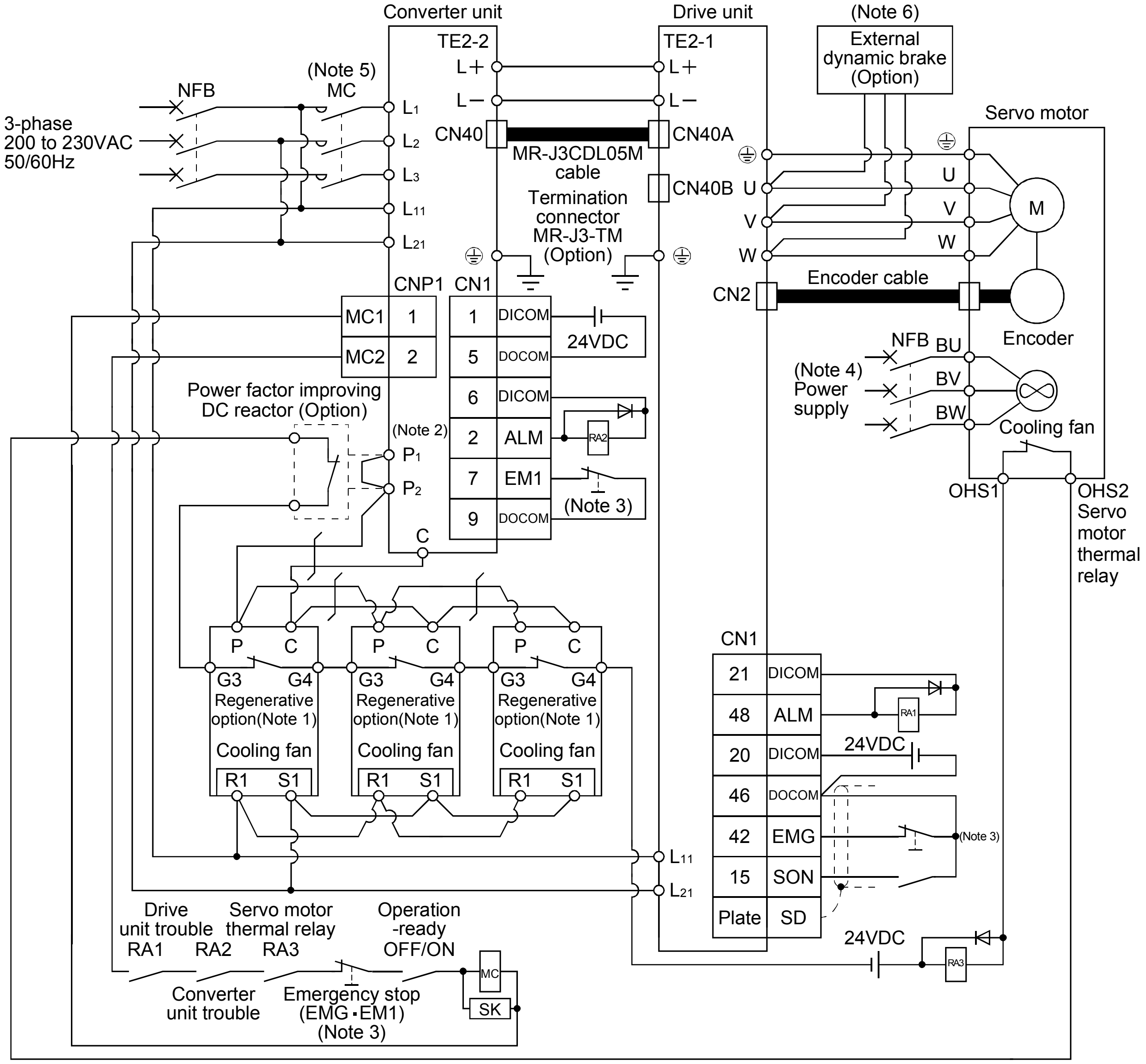
- Magnetic contactor control connector (CNP1) of the converter unit can be made valid or invalid with parameter No.PA02 of the converter unit. Refer to section 15.3.1 and 15.3.6 for details of CNP1 and section 15.5 for the parameter settings.
- For the external dynamic brake, refer to section 12.6 and 15.9.3.

(1) When magnetic contactor control connector (CNP1) is made valid (factory-set)

POINT

- The converter unit controls the main circuit magnetic contactor.
- Refer to section 15.3.7 (1) for the power circuit timing chart, section 15.3.7 (2) for the alarm occurrence timing chart, section 15.3.7 (3) for the forced stop (EM1) timing chart.
- Make sure to connect a protection coordination cable (MR-J3CDL05M) and a termination connector (MR-J3-TM). When they are not connected properly, the servo-on may not be turned ON.
- For the control power supplies of the converter unit and the drive unit, make sure to turn ON or OFF at the same time.

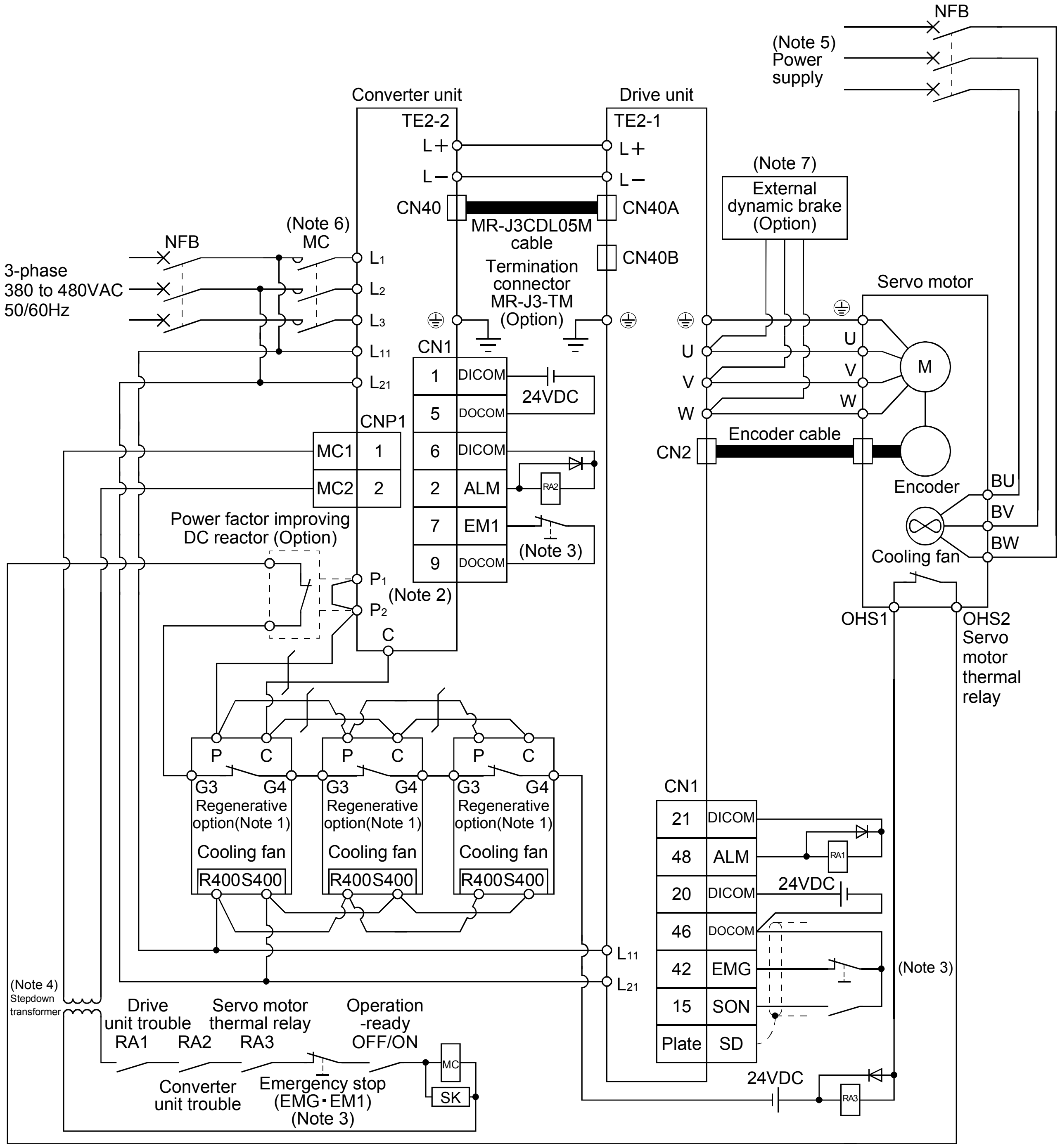
(a) 200V class (MR-J3-DU30KA・MR-J3-DU37KA)



Note 1. For the MR-RB137. For the MR-RB137, three units are used as one set (permissible wattage: 3900W).

2. When using the Power factor improving DC reactor, disconnect the short bar across P1-P2.
3. Make up a sequence that will concurrently turn off the Emergency stop (EMG) of the drive unit and the Forced stop (EM1) of the converter unit, and shut off the main circuit power supply by the external sequence.
4. For specifications of cooling fan power supply, refer to section 15.3.8.
5. Be sure to use a magnetic contactor with an operation delay time of 80ms or less. The operation delay time is the time interval between current being applied to the coil until closure of contacts.
6. Use an external dynamic brake for the drive unit. Failure to do so will cause an accident because the servo motor does not stop immediately but coasts at an emergency stop and such conditions. Ensure the safety in the entire system.

(b) 400V class (MR-J3-DU30KA4 to MR-J3-DU55KA4)



Note 1. For the MR-RB138-4. For the MR-RB138-4, three units are used as one set (permissible wattage: 3900W).

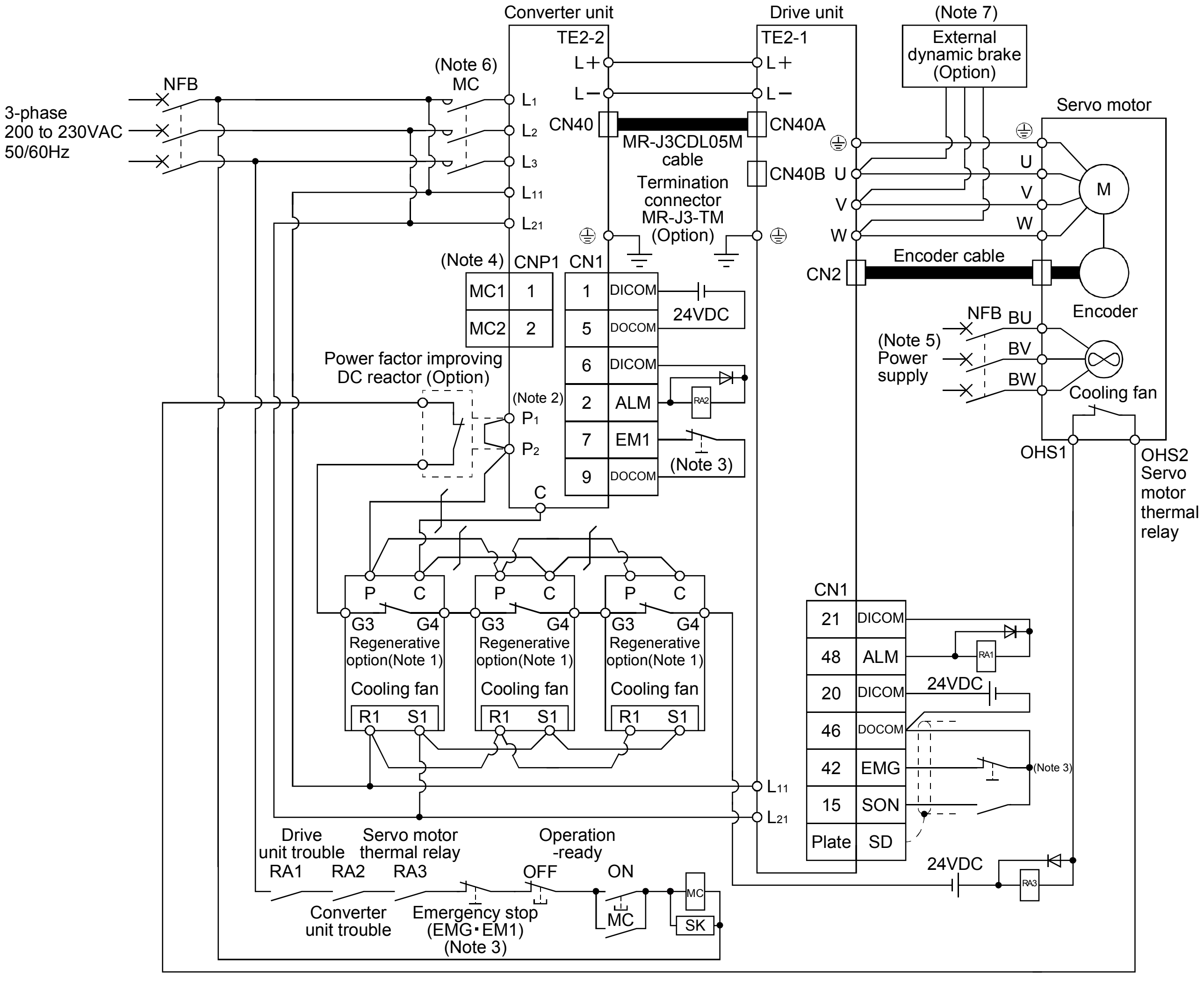
2. When using the Power factor improving DC reactor, disconnect the short bar across P_1-P_2.
3. Make up a sequence that will concurrently turn off the Emergency stop (EMG) of the drive unit and the Forced stop (EM1) of the converter unit, and shut off the main circuit power supply by the external sequence.
4. Stepdown transformer is required for coil voltage of magnetic contactor more than 200V class.
5. For specifications of cooling fan power supply, refer to section 15.3.8.
6. Be sure to use a magnetic contactor with an operation delay time of 80ms or less. The operation delay time is the time interval between current being applied to the coil until closure of contacts.
7. Use an external dynamic brake for the drive unit. Failure to do so will cause an accident because the servo motor does not stop immediately but coasts at an emergency stop and such conditions. Ensure the safety in the entire system.

(2) When magnetic contactor control connector (CNP1) is made invalid

POINT

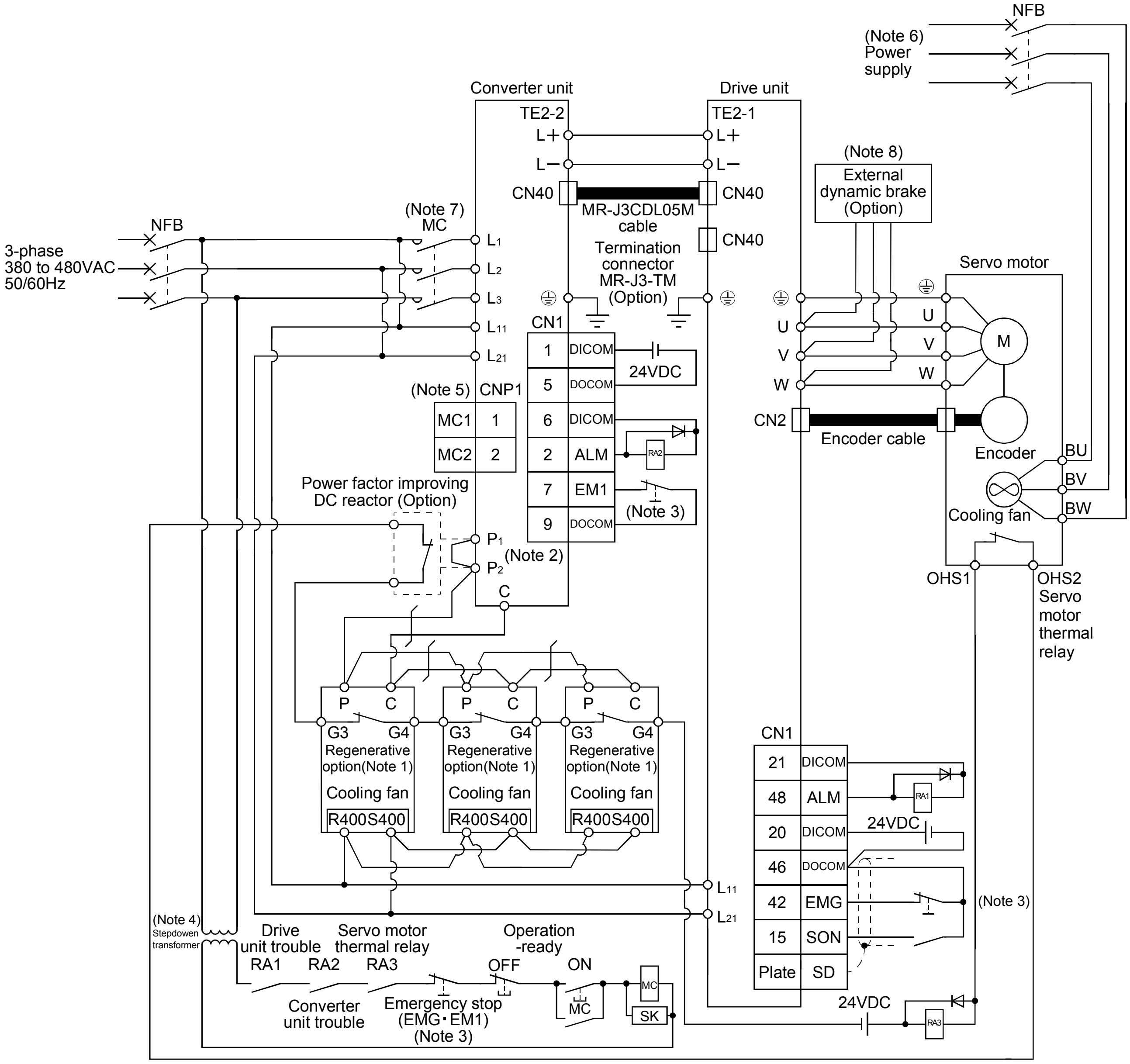
- When making CNP1 invalid, set "0000" in parameter No.PA02. (Refer to section 15.5.)
- Make sure to connect a protection coordination cable (MR-J3CDL05M) and a termination connector (MR-J3-TM). When they are not connected properly, the servo-on may not be turned ON.
- For the control power supplies of the converter unit and the drive unit, make sure to turn ON or OFF at the same time.

(a) 200V class (MR-J3-DU30KA · MR-J3-DU37KA)



Note 1. For the MR-RB137. For the MR-RB137, three units are used as one set (permissible wattage: 3900W).
2. When using the Power factor improving DC reactor, disconnect the short bar across P1-P2.
3. Make up a sequence that will concurrently turn off the Emergency stop (EMG) of the drive unit and the Forced stop (EM1) of the converter unit, and shut off the main circuit power supply by the external sequence.
4. Keep the wiring connector for the magnetic contactor connected to CNP1 of the converter unit. Unconnected status may cause an electric shock.
5. For specifications of cooling fan power supply, refer to section 15.3.8.
6. Be sure to use a magnetic contactor with an operation delay time of 80ms or less. The operation delay time is the time interval between current being applied to the coil until closure of contacts.
7. Use an external dynamic brake for the drive unit. Failure to do so will cause an accident because the servo motor does not stop immediately but coasts at an emergency stop and such conditions. Ensure the safety in the entire system.

(b) 400V class (MR-J3-DU30KA4 to MR-J3-DU55KA4)



Note 1. For the MR-RB138-4. For the MR-RB138-4, three units are used as one set (permissible wattage: 3900W).

2. When using the Power factor improving DC reactor, disconnect the short bar across P_1-P_2.
3. Make up a sequence that will concurrently turn off the Emergency stop (EMG) of the drive unit and the Forced stop (EM1) of the converter unit, and shut off the main circuit power supply by the external sequence.
4. Stepdown transformer is required for coil voltage of magnetic contactor more than 200V class.
5. Keep the wiring connector for the magnetic contactor connected to CNP1 of the converter unit. Unconnected status may cause an electric shock.
6. For specifications of cooling fan power supply, refer to section 15.3.8.
7. Be sure to use a magnetic contactor with an operation delay time of 80ms or less. The operation delay time is the time interval between current being applied to the coil until closure of contacts.
8. Use an external dynamic brake for the drive unit. Failure to do so will cause an accident because the servo motor does not stop immediately but coasts at an emergency stop and such conditions. Ensure the safety in the entire system.

15.3.3 Terminal

Refer to section 15.7 for the terminal block arrangement and signal layout.

(1) Converter unit

Connection target (Application)	Abbreviation	(Note) Terminal block	Description	
			MR-J3-CR55K	MR-J3-CR55K4
Main circuit power supply	L_1・L_2・L_3	TE1-1	Connect 3-phase 200 to 230VAC, 50/60Hz to L_1, L_2, L_3.	Connect 3-phase 380 to 480VAC, 50/60Hz to L_1, L_2, L_3.
Control circuit power supply	L_{11}・L_{21}	TE3	Connect 1-phase 200 to 230VAC, 50/60Hz.	Connect 1-phase 380 to 480VAC, 50/60Hz.
Power factor improving DC reactor	P_1・P_2	TE1-2	When using the power factor improving DC reactor, connect it after removing the connection plate across P_1-P_2.	
Regenerative brake	P_2・C	TE1-2	Connect to the P_2 and C terminals of the regenerative option.	
DC link	L＋・L－	TE2-2	Connect to the L＋, L－ terminals of the drive unit. Use the connection bar, which is supplied with the drive unit, to connect.	
Grounding	⏚	PE	Connect this terminal to the protective earth (PE) terminals of the servo motor and control box for grounding.	

Note. The permissible tension applied to any of the terminal blocks TE1-1, TE1-2, TE2-2 is 350[N].

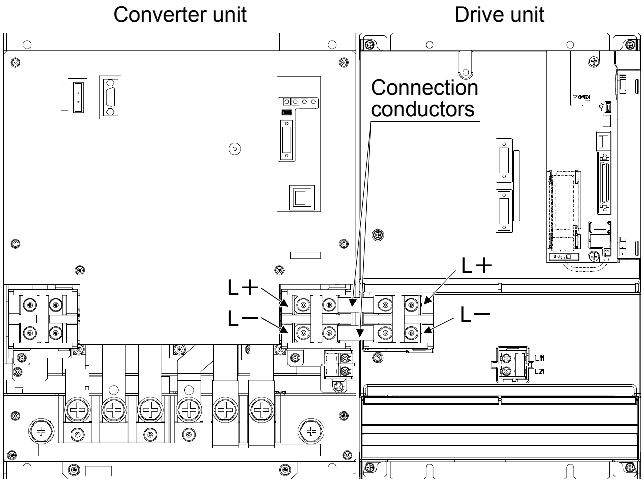
(2) Drive unit

Connection target (Application)	Abbreviation	(Note) Terminal block	Description	
			MR-J3-DU30KA・MR-J3-DU37KA	MR-J3-DU30KA4 to MR-J3-DU55KA4
Control circuit power supply	L_{11}・L_{21}	TE3	Connect 1-phase 200 to 230VAC, 50/60Hz.	Connect 1-phase 380 to 480VAC, 50/60Hz.
L＋L－ power supply input	L＋・L－	TE2-1	Connect to the L＋ and L－ terminals of the converter unit. Use the connection bar, which is supplied with the drive unit, to connect.	
Servo motor power	U・V・W	TE1	Connect to the servo motor power terminals (U, V, W).	
Grounding	⏚	PE	Connect this terminal to the protective earth (PE) terminals of the servo motor and control box for grounding.	

Note. The permissible tension applied to any of the terminal blocks TE1, TE2-1 is 350[N].

15.3.4 How to use the connection bars

Make sure to use the supplied connection conductors and connect the L＋ and L－ of the converter unit to those of the drive unit as shown below. Never use connection conductors other than the ones supplied with the drive unit. Both units are shown without the front covers.

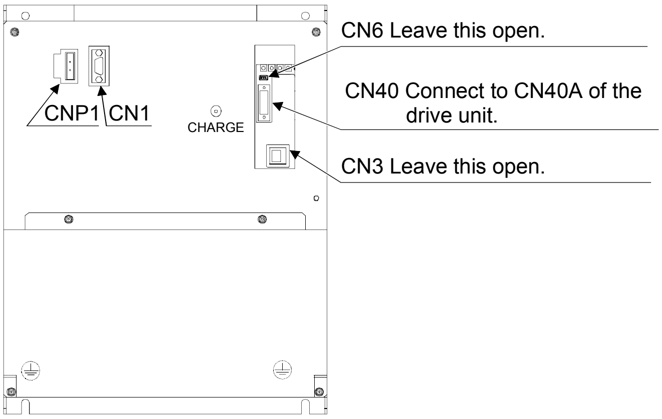


15.3.5 Connectors and signal arrangements

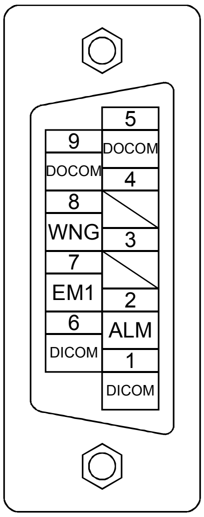
POINT

- The pin configurations of the connectors are as viewed from the cable connector wiring section.

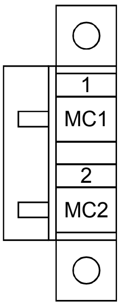
(1) Converter unit



CN1 (Digital I/O connector)
Model: 17JE-23090-02 (D8A) K11-CG (D-sub 9 pin or equivalent)
(DDK)

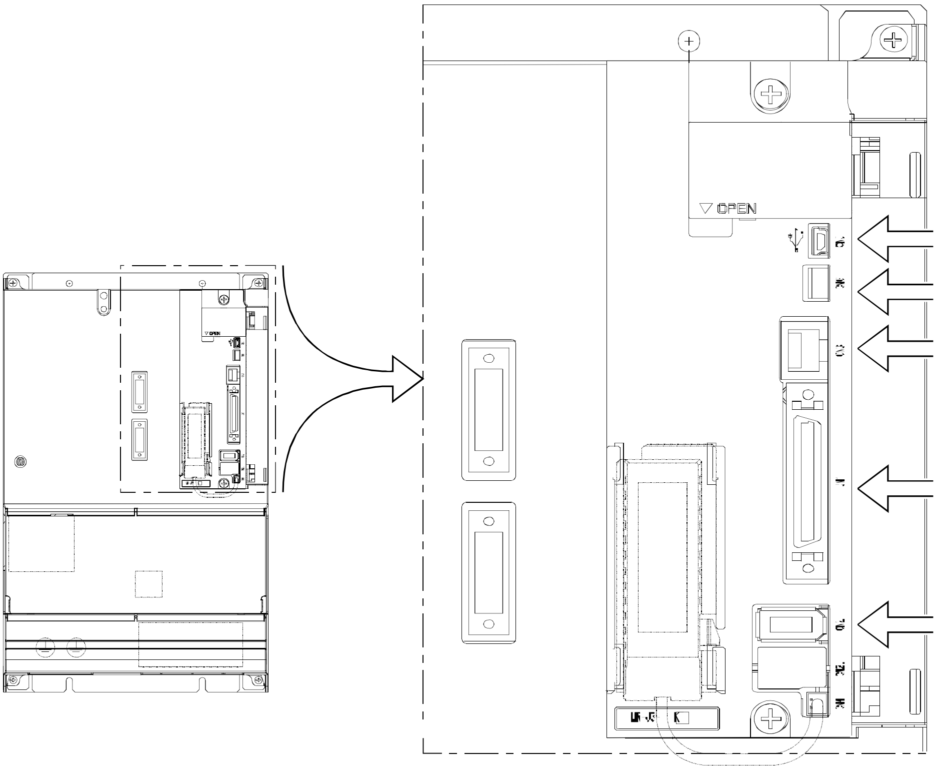


CNP1 (Magnetic contactor wiring connector)
Model: GFKC 2,5/2-STF-7,62
(Phoenix Contact)



(2) Drive unit

The drive unit front view shown is that of the MR-J3-DU30KA4, MR-J3-DU37KA4 or less. Refer to section 15.7 Outline Drawings for the appearances and connector layouts of the MR-J3-DU30KA, MR-J3-DU37KA, MR-J3-DU45KA4, MR-J3-DU55KA4.



CN5 (USB communication connector) Refer to section 12.8.

CN6 (Analog monitor connector) Refer to section 3.4.

CN3 (RS-422 communication connector) Refer to section 13.1.

CN1 (I/O signal connector) Refer to section 3.4.

CN2 (Encoder connector) Refer to section 3.4.

The frames of the CN2 and CN3 connectors are connected to the PE (earth) terminal in the amplifier.

15.3.6 Converter unit signal (device) explanations

POINT

- Explanations on the drive unit signals are the same as those for servo amplifiers with 22kW or less. Refer to section 3.5.

(1) Signals

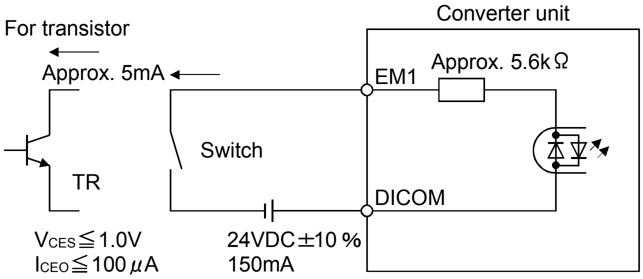
For the I/O interfaces (symbols in I/O column in the table), refer to (2) in this section.

Signal name	Pin code	Pin No.	Function/Application	I/O division
Digital I/F power supply input	DICOM	CN1-1 CN1-6	Used to input 24VDC (24VDC±10% 150mA) for I/O interface. The power supply capacity changes depending on the number of I/O interface points to be used. For sink interface, connect ⊕ of 24VDC external power supply. For source interface, connect ⊖ of 24VDC external power supply.	
Forced stop	EM1	CN1-7	Turn EM1 off to bring the motor to a forced stop state, in which the magnetic connector is turned off and the servo-off signal is output to the drive unit. Turn EM1 on in the forced stop state to reset that state.	DI
Trouble	ALM	CN1-2	ALM turns off when power is switched off or the protective circuit is activated. Without alarm occurring, ALM turns on within about 1.5s after power-on.	DO
Warning	WNG	CN1-8	When warning has occurred, WNG turns on.	DO
Digital I/F common	DOCOM	CN1-5 CN1-9	Common terminal for the ALM and WNG output signals of the converter unit. Separated from LG. Pins are connected internally. For sink interface, connect ⊖ of 24VDC external power supply. For source interface, connect ⊕ of 24VDC external power supply.	
Magnetic contactor drive output	MC1	CNP1-1	Connect to the operation coil of the magnetic contactor. Always supplies the control circuit power since it is conducted with L_{11} in the converter unit. ⚠WARNING - Magnetic contactor wiring connector on the converter unit. Connected state may cause an electric shock.	
	MC2	CNP1-2	Connect to the operation coil of the magnetic contactor. When the converter unit receives a start command from the drive unit, it is conducted with L_{21} inside, the control circuit power is supplied, and then the magnetic contactor is turned ON. Change parameter No.PA02 setting to "□□□0" when controlling without magnetic contactor control connector (CNP1). (Refer to section 15.3.1.)	

(2) I/O interfaces

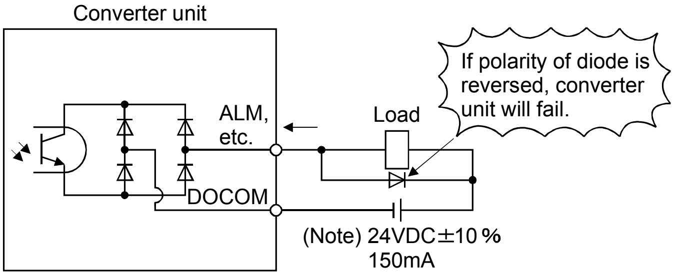
(a) Digital input interface (DI)

Give a signal with a relay or open collector transistor. Refer to section 3.8.3 for source input.



(b) Digital output interface (DO)

A lamp, relay or photocoupler can be driven. Install a diode for an inductive load, or install an inrush current suppressing resistor for a lamp load. (Rated current: 40mA or less, maximum current: 50mA or less, inrush current: 100mA or less) A maximum of 2.6V voltage drop occurs in the servo amplifier. Refer to section 3.8.3 for source output.



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

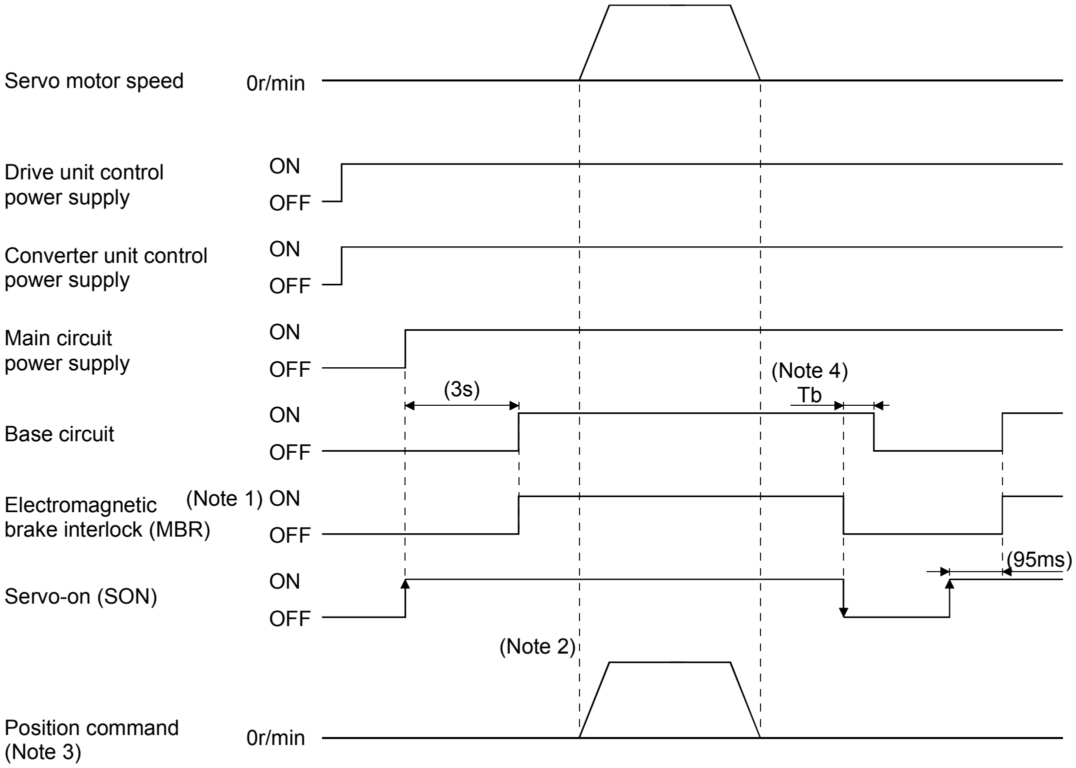
15.3.7 Timing chart

(1) Power circuit timing chart

Power-on procedure

(a) Make sure to wire the power supply as shown in above section 15.3.1 using the magnetic contactor with the main circuit power supply (3-phase: L_1, L_2, L_3). Configure up an external sequence to switch off the magnetic contactor as soon as an alarm occurs.

(b) In the case where control function of the magnetic contactor for the converter unit is enabled, turn on control circuit power supply (L_{11} and L_{21}) for the converter unit and the drive unit at the same time. After the converter unit and the drive unit are activated, main circuit power supply automatically turns on. When controlling the magnetic contactor by the external sequence, turn on the control circuit power supply (L_{11} and L_{21}) for the converter unit and the drive unit concurrently with the main circuit power supply or before switching on the main circuit power supply. However, by switching on the main circuit power supply, the warning disappears and the drive unit will operate properly.



Note 1. When setting up an electromagnetic brake at customer's side, make up a sequence which will operate the electromagnetic brake as follow using the electromagnetic brake interlock (MBR).

ON: Electromagnetic brake is not activated.

OFF: Electromagnetic brake is activated

2. Give a position command after the external electromagnetic brake is released.
3. For the position control mode.
4. “Tb” is a delay time from when the electromagnetic brake interlock (MBR) is turned off until when the base circuit is shut off at servo off. Set Tb using parameter No.PC16.

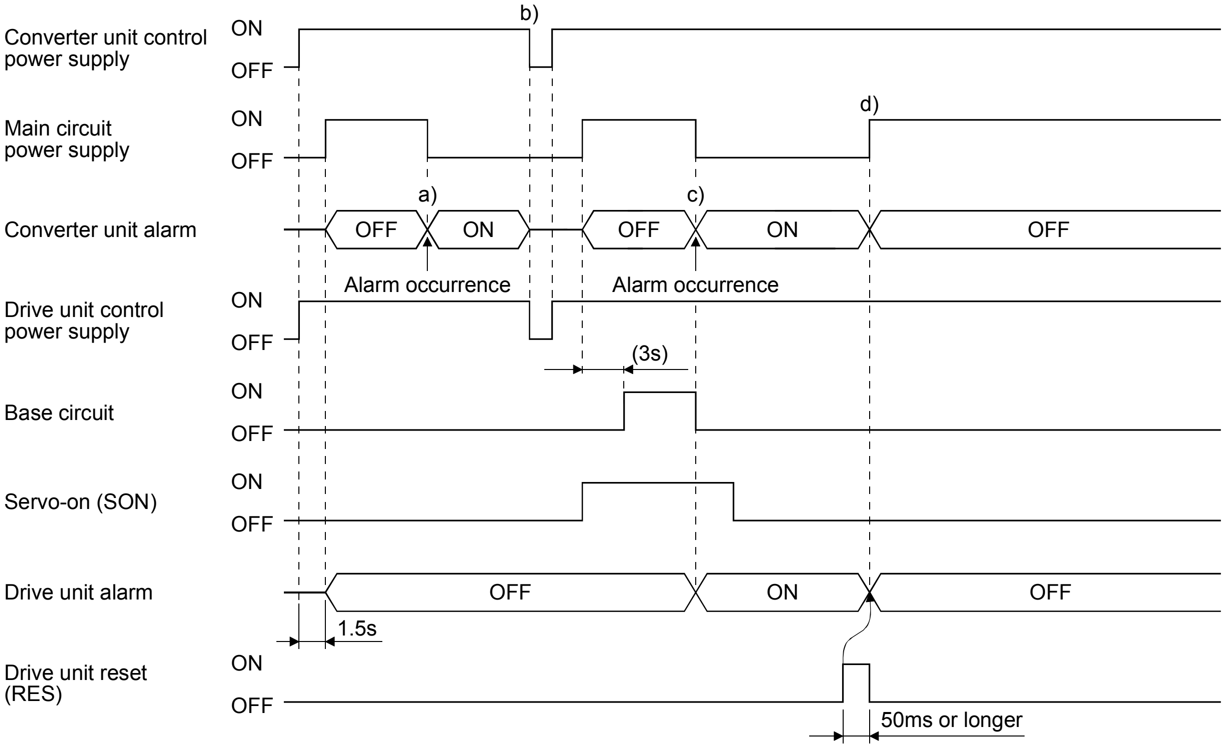
(2) Alarm occurrence timing chart

⚠CAUTION	- When an alarm has occurred, remove its cause, make sure that the operation signal is not being input, ensure safety, and reset the alarm before restarting operation. - As soon as an alarm occurs, make the Servo off status and interrupt the main circuit power.

(a) When control function of magnetic contactor is enabled

1) Converter unit

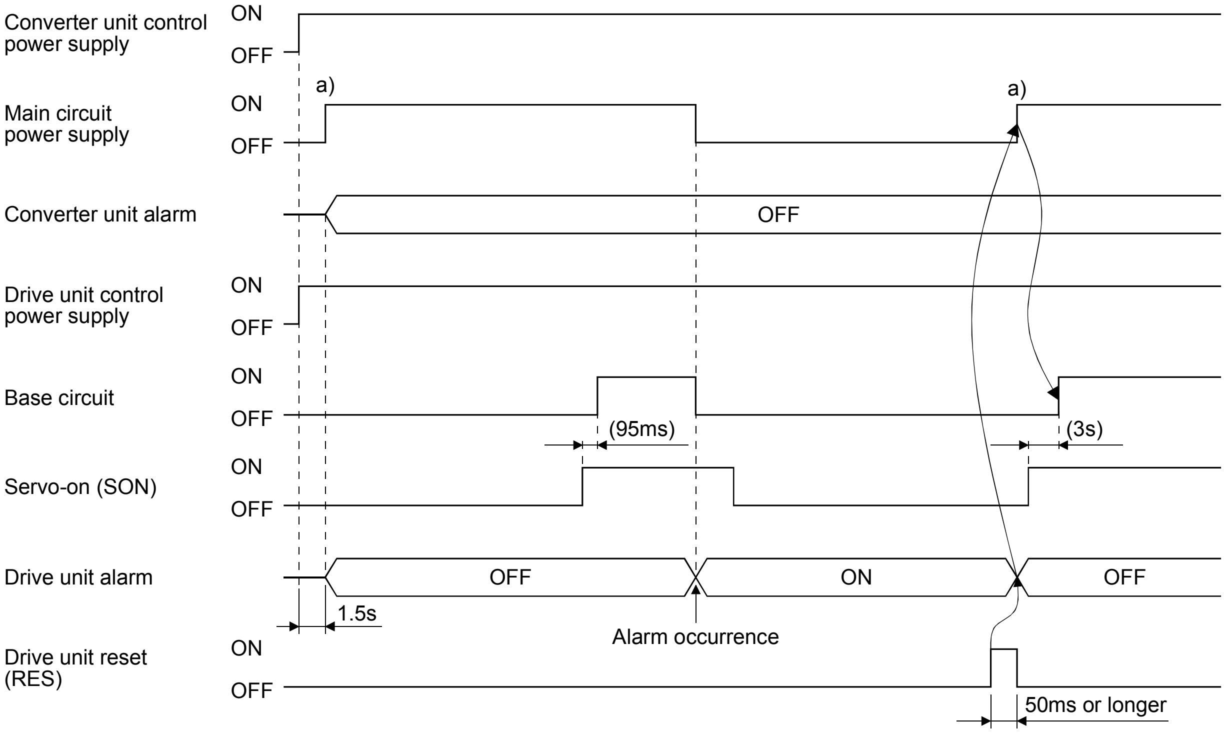
When an alarm occurs in the converter unit, the magnetic contactor is turned off and the main circuit magnetic contactor is shut off. The drive unit in operation stops. To deactivate the alarm, turn the control circuit power off, then on. However, the alarm cannot be deactivated unless its cause is removed.



a) in Figure	Even if an alarm occurs in the converter when the drive unit is at servo off, the drive unit does not detect the alarm.
b) in Figure	To deactivate the alarm of the converter unit, turn the power of the converter unit off, and then on. (Refer to section 15.6.1.)
c) in Figure	If an alarm occurs in the converter when the drive unit is at servo on, the alarm also occurs in the drive unit and the drive unit becomes servo off.
d) in Figure	When alarms are occurring on both the converter unit and the drive unit, by deactivating the alarm on the drive unit, the alarm on the converter unit can be deactivated.

2) Drive unit

When an alarm occurs on the drive unit, the base circuit is shut off and the servo motor coasts. When using an external dynamic brake (option), the external dynamic brake is activated to stop the servo motor. To deactivate the alarm, execute the following: turn off and then on the control circuit power supply, press the “SET” button on the current alarm screen, and turn off and then on the reset (RES). However, the alarm cannot be deactivated unless its cause is removed.

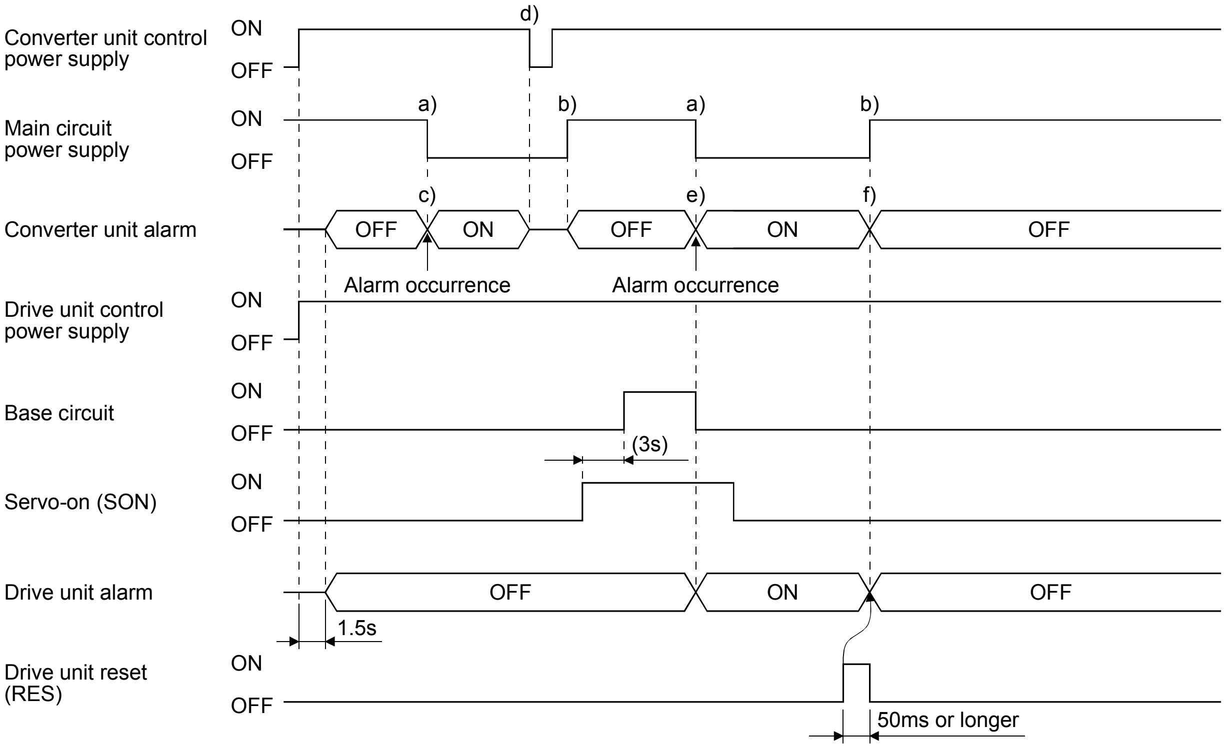


a) in Figure After completing to start the drive unit, the main circuit power is supplied while the drive unit and the converter unit have no alarms.

(b) When controlling magnetic contactor by external sequence

1) Converter unit

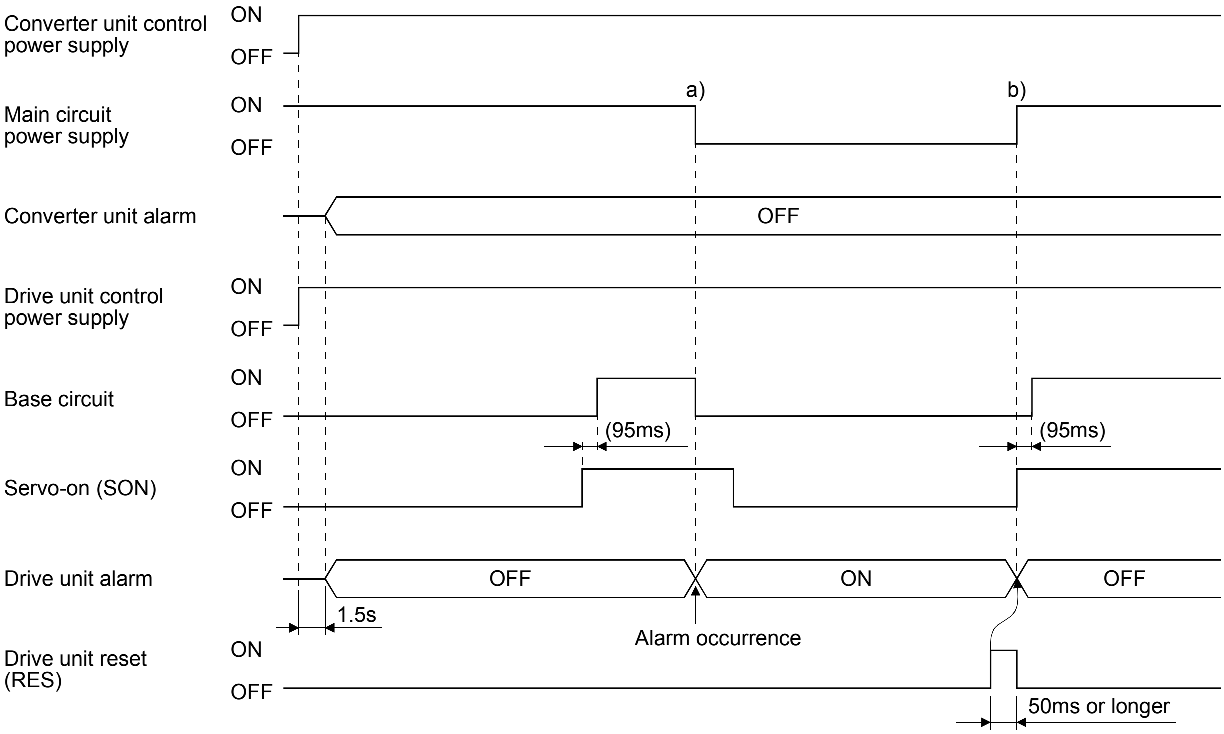
When an alarm occurs on the converter unit, the servo-on turns OFF; however, the main circuit power supply is not shut off. Therefore, shut off the main circuit power supply by the external sequence. After cancelling the alarm on the converter unit (when an alarm is also occurring on the drive unit after cancelling the alarm on the drive unit as well), turning ON the reset (RES) enables to operate again.



a) in Figure	If an alarm occurs on the converter unit, shut off the main circuit power supply by the external sequence.
b) in Figure	Turn on the main circuit power supply while alarms on the drive unit are deactivated.
c) in Figure	Even if an alarm occurs in the converter when the drive unit is at servo off, the drive unit does not detect the alarm.
d) in Figure	To deactivate the alarm of the converter unit, turn the power of the converter unit off, and then on. (Refer to section 15.6.1.)
e) in Figure	If an alarm occurs in the converter unit when the drive unit is at servo on, the alarm also occurs in the drive unit and the drive unit becomes servo off.
f) in Figure	When alarms are occurring on both the converter unit and the drive unit, by deactivating the alarm on the drive unit, the alarm on the converter unit can be deactivated.

2) Drive unit

When an alarm occurs in the drive unit, the drive unit turns into the servo off but the main circuit power supply is not shut off. Therefore, shut off the main circuit power supply using the external sequence. Operation can be resumed by turning the reset (RES) ON after the alarm is deactivated in the drive unit.



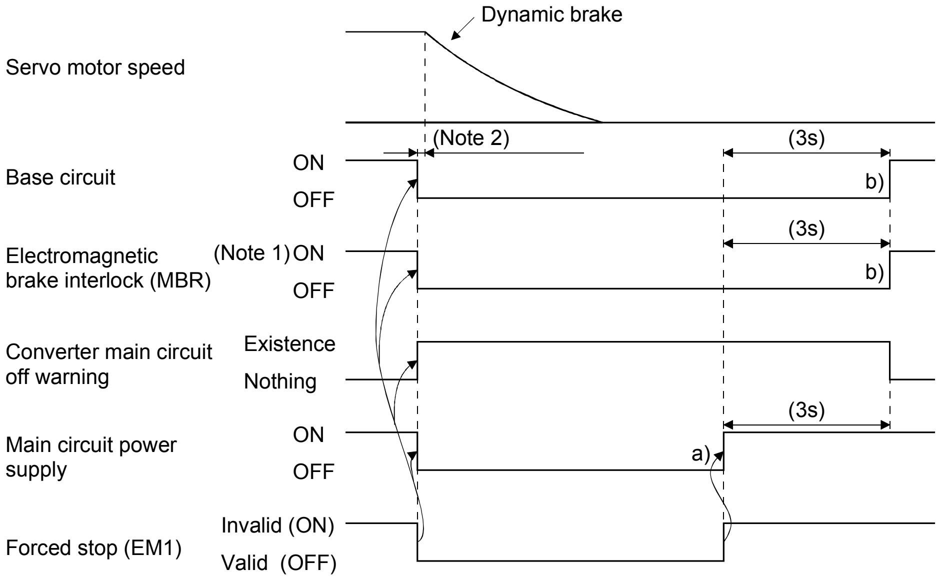
a) in Figure	When an alarm occurs on the drive unit, shut off the main circuit power supply by the external sequence.
b) in Figure	Turn ON the main circuit power supply while an alarm of the drive unit is cancelled.

(3) Forced stop (EM1) ON/OFF timing chart

(a) When control function of magnetic controller is enabled

1) Converter unit

When the forced stop (EM1) is made valid in the converter unit, the magnetic contactor is turned off and the main circuit power supply is shut off. The drive unit in operation stops, and Main circuit off warning (AL.E9) appears. When the forced stop (EM1) is deactivated in the converter unit, the magnetic contactor is turned on, the main circuit power is supplied, and then the drive unit automatically resumes the operation.



Note 1. When setting up an electromagnetic brake at customer's side, make up a sequence which will operate the electromagnetic brake as follow using the electromagnetic brake interlock (MBR).

ON: Electromagnetic brake is not activated.

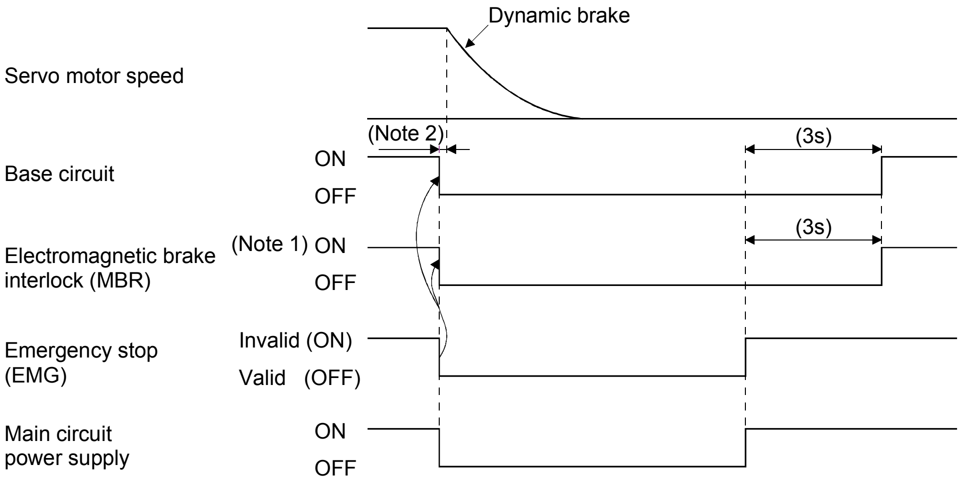
OFF: Electromagnetic brake is activated

2. There is delay caused by magnetic contactor built into the external dynamic brake (about 50ms) and delay caused by the external relay.

a) in Figure	As the forced stop (EM1) is disabled for the converter unit, the main circuit power supply turns on.
b) in Figure	After charging the main circuit condenser is completed, base circuit and electromagnetic brake interlock turn on.

2) Drive unit

When the Emergency stop (EMG) of the drive unit is activated, the base circuit shuts off in the operating drive unit, and the drive unit goes into the emergency stop status. If the drive unit becomes emergency stop status, the magnetic contactor turns off and the main circuit power supply is shut off.



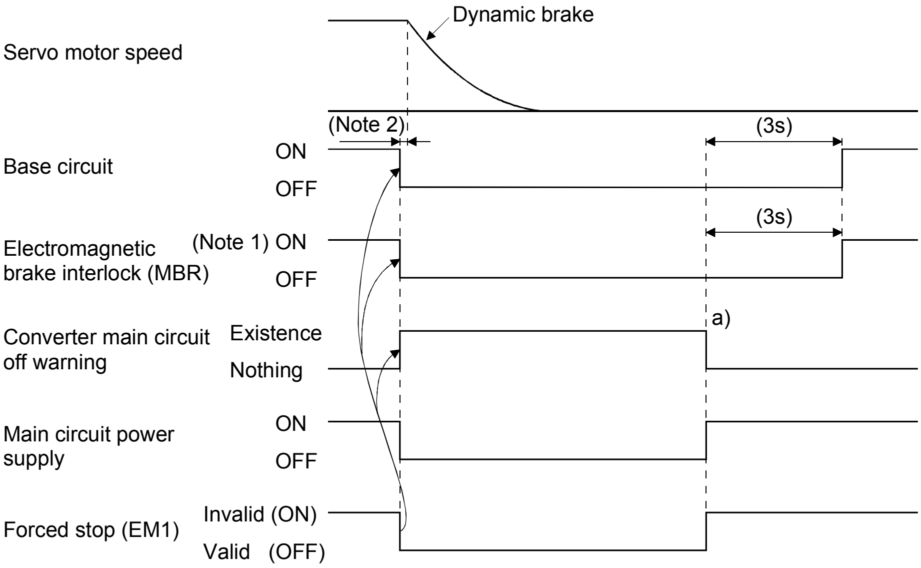
Note 1. When setting up an electromagnetic brake at customer's side, make up a sequence which will operate the electromagnetic brake as follow using the electromagnetic brake interlock (MBR).
ON: Electromagnetic brake is not activated.
OFF: Electromagnetic brake is activated

2. There is delay caused by magnetic contactor built into the external dynamic brake (about 50ms) and delay caused by the external relay.

(b) When turning off magnetic contactor by external sequence

1) Converter unit

When the Forced stop (EM1) of the converter unit is activated, the base circuit shuts off in the operating drive unit, and the Main circuit off warning (AL.E9) is displayed on the drive unit. When the Forced stop (EM1) of the converter unit is deactivated, the drive unit automatically restarts the operation. Shut off the main circuit power supply concurrently with the turn OFF of the Forced stop (EM1) of the converter unit and the Emergency stop (EMG) of the drive unit.

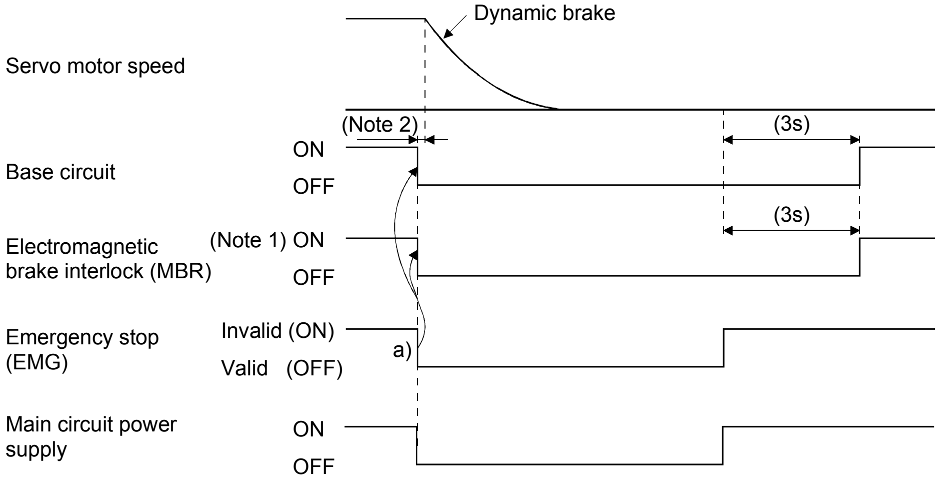


Note 1. When setting up an electromagnetic brake at customer's side, make up a sequence which will operate the electromagnetic brake as follow using the electromagnetic brake interlock (MBR).
ON: Electromagnetic brake is not activated.
OFF: Electromagnetic brake is activated

2. There is delay caused by magnetic contactor built into the external dynamic brake (about 50ms) and delay caused by the external relay.

a) in Figure When the forced stop is invalid, the converter main circuit off warning turns off.

2) Drive unit



Note 1. When setting up an electromagnetic brake at customer's side, make up a sequence which will operate the electromagnetic brake as follow using the electromagnetic brake interlock (MBR).

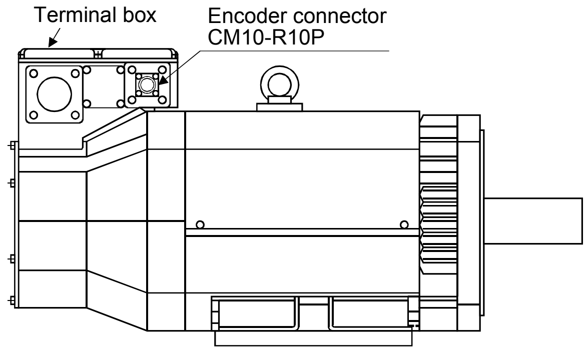
ON: Electromagnetic brake is not activated.

OFF: Electromagnetic brake is activated

2. There is delay caused by magnetic contactor built into the external dynamic brake (about 50ms) and delay caused by the external relay.

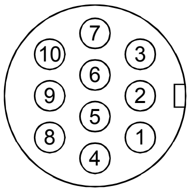
a) in Figure When the Emergency stop of the drive unit is activated, the base circuit shuts off in the operating drive unit, and the drive unit goes into the emergency stop status.

15.3.8 Servo motor side details



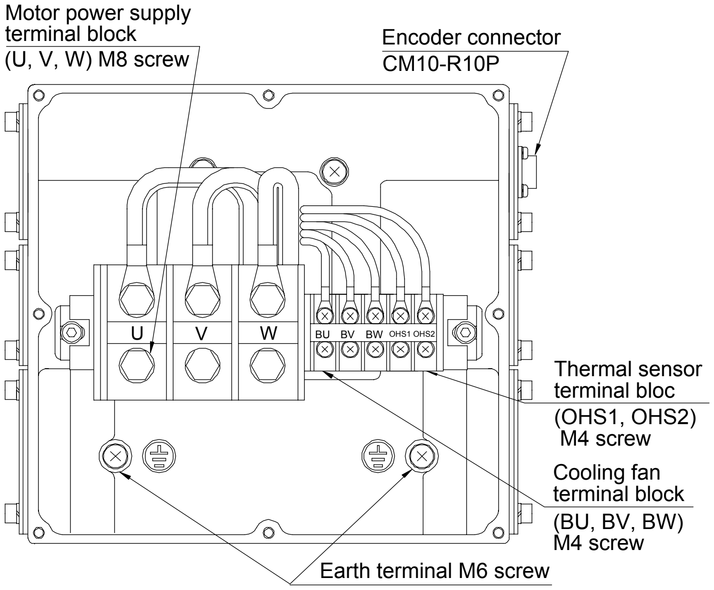
Encoder connector signal arrangement

CM10-R10P



Terminal No.	Signal
1	MR
2	MRR
3	
4	BAT
5	LG
6	
7	
8	P5
9	
10	SHD

	HA-LP30K1M4 HA-LP30K24 HA-LP37K24	HA-LP30K1 HA-LP37K1 HA-LP30K1M HA-LP37K1M HA-LP30K2 HA-LP37K2 HA-LP25K14 HA-LP30K14 HA-LP37K14 HA-LP37K1M4 HA-LP45K1M4 HA-LP50K1M4 HA-LP45K24 HA-LP55K24
Servo motor power supply terminal block screw size	M8	M10
Earth screw size	M6	M6



Terminal block signal arrangement

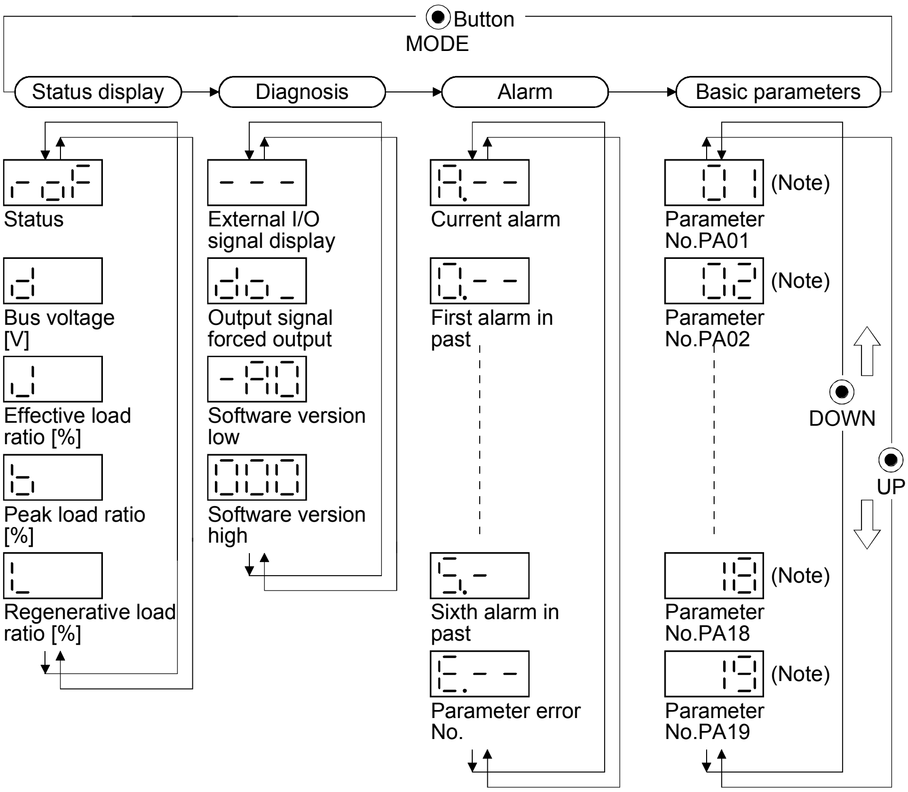
U	V	W	BU	BV	BW	OHS1	OHS2

<table>
<tr><th>Signal name</th><th>Abbreviation</th><th>Description</th></tr>
<tr><td>Servo motor power supply</td><td>U・V・W</td><td>Connect to the motor power terminals (U, V, W) of the drive unit. During power-on, do not open or close the motor power line.
Otherwise, a malfunction or faulty may occur.</td></tr>
<tr><td>Cooling fan</td><td>BU・BV・BW</td><td>Supply power which satisfies the following specifications.
<table>
<tr><th>Servo motor</th><th>Voltage division</th><th>Voltage, frequency</th><th>Power consumption [W]</th><th>Rated current [A]</th></tr>
<tr><td>HA-LP30K1M, 30K2, 37K2</td><td>200V class</td><td>3-phase 200 to 230VAC 50Hz/60Hz</td><td>65(50Hz)
85(60Hz)</td><td>0.20(50Hz)
0.22(60Hz)</td></tr>
<tr><td>HA-LP30K1, 37K1, 37K1M</td><td></td><td></td><td>120(50Hz)
175(60Hz)</td><td>0.65(50Hz)
0.80(60Hz)</td></tr>
<tr><td>HA-LP30K1M4, 30K24, 37K24</td><td>400V class</td><td>3-phase 380 to 460VAC 50Hz</td><td>65(50Hz)
85(60Hz)</td><td>0.12(50Hz)
0.14(60Hz)</td></tr>
<tr><td>HA-LP30K14, 37K14, 37K1M4, 45K1M4, 50K1M4, 45K24, 55K24</td><td></td><td>3-phase 380 to 480VAC 60Hz</td><td>110(50Hz)
150(60Hz)</td><td>0.20(50Hz)
0.22(60Hz)</td></tr>
</table>
</td></tr>
<tr><td>Motor thermal relay</td><td>OHS1・OHS2</td><td>OHS1-OHS2 are opened when heat is generated to an abnormal temperature.
Maximum rating: 125V AC/DC 3A or 250V AC/DC 2A
Minimum rating: 6V AC/DC 0.15A</td></tr>
<tr><td>Earth terminal</td><td>⏚</td><td>For grounding, connect to the earth of the control box via the earth terminal of the drive unit.</td></tr>
</table>

15.4 Display section and operation section of the converter unit

15.4.1 Display flowchart

Use the display (3-dight, 7-segment LED) on the front panel of the converter unit for status display, parameter setting, etc. Set the parameters before operation, diagnose an alarm, confirm external sequences, and/or confirm the operation status.
Press the MODE, UP or DOWN button once to move the next screen.



Note. When parameter is selected, parameter group and parameter No. are displayed alternately. Refer to section 15.4.5 for details.

15.4.2 Status display mode

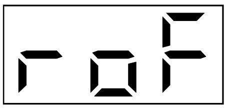
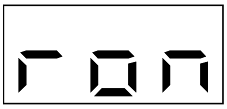
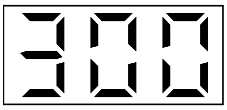
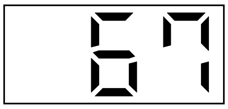
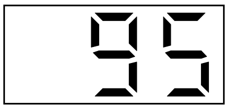
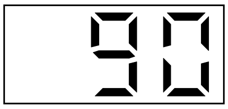
The servo status during operation is shown on the 3-digit, 7-segment LED display. Press the "UP" or "DOWN" button to change display data as desired.

When the required data is selected, the corresponding symbol is displayed. Press the "SET" button to display that data.

The converter unit display section can show four items of data such as the effective load ratio.

(1) Display examples

The following table shows the display examples.

Item	Status	Display
Status	Ready off	
	Ready on	
Bus voltage	300 [V]	
Effective load ratio	67 [%]	
Peak load ratio	95 [%]	
Regenerative load ratio	90 [%]	

(2) Status display list

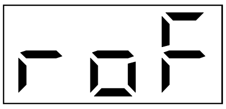
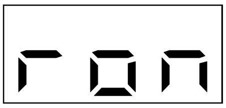
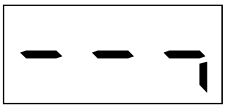
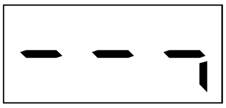
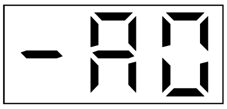
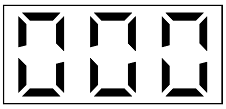
The following table lists the converter unit statuses that may be displayed.

Status display		Symbol	Unit	Description	Indication range
Status	Ready off			The ready off is displayed during initialization or alarm occurrence, in the forced stop status, or when the bus voltage is not established.	roF
	Ready on			The ready on is displayed when the servo was switched on after completion of initialization and the servo amplifier is ready to operate.	ron
Bus voltage		d	V	The converter unit voltage is displayed.	0 to 999
Effective load ratio		J	%	Continuous effective load torque is displayed. (Note) The effective value in the past 15 seconds is displayed relative to the rated current of 100%.	0 to 300
Peak load ratio		b	%	The peak output is displayed. (Note) The peak value in the past 15 seconds is displayed relative to the rated torque of 100%.	0 to 400
Regenerative load ratio		L	%	The percentage of regenerative power to the permissible regenerative value is displayed.	0 to 300

Note. Output = converter unit bus voltage × output current

15.4.3 Diagnostic mode

(1) Diagnostic list

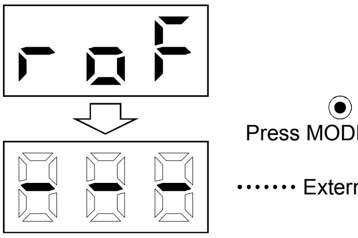
Name	Display	Unit
Sequence		Not ready. ・Initializing. ・An alarm occurred. ・External forced stop status. ・Bus voltage is not established.
		Ready Indicates that the servo was switched on after completion of initialization and the drive unit is ready to operate.
External I/O signal display		Indicates the ON/OFF status of external I/O signal. Lit : ON Extinguished: OFF For details, refer to (2) in this section.
Output signal forced output		Allows external I/O signal to be switched on/off forcibly. For details, refer to (3) in this section.
Software version low		Indicates the version of the software.
Software version high		Indicates the system number of the software.

(2) External I/O signal display

The ON/OFF states of the digital I/O signals connected to the converter unit can be confirmed.

(a) Operation

Call the display screen shown after power-on. Using the "MODE" button, show the diagnostic screen.

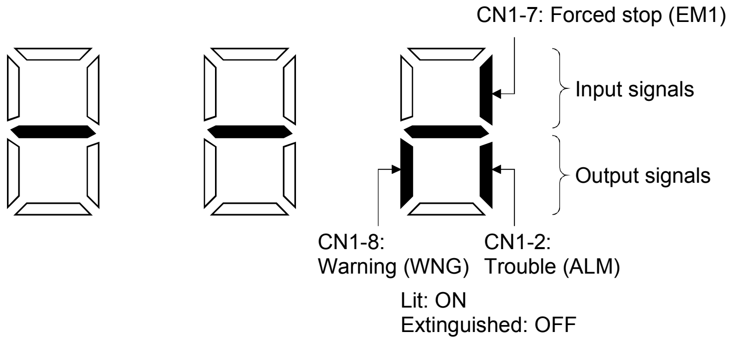


Press MODE once.

······· External I/O signal display screen

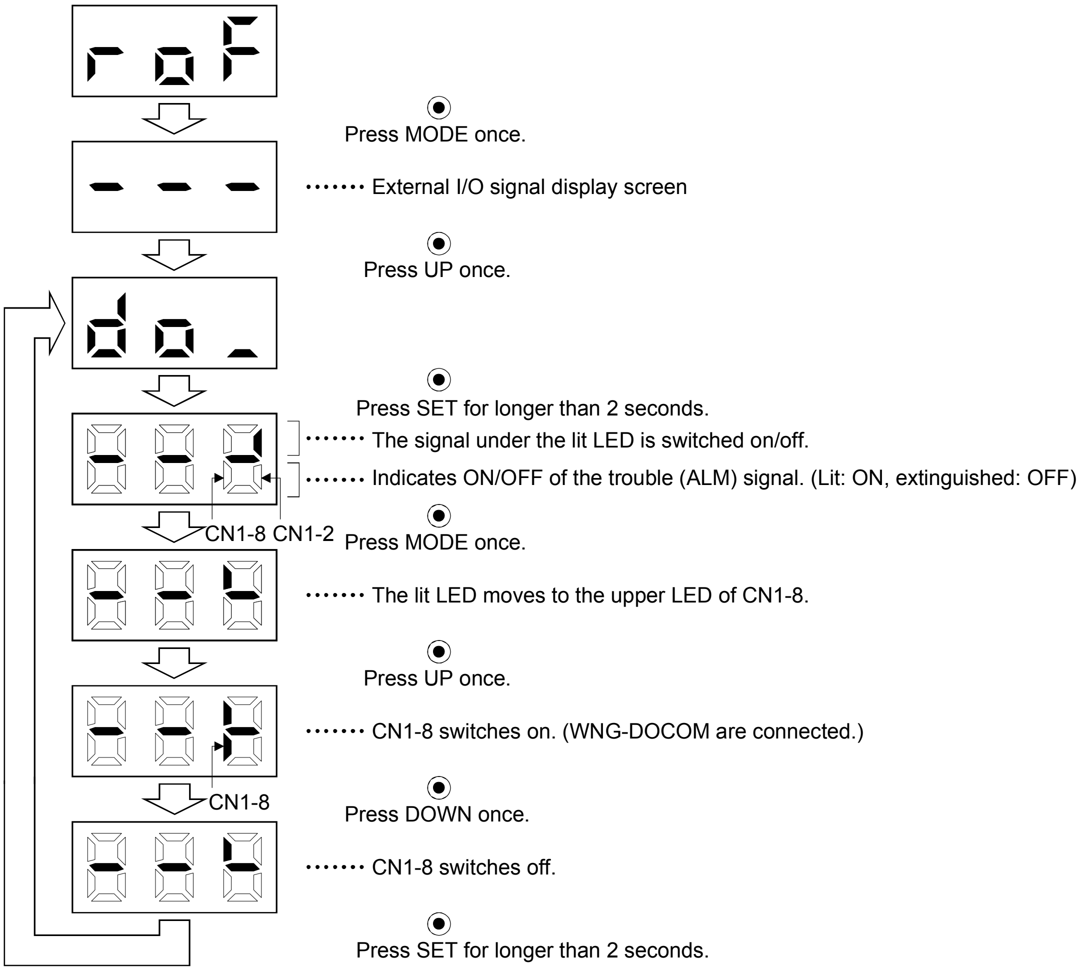
(b) Display definition

The LED segment corresponding to the pin is lit to indicate ON, and is extinguished to indicate OFF.
The 7-segment LED segments and CN1 connector pins correspond as shown below.



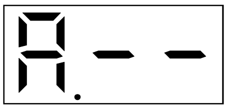
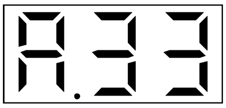
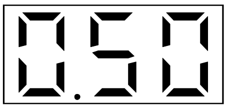
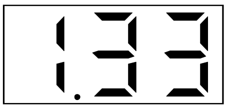
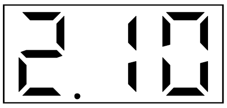
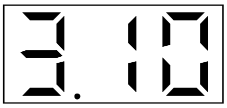
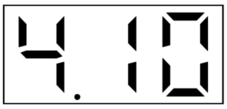
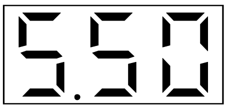
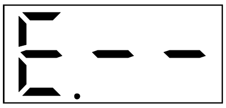
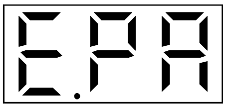
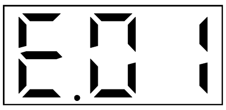
(3) Output signal forced output

You can force the output signal to be switched on/off, independently of the converter status.
This function is used for wiring check of output signal. Indicates the display screen shown after power-on.
When turning CN1-8 on and off



15.4.4 Alarm mode

The current alarm and parameter error are displayed.
The lower 2 digits on the display indicate the alarm number that has occurred or the parameter number in error.
Display example are shown below.

Name	Display	Description
Current alarm		Indicates on occurrence of an alarm.
		Indicates that overvoltage (A.33) occurred. Flickers at alarm occurrence.
Alarm history		Indicates that the last alarm is overload (A.50).
		Indicates that the second alarm in the past is overvoltage (A.33).
		Indicates that the third alarm in the past is undervoltage (A.10).
		Indicates that the fourth alarm in the past is undervoltage (A.10).
		Indicates that the fifth alarm in the past is undervoltage (A.10).
		Indicates that the sixth alarm in the past is overload (A.50).
Parameter error No.		Indicates no occurrence of parameter error (A.37).
	 ↕Displayed alternately 	Indicates that the data of parameter No.PA01 is faulty.

Functions at occurrence of an alarm

(1) Any mode screen displays the current alarm.

(2) The other screen is visible during occurrence of an alarm. At this time, the decimal point in the third digit flickers.

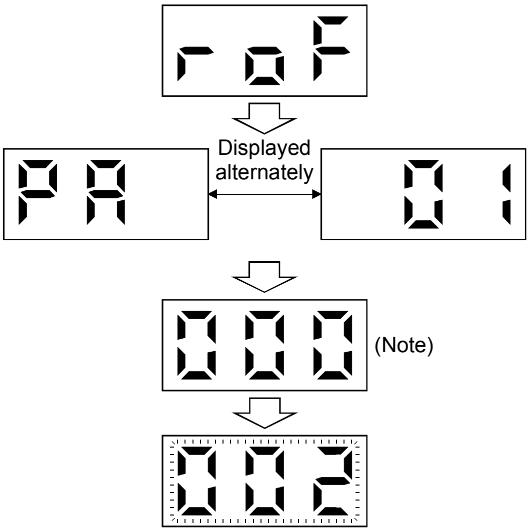
(3) To clear any alarm, switch power off, then on or press the "SET" button on the current alarm screen. Note that this should be done after removing the case of the alarm.

15.4.5 Parameter mode

POINT

- The display section of the converter unit has three digits. When a parameter No. is displayed, parameter group and parameter No. are displayed alternately. When, for example, "PA01" is displayed, PA and 01 are displayed alternately.

The following example gives the operation procedure after power-on for use of the regenerative options (MR-RB137).



◉
Press MODE three time
······· The parameter number is displayed.
For parameter No.PA01, “PA” and “01” are displayed alternately.

◉ ◉
Press UP or DOWN to change the number.

◉
Press MODE twice
······· The set value of the specified parameter number flickers.
In this case, the lower three digits “0000” of the set value “0000” are displayed.

◉
Press MODE once
······· During flickering, the set value can be change.

◉ ◉
Use UP or DOWN .
(□□□2: MR-RB137 (3 pcs.) are used.)

◉
Press SET to enter.

Note. If the "MODE" button is pressed when the lower three digits of the four digits "0000" are displayed, the fourth digit "0000" is displayed as - 0 . However, do not change the setting of the fourth digit. Press the "MODE" button again to reset the display to the lower three digits 000 .

To shift to the next parameter, press the "UP"/"DOWN" button.
When changing the parameter No.PA01 setting, change its set value, then switch power off once and switch it on again to make the new value valid.

15.5. Parameters for converter unit

⚠CAUTION

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

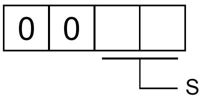
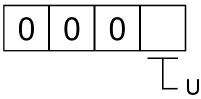
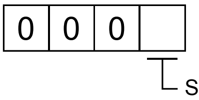
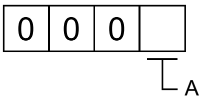
POINT

- Refer to chapter 5 for parameters for drive unit.
- The parameter whose symbol preceded by * can be validated with the following conditions:
  - * : Turn off the power and then on again, or reset the controller after setting the parameter.
- Never change parameters for manufacturer setting.

15.5.1 Parameter list

No.	Symbol	Name	Initial value	Unit
PA01	*REG	Regenerative option	0000h	
PA02	*MCC	Magnetic contactor drive output selection	0001h	
PA03		For manufacturer setting	0001h	
PA04			0	
PA05			100	
PA06			0	
PA07			100	
PA08	*DMD	Status display selection	0000h	
PA09	*BPS	Alarm history clear	0000h	
PA10		For manufacturer setting	0	
PA11			0000h	
PA12	*DIF	Input filter setting	0002h	
PA13		For manufacturer setting	0000h	
PA14			0000h	
PA15			0000h	
PA16			0000h	
PA17			0000h	
PA18			0000h	
PA19			0000h	

15.5.2 List of details

No.	Symbol	Name and function	Initial value	Unit	Setting range
PA01	*REG	Regenerative option Used to select the regenerative option.  Select the regenerative option. 00: No used 01: MR-RB139 02: MR-RB137(3 pcs.) } Only for MR-J3-CR55K 11: MR-RB136-4 12: MR-RB138-4(3 pcs.) } Only for MR-J3-CR55K4 "01" and "02" are the set values for the MR-J3-CR55K only, and "11" and "12" are those for the MR-J3-CR55K4 only. Incorrect setting will result in parameter alarm (A.37).	0000h		Refer to Name and function column.
PA02	*MCC	Magnetic contactor drive output selection Used to select the output of the magnetic contactor drive power supply.  Used to select the output of the magnetic contactor drive power supply. 0: No used 1: Used	0001h		Refer to Name and function column.
PA03		For manufacturer setting	0001h		
PA04		Do not change this value by any means.	0		
PA05			100		
PA06			0		
PA07			100		
PA08	*DMD	Status display selection Used to select the status display shown at power-on.  Status display of converter unit display section at power-on. 0: Status 1: Bus voltage 2: Effective load ratio 3: Peak load ratio 4: Regenerative load ratio	0000h		Refer to Name and function column.
PA09	*BPS	Alarm history clear Used to clear the alarm history.  Alarm history clear 0: Invalid 1: Valid When alarm history clear is made valid, the alarm history is cleared at next power-on. After the alarm history is cleared, the setting is automatically made invalid (reset to 0).	0000h		Refer to Name and function column.
PA10		For manufacturer setting	0		
PA11		Do not change this value by any means.	0000h		

No.	Symbol	Name and function	Initial value	Unit	Setting range
PA12	*DIF	Input filter setting Select the input filter. 0 0 0 □ └ Input signal filter If external input signal causes chattering due to noise, etc., input filter is used to suppress it. 0: None 1: 1.777[ms] 2: 3.555[ms] 3: 5.333[ms]	0002h		Refer to Name and function column.
PA13		For manufacturer setting Do not change this value by any means.	0000h		
PA14			0000h		
PA15			0000h		
PA16			0000h		
PA17			0000h		
PA18			0000h		
PA19			0000h		

15.6 Troubleshooting

15.6.1 Converter unit

(1) Alarms and warning list

When an error occurs during operation, the corresponding alarm or warning is displayed. If any alarm or warning has occurred, refer to (2) or (3) in this section and take the appropriate action.

Switch power off, then on to deactivate the alarm. The alarms marked "○" in the alarm deactivation column of the table can be deactivated by pressing the "RES" key of the converter unit side parameter unit or switching on the reset signal (RES).

	Display	Name	Alarm deactivation	
			Power OFF→ON	Error reset
Alarm	A.10	Undervoltage	○	○
	A.12	Memory error 1 (RAM)	○	
	A.15	Memory error 2 (EEP-ROM)	○	
	A.17	Board error	○	
	A.19	Memory error 3 (Flash-ROM)	○	
	A.30	Regenerative error	(Note)○	(Note) ○
	A.33	Over voltage	○	○
	A.37	Parameter error	○	
	A.38	MC drive circuit error	○	
	A.39	Open phase	○	
	A.3A	Inrush current suppressor circuit error	○	
	A.45	Main circuit device overheat	(Note) ○	(Note) ○
	A.47	Cooling fan error	○	
	A.50	Overload 1	(Note) ○	(Note) ○
	A.51	Overload 2	(Note) ○	(Note) ○
	888	Watchdog	○	

	Display	Name
Warning	A.91	Overheat warning
	A.E0	Excessive regenerative load warning
	A.E1	Overload warning
	A.E6	Converter forced stop warning
	A.E8	Cooling fan speed reduction warning

Note. Deactivate the alarm about 30 minutes of cooling time after removing the cause of occurrence.

(2) Remedies for alarms

⚠CAUTION

- When any alarm has occurred, eliminate its cause, ensure safety, then reset the alarm, and restart operation. Otherwise, injury may occur.

POINT

- When any of the following alarms has occurred, always remove its cause and allow about 30 minutes for cooling before resuming operation. If operation is resumed by switching control circuit power off, then on to reset the alarm, the converter unit and regenerative option may become faulty.
    - Regenerative error (A.30)
    - Overload 1 (A.50)
    - Overload 2 (A.51)
    - Main circuit device overheat (A.45)
- The alarm can be deactivated by switching the power off, then on. Refer to (1) in this section for details.

When an alarm occurs, the trouble (ALM) signal switches off and the display section shows the alarm number. Remove the cause of the alarm in accordance with this section.

Display	Name	Definition	Cause	Action
A.10	Undervoltage	Power supply voltage dropped.	1. Instantaneous control power failure occurred for longer than 60ms.	Review the power supply.
			2. Shortage of power supply capacity caused the power supply voltage to drop at start, etc.	
			3. Failure of the part in the converter unit. Checking method Alarm (A.10) occurs if power is switched on after connectors disconnected.	Change the Converter unit.
A.12	Memory error 1 (RAM)	RAM memory fault	Failure of the part in the converter unit. Checking method Alarm (A.12) occurs if power is switched on after connectors disconnected.	Change the converter unit.
A.15	Memory error 2 (EEP-ROM)	EEP-ROM fault	1. Failure of the part in the converter unit. Checking method Alarm (A.15) occurs if power is switched on after connectors disconnected.	Change the converter unit.
			2. The number of write times to EEP-ROM exceeded 100,000.	
A.17	Board error	CPU/parts fault	Failure of the part in the converter unit. Checking method Alarm (A.17/A.19) occurs if power is switched on after connectors disconnected.	Change the converter unit.
A.19	Memory error 3 (Flash-ROM)	ROM memory fault		

Display	Name	Definition	Cause	Action
A.30	Regenerative error	Permissible regenerative power of regenerative option is exceeded.	1. Incorrect setting of parameter No.PA01.	Set correctly.
			2. Regenerative option is not connected.	Connect correctly.
			3. High-duty operation or continuous regenerative operation caused the permissible regenerative power of the regenerative option to be exceeded. Checking method Call the status display or MR Configurator and check the regenerative load ratio.	1. Reduce the frequency of positioning. 2. Use the regenerative option of larger capacity. 3. Reduce the load.
			4. Power supply voltage is abnormal. MR-J3-CR55K: 260VAC or more MR-J3-CR55K4: 520VAC or more	Review power supply
			5. Regenerative option faulty.	Change regenerative option.
			6. Ground fault occurred in servo motor power (U, V, W).	Correct the wiring.
		Regenerative transistor fault	7. Regenerative transistor faulty. Checking method 1) The regenerative option has overheated abnormally. 2) The alarm occurs even after removal of the built-in regenerative resistor or regenerative option.	Change the converter unit.
A.33	Over voltage	Converter bus voltage exceeded to following voltage. MR-J3-CR55K: 400VDC MR-J3-CR55K4: 800VDC	1. Regenerative option is not used.	Use the regenerative option.
			2. Though the regenerative option is used, the parameter No.PA01 setting is "□□00 (not used)".	Set correctly.
			3. Lead of regenerative option is open or disconnected.	1. Change lead. 2. Connect correctly.
			4. Regenerative transistor faulty.	Change the converter unit.
			5. Wire breakage of regenerative option.	Change the regenerative option.
			6. Capacity of regenerative option is insufficient.	Add regenerative option or increase capacity.
			7. Power supply voltage high.	Review the power supply.
			8. Ground fault occurred in servo motor power (U, V, W).	Correct the wiring.
			9. Impedance at main circuit power supply cable (L_1, L_2, L_3) is high, and leak current from servo motor power supply cable (U, V, W) is large.	Use the regenerative option.
A.37	Parameter error	Parameter setting is incorrect.	1. Converter unit fault caused the parameter setting to be rewritten.	Change the converter unit.
			2. Regenerative option not used with converter unit was selected in parameter No.PA02.	Set parameter No.PA01 correctly.
			3. The number of write times to EEP-ROM exceeded 100,000 due to parameter write, etc.	Change the converter unit.

Display	Name	Definition	Cause	Action
A.38	MC drive circuit error	Magnetic contactor drive circuit error (When the magnetic contactor is turned on: the main circuit power supply is not turned on within two seconds after the servo-on of the drive unit. When the magnetic contactor is opened: the main circuit power supply is turned on although the magnetic contactor is opened.)	1. Incorrect connection of the magnetic contactor.	Review the wiring.
			2. Parameters specifying whether to use/not use the magnetic contactor do not match the configuration.	Set parameter No.PA02 correctly.
			3. Magnetic contactor failed.	Change the magnetic contactor.
			4. Magnetic contactor drive circuit faulty. Checking method Check the output of magnetic contactor control connector (CNP1) . Power supply voltage is applied to this connector. Take care to avoid an electric shock at connecting.	Change the converter unit.
			5. Mismatch of an external sequence.	Review the power-on sequence. (Refer to section 3.3.2.)
A.39	Open phase	Power supply error	1. Any of L_1, L_2 and L_3 is disconnected. Or, open.	Review the wiring.
			2. Failure of the part in the converter unit.	Change the converter unit.
A.3A	Inrush current suppressor circuit error	Inrush current suppressor circuit error	1. Power-on/off was repeated with high frequency.	Review operation pattern.
			2. Inrush current suppressor resistance overheated.	Change the converter unit.
			3. Inrush current suppressor circuit faulty.	
A.45	Main circuit device overheat	Main circuit device overheat.	1. The power supply was turned on and off continuously by overloaded status.	Review operation pattern.
			2. Ambient temperature of converter unit is over 55℃.	Review environment so that ambient temperature is 0 to 55℃.
			3. Converter unit faulty.	Change the converter unit.
A.47	Cooling fan alarm	The cooling fan of the converter unit stopped, or its speed decreased to or below the alarm level.	1. Cooling fan life expiration. (Refer to section 2.5.)	Change the cooling fan of the converter unit.
			2. Foreign matter caught in the cooling fan stopped rotation.	Remove the foreign matter.
			3. The power supply of the cooling fan failed.	Change the converter unit.
A.50	Overload 1	Load exceeded overload protection characteristic of converter unit.	Converter unit is used in excess of its continuous output current.	1. Reduce load. 2. Review operation pattern.
A.51	Overload 2	Load exceeded overload protection characteristic of converter unit.	Converter unit is used in excess of its output current for a short time.	Review operation pattern of a drive unit.
(Note) 888	Watchdog	CPU/parts fault	Failure of the part in the converter unit. Checking method Alarm (888) occurs if power is switched on after connectors disconnected.	Change the converter unit.

Note. At power-on, "888" appears instantaneously, but it is not an error.

(3) Remedies for warnings

Continuing operation in an alarm occurrence status may result in an alarm or disable proper operation. Eliminate the cause of the warning according to this section. The warning displayed will disappear when the cause of its occurrence is resolved.

Display	Name	Definition	Cause	Action
A.91	Overheat warning	The temperature of the heat sinks exceeded the warning level.	1. Operated in the overloaded status.	Review operation pattern.
			2. Ambient temperature of converter unit is over 55℃.	Review environment so that ambient temperature is 0 to 55℃.
			3. Converter unit faulty.	Change the converter unit.
A.E0	Excessive regenerative load warning	There is a possibility that regenerative power may exceed permissible regenerative power of regenerative option.	Regenerative power increased to 85% or more of permissible regenerative power of regenerative option. Checking method Call the status display or MR Configurator and check the regenerative load ratio.	1. Reduce frequency of positioning. 2. Change regenerative option for the one with larger capacity. 3. Reduce load.
A.E1	Overload warning	There is a possibility that overload alarm 1 or 2 may occur.	Load increased to 85% or more of overload alarm 1 or 2 occurrence level. Cause, checking method Refer to A.50, 51.	Refer to A.50, A.51.
A.E6	Converter forced stop warning	EM1 is off.	External forced stop was made valid. (EM1 was turned off.)	Ensure safety and deactivate forced stop.
A.E8	Cooling fan speed reduction warning	The speed of the converter unit cooling fan decreased to or below the warning level.	1. Cooling fan life expiration. (Refer to section 2.5.)	Change the cooling fan of the converter unit.
			2. The power supply of the cooling fan failed.	Change the converter unit.

(4) Clearing the alarm history

You can clear the alarm numbers stored in the alarm history of the alarm mode. To ensure that you can control the alarms that will occur after regular operation, make this setting before starting regular operation to clear the alarm history.

After setting "0001" in parameter No.PA09, switch power off once. Switching it on again clears the alarm history. At this time, the parameter No.PA09 setting returns to "0000".

15.6.2 Drive unit

POINT

- Explanation made in this section is exclusively for the driver unit.
  Other troubleshooting is the same as that for servo amplifiers with 22kW or less.
  Refer to chapter 9.
- As soon as an alarm occurs, make the Servo off status and interrupt the main circuit power.

(1) Alarms and warning list

When an error occurs during operation, the corresponding alarm or warning is displayed. If any alarm or warning has occurred, refer to (2) or (3) in this section and take the appropriate action. When an alarm occurs, the ALM turns OFF.

After its cause has been removed, the alarm can be deactivated in any of the methods marked in the alarm deactivation column. The alarm is automatically canceled after removing the cause of occurrence.

	Display	(Note)Alarm code			Name	Alarm deactivation		
		CN1 22 (bit 2)	CN1 23 (bit 2)	CN1 24 (bit 0)		Power OFF → ON	Error reset	CPU reset
Alarms	AL.1B	0	1	0	Converter alarm	○	○	○

	Display	Name
Alarms	AL.9C	Converter warning
	AL.E9	Main circuit off warning

Note. 0: OFF
1: ON

(2) Remedies for alarms

⚠CAUTION

- When any alarm has occurred, eliminate its cause, ensure safety, then reset the alarm, and restart operation. Otherwise, injury may occur.
- As soon as an alarm occurs, mark servo-off and power off the main circuit and control circuit.

POINT

- The alarm can be deactivated by switching power off, then on. For details, refer to (1) in this section.

If an alarm occurs, the trouble (ALM) turns off and alarm number is displayed in the display area.
The servo motor comes to a stop. Remove the cause of the alarm in accordance with this section. MR Configurator may be used to refer to the cause the alarm.

Display	Name	Definition	Cause	Action
AL.1B	Converter alarm	An alarm occurred in the converter unit during servo on.	1. An alarm occurred in the converter unit during servo on.	Check the alarm of the converter unit, and take the action following the remedies for alarms of the converter unit. (Refer to section 15.6.1 (2).)
			2. The protection coordination cable or terminal connector is not correctly connected.	Connect correctly.

(3) Remedies for warnings

Continuing operation in an alarm occurrence status may result in an alarm or disable proper operation. Eliminate the cause of the warning according to this section. The warning displayed will disappear when the cause of its occurrence is resolved.

Indication	Name	Definition	Cause	Action
AL.9C	Converter warning	A warning occurred in the converter unit during the servo-on command.		Check the warning of the converter unit, and take the action following the remedies for warnings of the converter unit. (Refer to section 15.6.1 (3).)
AL.E9	Main circuit off warning	The forced stop of the converter unit is made valid during the servo-on command.	1. The forced stop of the converter unit is made valid.	Deactivate the forced stop of the converter unit.
			2. The protection coordination cable or terminal connector is not correctly connected.	Connect correctly.

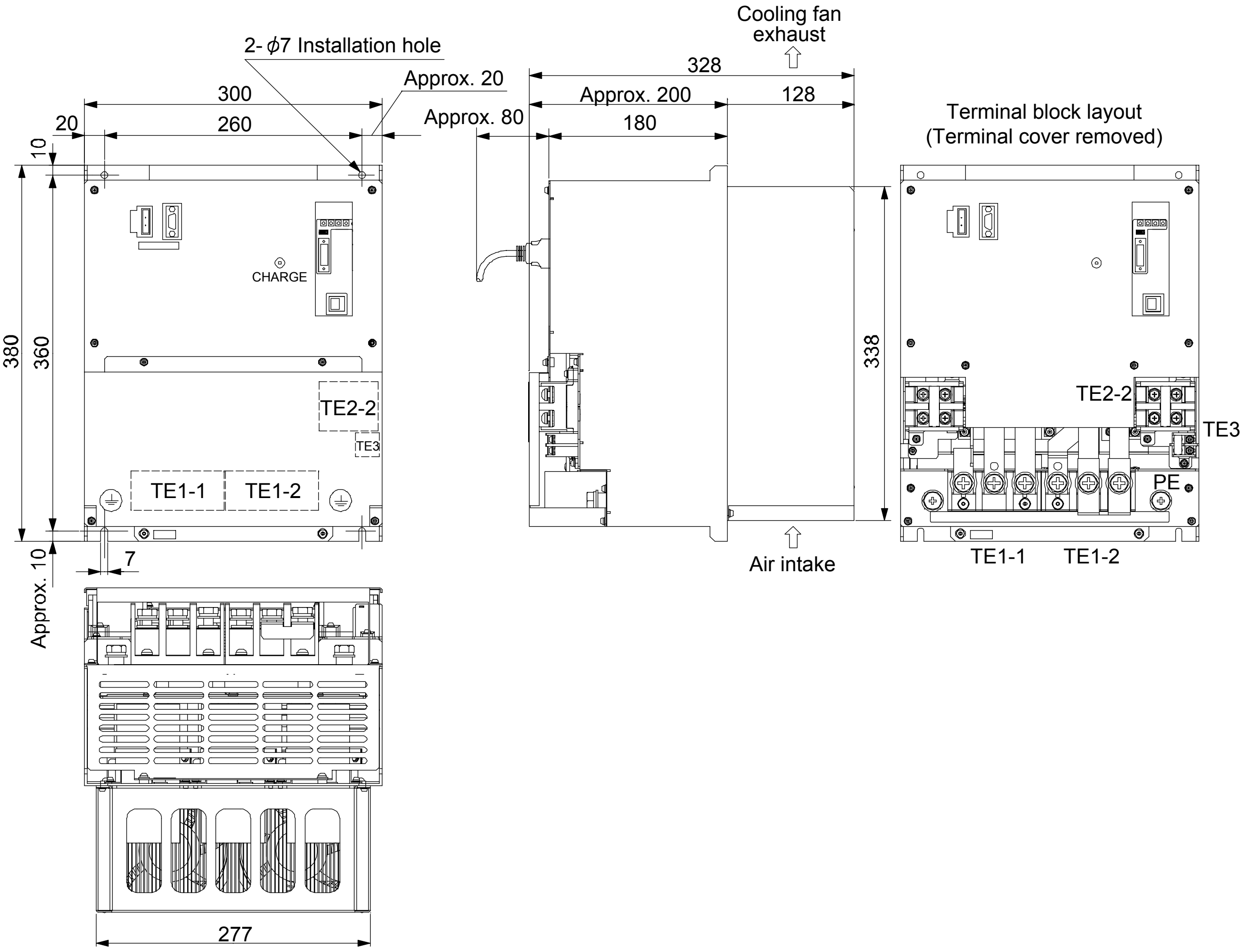
15.7 Outline drawings

POINT

- Refer to section 15.2.1 for outline dimension drawing.

15.7.1 Converter unit (MR-J3-CR55K(4))

[Unit: mm]



Mass: 25[kg] (55.2[lb])

Terminal block signal layout

TE2-2

L+
L−

Terminal block screw: M6
Tightening torque: 3.0 [N•m]
(26.6 [lb•in])

TE3

L_{11}
L_{21}

Terminal block screw: M4
Tightening torque: 1.2 [N•m]
(10.6 [lb•in])

TE1-1

L_1	L_2	L_3

Terminal block screw: M10
Tightening torque: 10.0 [N•m]
(88.5 [lb•in])

TE1-2

C	P2	P1

Terminal block screw: M10
Tightening torque: 10.0 [N•m]
(88.5 [lb•in])

PE

⏚	⏚

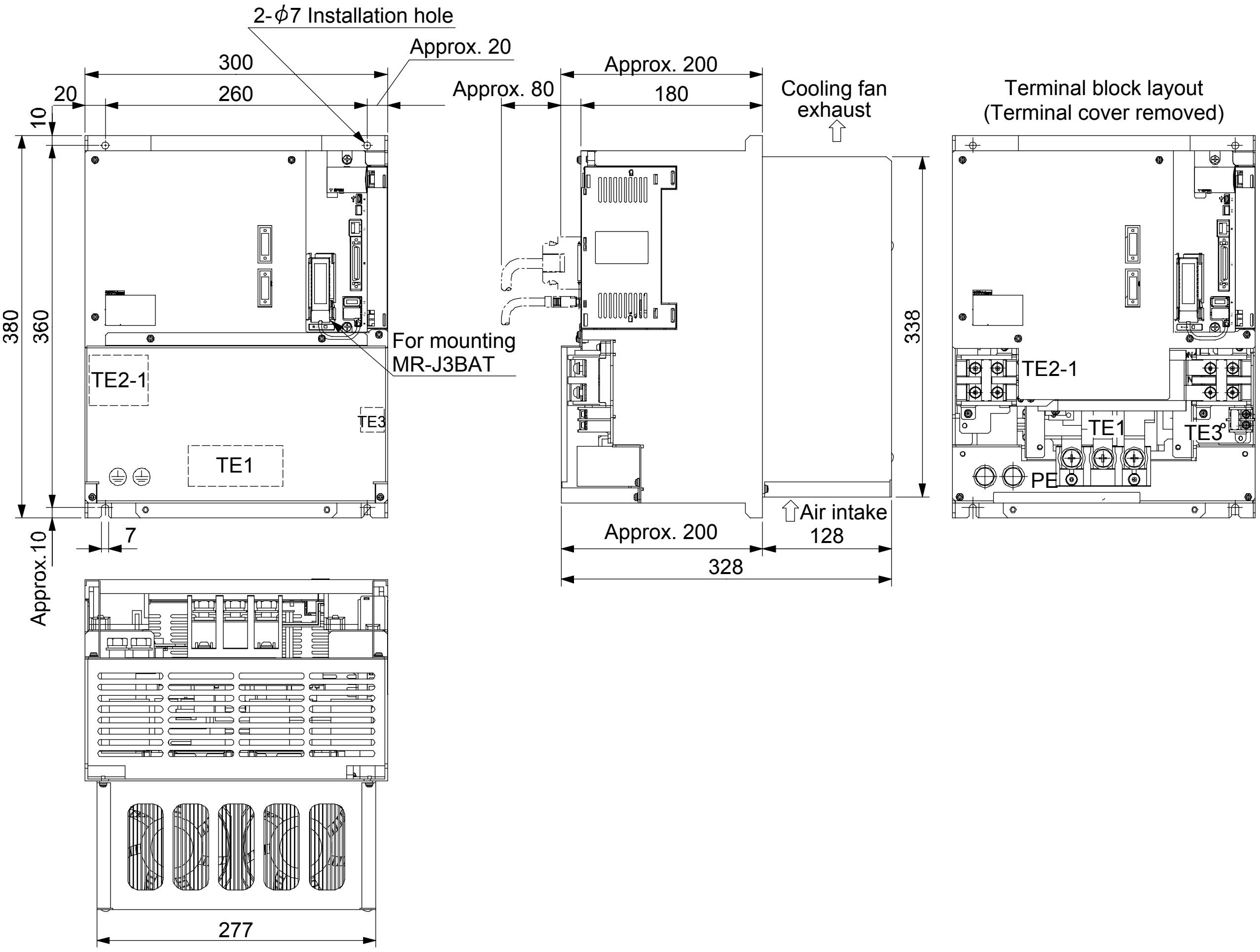
Terminal block screw: M10
Tightening torque: 10.0 [N•m]
(88.5 [lb•in])

Mounting screw
Screw size: M6
Tightening torque: 5.4 [N•m]
(47.8 [lb•in])

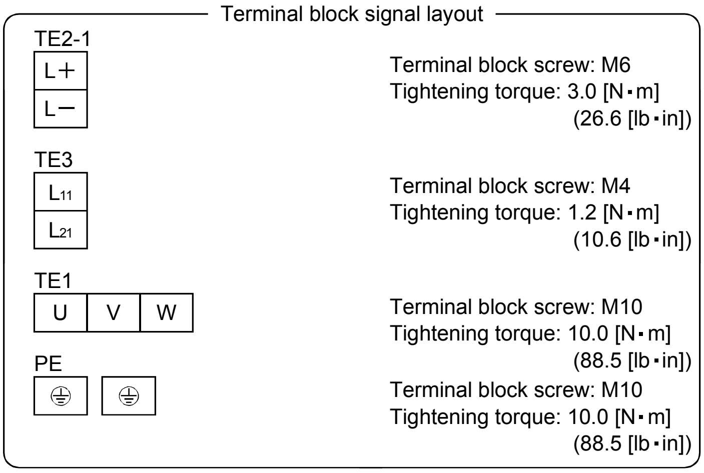
15.7.2 Drive unit

(1) MR-J3-DU30KA・MR-J3-DU37KA
MR-J3-DU45KA4・MR-J3-DU55KA4

[Unit: mm]



Mass: 26[kg] (57.3[lb])



TE2-1: Terminal block screw: M6
Tightening torque: 3.0 [N・m] (26.6 [lb・in])

TE3: Terminal block screw: M4
Tightening torque: 1.2 [N・m] (10.6 [lb・in])

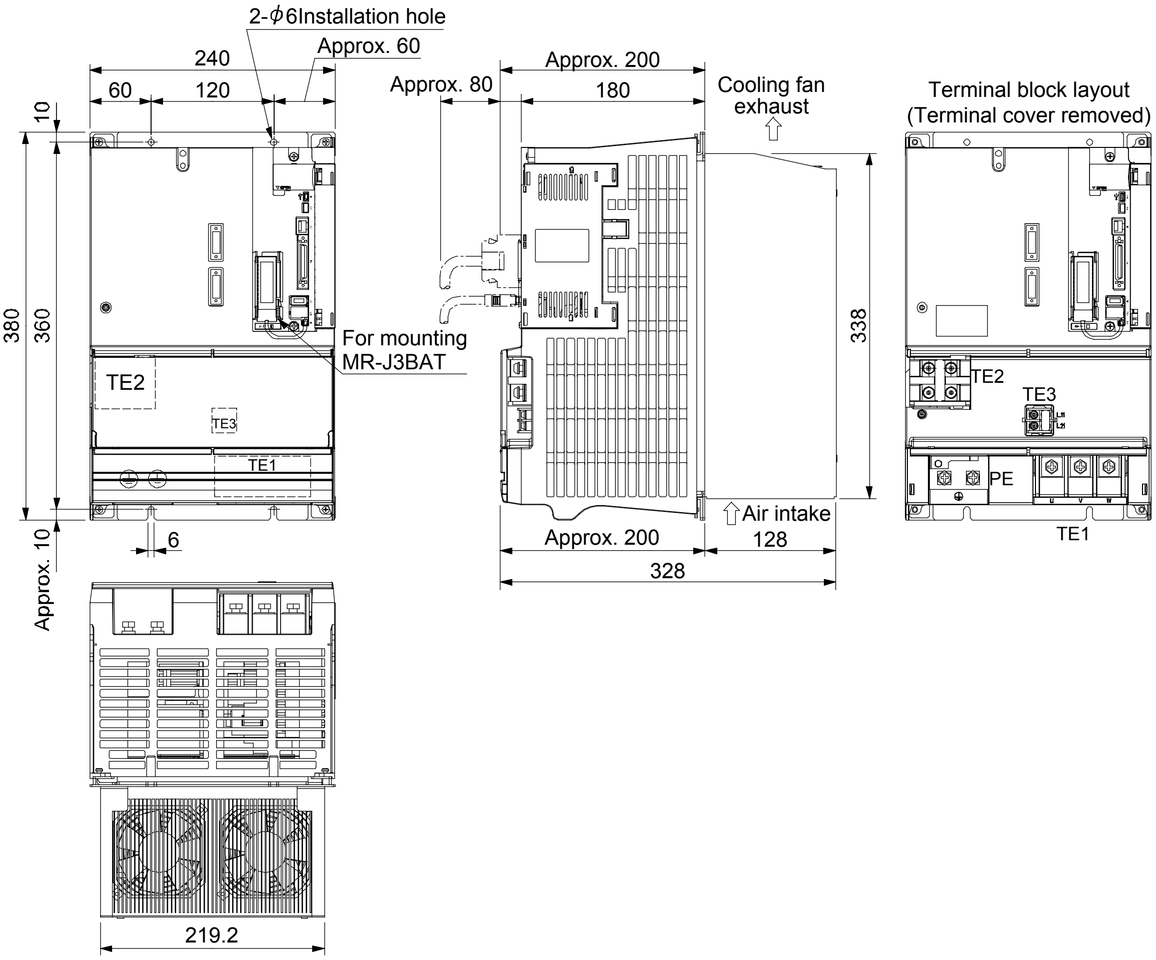
TE1: Terminal block screw: M10
Tightening torque: 10.0 [N・m] (88.5 [lb・in])

PE: Terminal block screw: M10
Tightening torque: 10.0 [N・m] (88.5 [lb・in])

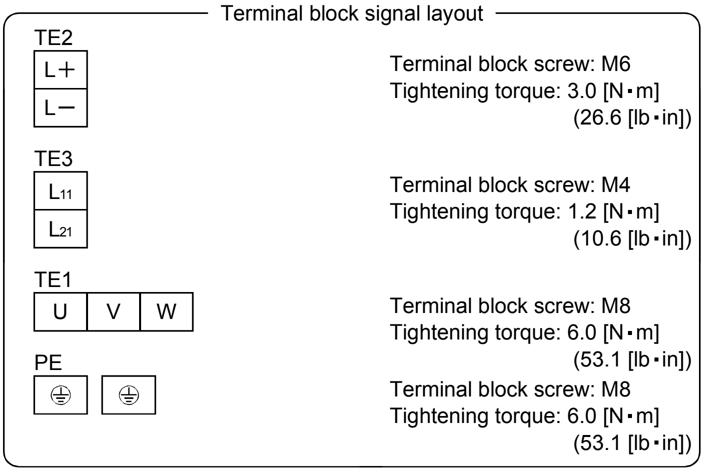
Mounting screw
Screw size: M6
Tightening torque: 5.4 [N・m] (47.8 [lb・in])

(2) MR-J3-DU30KA4 · MR-J3-DU37KA4

[Unit: mm]



Mass: 18[kg] (39.7[lb])



Terminal block screw: M6
Tightening torque: 3.0 [N·m]
(26.6 [lb·in])

Terminal block screw: M4
Tightening torque: 1.2 [N·m]
(10.6 [lb·in])

Terminal block screw: M8
Tightening torque: 6.0 [N·m]
(53.1 [lb·in])

Terminal block screw: M8
Tightening torque: 6.0 [N·m]
(53.1 [lb·in])

Mounting screw
Screw size: M5
Tightening torque: 3.24 [N·m]
(28.3 [lb·in])

15.8 Characteristics

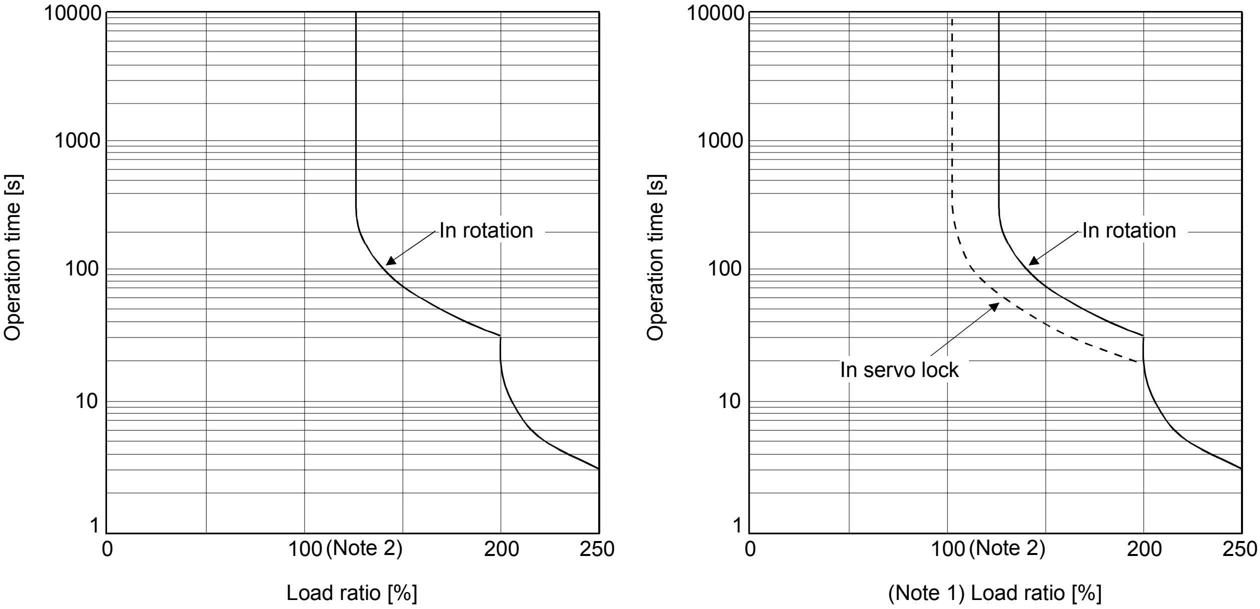
15.8.1 Overload protection characteristics

An electronic thermal relay is built in the converter unit and drive unit to protect the servo motor, converter unit, drive unit and servo motor power line from overloads.

Overload 1 alarm (AL.50) occurs if overload operation performed is above the electronic thermal relay protection curve shown below. Overload 2 alarm (AL.51) occurs if the maximum current flew continuously for several seconds due to machine collision, etc. Use the equipment on the left-hand side area of the continuous or broken line in the graph.

It is recommended to use the machine which generates unbalanced torque, e.g. a vertical lift application, so that the unbalanced torque is not more than 70% of the rated torque.

Servo amplifier MR-J3 series has solid-state servo motor overload protection. (The motor full load current is 115% rated current.)



Converter unit

Drive unit

Note 1. If operation that generates torque more than 100% of the rating is performed with an abnormally high frequency in a servo motor stop status (servo lock status) or in a 30r/min or less low-speed operation status, the drive unit may fail even when the electronic thermal relay protection is not activated.

2. Load ratio 100% indicates the rated output of each converter unit and drive unit. Refer to section 15.1.4 for rated output.

Fig. 15.1 Overload protection characteristics

15.8.2 Power supply equipment capacity and generated loss

POINT

- The calculation method of heat dissipation area for enclosed control panel is the same as that for servo amplifiers with 22kW or less. Refer to section 11.2 (2).

Table 15.1 indicates the generated loss and power supply capacity under rated load per combination of the converter unit and drive unit. When the servo motors is run at less than the maximum speed, the power supply equipment capacity is lower than the value in the table but the heat generated does not change.
Since the servo motor requires 2 to 2.5 times greater instantaneous power for acceleration, use the power supply which ensures that the voltage lies within the permissible voltage fluctuation at the main circuit power supply terminals (L_1, L_2, L_3) of the converter unit. The power supply equipment capacity changes with the power supply impedance.
The actually generated heat falls within the ranges at rated torque and at zero torque according to the frequencies of use during operation. When designing an enclosed control box, use the values in the table, considering the worst operating conditions. The generated heat in Table 15.1 does not include heat produced during regeneration.

Table 15.1 Power supply capacity and generated heat per servo amplifier at rated output

Converter unit	Drive unit	Servo motor	Power supply capacity [kVA]		(Note) Drive unit-generated heart[W]		Area required for heat dissipation [m^2]
			Power factor improving DC reactor is not used	Power factor improving DC reactor is used	At rated torque	At zero torque	
MR-J3-CR55K	MR-J3-DU30KA	HA-LP30K1 HA-LP30K1M HA-LP30K2	48	40	1550(1100＋450)	60 (30＋30)	31.0
	MR-J3-DU37KA	HA-LP37K1 HA-LP37K1M HA-LP37K2	59	49	1830(1280＋550)		36.6
MR-J3-CR55K4	MR-J3-DU30KA4	HA-LP25K14	40	35	1080(850＋230)		21.6
		HA-LP30K14 HA-LP30K1M4 HA-LP30K24	48	40	1290(1010＋280)		25.8
	MR-J3-DU37KA4	HA-LP37K14 HA-LP37K1M4 HA-LP37K24	59	49	1542(1200＋342)		30.8
	MR-J3-DU45KA4	HA-LP45K1M4 HA-LP45K24	71	59	1810(1370＋440)		36.2
	MR-J3-DU55KA4	HA-LP50K1M4	80	67	2120(1650＋470)		42.4
		HA-LP55K24	87	72	2150(1650＋500)		43.0

Note. The heat generated by the drive unit is indicated in the left term within the parentheses, and the heat generated by the converter unit in the right term.

15.8.3 Dynamic brake characteristics

POINT

- Dynamic brake operates at occurrence of alarm, servo emergency stop warning (AL.E6), and when power is turned off. Do not use dynamic brake to stop in a normal operation as it is the function to stop in emergency.
- Maximum usage time of dynamic brake for a machine operating under recommended load inertia moment ratio is 1000 time while decelerating from rated speed to a stop with frequency of once in 10 minutes.
- Be sure to make emergency stop (EMG・EM1) valid after servo motor stops when using emergency stop (EMG・EM1) frequently in other than emergency.

(1) Dynamic brake operation

(a) Calculation of coasting distance

Fig. 15.2 shows the pattern in which the servo motor comes to a stop when the dynamic brake is operated. Use Equation 15.1 to calculate an approximate coasting distance to a stop. The dynamic brake time constant τ varies with the servo motor and machine operation speeds. (Refer to (b). Please contact your local sales office for the servo motor not indicated.)

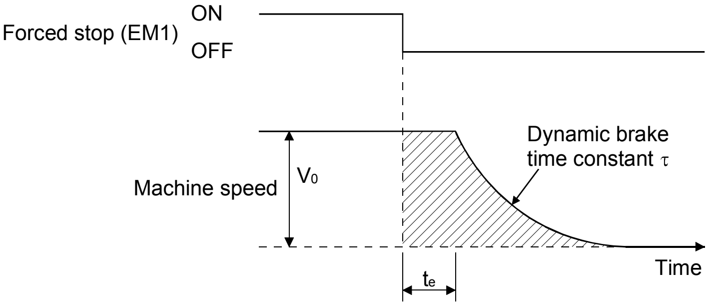


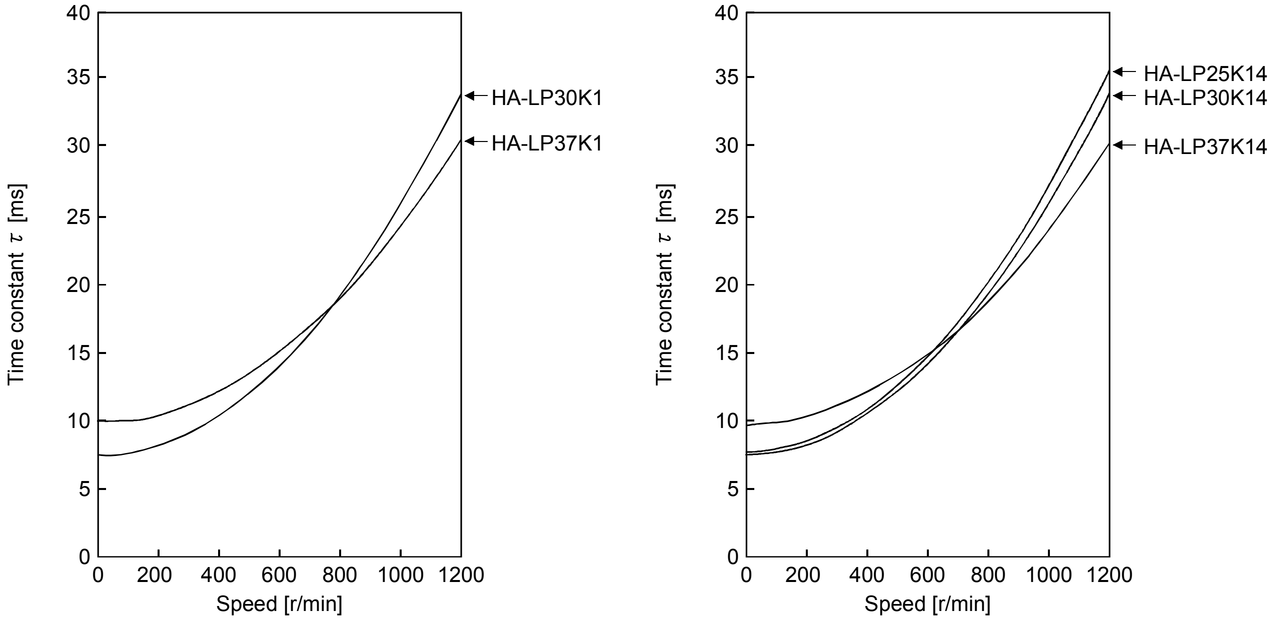
Fig 15.2 Dynamic Brake Operation Diagram

$$L_{max} = \frac{V_0}{60} \cdot \left\{ t_e + \tau \left(1 + \frac{J_L}{J_M} \right) \right\} \quad \cdots\cdots (15.1)$$

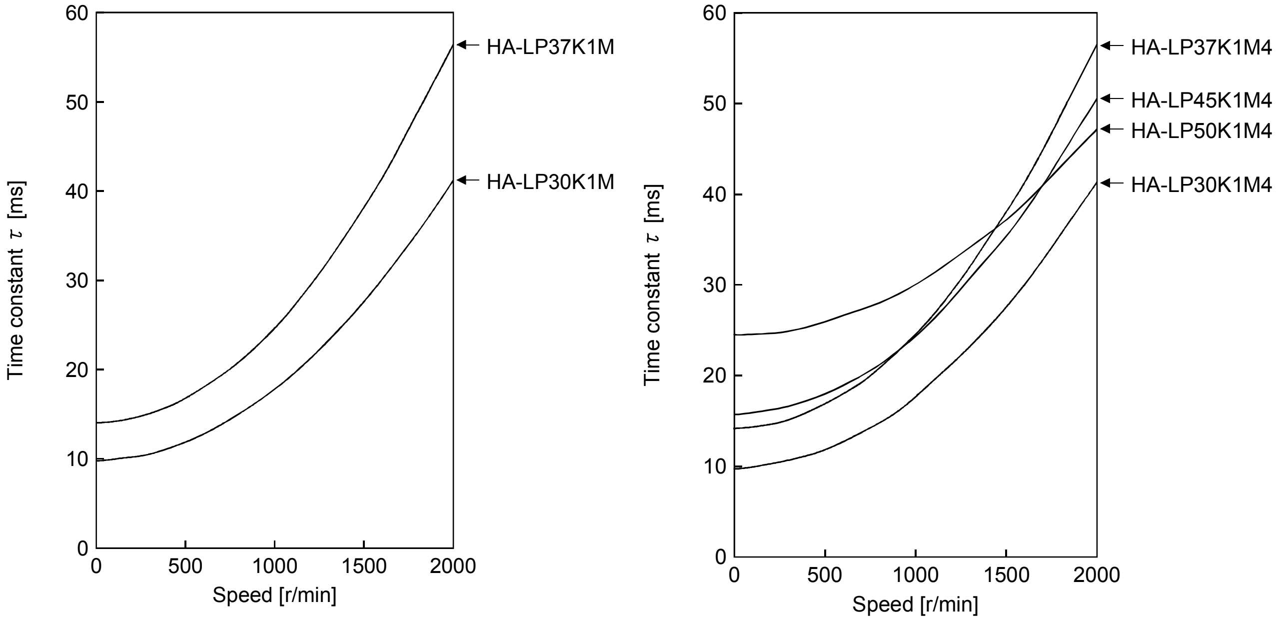
L_{max} : Maximum coasting distance ······ [mm]
V_0 : Machine rapid feed rate ······ [mm/min][in/min]
J_M : Servo motor inertial moment ······ [kg・cm^2][oz・in^2]
J_L : Load inertia moment converted into equivalent value on servo motor shaft ······ [kg・cm^2][oz・in^2]
τ : Dynamic brake time constant ······ [s]
t_e : Delay time of control section ······ [s]
There is delay caused by magnetic contactor built into the external dynamic brake (about 50ms) and delay caused by the external relay.

(b) Dynamic brake time constant

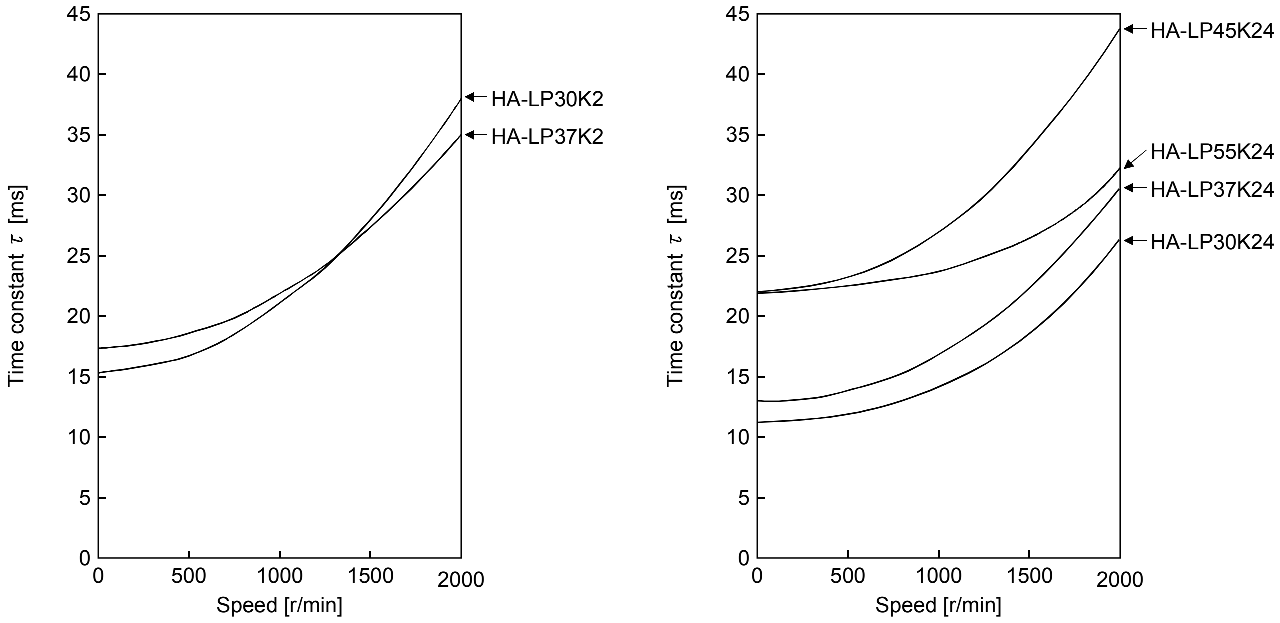
The following shows necessary dynamic brake time constant τ for the equations (15.1).



HA-LP1000r/min series



HA-LP1500r/min series



HA-LP2000r/min series

(2) Load to motor inertia moment ratio when using the dynamic brake

Use the dynamic brake under the load to motor inertia moment ratio indicated in the following table. If the load to motor inertia moment is higher than this value, the dynamic brake may burn. If there is a possibility that the load to motor inertia moment may exceed the value, contact your local sales office.

The values of the load inertia moment ratio in the table are the values at the maximum rotation speed of the servo motor.

Drive unit	Load to motor inertia moment ratio [Multiplier (× 1)]
MR-J3-DU30KA(4)	10
MR-J3-DU37KA(4)	
MR-J3-DU45KA4	
MR-J3-DU55KA4	

15.8.4 Inrush currents at power-on of main circuit and control circuit

The following table indicates the inrush currents (reference data) that will flow when the maximum permissible voltage (200V class: 253VAC, 400V class: 528VAC) is applied at the power supply capacity of 2500kVA and the wiring length of 1m.

Converter unit	Drive unit	Inrush currents (A_{0-P})	
		Main circuit power supply (L_1, L_2, L_3)	Control circuit power supply (L_{11}, L_{21})
MR-J3-CR55K	MR-J3-DU30KA	163A (Attenuated to approx. 20A in 180ms)	18A (Attenuated to approx. 0A in 100ms)
	MR-J3-DU37KA		
MR-J3-CR55K4	MR-J3-DU30KA4	339A (Attenuated to approx. 20A in 70ms)	19A (Attenuated to approx. 0A in 60ms)
	MR-J3-DU37KA4		
	MR-J3-DU45KA4		
	MR-J3-DU55KA4		

Since large inrush currents flow in the power supplies, make sure to use no-fuse breakers and magnetic contactors. (Refer to section 15.9.5.)
When circuit protectors are used, it is recommended to use the inertia delay type that will not be tripped by an inrush current.

15.9 Options

⚠WARNING

- Before connecting any option or peripheral equipment, turn off the power and wait for 20 minutes or longer until the charge lamp turns off. Then, confirm that the voltage between L＋ and L− is safe with a voltage tester and others. Otherwise, an electric shock may occur. In addition, make sure to confirm from the front of the converter unit whether the charge lamp is off or not.

⚠CAUTION

- Use the specified auxiliary equipment and options. Unspecified ones may lead to a fault or fire.

POINT

- Explanations on the following item are the same as those for servo amplifiers with 22kW or less. Refer to the section below for details.
  - Cable/connector sets Refer to section 12.1.
  - Junction terminal block Refer to section 12.7.
  - MR Configurator Refer to section 12.8.
  - Battery Refer to section 12.9.
  - Relays Refer to section 12.15.
  - Surge absorbers Refer to section 12.16.
  - Radio noise filter (FR-BIF-(H)) Refer to section 12.17 (2) (e).

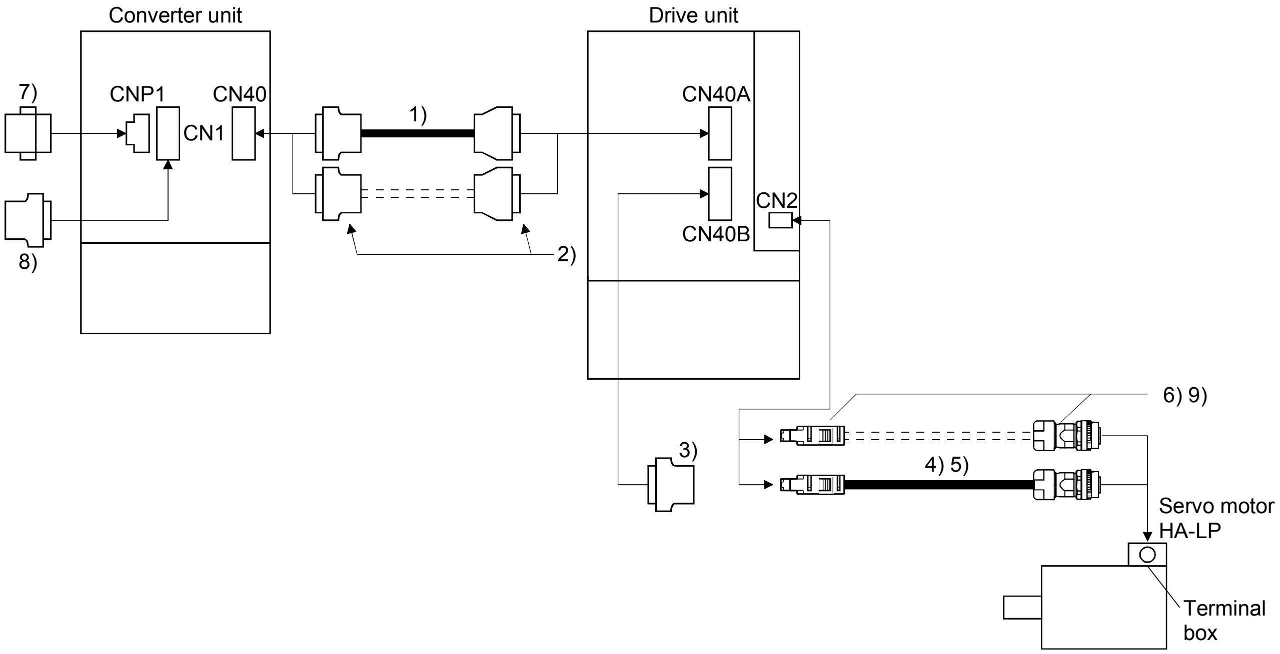
15.9.1 Cables and connectors

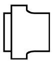
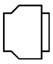
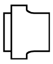
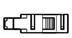
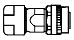
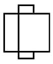
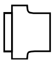
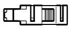
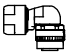
POINT

- Other connectors are the same as those for servo amplifiers with 22kW or less. Refer to section 12.1.

(1) Makeup of cables and like

The following shows the cable makeup for connection with the servo motor and other model.



No.	Product	Model	Description	Application
1)	Protection coordination cable	MR-J3CDL05M Refer to (2) in this section.	Connector: 10120-3000PE Shell kit: 10320-52F0-008 (3M or equivalent) Connector: PCR-S20FS+ Case: PCR-LS20LA1 (Honda Tsushin Kogyo) 	
2)	Connector set	MR-J2CN1-A Refer to (2) in this section.	Connector: 10120-3000PE Shell kit: 10320-52F0-008 (3M or equivalent) Connector: PCR-S20FS+ Shell kit: PCR-LS20LA1 (Honda Tsushin Kogyo) 	
3)	Termination connector	MR-J3-TM		
4)	Encoder cable	MR-J3ENSCBL□M-L Cable length: 2 · 5 · 10 · 20 · 30m		IP67 Standard life
5)	Encoder cable	MR-J3ENSCBL□M-H Cable length: 2 · 5 · 10 · 20 · 30 · 40 · 50m	For HA-LP series Refer to section 12.1.2 (4) for details.	IP67 Long flex life
6)	Encoder connector set	MR-J3SCNS	 For HA-LP series Refer to section 12.1.2 (4) for details.	IP67
7)	Magnetic contactor wiring connector		Converter unit side connector (Phoenix Contact) Socket: GFKC 2,5/2-STF-7,62 	Supplied with converter unit
8)	Digital I/O connector		Converter unit side connector (DDK) Connector: 17JE23090-02(D8A)K11-CG 	
9)	Encoder connector set	MR-J3SCNSA	 For HA-LP series Refer to section 12.1.2 (4) for details.	IP67

(2) MR-J3CDL05M(0.5m) Protection coordination cable

⚠CAUTION

- Connect protection coordination cables correctly if they are fabricated. Otherwise, the system may perform unexpected operation.

When fabricating a protection coordination cable, fabricate the cable as shown in the wiring diagram in this section.

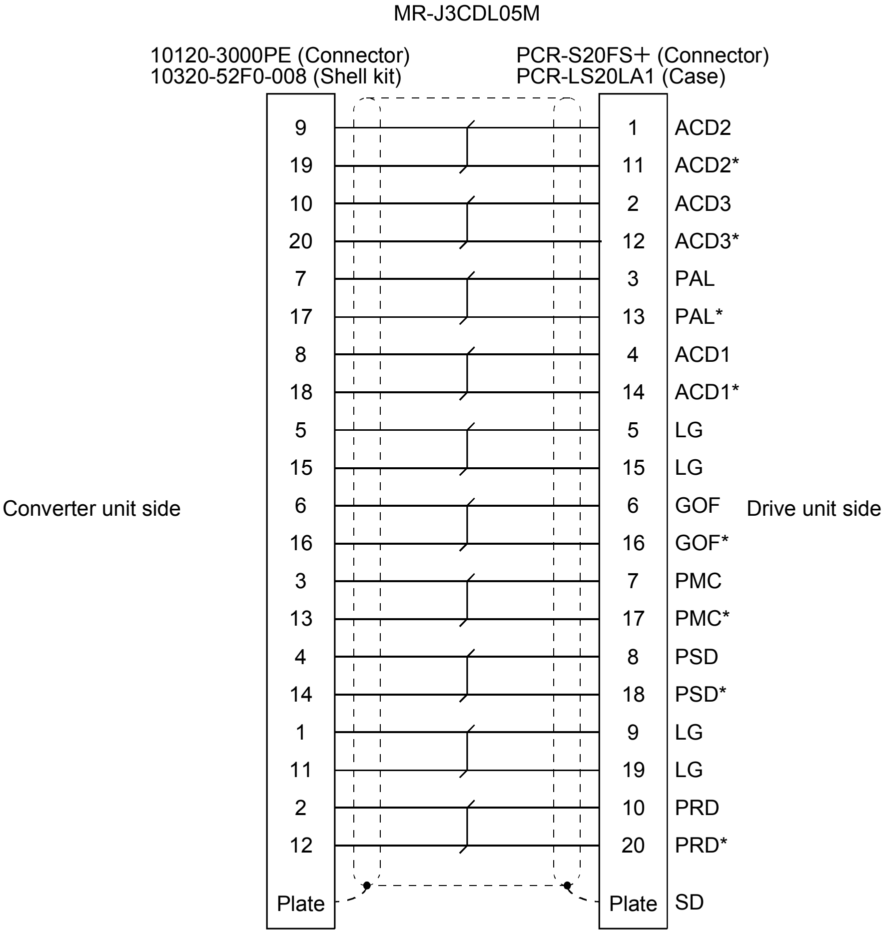
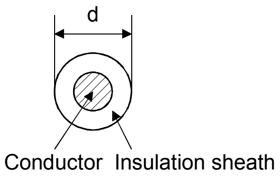


Table 15.2 Recommended wire

Model	Length [m(ft)]	Core size $[mm^2]$	Number of Cores	Characteristics of one core			(Note 2) Finishing OD [mm]	Wire model
				Structure [Wires/mm]	Conductor resistance [Ω/mm]	Insulation coating OD d[mm] (Note 1)		
MR-J3CDL05M	0.5 to 5 (1.64 to 16.4)	0.08	20 (10 pairs)	7/0.127	222	0.38	6.1	UL20276 AWG#28 10pair (CREAM)

Note 1. d is as shown below.



2. Standard OD. Max. OD is about 10% greater.

15.9.2 Regenerative option

⚠CAUTION

- The specified combinations of regenerative options, converter unit and drive unit may only be used. Otherwise, a fire may occur.

POINT

- The calculation method of regenerative energy is the same as that for servo amplifiers with 22kW or less. Refer to section 12.2 (2).

(1) Combination and regenerative power

The regenerative power values in the table are the regenerative power of the resistor and are not the rated power.

Converter unit	Drive unit	Regenerative power [W]			
		MR-RB139 (1.3Ω)	(Note 1) Three MR-RB137 (1.3Ω) in parallel	MR-RB136-4 (5Ω)	(Note 2) Three MR-RB138-4 (5Ω) in parallel
MR-J3-CR55K	MR-J3-DU30KA MR-J3-DU37KA	1300	3900		
MR-J3-CR55K4	MR-J3-DU30KA4 MR-J3-DU37KA4 MR-J3-DU45KA4 MR-J3-DU55KA4			1300	3900

Note. 1. The composite resistance value of three options is 1.3Ω. The resistance value of each is 4Ω.
2. The composite resistance value of three options is 5Ω. The resistance value of each is 15Ω.

(2) Parameter setting

POINT

- Make sure to set parameter No.PA02 of the drive unit to "□□00" (Not used) since the regenerative option cannot be connected to the drive unit.

When using the regenerative option, set the parameter of the converter unit. Match parameter No.PA01 to the regenerative option used.

Parameter No.PA01

0 0 □ □

Regenerative option selection
00: Not used
01: MR-RB139
02: MR-RB137 (3 pcs.)
11: MR-RB136-4
12: MR-RB138-4 (3 pcs.)

(3) Regenerative loss of drive unit and servo motor

Drive unit	Inverse efficiency [%]	C charge [J]
MR-J3-DU30KA	90	450
MR-J3-DU37KA		
MR-J3-DU30KA4		
MR-J3-DU37KA4		
MR-J3-DU45KA4		
MR-J3-DU55KA4		

(4) Connection of the regenerative option

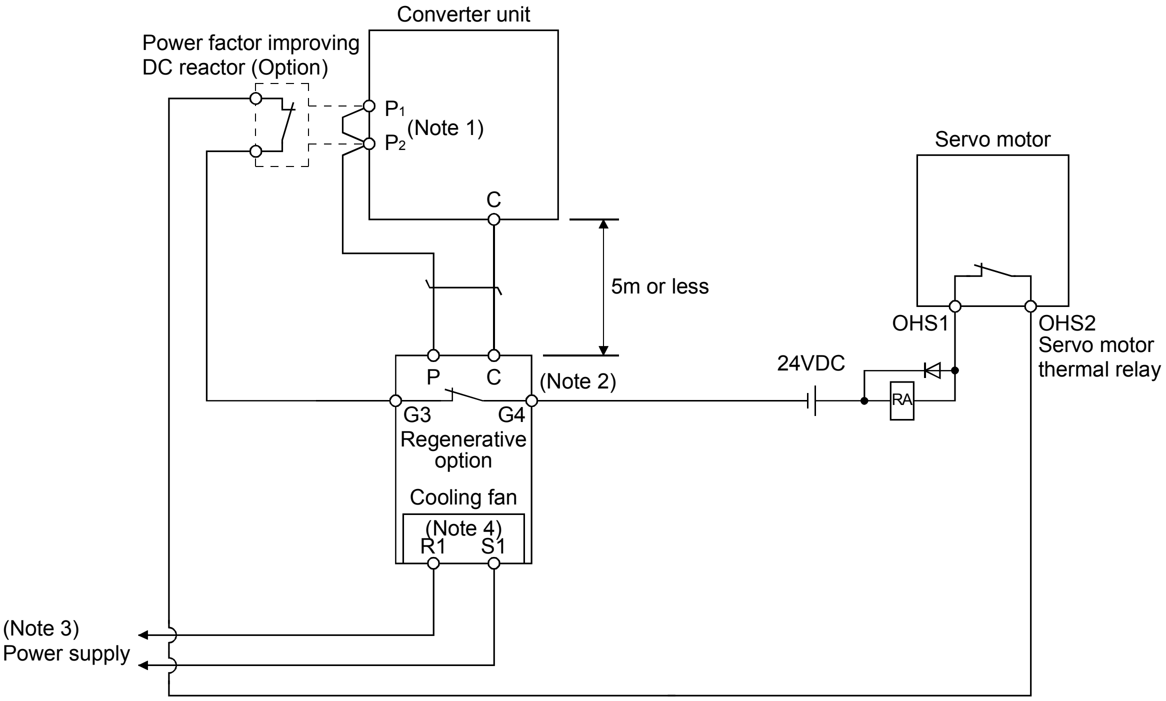
Make sure to supply 1-phase 200V and 400V respectively to the cooling fan. The cooling fan specifications are as follows.

Table 15.3 Cooling fan

Item	200V class	400V class
Model	MR-RB137 · MR-RB139	MR-RB136-4 · MR-RB138-4
Voltage · Frequency	1-phase 198 to 242VAC, 50/60Hz	1-phase 380 to 480VAC, 50/60Hz
Power consumption [W]	20 (50Hz)/18 (60Hz)	20 (50Hz)/18 (60Hz)

The regenerative option generates heat of 100℃ higher than the ambient temperature. Fully consider heat dissipation, installation position, used wires, etc. to place the option. For wiring, use flame-resistant wires or make the wires flame-resistant and keep them away from the regenerative option. The G3 and G4 terminals act as a thermal sensor. G3-G4 are opened when the regenerative option overheats abnormally.
Make sure to twist the wires for connection with the converter unit and connect the wires within the overall distance of 5m.

(a) MR-RB139 · MR-RB136-4

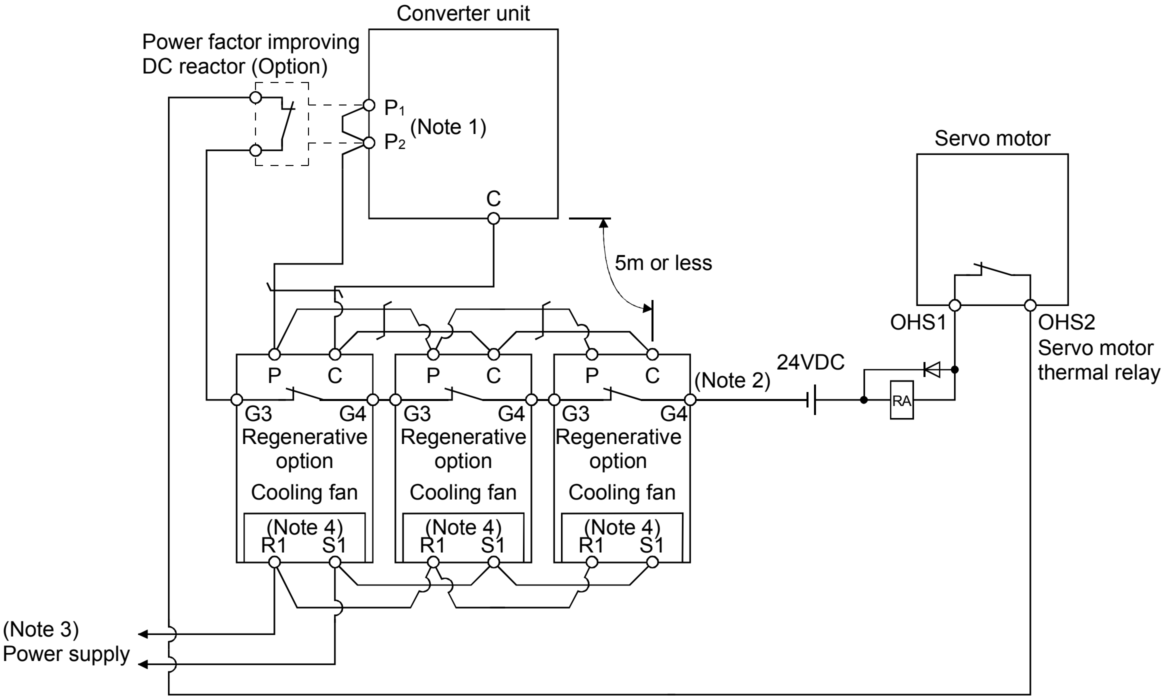


Note 1. When using the power factor improving DC reactor, remove the short bar across P1-P2.

2. G3-G4 contact specifications
   Maximum voltage: 120V AC/DC
   Maximum current: 0.5V/4.8VDC
   Maximum capacity: 2.4VA
3. For specifications of cooling fan power supply, refer to Table 15.3.
4. For MR-RB136-4, "R1" is "R400" and "S1" is "S400".

(b) MR-RB137 · MR-RB138-4

POINT
· Three of MR-RB137 or MR-RB138-4 are required per converter unit. Please purchase three of MR-RB137 or MR-RB138-4.



Note 1. When using the power factor improving DC reactor, remove the short bar across P_1-P_2.

2. G3-G4 contact specifications

   Maximum voltage: 120V AC/DC

   Maximum current: 0.5V/4.8VDC

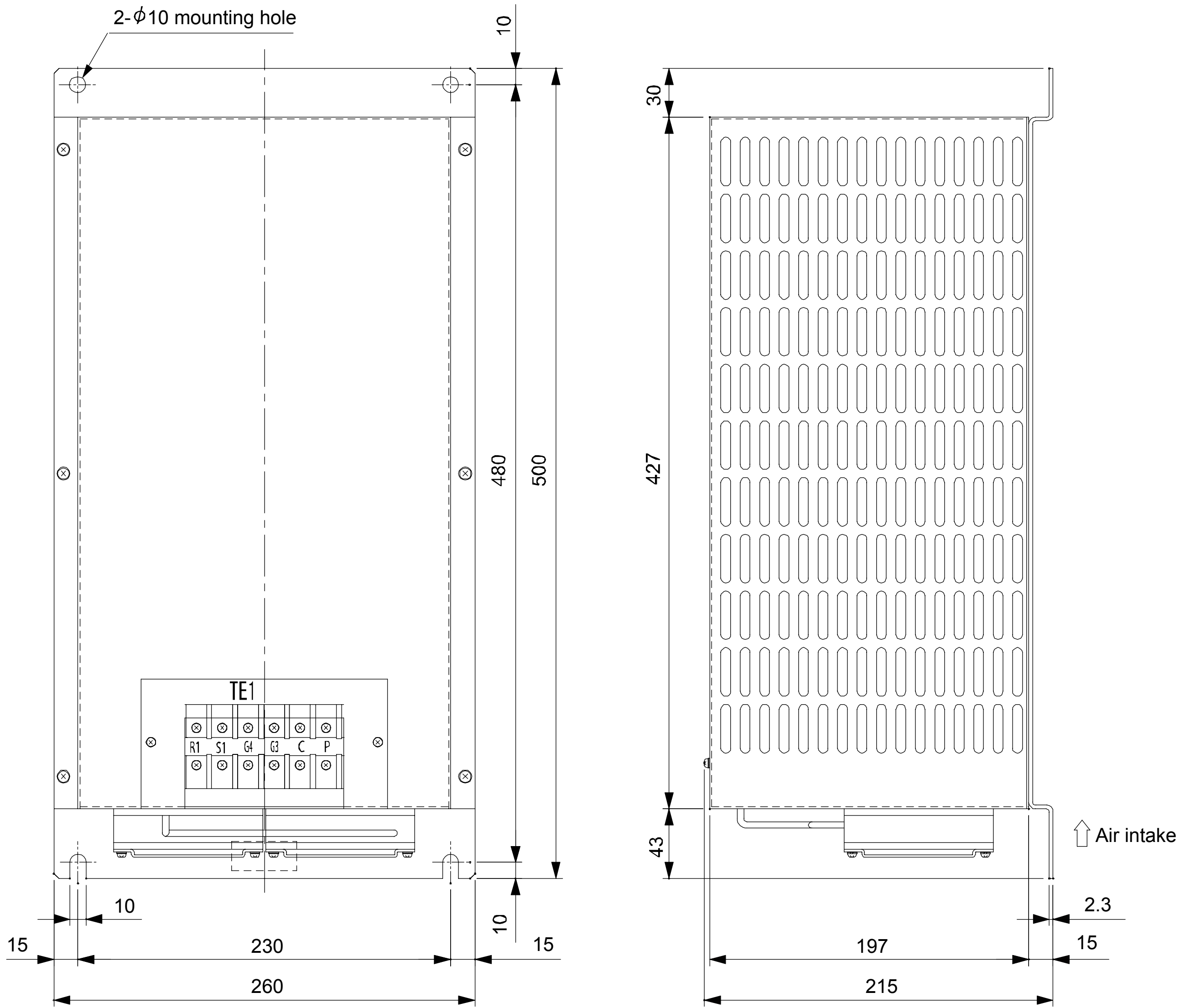
   Maximum capacity: 2.4VA

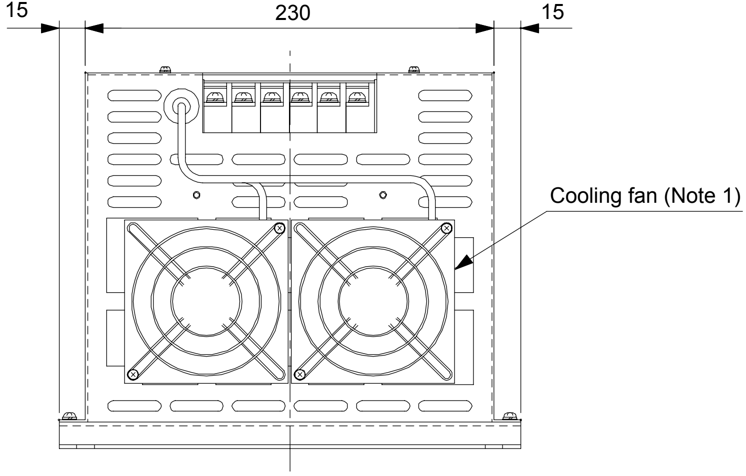
3. For specifications of cooling fan power supply, refer to Table 15.3.

4. For MR-RB138-4, "R1" is "R400" and "S1" is "S400".

(5) Outline dimension drawings

[Unit:mm]





Regenerative option	Mass [kg(lb)]
MR-RB139・MR-RB136-4	10(22.05)
MR-RB137・MR-RB138-4	11(24.25)

- Terminal block signal layout
  TE1

R1 (Note 2)	S1 (Note 2)	G4	G3	C	P

Terminal screw: M5
Tightening torque: 2.0 [N・m] (17.7 [lb・in])

- Mounting screw
  Screw size: M8
  Tightening torque: 13.2 [N・m] (117 [lb・in])

Note 1. One cooling fan for MR-RB136-4, MR-RB138-4.
2. For MR-RB138-4, "R1" is "R400" and "S1" is "S400".

15.9.3 External dynamic brake

⚠CAUTION

- Use an external dynamic brake for the drive unit. Failure to do so will cause an accident because the servo motor does not stop immediately but coasts at an emergency stop and such conditions. Ensure the safety in the entire system.

POINT

- Configure up a sequence which switches off the magnetic contactor of the brake unit after (or as soon as) the servo on (SON) has been turned off at a power failure or failure.
- For the braking time taken when the dynamic brake is operated, refer to section 15.8.3.
- The brake unit is rated for a short duration. Do not use it for high duty.
- The specifications of the input power supply for external dynamic brake are the same as those of the converter unit control circuit power supply.
- Operation timing is the same as that for servo amplifiers with 22kW or less. Refer to section 12.6.
- Dynamic brake operates at occurrence of alarm, servo emergency stop warning (AL.E6), and when power is turned off. Do not use dynamic brake to stop in a normal operation as it is the function to stop in emergency.
- Maximum usage time of dynamic brake for a machine operating under recommended load inertia moment ratio is 1000 time while decelerating from rated speed to a stop with frequency of once in 10 minutes.
- Be sure to make emergency stop (EMG・EM1) valid after servo motor stops when using emergency stop (EMG・EM1) frequently in other than emergency.

(1) Selection of dynamic brake

The dynamic brake is designed to bring the servo motor to a sudden stop when a power failure occurs or the protective circuit is activated. When using the external dynamic brake, assign the dynamic brake interlock (DB) to any of CN1-22, CN1-23, CN1-24, CN1-25 and CN1-49 pins in parameter No.PD13 to PD16 and PD18.

Converter unit	Drive unit	Dynamic brake
MR-J3-CR55K	MR-J3-DU30KA	DBU-37K
	MR-J3-DU37KA	
MR-J3-CR55K4	MR-J3-DU30KA4	DBU-55K-4
	MR-J3-DU37KA4	
	MR-J3-DU45KA4	
	MR-J3-DU55KA4	

(2) Connection example

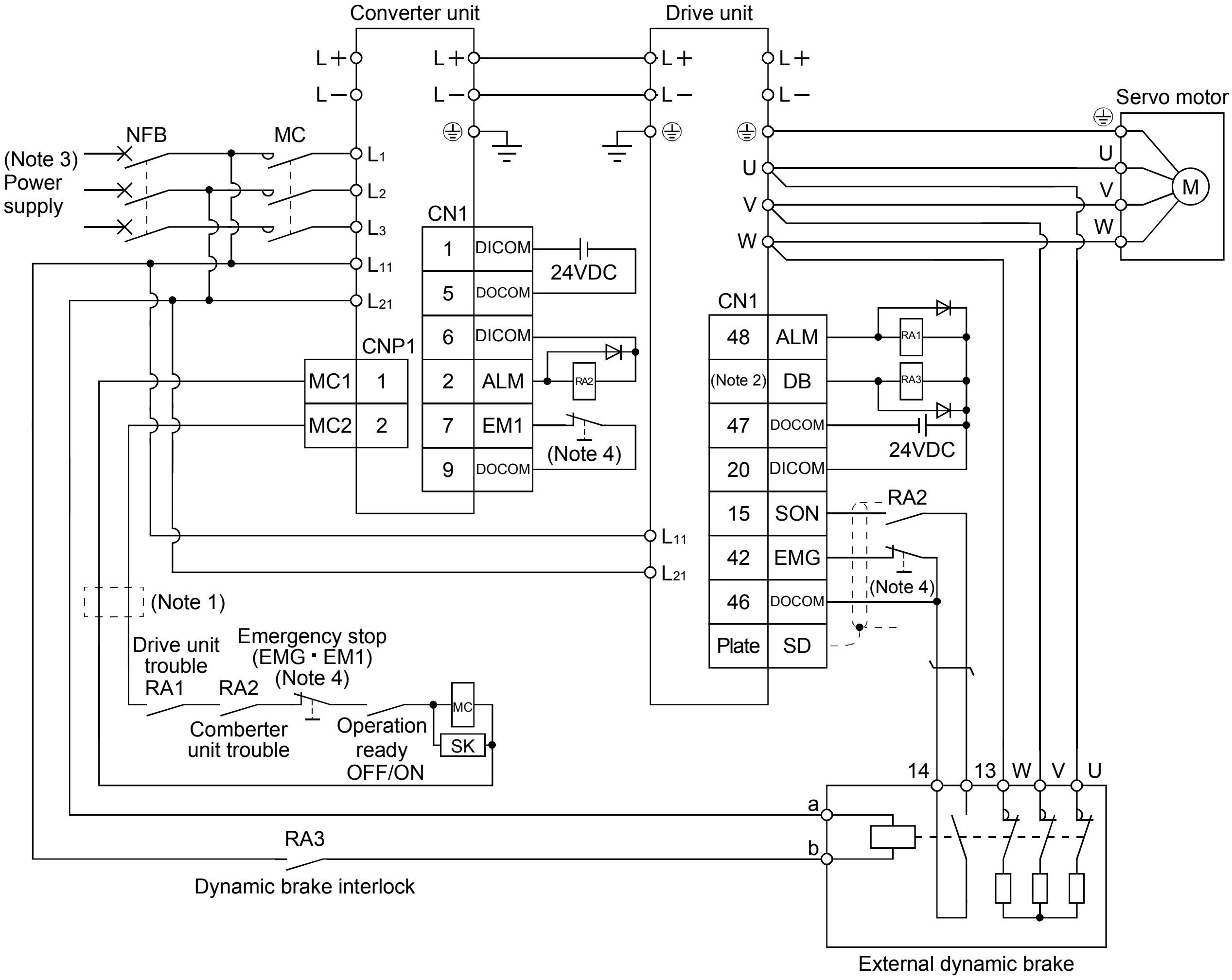
Use the following wires to connect the dynamic brake.

Dynamic brake	Wire[mm^2] (Note)	
	a・b	U・V・W
DBU-37K	2	14
DBU-55K-4		

Note. Selection condition of wire size is as follows.

Wire type: 600V Polyvinyl chloride insulated wire (IV wire)

Construction condition: One wire is constructed in the air

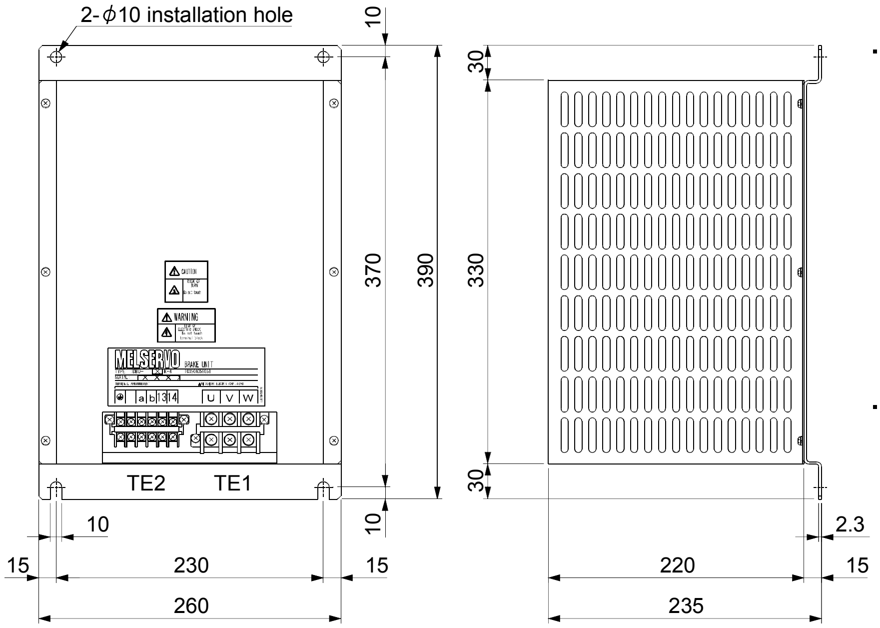


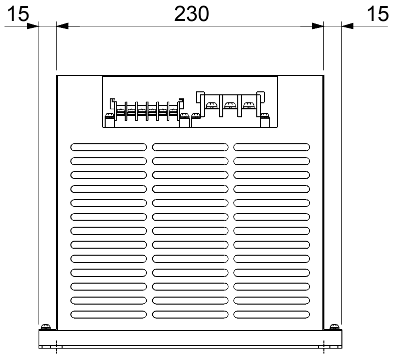
Note 1 For converter unit and servo amplifier 400V class, stepdown transformer is required for coil voltage of magnetic contactor more than 200V class.

2. Assign the dynamic brake interlock (DB) in parameter No.PD13 to PD16 and PD18.
3. Refer to section 15.1.3 for the power supply specifications.
4. Make up a sequence that will concurrently turn off the Emergency stop (EMG) of the drive unit and the Forced stop (EM1) of the converter unit, and shut off the main circuit power supply by the external sequence.

(3) Outline dimension drawing

[Unit:mm]





- Terminal block

TE1

U	V	W

Terminal screw: M5
Tightening torque: 2.0 [N・m] (17.7 [lb・in])

TE2

⏚		a	b	13	14

Terminal screw: M5
Tightening torque: 0.8 [N・m] (7.1 [lb・in])

- Mounting screw
  Screw size: M8
  Tightening torque: 13.2 [N・m] (117 [lb・in])

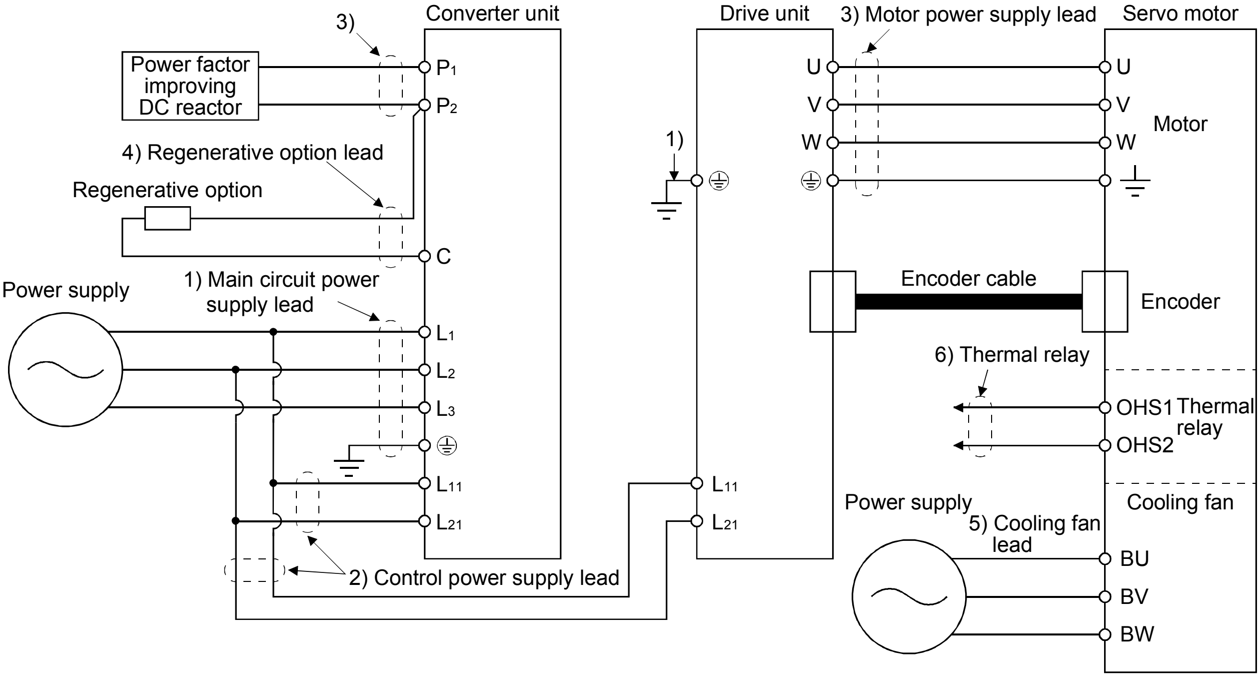
Dynamic brake	Mass [kg(lb)]
DBU-37K	8(17.64)
DBU-55K-4	11(24.25)

15.9.4 Selection example of wires

POINT

- Wires indicated in this section are separated wires. When using a cable for power line (U, V, and W) between the drive unit and servo motor, use a 600V grade EP rubber insulated chloroprene sheath cab-tire cable (2PNCT). For selection of cables, refer to appendix 6.
- To comply with the UL/CSA Standard, use the wires shown in appendix 10 for wiring. To comply with other standards, use a wire that is complied with each standard.
- Selection condition of wire size is as follows.
  - Wire type: 600V Polyvinyl chloride insulated wire (IV wire)
  - Construction condition: One wire is constructed in the air

The following diagram shows the wires used for wiring. Use the wires given in this paragraph or equivalent.



(1) When using the 600V Polyvinyl chloride insulated wire (IV wire)
Selection example of wire size when using IV wires is indicated below.

Table 15.4 Wire size selection example 1 (IV wire)

Converter unit	(Note 2) Drive unit	Wires[mm^2] (Note 1, 3)					
		1) L_1・L_2・L_3・⏚	2) L_{11}・L_{21}	3) U・V・W P_1・P_2・⏚	4) P_2・C	5) BU・BV・BW	6) OHS1・OHS2
MR-J3-CR55K	MR-J3-DU30KA	50(AWG1/0): d	2(AWG14)	60(AWG2/0): d	5.5(AWG10): a	2(AWG14)	1.25(AWG16)
	MR-J3-DU37KA	60(AWG2/0): d		(Note 4)			
MR-J3-CR55K4	MR-J3-DU30KA4	22(AWG4): b		30(AWG2): f		1.25(AWG16)	
	MR-J3-DU37KA4	30(AWG2): c		38(AWG2): f			
	MR-J3-DU45KA4	38(AWG2): c		50(AWG1/0): d			
	MR-J3-DU55KA4	50(AWG1/0): d		60(AWG2/0): d			

Note 1. Alphabets in the table indicate crimping tools. For crimping terminals and applicable tools, refer to (3) in this section.
2. When connecting to the terminal block, be sure to use the screws which are provided with the terminal block.
3. For the servo motor with a cooling fan.
4. Wires are selected based on the highest rated current among combining servo motors.

(2) When using the 600V Grade heat-resistant polyvinyl chloride insulated wire (HIV wire)
Selection example of wire size when using HIV wires is indicated below.

Table 15.5 Wire size selection example 2 (HIV wire)

Converter unit	(Note 2) Drive unit	Wires[mm^2] (Note 1, 3)					
		1) L_1・L_2・L_3・⏚	2) L_{11}・L_{21}	3) U・V・W P_1・P_2・⏚	4) P_2・C	5) BU・BV・BW	6) OHS1・OHS2
MR-J3-CR55K	MR-J3-DU30KA	38(AWG2): c	2(AWG14)	60(AWG2/0): d	5.5(AWG10): a	2(AWG14)	1.25(AWG16)
	MR-J3-DU37KA	60(AWG2/0): d		60(AWG2/0): d			
MR-J3-CR55K4	MR-J3-DU30KA4	22(AWG4): b		22(AWG4): e		1.25(AWG16)	
	MR-J3-DU37KA4	22(AWG4): b		22(AWG4): e			
	MR-J3-DU45KA4	38(AWG2): c		38(AWG2): c			
	MR-J3-DU55KA4	38(AWG2): c		38(AWG2): c			

Note 1. Alphabets in the table indicate crimping tools. For crimping terminals and applicable tools, refer to (3) in this section.
2. When connecting to the terminal block, be sure to use the screws which are provided with the terminal block.
3. For the servo motor with a cooling fan.

(3) Selection example of crimping terminals

The table below shows a selection example of crimping terminals for the servo amplifier terminal block when using the wires mentioned in (1) and (2) in this section.

Symbol	Servo amplifier side crimping terminals				
	(Note 2) Crimping terminal	Applicable tool			Manufacturer
		Body	Head	Dice	
a	FVD5.5-10	YNT-1210S			Japan Solderless Terminals
b	FVD22-10	YF-1・E-4	YNE-38	DH-123・DH113	
(Note 1) c	R38-10	YPT-60-21		TD-124・TD-112	
		YF-1・E-4	YET-60-1		
(Note 1) d	R60-10	YPT-60-21		TD-125・TD-113	
		YF-1・E-4	YET-60-1		
e	FVD22-8	YF-1・E-4	YNE-38	DH-123・DH-113	
(Note 1) f	R38-8	YPT-60-21		TD-124・TD-112	
		YF-1・E-4	YET-60-1		

Note 1. Coat the part of crimping with the insulation tube.

2. Make sure to use recommended crimping terminals or equivalent since some crimping terminals cannot be installed depending on the size.

15.9.5 No-fuse breakers, fuses, magnetic contactors

Make sure to use one no-fuse breakers and one magnetic contactor with one drive unit.

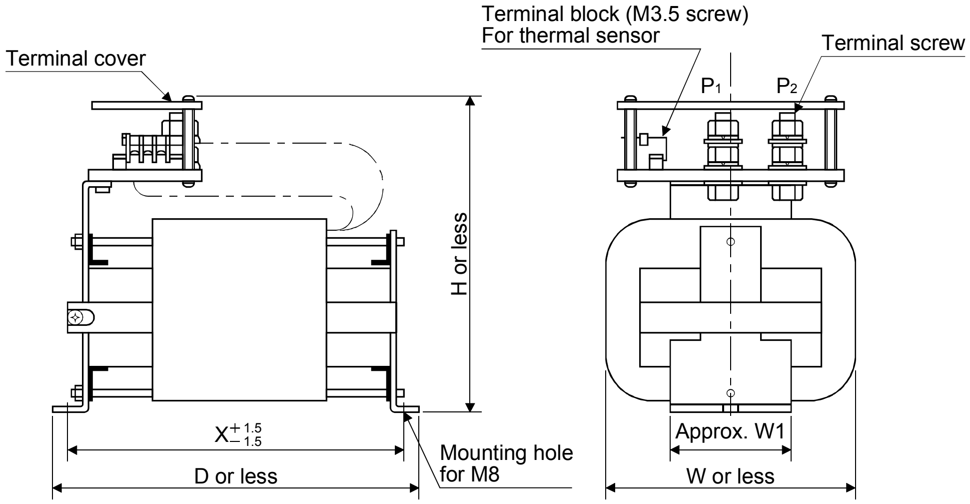
Converter unit	Drive unit	No-fuse breaker		Fuse				(Note) Magnetic contactor
		Power factor improving DC reactor is not used	Power factor improving DC reactor is used	Voltage AC	Class	Current [A]	Voltage AC [V]	
MR-J3-CR55K	MR-J3-DU30KA	400A frame 250A	225A frame 225A	240V	T	500	360	S-N150
	MR-J3-DU37KA	400A frame 300A	400A frame 300A			600		S-N180
MR-J3-CR55K4	MR-J3-DU30KA4	225A frame 125A	225A frame 125A	600Y/ 347V		250	600	S-N95
	MR-J3-DU37KA4	225A frame 150A	225A frame 150A			300		S-N125
	MR-J3-DU45KA4	225A frame 175A	225A frame 175A			400		S-N150
	MR-J3-DU55KA4	400A frame 225A	225A frame 225A			450		S-N180

Note. Be sure to use a magnetic contactor with an operation delay time of 80ms or less. The operation delay time is the time interval between current being applied to the coil until closure of contacts.

15.9.6 Power factor improving DC reactor

The input power factor is improved to about 95%.

Converter unit	Drive unit	Power factor improving DC reactor	Dimension [mm]					Terminal screw	Mass [kg (lb)]
			W	D	H	W1	X		
MR-J3-CR55K	MR-J3-DU30KA	MR-DCL30K	135	255	215	80	232	M12	9.5 (20.94)
	MR-J3-DU37KA	MR-DCL37K							
MR-J3-CR55K4	MR-J3-DU30KA4	MR-DCL30K-4		205	200	75	175	M8	6.5 (14.33)
	MR-J3-DU37KA4	MR-DCL37K-4		225		80	197		7 (15.43)
	MR-J3-DU45KA4	MR-DCL45K-4		240			212		7.5 (16.54)
	MR-J3-DU55KA4	MR-DCL55K-4		260	215		232		9.5 (20.94)



15.9.7 Line noise filter (FR-BLF)

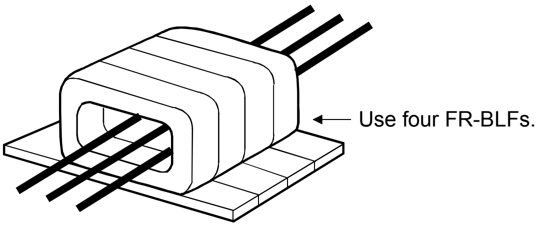
POINT

- This section explains how to use the line noise filter unique to servo amplifiers with a large capacity. Other noise reduction products are the same as those for servo amplifiers with 22kW or less. Refer to section 12.17.

This filter is effective in suppressing noises radiated from the power supply side and output side of the converter unit, drive unit and also in suppressing high-frequency leakage current (zero-phase current) especially within 0.5M to 5MHz band. The filters are used with the converter power supply wires (L_1 · L_2 · L_3) and drive unit power wires (U · V · W).

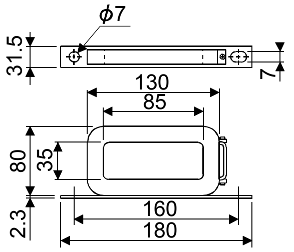
(1) Usage

Pass the 3-phase wires through four line noise filters. When using the line noise filters with the power wires, passing the power wires together with the ground wire will reduce the filter effect. Run the ground wire separately from the power wires.



(2) Outline drawing

[Unit: mm]



15.9.8 Leakage current breaker

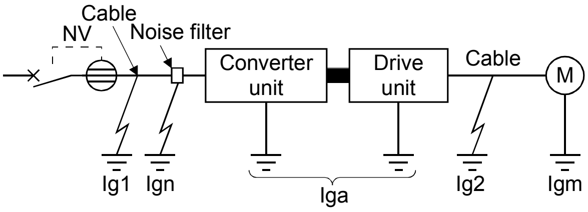
(1) Selection method

High-frequency chopper currents controlled by pulse width modulation flow in the AC servo circuits. Leakage currents containing harmonic contents are larger than those of the motor which is run with a commercial power supply.

Select a leakage current breaker according to the following formula, and ground the drive unit, servo motor, etc. securely.

Make the input and output cables as short as possible, and also make the grounding cable as long as possible (about 30cm) to minimize leakage currents.

Rated sensitivity current $\geq 10 \cdot \{Ig1 + Ign + Iga + K \cdot (Ig2 + Igm)\} + $[mA] ·· (15.2)



K: Constant considering the harmonic contents

Leakage current breaker		K
Type	Mitsubishi products	
Models provided with harmonic and surge reduction techniques	NV-SP NV-SW NV-CP NV-CW NV-HW	1
General models	BV-C1 NFB NV-L	3

Ig1: Leakage current on the electric channel from the leakage current breaker to the input terminals of the drive unit (Found from Fig. 15.3.)

Ig2: Leakage current on the electric channel from the output terminals of the servo amplifier to the servo motor (Found from Fig. 15.3.)

Ign: Leakage current when a filter is connected to the input side (4.4mA per one FR-BIF or FR-BIF-H)

Iga: Leakage current of the drive unit (Found from Table 15.7.)

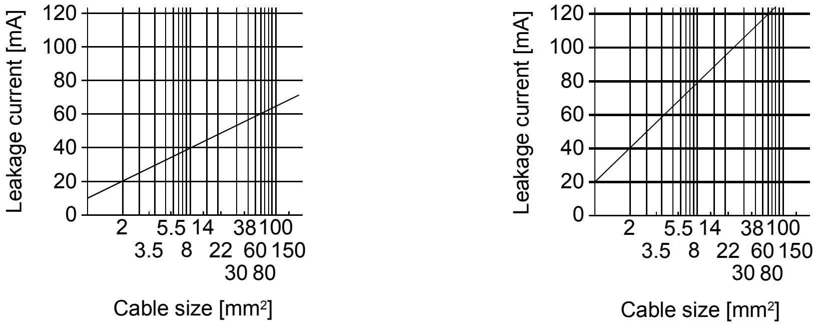
Igm: Leakage current of the servo motor (Found from Table 15.6.)

Table 15.6 Servo motor's leakage current example (Igm)

Servo motor power [kW]	Leakage current [mA]
30 to 55	2.5

Table 15.7 Converter unit・drive unit's leakage current Example (Iga)

Converter unit Drive unit	Leakage current [mA]
All series	5



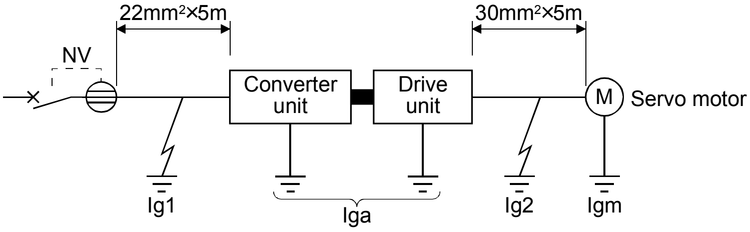
a) 200V class

b) 400V class

Fig.15.3 Leakage current example (Ig1, Ig2) for CV cable run in metal conduit

(2) Selection example

Indicated below is an example of selecting a leakage current breaker under the following conditions.



Use a leakage current breaker designed for suppressing harmonics/surges.

Find the terms of Equation (15.2) from the diagram.

$$Ig1 = 95 \times \frac{5}{1000} = 0.475 \text{ [mA]}$$

$$Ig2 = 105 \times \frac{5}{1000} = 0.525 \text{ [mA]}$$

$Ign = 0$ (not used)

$Iga = 5$ [mA]

$Igm = 2.5$ [mA]

Insert these values in Equation (15.2).

$$\begin{aligned} Ig &\geq 10 \cdot \{0.475 + 0 + 5 + 1 \cdot (0.525 + 2.5)\} \\ &\geq 85 \text{ [mA]} \end{aligned}$$

According to the result of calculation, use a leakage current breaker having the rated sensitivity current (Ig) of 85 [mA] or more. A leakage current breaker having Ig of 200 [mA] is used with the NV-SP/SW/CP/CW/HW series.

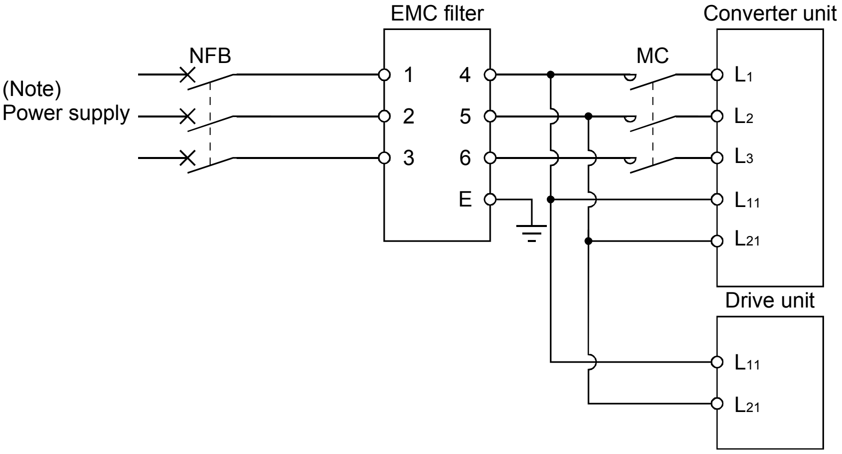
15.9.9 EMC filter (recommended)

For compliance with the EMC directive of the IEC/EN Standard, it is recommended to use the following filter. Some EMC filters are large in leakage current.

(1) Converter unit・Drive unit

Converter unit	Drive unit	Recommended filter (Soshin Electric)		Mass [kg]
		Model	Leakage current [mA]	
MR-J3-CR55K	MR-J3-DU30KA・MR-J3-DU37KA	HF3200A-UN	9	18
MR-J3-CR55K4	MR-J3-DU30KA4 to MR-J3-DU55KA4	TF3150C-TX	5.5	31

(2) Connection example

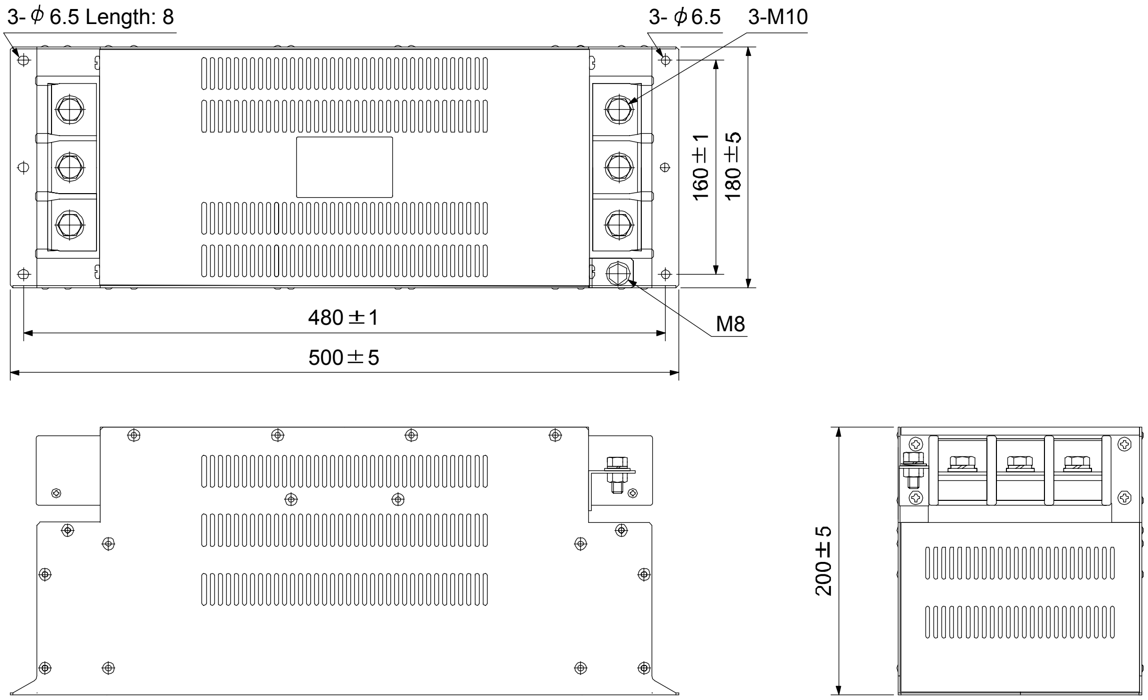


Note. For power supply specifications, refer to section 15.1.3.

(3) Outline drawing

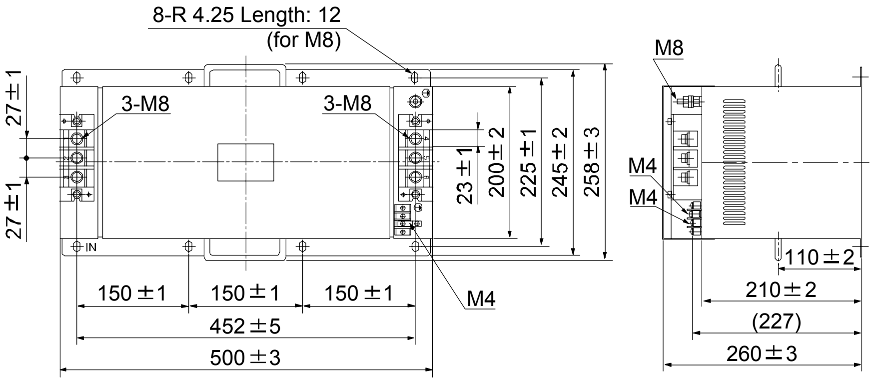
HF3200A-UN

[Unit: mm]



TF3150C-TX

[Unit: mm]



15.9.10 FR-BU2-(H) brake unit

POINT

- Use a 200V class brake unit and a resistor unit with a 200V class converter unit, and a 400V class brake unit and a resistor unit with a 400V class converter unit. Combination of different voltage class units cannot be used.
- Install a brake unit and a resistor unit on a flat surface vertically. When the unit is installed horizontally or diagonally, the heat dissipation effect diminishes.
- Temperature of the resistor unit case rises to higher than 100℃. Keep cables and flammable materials away from the case.
- Ambient temperature condition of the brake unit is between －10℃ (14℉) to 50℃ (122℉). Note that the condition is different from the ambient temperature condition of the converter unit (between 0℃ (32℉) to 55℃ (131℉)).
- Configure the circuit to shut down the power-supply with the alarm output of the brake unit and the resistor unit under abnormal condition.
- Use the brake unit with a combination indicated in (1) in this section.
- For executing a continuous regenerative operation, use FR-RC-(H) power regenerative converter or FR-CV-(H) power regenerative common converter.
- When using the brake unit, set the parameters as shown below.

	Setting value
Parameter No.PA01 of the MR-J3-CR55K(4) converter unit	☐☐00 (Initial value)
Parameter No.PA02 of the drive unit	☐☐00 (Initial value)

Connect the brake unit to the bus of the converter unit (L＋ and L－ of TE2-1) for use. As compared to the MR-RB regenerative option, the brake unit can return larger power. Use the brake unit when the regenerative option cannot provide sufficient regenerative capability.
When using the brake unit, make sure to refer to the FR-BU2-(H) Brake Unit Instruction Manual.

(1) Selection

Use a combination of converter unit, brake unit and resistor unit listed below.

Brake unit		Resistor unit	Number of connected units	Permissible continuous power [kW]	Total resistance [Ω]	Applicable converter unit
200V class	FR-BU2-55K	FR-BR-55K	2 (parallel)	7.82	1	MR-J3-CR55K
		MT-BR5-55K	2 (parallel)	11.0	1	MR-J3-CR55K
400V class	FR-BU2-H55K	FR-BR-H55K	2 (parallel)	7.82	4	MR-J3-CR55K4
	FR-BU2-H75K	MT-BR5-H75K	2 (parallel)	15.0	3.25	MR-J3-CR55K4

(2) Brake unit parameter setting

Normally, changing parameters of the FR-BU2-(H) is not necessary. Whether a parameter can be changed or not is listed below.

Parameter		Change possible/ impossible	Remarks
No.	Name		
0	Brake mode switchover	Impossible	Do not change the parameter.
1	Monitor display data selection	Possible	Refer to FR-BU2-(H) Brake Unit Instruction Manual.
2	Input terminal function selection 1	Impossible	Do not change the parameter.
3	Input terminal function selection 2		
77	Parameter write selection		
78	Cumulative energization time carrying-over times		
CLr	Parameter clear		
ECL	Alarm history clear		
C1	For manufacturer setting		

(3) Connection example

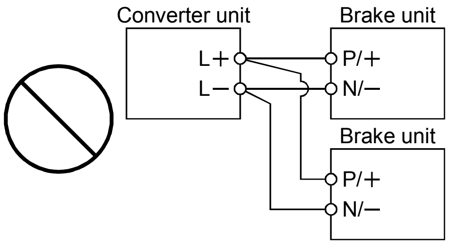
POINT

- Connecting PR terminal of the brake unit to L＋ terminal of the converter unit results in a brake unit malfunction. Make sure to connect the PR terminal of the brake unit to the PR terminal of the resistor unit.

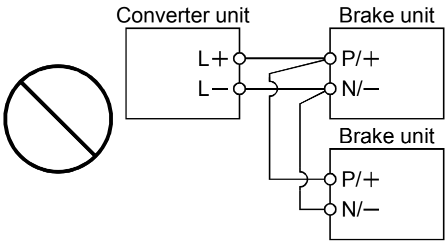
(a) Combination with FR-BR-(H) resistor unit

POINT

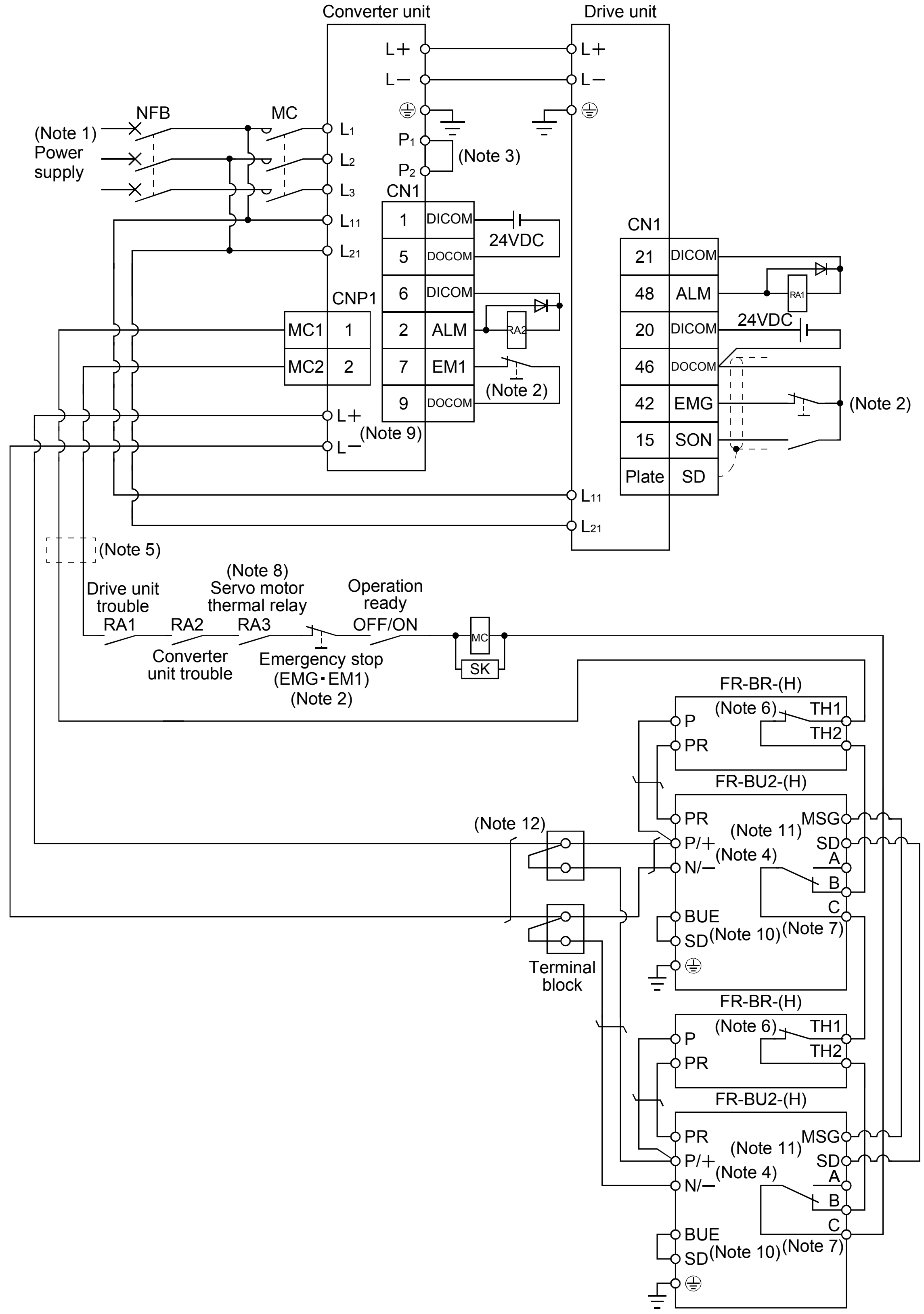
- To use brake units with a parallel connection, use two sets of FR-BU2-(H) brake unit. Combination with other brake unit results in alarm occurrence or malfunction.
- Make sure to connect the master and slave terminals (MSG and SD) of the two brake units.
- Do not connect as shown below.



Connecting two cables to
P and N terminals



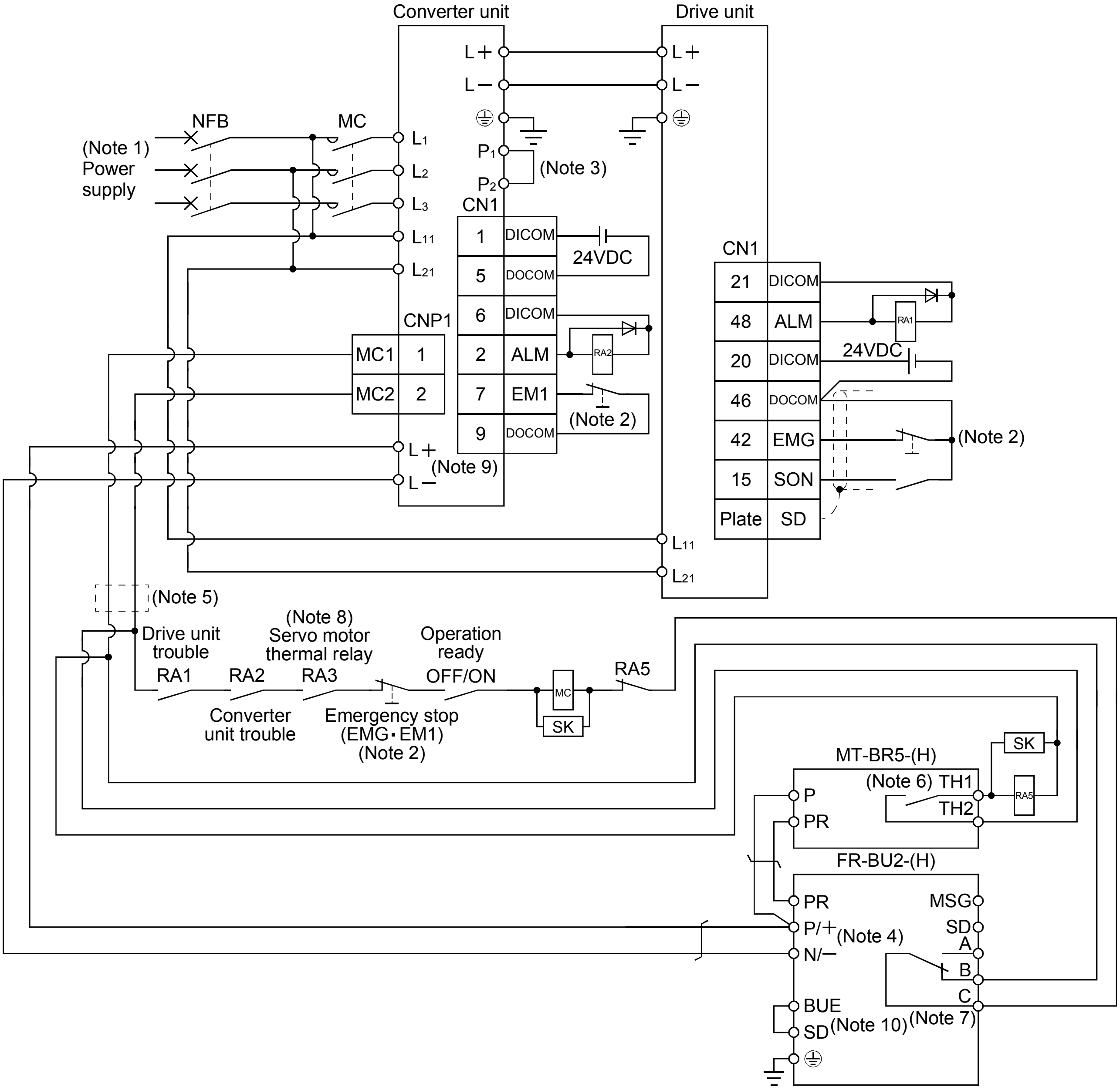
Passing wiring


Converter unit
Drive unit
L+
L−
P1
P2
(Note 3)
NFB
MC
(Note 1)
Power supply
L1
L2
L3
L11
L21
CN1
1 DICOM
5 DOCOM
6 DICOM
2 ALM
7 EM1
9 DOCOM
24VDC
RA2
(Note 2)
CNP1
MC1 1
MC2 2
L+
L−
(Note 9)
CN1
21 DICOM
48 ALM
20 DICOM
46 DOCOM
42 EMG
15 SON
Plate SD
RA1
24VDC
(Note 2)
L11
L21
(Note 5)
Drive unit trouble
RA1
Converter unit trouble
RA2
(Note 8)
Servo motor thermal relay
RA3
Emergency stop
(EMG・EM1)
(Note 2)
Operation ready
OFF/ON
MC
SK
FR-BR-(H)
P
PR
(Note 6)
TH1
TH2
FR-BU2-(H)
PR
P/+
N/−
(Note 11)
(Note 4)
MSG
SD
A
B
C
BUE
SD
(Note 10)
(Note 7)
(Note 12)
Terminal block
FR-BR-(H)
P
PR
(Note 6)
TH1
TH2
FR-BU2-(H)
PR
P/+
N/−
(Note 11)
(Note 4)
MSG
SD
A
B
C
BUE
SD
(Note 10)
(Note 7)

Note 1. For power supply specifications, refer to section 15.1.3.
2. Make up a sequence that will concurrently turn off the Emergency stop (EMG) of the drive unit and the Forced stop (EM1) of the converter unit, and shut off the main circuit power supply by the external sequence.
3. Make sure to connect between P_1 and P_2 terminals (Factory-wired). When using the power factor improving DC reactor, refer to section 15.9.6.
4. Connect P/＋ and N/－ terminals of the brake unit to a correct destination. Incorrect connection results in the converter unit and brake unit malfunction.
5. For the converter unit and the drive unit of 400V class, a stepdown transformer is required.
6. Contact rating: 1b contact, 110VAC_5A/220VAC_3A
Normal condition: TH1-TH2 is conducting. Abnormal condition: TH1-TH2 is not conducting.
7. Contact rating: 230VAC_0.3A/30VDC_0.3A
Normal condition: B-C is conducting/A-C is not conducting. Abnormal condition: B-C is not conducting/A-C is conducting.
8. Connect the thermal relay censor of the servo motor.
9. Do not connect more than one cable to each L＋ and L－ terminals of TE2-1 of the converter unit.
10. Make sure to connect between BUE and SD terminals (Factory-wired).
11. Connect MSG and SD terminals of the brake unit to a correct destination. Incorrect connection results in the converter unit and brake unit malfunction.
12. For connecting L＋ and L－- terminals of TE2-1 of the converter unit to the terminal block, use the cable indicated in (3) (d) in this section.

(b) Combination with MT-BR5-(H) resistor unit

1) When connecting a brake unit to a converter unit



Note 1. For power supply specifications, refer to section 15.1.3.

2. Make up a sequence that will concurrently turn off the Emergency stop (EMG) of the drive unit and the Forced stop (EM1) of the converter unit, and shut off the main circuit power supply by the external sequence.

3. Make sure to connect between P_1 and P_2 terminals (Factory-wired). When using the power factor improving DC reactor, refer to section 15.9.6.

4. Connect P/+ and N/− terminals of the brake unit to a correct destination. Incorrect connection results in the converter unit and brake unit malfunction.

5. For the converter unit and the drive unit of 400V class, a stepdown transformer is required.

6. Contact rating: 1a contact, 110VAC_5A/220VAC_3A
Normal condition: TH1-TH2 is not conducting. Abnormal condition: TH1-TH2 is conducting.

7. Contact rating: 230VAC_0.3A/30VDC_0.3A
Normal condition: B-C is conducting/A-C is not conducting. Abnormal condition: B-C is not conducting/A-C is conducting.

8. Connect the thermal relay censor of the servo motor.

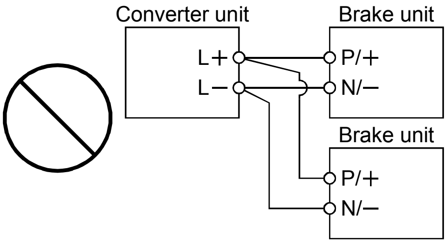
9. Do not connect more than one cable to each L+ and L− terminals of TE2-1 of the converter unit.

10. Make sure to connect between BUE and SD terminals (Factory-wired).

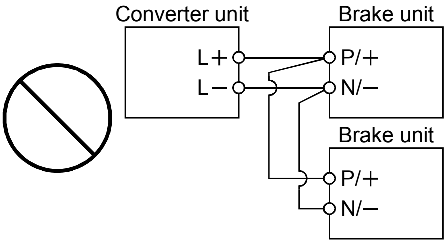
2) When connecting two brake units to a converter unit

POINT

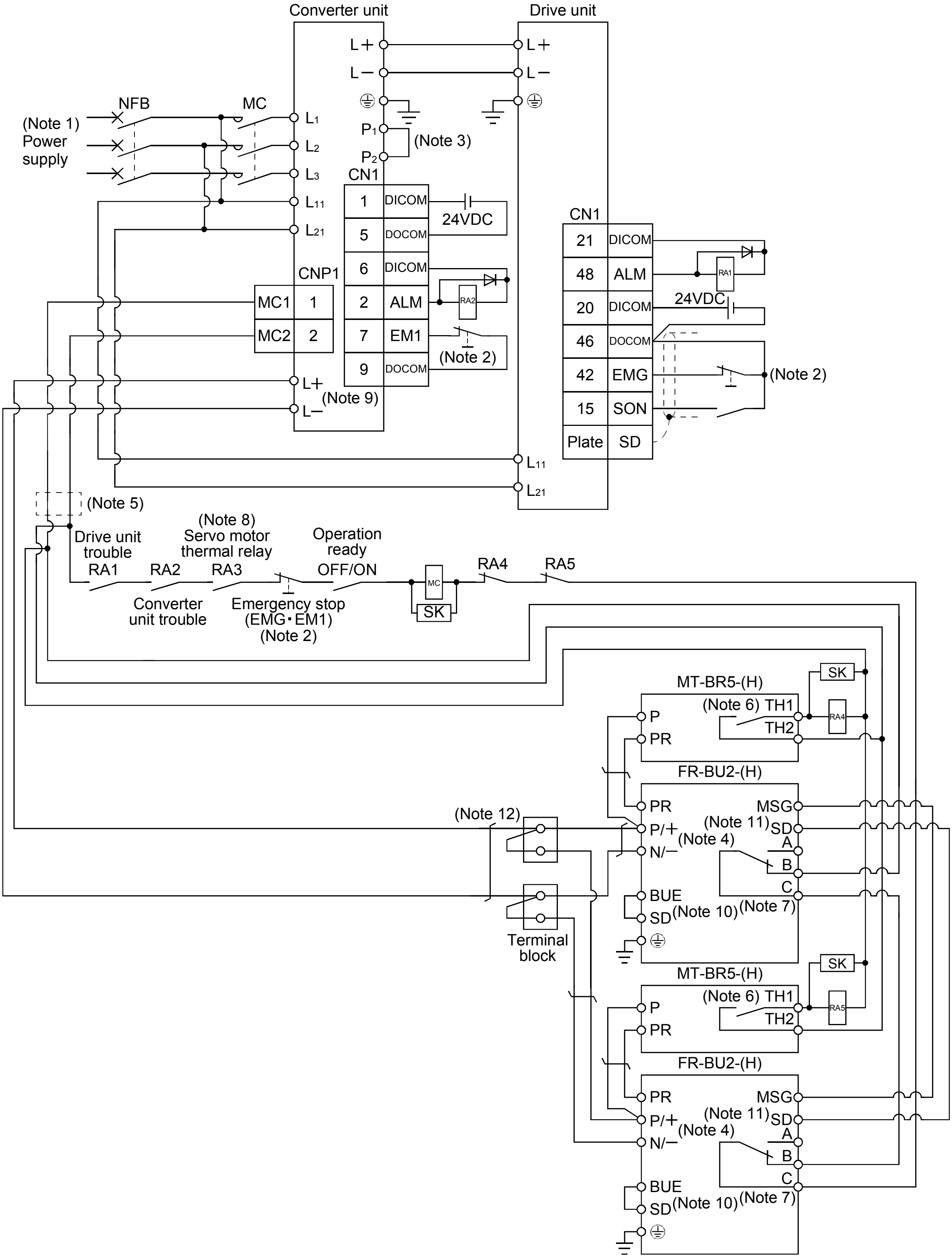
- To use brake units with a parallel connection, use two sets of FR-BU2-(H) brake unit. Combination with other brake unit results in alarm occurrence or malfunction.
- Make sure to connect the master and slave terminals (MSG and SD) of the two brake units.
- Do not connect the converter unit and brake units as below. Connect the cables with a terminal block to distribute as indicated in this section.



Connecting two cables to
P and N terminals



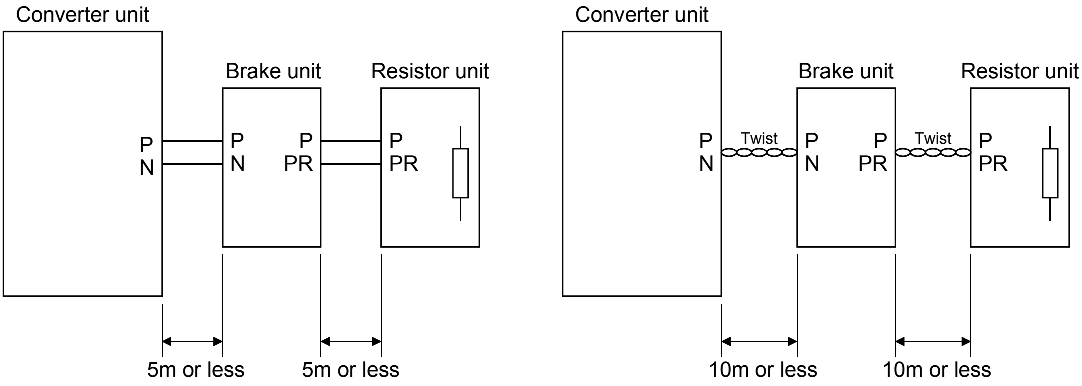
Passing wiring


Converter unit
Drive unit
L+
L−
NFB
MC
(Note 1)
Power
supply
L1
L2
L3
L11
L21
P1
P2
(Note 3)
CN1
1 DICOM
5 DOCOM
6 DICOM
2 ALM
7 EM1
9 DOCOM
24VDC
RA2
(Note 2)
CNP1
MC1 1
MC2 2
(Note 9)
CN1
21 DICOM
48 ALM
20 DICOM
46 DOCOM
42 EMG
15 SON
Plate SD
RA1
24VDC
(Note 2)
L11
L21
(Note 5)
(Note 8)
Drive unit
trouble
Servo motor
thermal relay
Operation
ready
RA1
RA2
RA3
OFF/ON
MC
SK
RA4
RA5
Converter
unit trouble
Emergency stop
(EMG･EM1)
(Note 2)
MT-BR5-(H)
SK
(Note 6) TH1
TH2
RA4
P
PR
FR-BU2-(H)
PR
MSG
(Note 12)
P/+
(Note 11)
SD
(Note 4)
N/−
A
B
C
BUE
SD
(Note 10)
(Note 7)
Terminal
block
MT-BR5-(H)
SK
(Note 6) TH1
TH2
RA5
P
PR
FR-BU2-(H)
PR
MSG
P/+
(Note 11)
SD
(Note 4)
N/−
A
B
C
BUE
SD
(Note 10)
(Note 7)

Note 1. For power supply specifications, refer to section 15.1.3.
2. Make up a sequence that will concurrently turn off the Emergency stop (EMG) of the drive unit and the Forced stop (EM1) of the converter unit, and shut off the main circuit power supply by the external sequence.
3. Make sure to connect between P_1 and P_2 terminals (Factory-wired). When using the power factor improving DC reactor, refer to section 15.9.6.
4. Connect P/+ and N/− terminals of the brake unit to a correct destination. Incorrect connection results in the converter unit and brake unit malfunction.
5. For the converter unit and the drive unit of 400V class, a stepdown transformer is required.
6. Contact rating: 1a contact, 110VAC_5A/220VAC_3A
Normal condition: TH1-TH2 is conducting. Abnormal condition: TH1-TH2 is not conducting.
7. Contact rating: 230VAC_0.3A/30VDC_0.3A
Normal condition: B-C is conducting/A-C is not conducting. Abnormal condition: B-C is not conducting/A-C is conducting.
8. Connect the thermal relay censor of the servo motor.
9. Do not connect more than one cable to each L+ and L− terminals of TE2-1 of the converter unit.
10. Make sure to connect between BUE and SD terminals (Factory-wired).
11. Connect MSG and SD terminals of the brake unit to a correct destination. Incorrect connection results in the converter unit and brake unit malfunction.
12. For connecting L+ and L−- terminals of TE2-1 of the converter unit to the terminal block, use the cable indicated in (3) (d) in this section.

(c) Precautions for wiring

The cables between the converter unit and the brake unit, and between the resistor unit and the brake unit should be as short as possible. Make sure to twist the cable longer than 5m (twist five times or more per one meter). Even when the cable is twisted, the cable should be less than 10m. Using cables longer than 5m without twisting or twisted cables longer than 10m, may result in the brake unit malfunction.

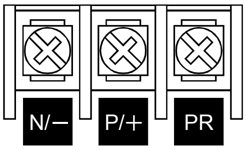


(d) Cables

1) Cables for the brake unit

For the brake unit, HIV cable (600V grade heat-resistant PVC insulated wire) is recommended.

a) Main circuit terminal



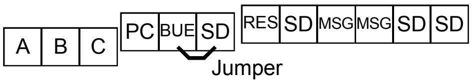
Terminal block

Brake unit		Main circuit terminal screw size	Crimping terminal	Tightening torque [N・m] ([lb・in])	Wire size	
					N/−, P/+, PR, ⏚	
			N/−, P/+, PR, ⏚		HIV wire [mm²]	AWG
200V class	FR-BU2-55K	M6	14-6	4.4 (38.9)	14	6
400V class	FR-BU2-H55K	M5	5.5-5	2.5 (22.1)	5.5	10
	FR-BU2-H75K	M6	14-6	4.4 (38.9)	14	6

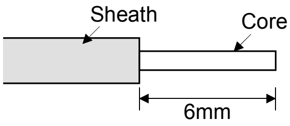
b) Control circuit terminal

POINT

- Undertightening can cause a cable disconnection or malfunction. Overtightening can cause a short circuit or malfunction due to damage to the screw or the brake unit.



Terminal block



Wire the stripped cable after twisting to prevent the cable from becoming loose. In addition, do not solder it.
Screw size: M3
Tightening torque: 0.5 to 0.6N・m
Wire size: 0.3 to 0.75 mm^2
Screw driver: Small flat-blade screwdriver
(Tip thickness: 0.4mm/Tip width 2.5mm)

2) Cables for connecting the servo amplifier and a distribution terminal block when connecting two sets of the brake unit

Brake unit		Wire size	
		HIV wire [mm^2]	AWG
200V class	FR-BU2-55K	38	2
400V class	FR-BU2-H55K	14	6
	FR-BU2-H75K	38	2

(e) Crimping terminals for L＋ and L－ terminals of TE2-1 of servo amplifier

1) Recommended crimping terminals

POINT

- Make sure to use recommended crimping terminals or equivalent since some crimping terminals cannot be installed depending on the size.

	Converter unit	Brake unit	Number of connected units	Crimping terminal (Manufacturer)	(Note 1) Applicable tool
200V class	MR-J3-CR55K	FR-BU2-55K	2	38-S6(Japan Solderless Terminals) (Note 2) R38-6S (NICHIFU) (Note 2)	a
400V class	MR-J3-CR55K4	FR-BU2-H55K	2	FVD14-6(Japan Solderless Terminals)	b
		FR-BU2-H75K	2	38-S6(Japan Solderless Terminals) (Note 2) R38-6S (NICHIFU) (Note 2)	a

Note 1. Symbols in the applicable tool field indicate the following applicable tools.

2. Coat the crimping part with an insulation tube.

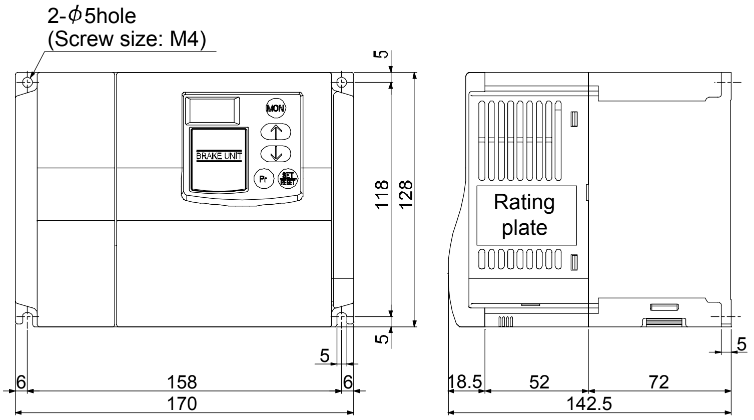
Symbol	Servo amplifier side crimping terminals				
	Crimping terminal	Crimping terminal			Manufacturer
		Body	Head	Dice	
a	38-S6	YPT-60-21		TD-124・TD-112	Japan Solderless Terminals
		YF-1・E-4	YET-60-1		
	R38-6S	NOP60 NOM60			NICHIFU
b	FDV14-6	YF-1・E-4	YNE-38	DH-112・DH-122	Japan Solderless Terminals

(4) Outline dimension drawings

(a) FR-BU2- (H) brake unit

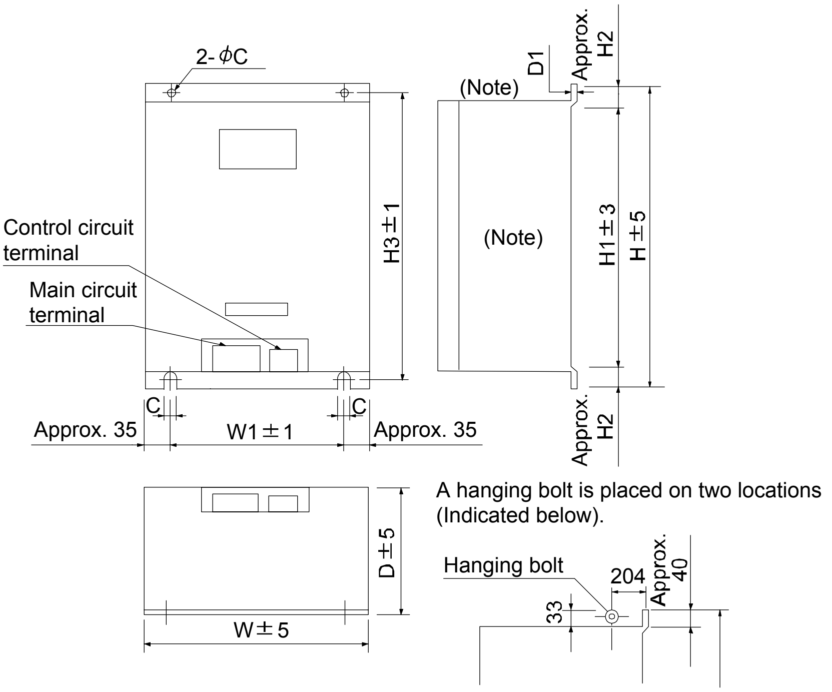
[Unit: mm]

FR-BU2-55K
FR-BU2-H55K, H75K



(b) FR-BR- (H) resistor unit

[Unit: mm]

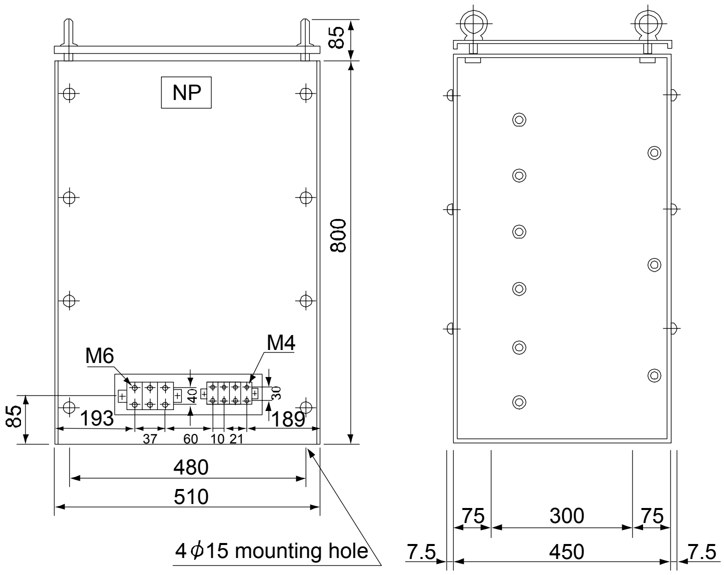


Note. Ventilation ports are provided on both sides and the top. The bottom is open.

Resistor unit		W	W1	H	H1	H2	H3	D	D1	C	Approximate mass [kg] ([lb])
200V class	FR-BR-55K	480	410	700	620	40	670	450	3.2	12	70 (154)
400V class	FR-BR-H55K	480	410	700	620	20	670	450	3.2	12	70 (154)

(c) MT-BR5- (H) resistor unit

[Unit: mm]



Resistor unit		Resistance value	Approximate mass [kg] ([lb])
200V class	MT-BR5-55K	2.0Ω	50 (110)
400V class	MT-BR5-H75K	6.5Ω	70 (154)

MEMO

16. PARAMETER UNIT (MR-PRU03)

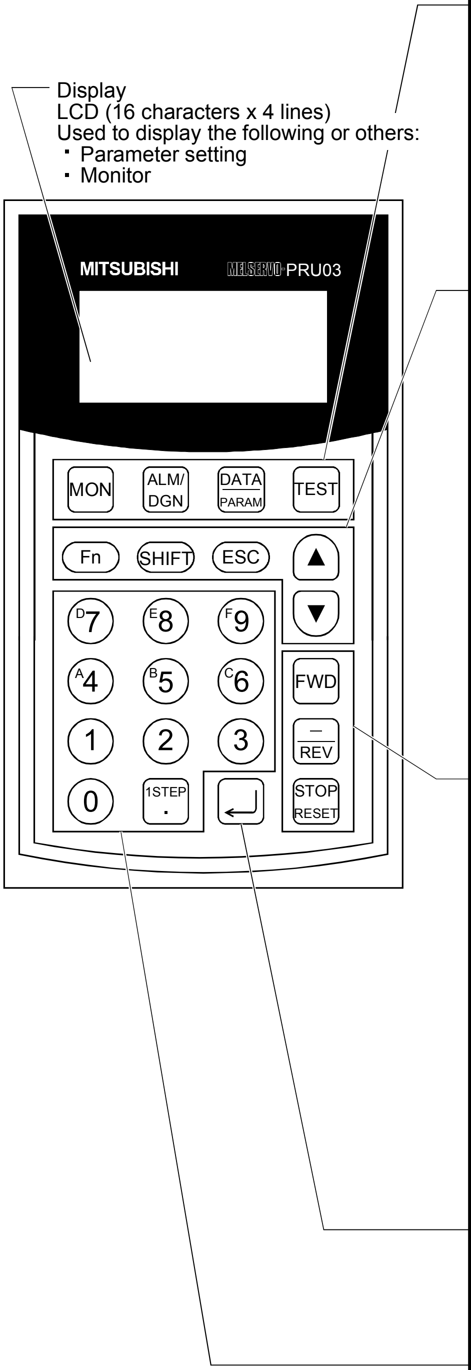
POINT

- Do not use MR-PRU03 parameter unit and MR Configurator together.

Perform simple data setting, test operation, parameter setting, etc. without MR Configurator by connecting the MR-PRU03 parameter unit to the servo amplifier (drive unit).

16.1 External appearance and key explanations

This section gives the external appearance and explanations of the keys.

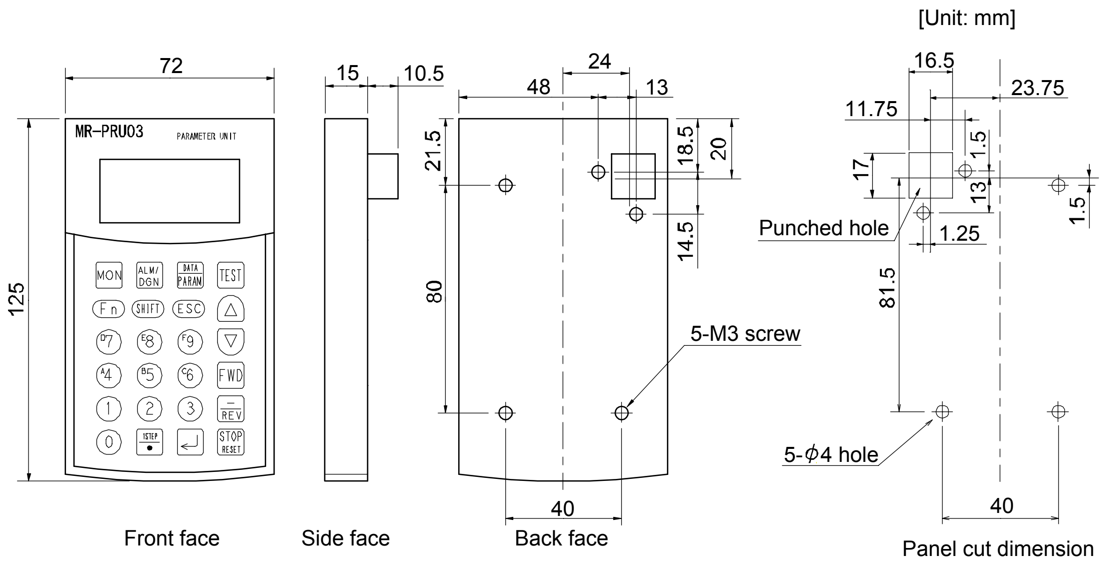


Key		Key explanations
Mode key	MON	Monitor mode key ・Used to display the monitor screen.
	ALM/ DGN	Alarm/diagnosis mode ・Used to display the alarm/DO forced output/diagnosis selection screen.
	DATA PARAM	Parameter mode key ・Used to display parameter selection screen.
	TEST	Test operation mode key ・Used to display the exit/JOG operation/positioning operation/motor-less operation/DO forced output/single-step feed selection screen.
Operation key	Fn	Function key ・Used to perform various operations in the test operation mode. ・Used to display the parameter range.
	SHIFT	SHIFT key ・Used to enter hexadecimal values. Press the "4" to "9" keys while holding down the "SHIFT" key to enter A to F. ・Press the "▲▼" keys while holding down the "SHIFT" key to move to the previous or next screen.
	ESC	ESC key ・Used to display the screen at one step upper hierarchical level. (not the pervious screen) ・Used to display the setting selection screen (the initial screen) of the monitor mode.
	▲ ▼	Scroll key ・Used to move the cursor across the screen or scroll the screen. Press this key while holding down the "SHIFT" key to move to the previous or next screen. ・Used to change parameter No.
Test Operation key	FWD	Forward rotation key ・Used to start the forward rotation in the test operation mode (JOG operation/positioning operation).
	– REV	Symbol key/reverse rotation key ・Used to start the reverse rotation in the test operation mode (JOG operation/positioning operation). ・Used together with the "SHIFT" key to enter negative values. To exit the negative value entry mode, press the "SHIFT" key again and press the "-" key. ("-" disappears.)
	STOP RESET	Stop/reset key ・Used to stop temporarily in the JOG operation/positioning operation. ・The "RESET" key is valid when the "Fn" key is not pressed (i.e. at a stop). ・Used to reset alarms or alarm history, or clear cumulated monitor data or inputs. ・Normal operation cannot be stopped with this key.
Enter key	↵	Enter key ・Used to determine the selection, numerical values, etc. ・Used to determine to exit the test operation mode, or enter the motor-less operation. ・Used to switch ON/OFF in the DO output screen.
Numerical key	0 to F9	Numerical keys ・Used to enter parameter No., setting values, etc. ・Press the "4" to "9" keys while holding down the "SHIFT" key to enter A to F.
	1STEP .	Decimal point key ・Used to enter a decimal point.

16.2 Specifications

Item		Description
Model		MR-PRU03
Power supply		Supplied from the servo amplifier (drive unit)
Functions	Parameter mode	Basic setting parameters, Gain/filter parameters, Extension setting parameters, I/O setting parameters
	Monitor mode (Status display)	Cumulative command pulses, Command pulse frequency, Analog speed command voltage/Analog speed limit voltage, Analog torque command voltage/Analog torque limit voltage, Feedback pulse value, Servo motor speed, Droop pulse, Regenerative load ratio, Effective load ratio, Peak load ratio, Instantaneous torque, Within one-revolution position, ABS counter, Load inertia moment ratio, Bus voltage
	Diagnosis mode	External I/O display, motor information
	Alarm mode	Current alarm, Alarm history
	Test operation mode	JOG operation, Positioning operation, DO forced output, Motor-less operation
Display section		LCD system (16 characters × 4 lines)
Environment	Ambient temperature	−10 to 55℃ (14 to 131℉) (non-freezing)
	Ambient humidity	90%RH or less (non-condensing)
	Storage temperature range	−20 to 65℃ (−4 to 149℉) (non-freezing)
	Storage humidity range	90%RH or less (non-condensing)
	Ambience	Indoors (no direct sunlight) Free from corrosive gas, flammable gas, oil mist, dust and dirt
Mass [g] ([lb])		130 (0.287)

16.3 Outline dimension drawings



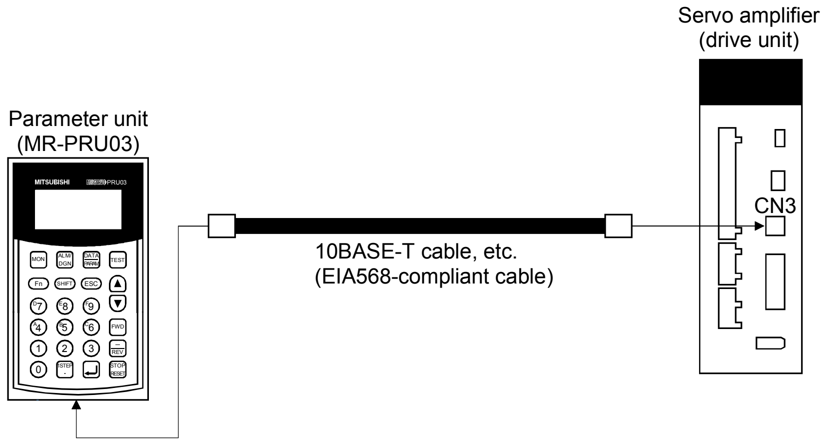
Front face Side face Back face Panel cut dimension

16.4 Connection with servo amplifier

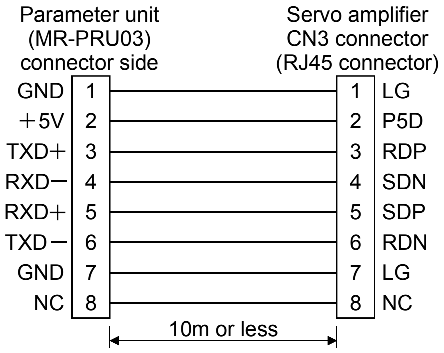
16.4.1 Single axis

(1) Configuration diagram

Operate the single-axis servo amplifier (drive unit). It is recommended to use the following cable.



(2) Cable internal wiring diagram

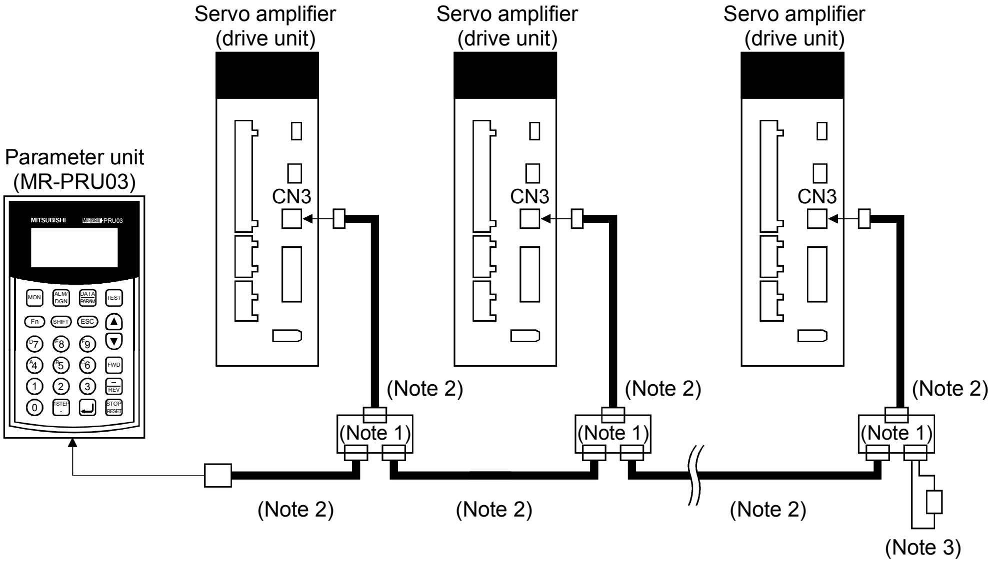


GND	1	1	LG
+5V	2	2	P5D
TXD+	3	3	RDP
RXD−	4	4	SDN
RXD+	5	5	SDP
TXD−	6	6	RDN
GND	7	7	LG
NC	8	8	NC

16.4.2 Multidrop connection

(1) Configuration diagram

Up to 32 axes of servo amplifiers (drive units) from stations 0 to 31 can be operated on the same bus.



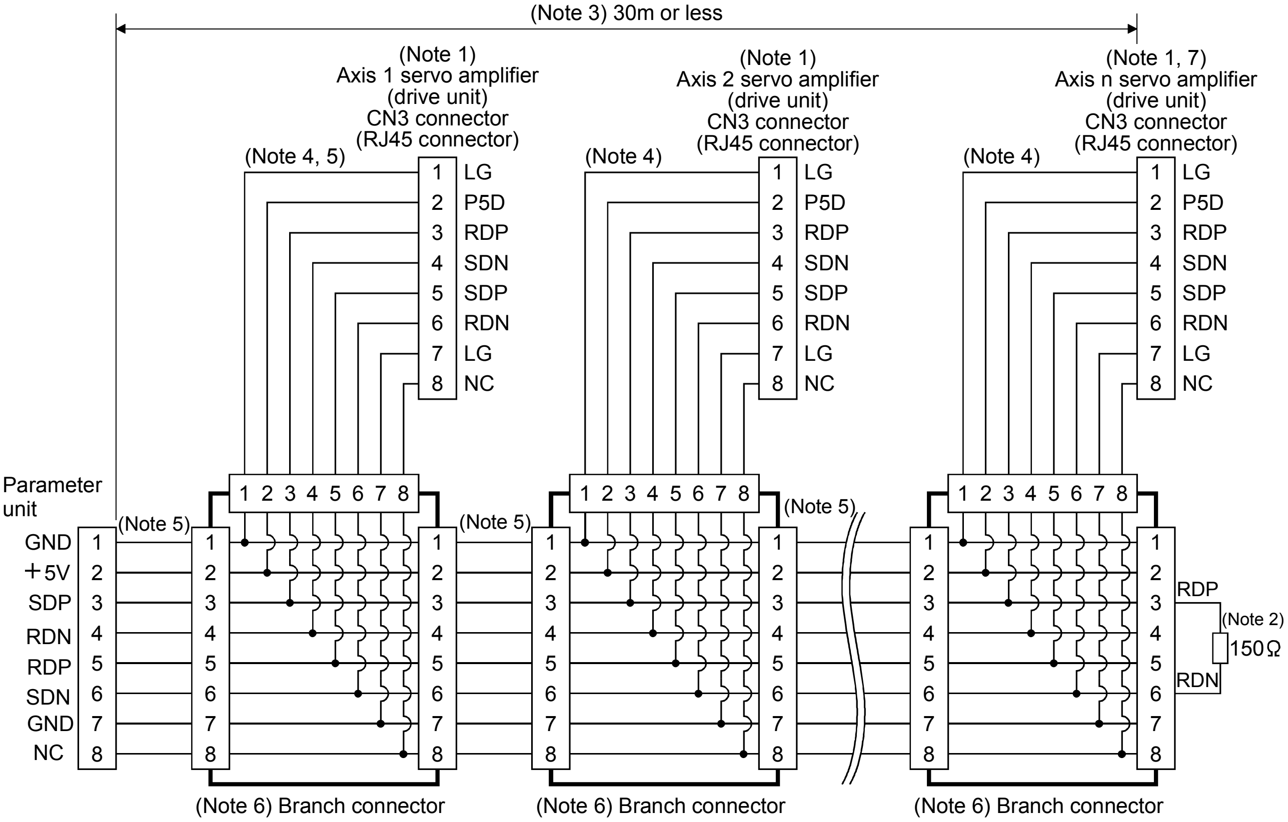
Note 1. The BMJ-8 (Hakko Electric Machine Works) is recommended as the branch connector.

2. Use the 10BASE-T cable (EIA568-compliant), etc.

3. The final axis must be terminated between RDP (pin No.3) and RDN (pin No.6) on the receiving side (servo amplifier (drive unit)) with a 150Ω resistor.

(2) Cable internal wiring diagram

Wire the cables as shown below.



Note 1. Recommended connector (Hirose Electric)

Plug: TM10P-88P

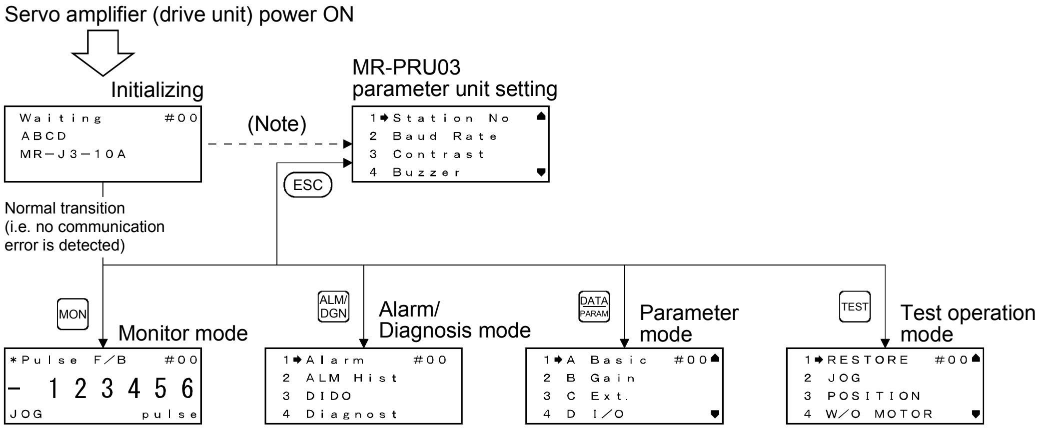
Connection tool: CL250-0228-1

2. The final axis must be terminated between RDP (pin No.3) and RDN (pin No.6) on the receiving side (servo amplifier (drive unit)) with a 150Ω resistor.
3. The overall length is 30m or less in low-noise environment.
4. The wiring between the branch connector and servo amplifier should be as short as possible.
5. Use the EIA568-compliant cable (10BASE-T cable, etc.).
6. Recommended branch connector: BMJ-8 (Hakko Electric Machine Works)
7. n ≤ 32 (Up to 32 axes can be connected.)

16.5 Display

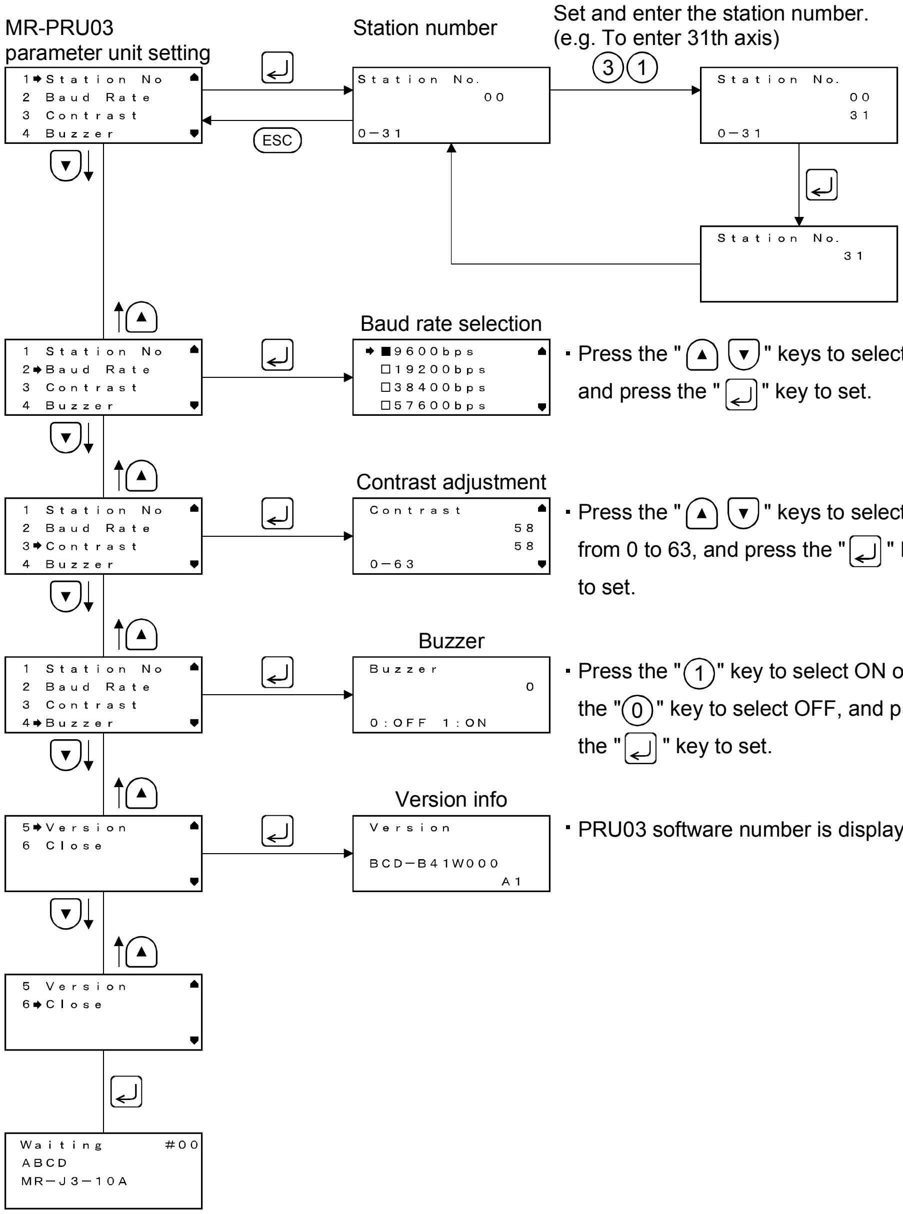
Connect the MR-PRU03 parameter unit to the servo amplifier (drive unit), and turn ON the power of the servo amplifier (drive unit). In this section, the screen transition of the MR-PRU03 parameter unit is explained, together with the operation procedure in each mode.

16.5.1 Outline of screen transition



Note. If initialization communication fails, a communication error is displayed. Press the "ESC" key to return to the PRU setting screen.

16.5.2 MR-PRU03 parameter unit setting



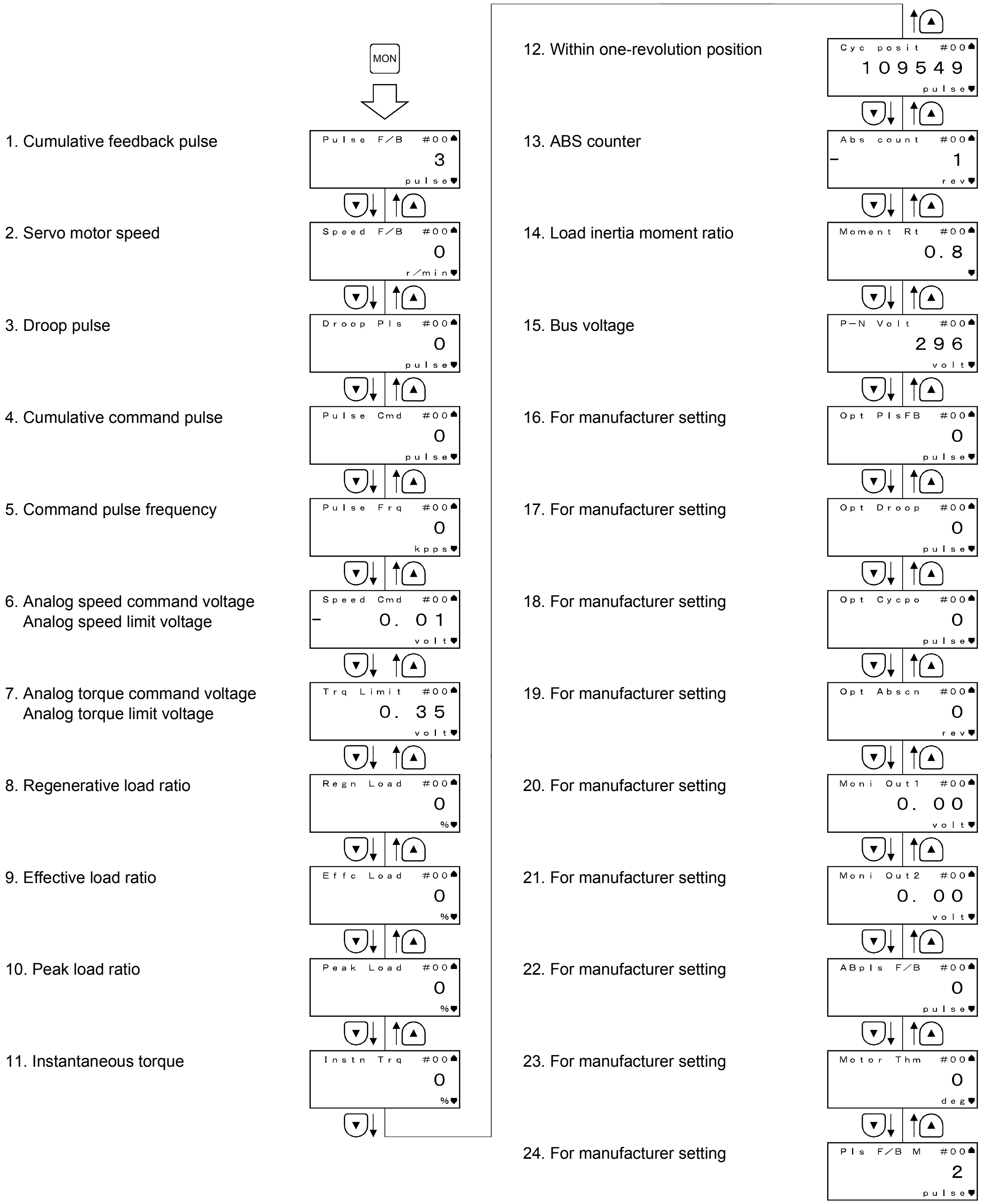
- Press the "▲ ▼" keys to select, and press the "↵" key to set.
- Press the "▲ ▼" keys to select from 0 to 63, and press the "↵" key to set.
- Press the "①" key to select ON or the "⓪" key to select OFF, and press the "↵" key to set.
- PRU03 software number is displayed.

Note. Press the "SHIFT" key and "ESC" key together on any screen to return to the station number setting screen.

16.5.3 Monitor mode (status display)

(1) Monitor display

The servo status during operation is shown on the display. Refer to (2) in this section for details.



(2) Monitor display list

The following table lists the items and descriptions of monitor display.

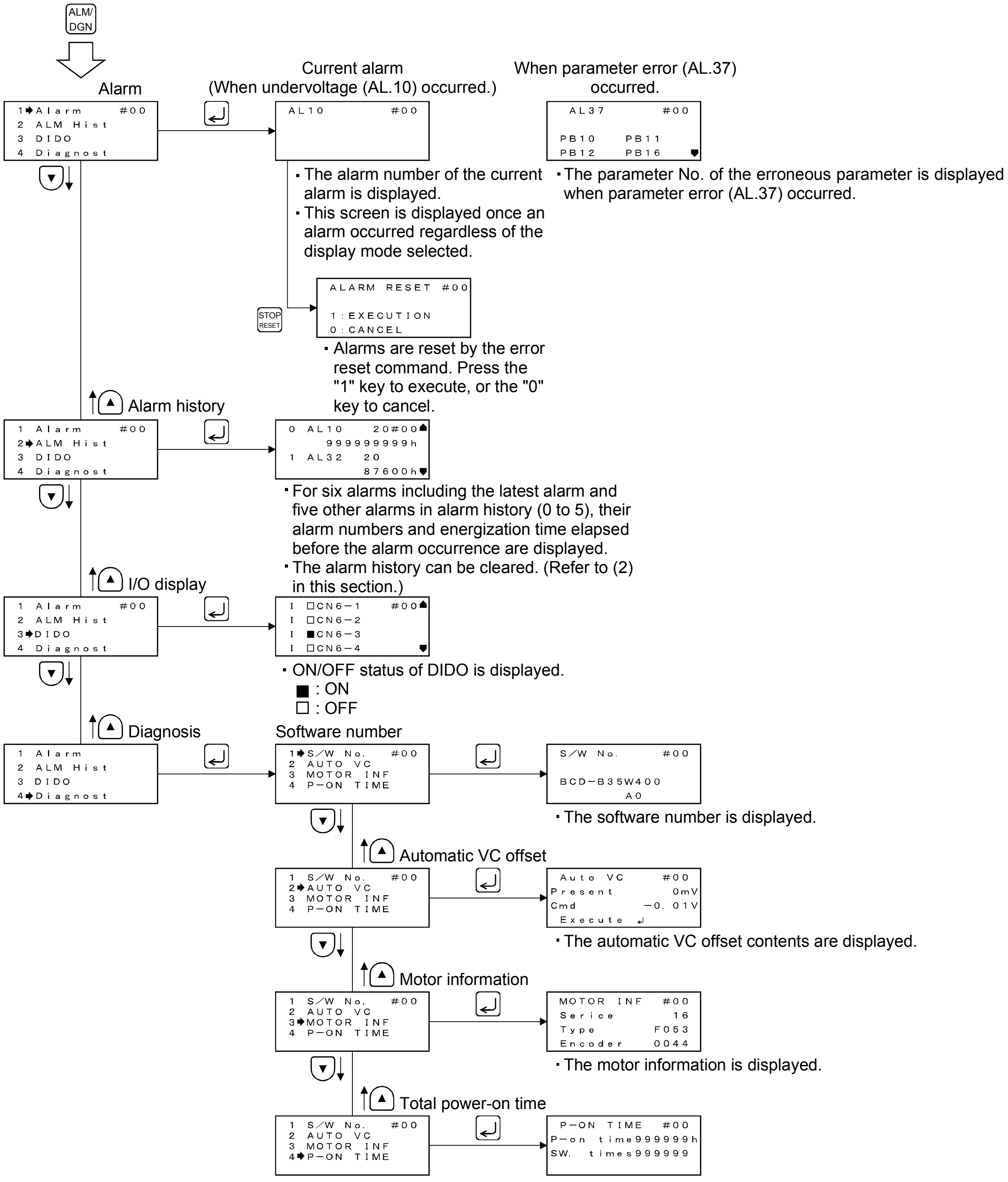
Status display	Display on parameter unit	Unit	Description	Display range
Cumulative feedback pulses	Pulse F/B	pulse	Feedback pulses from the servo motor encoder are counted and displayed. When the value exceeds ±999999, characters are displayed smaller. Press the "RESET" key of the parameter unit to reset the display value to zero.	−999999999 to 999999999
Servo motor speed	Speed F/B	r/min	The servo motor speed is displayed. "-" is added to the speed of the servo motor rotating in the reverse rotation. The value rounded off is displayed in ×0.1r/min.	−7200 to 7200
Droop pulse	Droop Pls	pulse	The number of droop pulses in the deviation counter is displayed. "- " is added to the reverse pulses. When the value exceeds ±999999, characters are displayed smaller. The number of pulses displayed is in the encoder pulse unit.	−999999999 to 999999999
Cumulative command pulses	Pulse Cmd	pulse	The position command input pulses are counted and displayed. As the value displayed is not yet multiplied by the electronic gear (CMX/CDV), it may not match the indication of the cumulative feedback pulses. When the value exceeds ±999999, characters are displayed smaller. Press the "RESET" key of the parameter unit to reset the display value to "0".	−999999999 to 999999999
Command pulse frequency	Pulse Frq	kpps	The frequency of the position command input pulses is displayed. The value displayed is not multiplied by the electronic gear (CMX/CDV).	−1500 to 1500
Analog speed command voltage Analog speed limit voltage	Speed Cmd	V	(1) Torque control mode Analog speed limit (VLA) voltage is displayed.	−10.00 to 10.00
			(2) Speed control mode Analog speed command (VC) voltage is displayed.	
Analog torque command voltage Analog torque limit voltage	Trq Limit	V	(1) Position control mode, speed control mode Analog torque limit (TLA) voltage is displayed.	0 to 10.00
			(2) Torque control mode Analog torque command (TLA) voltage is displayed.	−8.00 to +8.00
Regenerative load ratio	Regn Load	%	The ratio of regenerative power to permissible regenerative power is displayed in %. When regenerative option is used, the ratio to the permissible regenerative power is displayed.	0 to 100
Effective load ratio	Effc Load	%	The continuous effective load current is displayed. The effective value is displayed relative to the rated current of 100%.	0 to 300
Peak load ratio	Peak Load	%	The maximum torque is displayed. The highest value in the past 15 seconds is displayed relative to the rated torque of 100%.	0 to 400
Instantaneous torque	Instn Trq	%	Torque that occurred instantaneously is displayed. The value of the torque that occurred is displayed in real time relative to the rate torque of 100%.	0 to 400

Status display	Display on parameter unit	Unit	Description	Display range
Within one-revolution position	Cyc posit	pulse	Position within one revolution is displayed in encoder pulses. The value returns to 0 when it exceeds the maximum number of pulses. The value is incremented in the CCW direction of rotation.	0 to 262143
ABS counter	Abs count	rev	Travel value from the home position in the absolute position detection systems is displayed in terms of the absolute position detectors counter value.	－32768 to 32767
Load inertia moment ratio	Moment Rt	Multiplier (×1)	The estimated ratio of the load inertia moment to the servo motor shaft inertia moment is displayed.	0.0 to 300.0
Bus voltage	P-N Volt	V	The voltage (across P(＋) - N(－)) of the main circuit converter is displayed.	0 to 900

16.5.4 Alarm/diagnostic mode

(1) Alarm display

The flowchart below shows the procedure of settings involving alarms, alarm history, external I/O signal (DIDO) display, device and diagnosis.



- The alarm number of the current alarm is displayed.
- This screen is displayed once an alarm occurred regardless of the display mode selected.

- The parameter No. of the erroneous parameter is displayed when parameter error (AL.37) occurred.

- Alarms are reset by the error reset command. Press the "1" key to execute, or the "0" key to cancel.

- For six alarms including the latest alarm and five other alarms in alarm history (0 to 5), their alarm numbers and energization time elapsed before the alarm occurrence are displayed.
- The alarm history can be cleared. (Refer to (2) in this section.)

- ON/OFF status of DIDO is displayed.
  ■ : ON
  ☐ : OFF

- The software number is displayed.

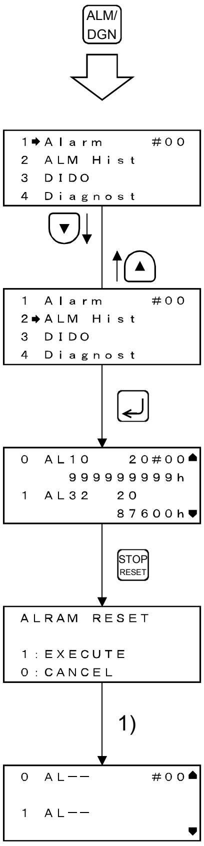
- The automatic VC offset contents are displayed.

- The motor information is displayed.

- The total power-on time (P-on) and the number of power-on times (SW.) since shipped are displayed.

(2) Alarm history clear

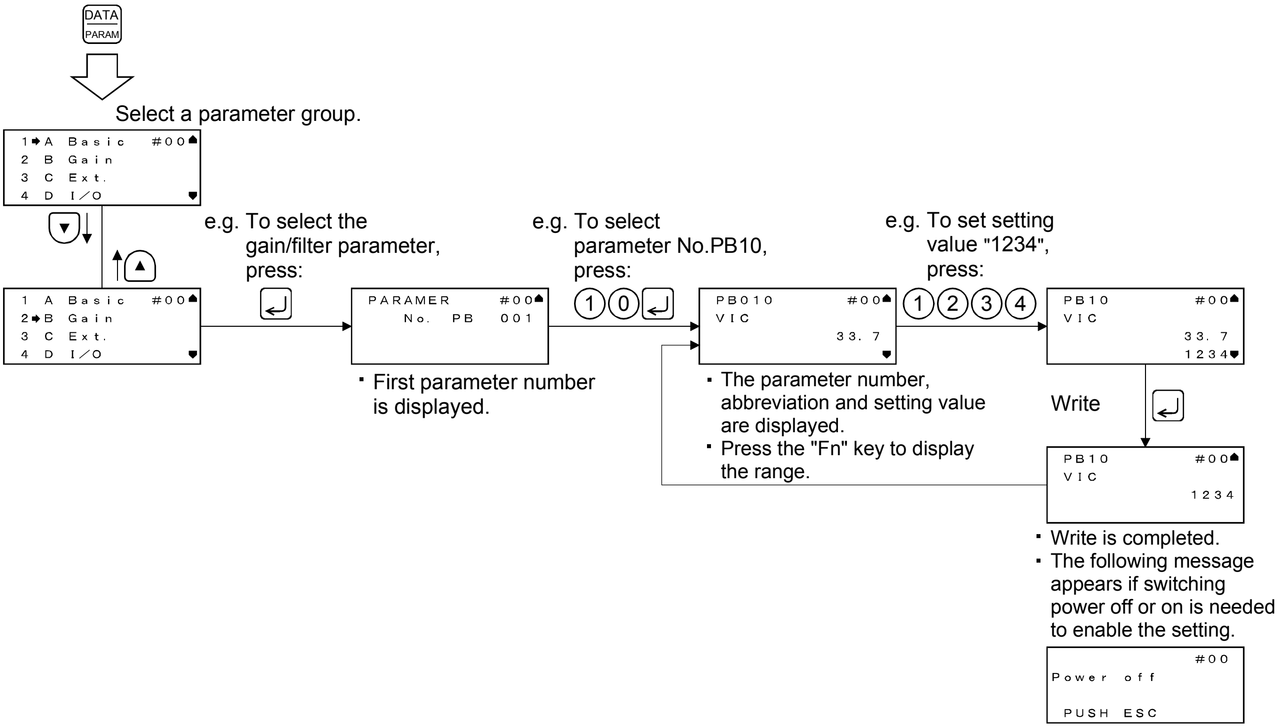
The servo amplifier stores one current alarm and five past alarms from when its power is switched on first. To control alarms which will occur during operation, clear the alarm history before starting operation.



- Select "ALM Hist".
- For six alarms including the latest alarm and five other alarms in alarm history (0 to 5), their alarm numbers and energization time elapsed before the alarm occurrence are displayed.
- The alarm history clear menu is displayed.
- Select "1" to clear the alarm history.

16.5.5 Parameter mode

The flowchart below shows the procedure for setting parameters.



Select a parameter group.

e.g. To select the gain/filter parameter, press:

e.g. To select parameter No.PB10, press:

e.g. To set setting value "1234", press:

- First parameter number is displayed.

- The parameter number, abbreviation and setting value are displayed.
- Press the "Fn" key to display the range.

Write

- Write is completed.
- The following message appears if switching power off or on is needed to enable the setting.

16.5.6 Test operation mode

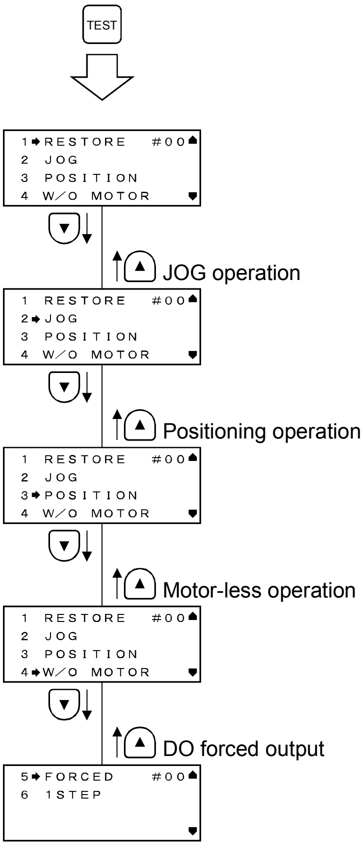
⚠ CAUTION

- When confirming the machine operation in the test operation mode, use the machine after checking that the safety mechanism such as the emergency stop (EMG) operates.
- If any operational fault has occurred, stop operation using the emergency stop (EMG).

POINT

- The test operation mode cannot be used in the absolute position detection system. Use it after choosing "□□□0" in parameter No.PA03.
- Test operation cannot be executed without turning the servo OFF.

Exiting test/JOG operation/positioning operation/motor-less operation/DO forced stop can be performed in this mode. The following shows how to set each operation.
When the servo motor with an electromagnetic brake is used, make sure to program a sequence circuit which will operate the electromagnetic brake by the servo amplifier electromagnetic brake interlock (MBR).



(1) JOG operation

JOG operation can be performed when there is no command from the external command device. Connect EMG-DOCOM to start JOG operation.

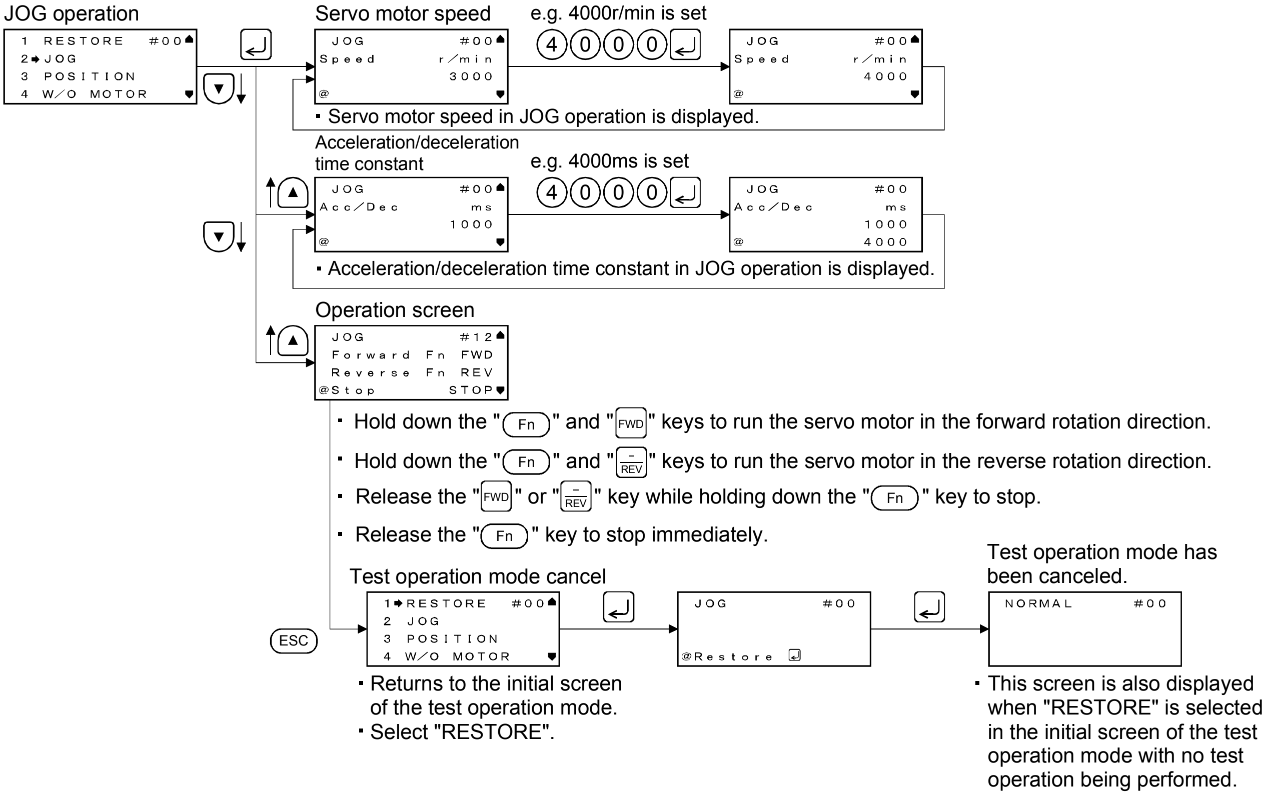
(a) Operation/cancel

You can change the operation conditions with the parameter unit. The initial conditions and setting ranges for operation are listed below.

Item	Initial setting	Setting range
Speed [r/min]	200	0 to instantaneous permissible speed
(Note) Acceleration/deceleration time constant [ms]	1000	0 to 20000

Note. Acceleration time constant refers to time required to reach the rated speed from stop status (0r/min), and deceleration time constant refers to time required to reach 0r/min from the rated speed.

The following shows the operation condition settings and the operation procedures.



- Servo motor speed in JOG operation is displayed.
- Acceleration/deceleration time constant in JOG operation is displayed.
- Hold down the "Fn" and "FWD" keys to run the servo motor in the forward rotation direction.
- Hold down the "Fn" and "REV" keys to run the servo motor in the reverse rotation direction.
- Release the "FWD" or "REV" key while holding down the "Fn" key to stop.
- Release the "Fn" key to stop immediately.
- Returns to the initial screen of the test operation mode.
- Select "RESTORE".
- This screen is also displayed when "RESTORE" is selected in the initial screen of the test operation mode with no test operation being performed.

If the parameter unit cable is disconnected during JOG operation, the servo motor will be decelerated to a stop.

(b) Status display

You can monitor the status display even during JOG operation. At this time, the "FWD", "REV" and "STOP" keys can be used.

(2) Positioning operation

Positioning operation can be performed once when there is no command from the external command device.

Connect EMG-DOCOM to start positioning operation.

(a) Operation/cancel

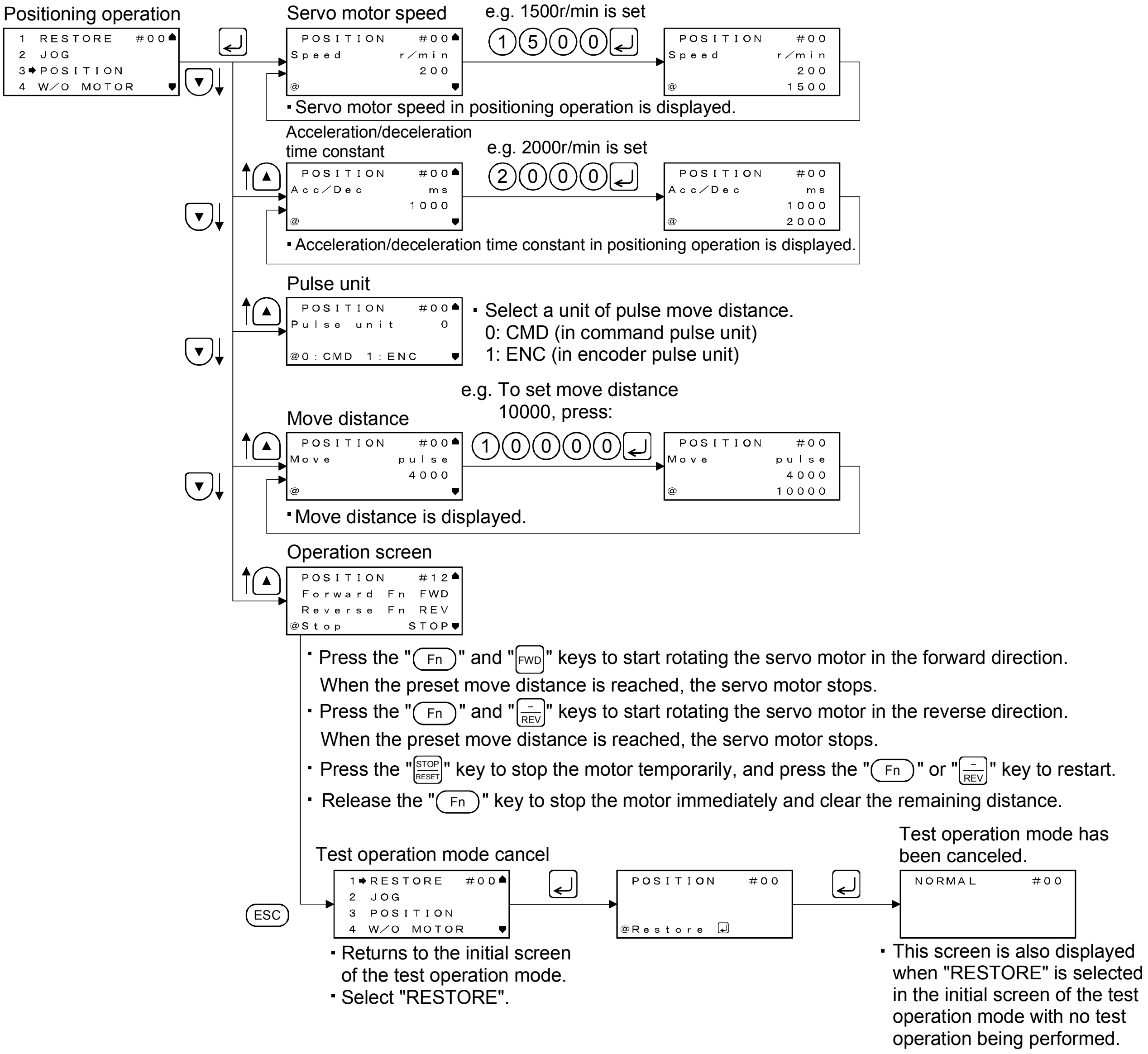
You can change the operation conditions with the parameter unit. The initial conditions and setting ranges for operation are listed below.

Item	Initial setting	Setting range
Speed [r/min]	200	0 to instantaneous permissible speed
(Note 2) Acceleration/deceleration time constant [ms]	1000	0 to 20000
(Note 1) Travel distance [pulse]	4000	0 to 99999999

Note 1. The unit of move distance can be changed using feed length multiplication factor selection of parameter No.PA05.

2. Acceleration time constant refers to time required to reach the rated speed from stop status (0r/min), and deceleration time constant refers to time required to reach 0r/min from the rated speed.

The following shows the operation condition settings and the operation procedures.



- Servo motor speed in positioning operation is displayed.
- Acceleration/deceleration time constant in positioning operation is displayed.
- Select a unit of pulse move distance.
  0: CMD (in command pulse unit)
  1: ENC (in encoder pulse unit)
- Move distance is displayed.
- Press the "Fn" and "FWD" keys to start rotating the servo motor in the forward direction. When the preset move distance is reached, the servo motor stops.
- Press the "Fn" and "–REV" keys to start rotating the servo motor in the reverse direction. When the preset move distance is reached, the servo motor stops.
- Press the "STOP RESET" key to stop the motor temporarily, and press the "Fn" or "–REV" key to restart.
- Release the "Fn" key to stop the motor immediately and clear the remaining distance.
- Returns to the initial screen of the test operation mode.
- Select "RESTORE".
- This screen is also displayed when "RESTORE" is selected in the initial screen of the test operation mode with no test operation being performed.

If the communication cable is disconnected during positioning operation, the servo motor will come to a sudden stop.

(b) Status display

You can monitor the status display even during positioning operation. At this time, the "FWD", "REV" and "STOP" keys can be used.

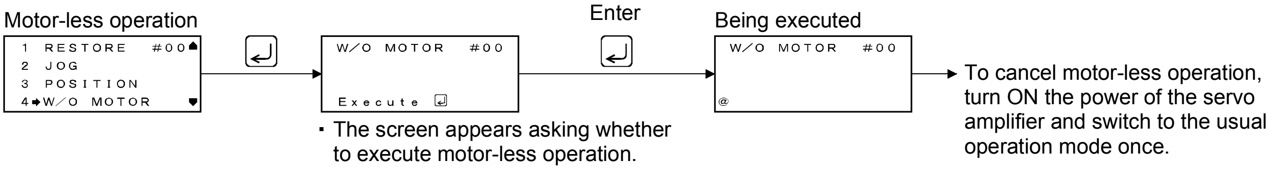
(3) Motor-less operation

Without connecting the servo motor, you can provide output signals or monitor the status display as if the servo motor is running in response to. This operation can be used to check the sequence of a sequencer or the like.

(a) Operation/cancel

After turning off the SON signal, choose motor-less operation. After that, perform external operation as in ordinary operation.

The following shows the operation procedures.



- The screen appears asking whether to execute motor-less operation.

To cancel motor-less operation, turn ON the power of the servo amplifier and switch to the usual operation mode once.

(b) Status display

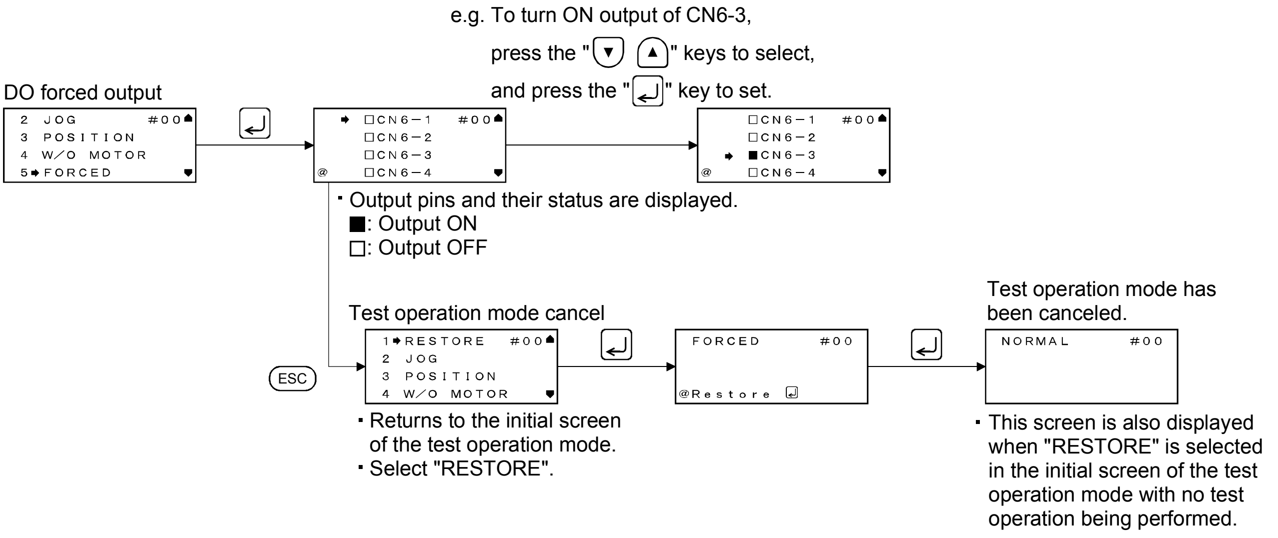
You can monitor the status display even during motor-less operation.

(4) DO forced output

Each output signal can be forced on/off independently of the servo status. This function is used for the servo wiring check, etc.

Connect EMG-DOCOM to start DO forced output.

The following shows the operation procedures.



e.g. To turn ON output of CN6-3, press the "▼ ▲" keys to select, and press the "↵" key to set.

- Output pins and their status are displayed.
  ■: Output ON
  □: Output OFF

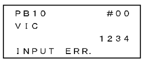
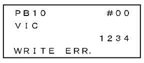
- Returns to the initial screen of the test operation mode.
- Select "RESTORE".

- This screen is also displayed when "RESTORE" is selected in the initial screen of the test operation mode with no test operation being performed.

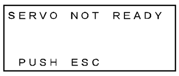
16.6 Error message list

When using the MR-PRU03 parameter unit, the following error messages may be displayed. When displayed, refer to this section to remove cause.

(1) Error messages

Error description	Message	Cause
Communication error	 #00 COMMUNICATION ERROR PUSH ESC	1. Hardware reason 2. Mismatch in station number 3. Mismatch in baud rate
Setting error	 PB10 #00 VIC 1234 INPUT ERR.	Incorrect input, etc.
Write error	 PB10 #00 VIC 1234 WRITE ERR.	Value is written while write is disabled.
EEP-ROM write error	 #00 EEPROM ERR. PUSH ESC	1. Parts in the MR-PRU03 parameter unit are faulty. 2. EEP-ROM built in the MR-PRU03 parameter unit has been overwritten more than 100000 times.

(2) Messages

Message	Description
 #00 Power off PUSH ESC	Valid parameters were written when power is off.
 #00 DO NOT CHANGE STATION NO PUSH ESC	The MR-PRU03 parameter unit was used to set a station number and perform transition during the test operation mode.
 #00 SET TEST DRIVE DIFFER PUSH ESC	Operation mode is the test operation mode.
 #00 TEST MODE CHANGED PUSH ESC	The test mode was changed due to external factor.
 #00 DO NOT READ PARAMETER PUSH ESC	Reading settings specified for the parameter write disable (parameter No.PA19) was attempted.
 TEST DRIVE ON PUSH ESC	In the test operation, the "ESC" key was pressed while the "Fn" key was held down to switch the screen to the MR-PRU03 parameter unit setting screen.
 SERVO NOT READY PUSH ESC	The ready cannot be turned ON due to alarm, etc.
 #12 SON ON PUSH ESC	Operation mode can be switched to the test operation mode at servo-on.
 #12 DO NOT CHANGE STATION NO PUSH ESC	Station number change was attempted in the test operation mode.

MEMO

App. 1 Parameter list

POINT

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

App. 1.1 Servo amplifier (drive unit)

Basic setting parameters (PA□□)			
No.	Symbol	Name	Control mode
PA01	*STY	Control mode	P・S・T
PA02	*REG	Regenerative option	P・S・T
PA03	*ABS	Absolute position detection system	P
PA04	*AOP1	Function selection A-1	P・S・T
PA05	*FBP	Number of command input pulses per revolution	P
PA06	CMX	Electronic gear numerator (Command pulse multiplying factor numerator)	P
PA07	CDV	Electronic gear denominator (Command pulse multiplying factor denominator)	P
PA08	ATU	Auto tuning mode	P・S
PA09	RSP	Auto tuning response	P・S
PA10	INP	Control mode, regenerative option selection	P
PA11	TLP	Forward rotation torque limit	P・S・T
PA12	TLN	Reverse rotation torque limit	P・S・T
PA13	*PLSS	Command pulse input form	P
PA14	*POL	Rotation direction selection	P
PA15	*ENR	Encoder output pulses	P・S・T
PA16 to PA18		For manufacturer setting	
PA19	*BLK	Parameter write inhibit	P・S・T

Gain/filter parameters (PB□□)			
No.	Symbol	Name	Control mode
PB01	FILT	Adaptive tuning mode (Adaptive filter Ⅱ)	P・S
PB02	VRFT	Vibration suppression control tuning mode (Advanced vibration suppression control)	P
PB03	PST	Position command acceleration/ deceleration time constant (Position smoothing)	P
PB04	FFC	Feed forward gain	P
PB05		For manufacturer setting	
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment	P・S
PB07	PG1	Model loop gain	P
PB08	PG2	Position loop gain	P
PB09	VG2	Speed loop gain	P・S
PB10	VIC	Speed integral compensation	P・S
PB11	VDC	Speed differential compensation	P・S
PB12	OVA	Overshoot amount compensation	P・S
PB13	NH1	Machine resonance suppression filter 1	P・S
PB14	NHQ1	Notch shape selection 1	P
PB15	NH2	Machine resonance suppression filter 2	P
PB16	NHQ2	Notch shape selection 2	P
PB17		Automatic setting parameter	
PB18	LPF	Low-pass filter setting	P
PB19	VRF1	Vibration suppression control vibration frequency setting	P
PB20	VRF2	Vibration suppression control resonance frequency setting	P
PB21		For manufacturer setting	
PB22			
PB23	VFBF	Low-pass filter selection	P
PB24	*MVS	Slight vibration suppression control selection	P・S
PB25	*BOP1	Function selection B-1	P
PB26	*CDP	Gain changing selection	P・S
PB27	CDL	Gain changing condition	P・S
PB28	CDT	Gain changing time constant	P・S
PB29	GD2B	Gain changing ratio of load inertia moment to servo motor inertia moment	P・S
PB30	PG2B	Gain changing position loop gain	P
PB31	VG2B	Gain changing speed loop gain	P・S
PB32	VICB	Gain changing speed integral compensation	P・S
PB33	VRF1B	Gain changing vibration suppression control vibration frequency setting	P
PB34	VRF2B	Gain changing vibration suppression control resonance frequency setting	P
PB35 to PB44		For manufacturer setting	
PB45	CNHF	Vibration suppression control filter 2	P

Extension setting parameters (PC□□)			
No.	Symbol	Name	Control mode
PC01	STA	Acceleration time constant	S・T
PC02	STB	Deceleration time constant	S・T
PC03	STC	S-pattern acceleration/ deceleration time constant	S・T
PC04	TQC	Torque command time constant	T
PC05	SC1	Internal speed command 1	S
		Internal speed limit 1	T
PC06	SC2	Internal speed command 2	S
		Internal speed limit 2	T
PC07	SC3	Internal speed command 3	S
		Internal speed limit 3	T
PC08	SC4	Internal speed command 4	S
		Internal speed limit 4	T
PC09	SC5	Internal speed command 5	S
		Internal speed limit 5	T
PC10	SC6	Internal speed command 6	S
		Internal speed limit 6	T
PC11	SC7	Internal speed command 7	S
		Internal speed limit 7	T
PC12	VCM	Analog speed command maximum speed	S
		Analog speed limit maximum speed	T
PC13	TLC	Analog torque command maximum output	T
PC14	MOD1	Analog monitor 1 output	P・S・T
PC15	MOD2	Analog monitor 2 output	P・S・T
PC16	MBR	Electromagnetic brake sequence output	P・S・T
PC17	ZSP	Zero speed	P・S・T
PC18	*BPS	Alarm history clear	P・S・T
PC19	*ENRS	Encoder output pulses selection	P・S・T
PC20	*SNO	Parameter block	P・S・T
PC21	*SOP	communication function selection	P・S・T
PC22	*COP1	Function selection C-1	P・S・T
PC23	*COP2	Function selection C-2	S・T
PC24	*COP3	Function selection C-3	P
PC25		For manufacturer setting	
PC26	*COP5	Function selection C-5	P・S
PC27	*COP6	Function selection C-6	P・S・T
PC28		For manufacturer setting	
PC29			
PC30	STA2	Acceleration time constant 2	S・T
PC31	STB2	Deceleration time constant 2	S・T
PC32	CMX2	Command pulse multiplying factor numerator 2	P
PC33	CMX3	Command pulse multiplying factor numerator 3	P
PC34	CMX4	Command pulse multiplying factor numerator 4	P
PC35	TL2	Internal torque limit 2	P・S・T
PC36	*DMD	Status display selection	P・S・T
PC37	VCO	Analog speed command offset	S
		Analog speed limit offset	T
PC38	TPO	Analog torque command offset	T
		Analog torque limit offset	S
PC39	MO1	Analog monitor 1 offset	P・S・T
PC40	MO2	Analog monitor 2 offset	P・S・T
PC41 to PC50		For manufacturer setting	

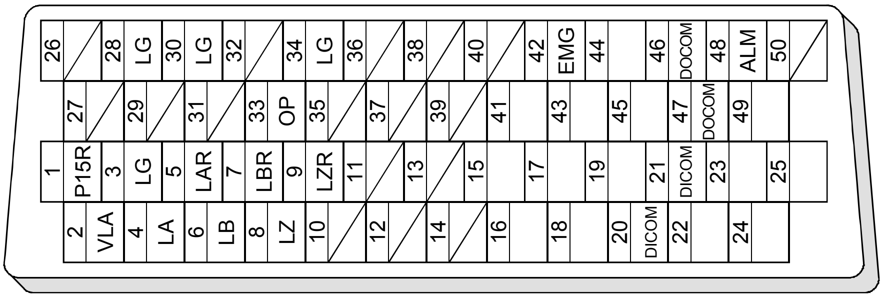
I/O setting parameters (PD□□)			
No.	Symbol	Name	Control mode
PD01	*DIA1	Input signal automatic ON selection 1	P・S・T
PD02		For manufacturer setting	
PD03	*DI1	Input signal device selection 1 (CN1-pin 15)	P・S・T
PD04	*DI2	Input signal device selection 2 (CN1-pin 16)	P・S・T
PD05	*DI3	Input signal device selection 3 (CN1-pin 17)	P・S・T
PD06	*DI4	Input signal device selection 4 (CN1-pin 18)	P・S・T
PD07	*DI5	Input signal device selection 5 (CN1-pin 19)	P・S・T
PD08	*DI6	Input signal device selection 6 (CN1-pin 41)	P・S・T
PD09		For manufacturer setting	
PD10	*DI8	Input signal device selection 8 (CN1-pin 43)	P・S・T
PD11	*DI9	Input signal device selection 9 (CN1-pin 44)	P・S・T
PD12	*DI10	Input signal device selection 10 (CN1-pin 45)	P・S・T
PD13	*DO1	Output signal device selection 1 (CN1-pin 22)	P・S・T
PD14	*DO2	Output signal device selection 2 (CN1-pin 23)	P・S・T
PD15	*DO3	Output signal device selection 3 (CN1-pin 24)	P・S・T
PD16	*DO4	Output signal device selection 4 (CN1-pin 25)	P・S・T
PD17		For manufacturer setting	
PD18	*DO6	Output signal device selection 6 (CN1-pin 49)	P・S・T
PD19	*DIF	Input filter setting	P・S・T
PD20	*DOP1	Function selection D-1	P・S・T
PD21		For manufacturer setting	
PD22	*DOP3	Function selection D-2	P
PD23		For manufacturer setting	
PD24	*DOP5	Function selection D-4	P・S・T
PD25 to PD30		For manufacturer setting	

App. 1.2 Converter unit

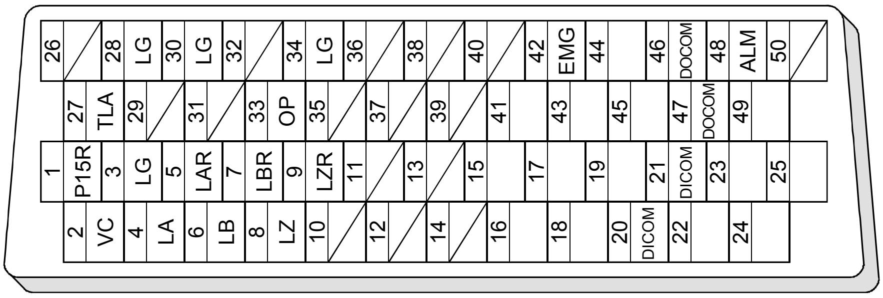
No.	Symbol	Name
PA01	*REG	Regenerative selection
PA02	*MCC	Magnetic contactor drive output selection
PA03 to PA07		For manufacturer setting
PA08	*DMD	Auto tuning mode
PA09	*BPS	Alarm history clear
PA10		For manufacturer setting
PA11		
PA12	*DIF	Input filter setting
PA13 to PA19		For manufacture setting

App. 2 Signal layout recording paper

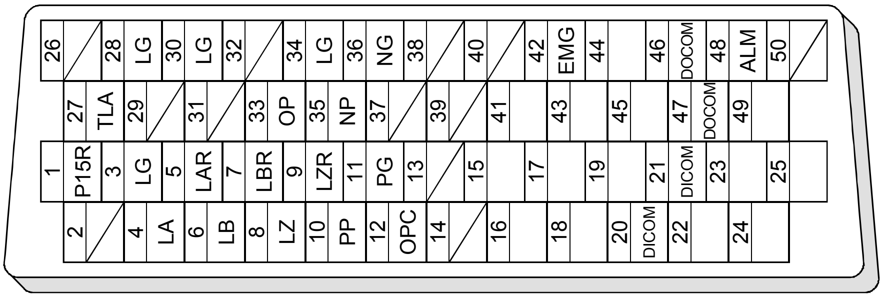
Torque control mode
CN1



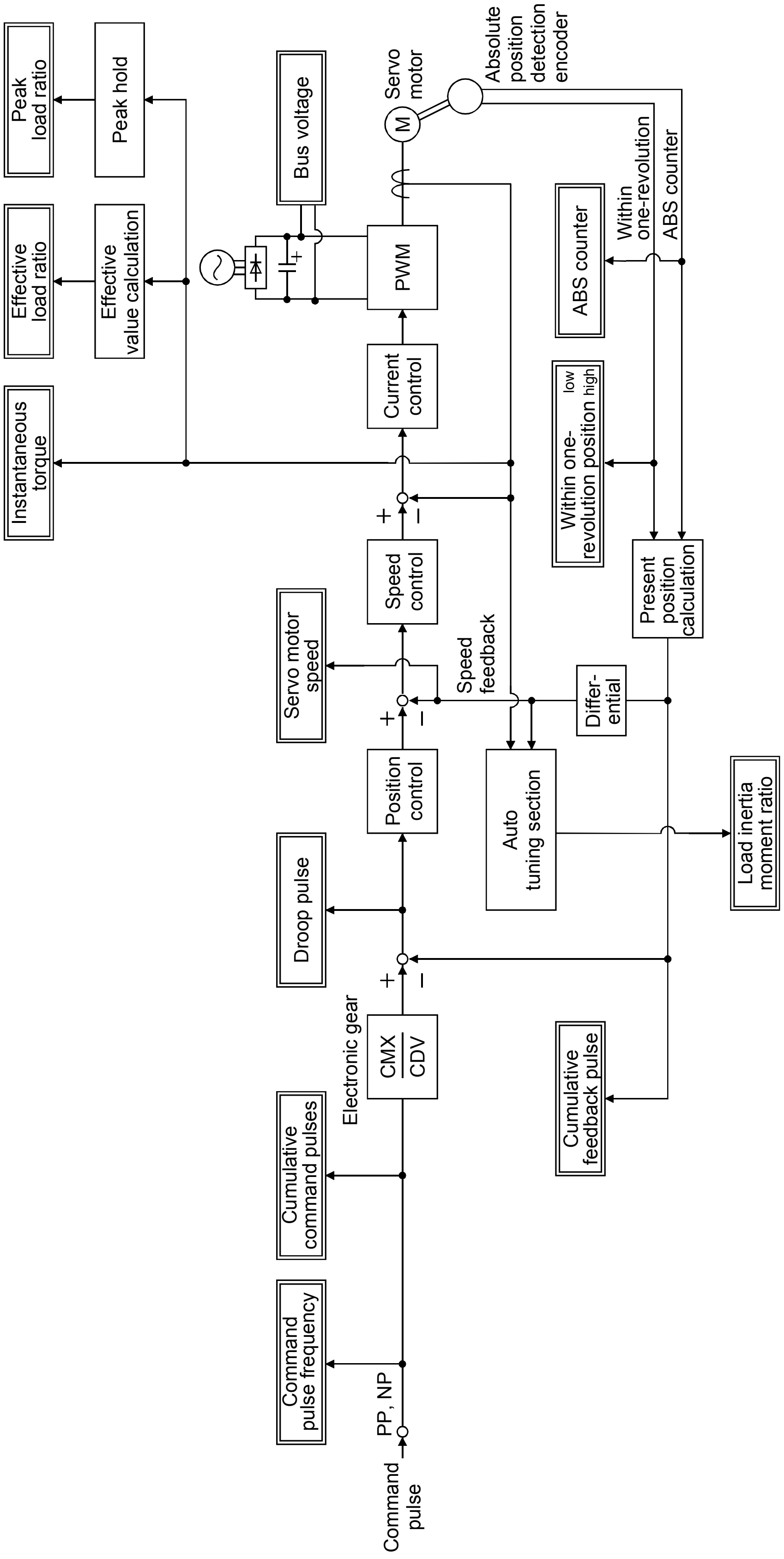
Speed control mode
CN1



Position control mode
CN1



App. 3 Status display block diagram



App. 4 Change of connector sets to the RoHS compatible products

The following connector sets have changed to RoHS compliant since September 2006.
Only the components of the connector set that have changed are listed below.

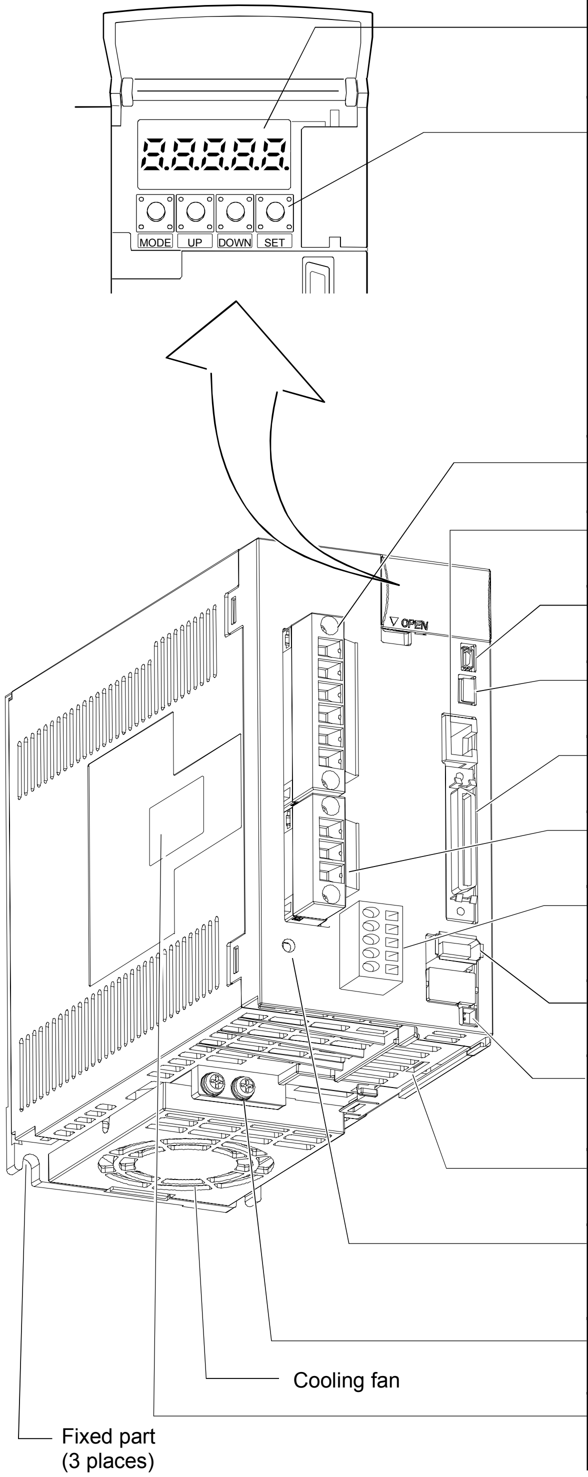
Model	Current product	RoHS compatible product
MR-J3SCNS MR-ECNM	Amplifier connector (3M or equivalent of 3M) 36210-0100JL (Receptacle) (Note)	Amplifier connector (3M or equivalent of 3M) 36210-0100PL (Receptacle)
MR-PWCNS4	Power supply connector (DDK) CE05-6A18-10SD-B-BSS (Connector and Back shell) CE3057-10A-1 (D265) (Cable clump)	Power supply connector (DDK) CE05-6A18-10SD-D-BSS (Connector and Back shell) CE3057-10A-1-D (Cable clump)
MR-PWCNS5	Power supply connector (DDK) CE05-6A22-22SD-B-BSS (Connector and Back shell) CE3057-12A-1 (D265) (Cable clump)	Power supply connector (DDK) CE05-6A22-22SD-D-BSS (Connector and Back shell) CE3057-12A-1-D (Cable clump)
MR-PWCNS3	Power supply connector (DDK) CE05-6A32-17SD-B-BSS (Connector and Back shell) CE3057-20A-1 (D265) (Cable clump)	Power supply connector (DDK) CE05-6A32-17SD-D-BSS (Connector and Back shell) CE3057-20A-1-D (Cable clump)
MR-PWCNS1	Power supply connector (DDK) CE05-6A22-23SD-B-BSS (Connector and Back shell) CE3057-12A-2 (D265) (Cable clump)	Power supply connector (DDK) CE05-6A22-23SD-D-BSS (Connector and Back shell) CE3057-12A-2-D (Cable clump)
MR-PWCNS2	Power supply connector (DDK) CE05-6A24-10SD-B-BSS (Connector and Back shell) CE3057-16A-2 (D265) (Cable clump)	Power supply connector (DDK) CE05-6A24-10SD-D-BSS (Connector and Back shell) CE3057-16A-2-D (Cable clump)
MR-BKCN	Electromagnetic brake connector MS3106A10SL-4S(D190) (Plug, DDK)	Electromagnetic brake connector D/MS3106A10SL-4S(D190) (Plug, DDK)
MR-J3CN1	Amplifier connector (3M or equivalent of 3M) 10150-3000VE (connector)	Amplifier connector (3M or equivalent of 3M) 10150-3000PE (connector)

Note. RoHS compatible 36210-0100FD may be packed with current connector sets.

App. 5 MR-J3-200A-RT servo amplifier

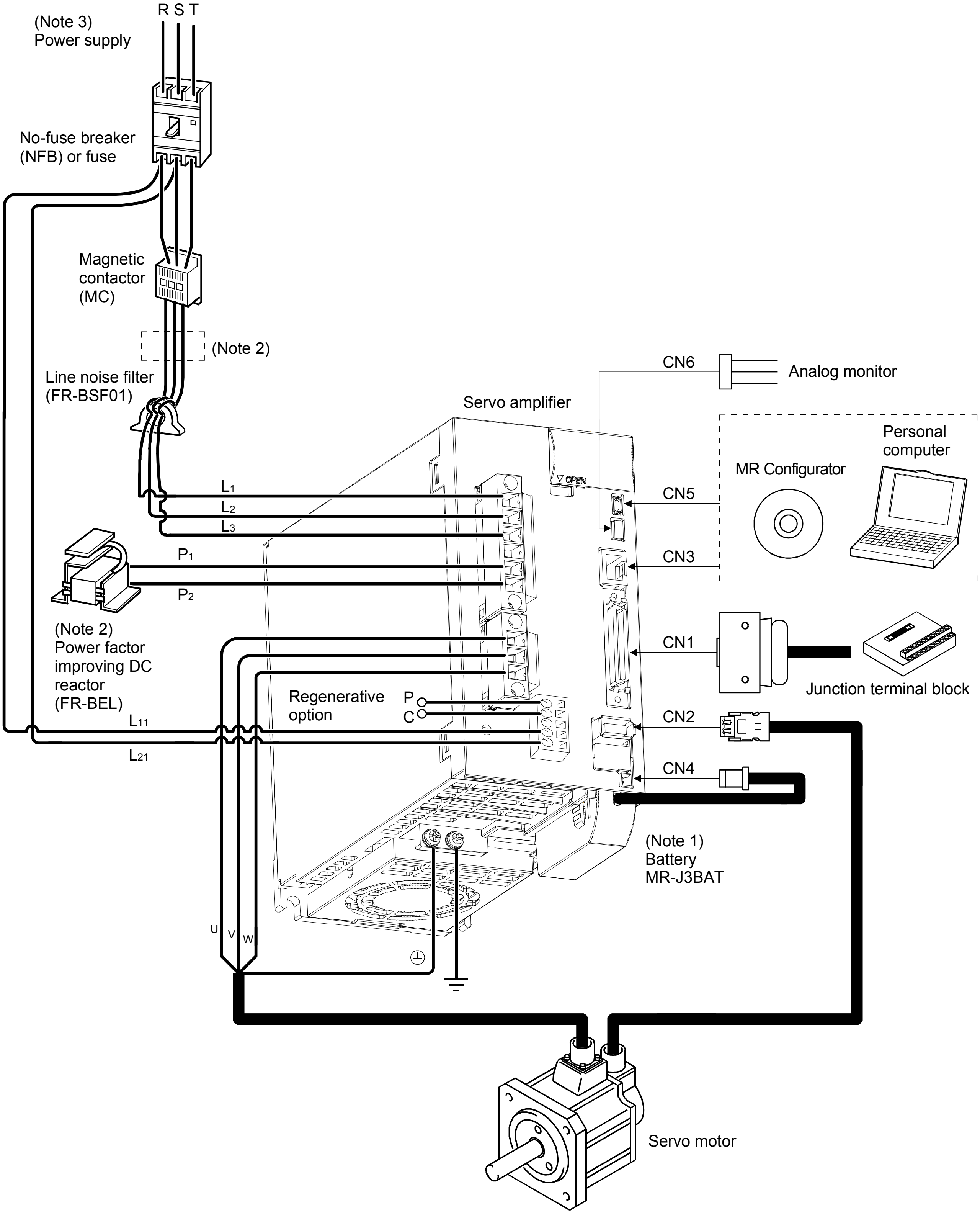
Connectors (CNP1, CNP2, and CNP3) and appearance of MR-J3-200A servo amplifier have been changed from April 2008 production. Model name of the servo amplifier before March 2008 is changed to MR-J3-200A-RT. The difference between new MR-J3-200A servo amplifier and existing MR-J3-200A-RT servo amplifier is described in this appendix. Sections within parentheses in the following sections indicate corresponding sections of the instruction manual.

App. 5.1 Parts identification (1.7.1 Parts identification)



Name/Application	Detailed explanation
Display The 5-digit, seven-segment LED shows the servo status and alarm number.	Chapter 6
Operation section Used to perform status display, diagnostic, alarm and parameter setting operations. ⊙ ⊙ ⊙ ⊙ MODE UP DOWN SET Used to set data. Used to change the display or data in each mode. Used to change the mode.	Chapter 6
Main circuit power supply connector (CNP1) Connect the input power supply.	Section 3.1 Section 3.3
RS-422 communication connector (CN3) Connect the personal computer.	Section 12.8 Chapter 13
USB communication connector (CN5) Connect the personal computer.	Section 12.8
Analog monitor connector (CN6) Outputs the analog monitor.	Section 3.2 Section 3.4
I/O signal connector (CN1) Used to connect digital I/O signals.	Section 3.2 Section 3.4
Servo motor power connector (CNP3) Connect the servo motor.	Section 3.1 Section 3.3
Control circuit connector (CNP2) Connect the control circuit power supply/regenerative option.	Section 3.1 Section 3.3
Encoder connector (CN2) Used to connect the servo motor encoder.	Section 3.4 Section 12.1
Battery connector (CN4) Used to connect the battery for absolute position data backup.	Section 12.9 Chapter 14
Battery holder Contains the battery for absolute position data backup.	Section 14.3
Charge lamp Lit to indicate that the main circuit is charged. While this lamp is lit, do not reconnect the cables.	
Protective earth (PE) terminal (⏚) Ground terminal.	Section 3.1 Section 3.3
Rating plate	Section 1.5

App. 5.2 Configuration including auxiliary equipment (1.8 Configuration including auxiliary equipment)



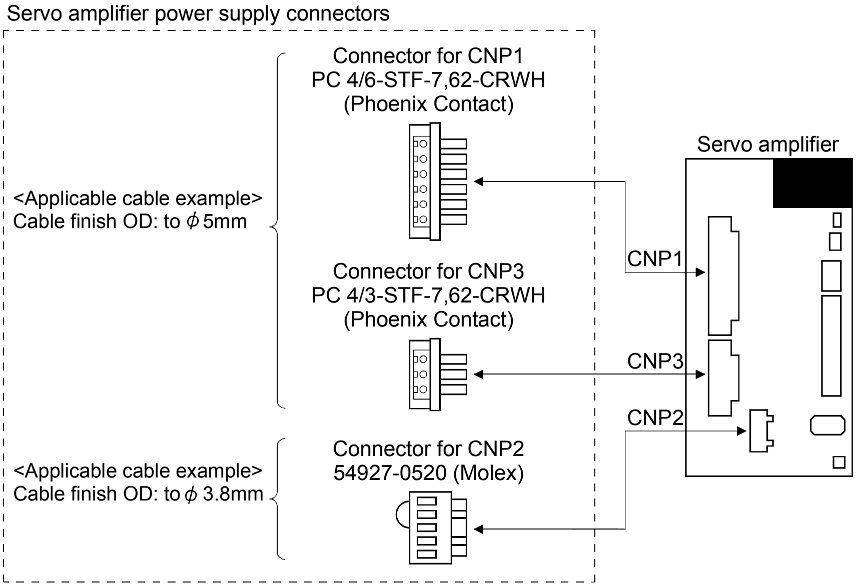
Note 1. The battery (option) is used for the absolute position detection system in the position control mode.

2. The power factor improving AC reactor can also be used. In this case, the power factor improving DC reactor cannot be used. When not using the power factor improving DC reactor, short P_1 and P_2.

3. Refer to section 1.3 for the power supply specification.

App. 5.3 CNP1, CNP2, CNP3 wiring method (3.3.3 CNP1, CNP2, CNP3 wiring method)

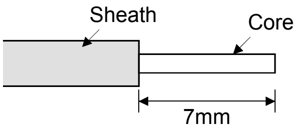
(a) Servo amplifier power supply connectors



(b) Termination of the cables

1) CNP1・CNP3

Solid wire: After the sheath has been stripped, the cable can be used as it is.



Twisted wire: Use the cable after stripping the sheath and twisting the core. At this time, take care to avoid a short caused by the loose wires of the core and the adjacent pole. Do not solder the core as it may cause a contact fault. Alternatively, a ferrule may be used to put the wires together.

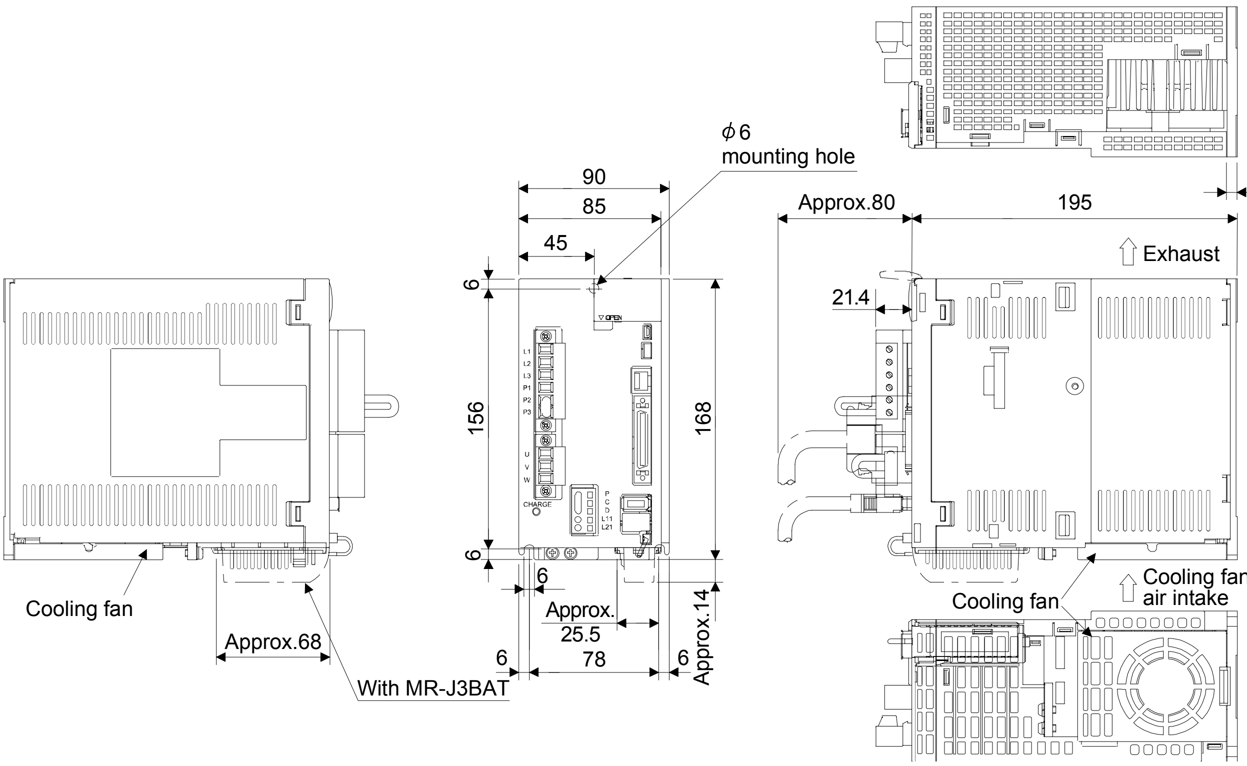
Cable size		Ferrule type		Crimping tool	Manufacturer
[mm^2]	AWG	For 1 cable	For 2 cables		
1.25/1.5	16	AI 1,5-8 BK	AI-TWIN2×1,5-8 BK	CRIMPFOX-ZA3	Phoenix Contact
2.0/2.5	14	AI 2,5-8 BU	AI-TWIN2×2,5-10 BU		
3.5	12	AI 4-10 Y			

2) CNP2

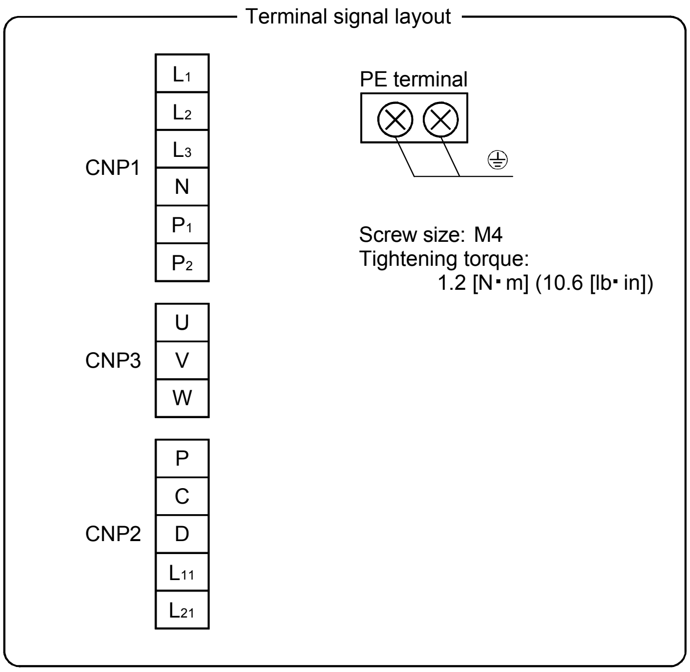
CNP2 is the same as MR-J3-100A or smaller capacities. Refer to section 3.3.3 (1) (b).

App. 5.4 OUTLINE DRAWINGS (Chapter 10 OUTLINE DRAWINGS)

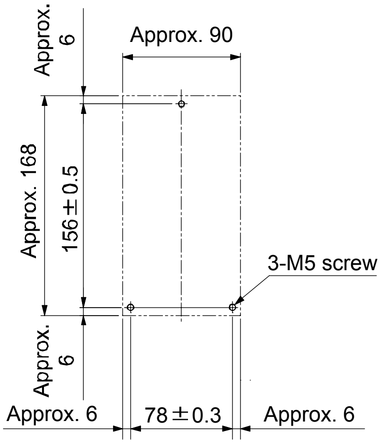
[Unit: mm]



Mass: 2.3 [kg] (5.07 [lb])



Screw size: M4
Tightening torque:
1.2 [N・m] (10.6 [lb・in])



Mounting hole process drawing

Mounting screw
Screw size: M5
Tightening torque: 3.24[N・m] (28.7[lb・in])

App. 6 Selection example of servo motor power cable

POINT

- Selection condition of wire size is as follows.
  Wire length: 30m or less
- Depending on the cable selected, there may be cases that the cable does not fit into the Mitsubishi optional or recommended cable clamp. Select a cable clamp according to the cable diameter.

Selection example when using the 600V grade EP rubber insulated chloroprene sheath cab-tire cable (2PNCT) for servo motor power (U, V, and W) is indicated below.

Servo motor	Wire size [mm^2]
HF-SP52	1.25
HF-SP102	1.25
HF-SP152	2
HF-SP202	2
HF-SP352	3.5
HF-SP502	5.5
HF-SP702	8
HF-SP51	1.25
HF-SP81	1.25
HF-SP121	2
HF-SP201	2
HF-SP301	3.5
HF-SP421	5.5
HF-SP524	1.25
HF-SP1024	1.25
HF-SP1524	2
HF-SP2024	2
HF-SP3524	2
HF-SP5024	3.5
HF-SP7024	5.5
HC-RP103	2
HC-RP153	2
HC-RP203 (Note)	3.5
HC-RP353 (Note)	5.5
HC-RP503 (Note)	5.5
HC-LP52	1.25
HC-LP102	1.25
HC-LP152	2
HC-LP202	3.5
HC-LP302	5.5
HC-UP72	1.25
HC-UP152	2
HC-UP202	3.5

Servo motor	Wire size [mm^2]
HC-UP352	5.5
HC-UP502	5.5
HA-LP601	8
HA-LP801	14
HA-LP12K1	14
HA-LP15K1	22
HA-LP20K1	38
HA-LP25K1	38
HA-LP30K1	38
HA-LP37K1	60
HA-LP701M	8
HA-LP11K1M	14
HA-LP15K1M	22
HA-LP22K1M	38
HA-LP30K1M	60
HA-LP37K1M	60
HA-LP502	5.5
HA-LP702	8
HA-LP11K2	14
HA-LP15K2	22
HA-LP22K2	22
HA-LP30K2	60
HA-LP37K2	60
HA-LP6014	5.5
HA-LP8014	5.5
HA-LP12K14	8
HA-LP15K14	14
HA-LP20K14	14
HA-LP25K14	22
HA-LP30K14	22
HA-LP37K14	22
HA-LP701M4	5.5
HA-LP11K1M4	8

Servo motor	Wire size [mm^2]
HA-LP15K1M4	14
HA-LP22K1M4	14
HA-LP30K1M4	22
HA-LP37K1M4	22
HA-LP45K1M4	38
HA-LP50K1M4	38
HA-LP11K24	8
HA-LP15K24	14
HA-LP22K24	14
HA-LP30K24	22
HA-LP37K24	22
HA-LP45K24	38
HA-LP55K24	38
HF-JP53	1.25
HF-JP73	1.25
HF-JP103	2
HF-JP153	2
HF-JP203	2
HF-JP353	3.5
HF-JP503	5.5
HF-JP11K1M	22
HF-JP15K1M	30
HF-JP534	1.25
HF-JP734	2
HF-JP1034	2
HF-JP1534	2
HF-JP2034	2
HF-JP3534	5.5
HF-JP5034	5.5
HF-JP11K1M4	8
HF-JP15K1M4	22

Note. Use a composite cable and others when combining with wiring of the electromagnetic brake power in the same cable.

App. 7 Handling of AC servo amplifier batteries for the United Nations Recommendations on the Transport of Dangerous Goods

United Nations Recommendations on the Transport of Dangerous Goods Rev. 15 (hereinafter Recommendations of the United Nations) has been issued. To reflect this, transport regulations for lithium metal batteries are partially revised in the Technical Instruction (ICAO-TI) by the International Civil Aviation Organization (ICAO) and the International Maritime Dangerous Goods Code (IMDG Code) by the International Maritime Organization (IMO).
To comply the instruction and code, we have modified the indication on the package for general-purpose AC servo batteries.

(1) Target model
Battery (Cell): MR-J3BAT, MR-BAT, A6BAT
Battery unit (Battery): MR-J2M-BT

(2) Purpose
Safer transportation of lithium metal batteries.

(3) Change in regulations
The following points are changed for lithium metal batteries transportation by sea or air due to Recommendations of the United Nations Rev. 15 and ICAO-TI 2009-2010 edition. For lithium metal batteries, cells are classified as UN3090, and batteries contained in or packed with equipment are classified as UN3091.

(a) A package containing 24 cells or 12 batteries or less that are not contained in equipment are no longer exempt from the following: attachment of a handling label, submission of the Shipper's Declaration for Dangerous Goods, and a 1.2m drop test.

(b) A battery handling label (size: 120 × 110mm) is required. Emergency telephone number must be filled out in the additional handling information of the Shipper's Declaration for Dangerous Goods.

(c) New handling label design containing battery illustration (Figure) must be used.

Figure. Example of Mitsubishi Label with Battery Illustration (size: 120 × 110mm)

(4) Action taken by Mitsubishi
The following caution will be added to the packages of the target batteries.
"Containing lithium metal battery. Regulations apply for transportation."

(5) Transportation precaution for customers

For sea or air transportation, the handling label (Figure) is required for the package of a Mitsubishi cell or battery and the outer package containing several packages of Mitsubishi cells or batteries. Documentations like the handling label in the specified design and the Shipper's Declaration for Dangerous Goods are required. Please attach the documentations to the packages. The above change will not affect the function and performance of the product.

App. 8 Symbol for the new EU Battery Directive

Symbol for the new EU Battery Directive (2006/66/EC) that is plastered to general-purpose AC servo battery is explained here.

Note. This symbol mark is for EU countries only.

This symbol mark is according to the directive 2006/66/EC Article 20 Information for end-users and Annex II.

Your MITSUBISHI ELECTRIC product is designed and manufactured with high quality materials and components which can be recycled and/or reused.

This symbol means that batteries and accumulators, at their end-of-life, should be disposed of separately from your household waste.

If a chemical symbol is printed beneath the symbol shown above, this chemical symbol means that the battery or accumulator contains a heavy metal at a certain concentration. This will be indicated as follows.
Hg: mercury (0.0005%), Cd: cadmium (0.002%), Pb: lead (0.004%)

In the European Union there are separate collection systems for used batteries and accumulators.

Please, dispose of batteries and accumulators correctly at your local community waste collection/recycling centre.

Please, help us to conserve the environment we live in!

App. 9 Compliance with the European EC directives

App. 9.1 What are EC directives?

The EC directives were issued to standardize the regulations of the EU countries and ensure smooth distribution of safety-guaranteed products. In the EU countries, the machinery directive (effective in January, 1995), EMC directive (effective in January, 1996) and low voltage directive (effective in January, 1997) of the EC directives require that products to be sold should meet their fundamental safety requirements and carry the CE marks (CE marking). CE marking applies also to machines and equipment into which servos have been installed.

(1) EMC directive

The EMC directive applies to the servo units alone. This servo is designed to comply with the EMC directive. The EMC directive also applies the servo-incorporated machines and equipment. This requires the EMC filters to be used with the servo-incorporated machines and equipment to comply with the EMC directive. For specific EMC directive conforming methods, refer to the EMC Installation Guidelines (IB(NA)67310).

(2) Low voltage directive

The low voltage directive applies also to servo units alone. This servo is designed to comply with the low voltage directive.

(3) Machinery directive

Not being machines, the converter units and servo amplifiers (drive units) need not comply with this directive.

App. 9.2 For compliance

Be sure to perform an appearance inspection of every unit before installation. In addition, have a final performance inspection on the entire machine/system, and keep the inspection record.

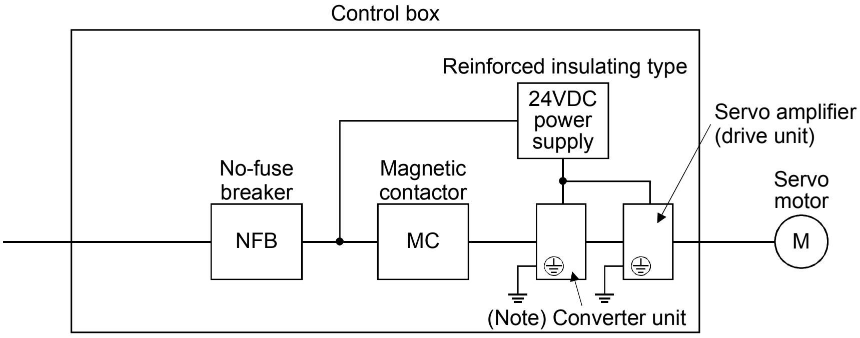
(1) Converter units, servo amplifiers (drive units) and servo motors used

Use the converter units, servo amplifiers (drive units) and servo motors which standard product.

Converter unit : MR-J3-CR55K·MR-J3-CR55K4
Servo amplifier : MR-J3-10A to MR-J3-22KA・MR-J3-10A1 to MR-J3-40A1・MR-J3-60A4 to MR-J3-22KA4
Drive unit : MR-J3-DU30KA・MR-J3-DU37KA・MR-J3-DU30KA4 to MR-J3-DU55KA4
Servo motor series : HF-MP□・HF-KP□・HF-SP□・HF-SP□4・HC-RP□・HC-UP□・HC-LP□・HA-LP□・HA-LP□4

(2) Structure

The control circuit provide safe separation to the main circuit in the servo amplifier.



Note. Servo amplifiers of 22kW or less do not have a converter unit.

(3) Environment

(a) Operate the converter unit and servo amplifier (drive unit) at or above pollution degree 2 set forth in IEC/EN 60664-1. For this purpose, install the servo amplifier in a control box which is protected against water, oil, carbon, dust, dirt, etc. (IP54).

(b) Environment

Environment			Conditions
(Note 1) Ambient temperature	In operation	[℃]	(Note 2) 0 to 55
		[℉]	32 to 131
	In storage, in transportation	[℃]	−20 to 65
		[℉]	−4 to 149
Ambient humidity	In operation, in storage, in transportation		90% RH or less
Maximum altitude	In operation, in storage		1000m or less
	In transportation		10000m or less

Note 1. Ambient temperature is the internal temperature of the control box.

2. The servo amplifier 200V 3.5kW or less and 100V 400W or less can be mounted closely. In this case, keep the ambient temperature within 0 to 45℃ (32 to 113℉) or use the servo amplifier with 75% or less of the effective load ratio.

(4) Power supply

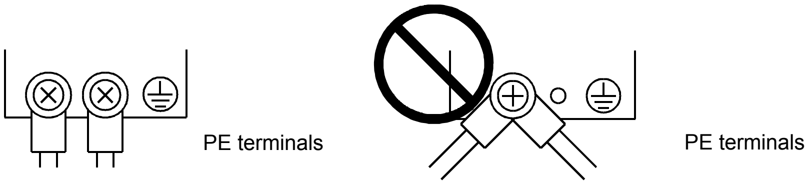
(a) This converter unit and servo amplifier (drive unit) can be supplied from star-connected supply with earthed neutral point of overvoltage category Ⅲ set forth in IEC/EN 60664-1. However, when using the neutral point of 400V system for single phase supply, a reinforced insulating transformer is required in the power input section.

(b) For the interface power supply, use a 24VDC power supply with reinforced insulation on I/O terminals.

(5) Grounding

(a) To prevent an electric shock, the protective earth (PE) terminal (marked ⏚) of the converter unit, servo amplifier (drive unit) must be connected to the protective earth (PE) of the control box.

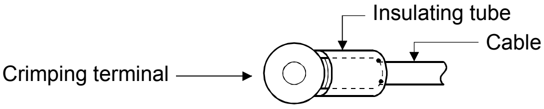
(b) Do not connect two ground cables to the same protective earth (PE) terminal. Always connect cables to the terminals one-to-one.



(c) If an earth leakage circuit breaker is used, always earth the protective earth (PE) terminal of the servo amplifier to prevent an electric shock.

(6) Wiring

(a) The cables to be connected to the terminal block of the converter unit, servo amplifier (drive unit) must have crimping terminals provided with insulating tubes to prevent contact with adjacent terminals.



(b) Use the servo motor side power connector which complies with the IEC/EN Standard.
The IEC/EN Standard-compliant power connector sets are available as options.

(c) The converter unit and servo amplifier (drive unit) must be installed in the metal cabinet (control box).

(7) Peripheral devices, options

(a) Use the circuit breaker and magnetic contactor models which are IEC/EN Standard-compliant products given in this Instruction Manual.
Use a type B (Note) breaker. When it is not used, provide insulation between the servo amplifier and other device by double insulation or reinforced insulation, or install a transformer between the main power supply and servo amplifier (drive unit).

Note. Type A: AC and pulse detectable
Type B: Both AC and DC detectable

(b) The sizes of the wires given in this Instruction Manual meet the following conditions. For use in any other conditions, follow Table 5 and Annex C of IEC/EN 60204-1.

- Ambient temperature : 40℃ (104℉)
- Sheath : PVC (polyvinyl chloride)
- Installation on wall surface or open table tray

(c) Use the EMC filter for noise reduction.

(8) Performing EMC tests

When EMC tests are run on a machine/device into which the converter unit and servo amplifier (drive unit) has been installed, it must conform to the electromagnetic compatibility (immunity/emission) standards after it has satisfied the operating environment/electrical equipment specifications.
For the other EMC directive guidelines on the converter unit and servo amplifier (drive unit), refer to the EMC Installation Guidelines (IB(NA)67310).

App. 10 Conformance with UL/C-UL standard

This servo amplifier complies with UL 508C and CSA C22.2 No.14 standard.

(1) Converter units, servo amplifiers (drive units) and servo motors used

Use the converter units, servo amplifiers (drive units) and servo motors which standard product.

Servo amplifier	Servo motor						
	HF-KP	HF-MP	HF-SP	HC-RP	HC-UP	HC-LP	HA-LP
MR-J3-10A(1)	053・13	053・13					
MR-J3-20A(1)	23	23					
MR-J3-40A(1)	43	43					
MR-J3-60A			51・52			52	
MR-J3-70A	73	73			72		
MR-J3-100A			81・102			102	
MR-J3-200A			121・201・152・202	103・153	152	152	
MR-J3-350A			301・352	203	202	202	
MR-J3-500A			421・502	353・503	352・502	302	502
MR-J3-700A			702				601・701M・702
MR-J3-11KA							801・12K1・11K1M・11K2
MR-J3-15KA							15K1・15K1M・15K2
MR-J3-22KA							20K1・25K1・22K1M・22K2

Servo amplifier	Servo motor	
	HF-SP	HA-LP
MR-J3-60A4	524	
MR-J3-100A4	1024	
MR-J3-200A4	1524・2024	
MR-J3-350A4	3524	
MR-J3-500A4	5024	
MR-J3-700A4	7024	6014・701M4
MR-J3-11KA4		8014・12K14・11K1M4・11K24
MR-J3-15KA4		15K14・15K1M4・15K24
MR-J3-22KA4		20K14・22K1M4・22K24

Converter unit	Drive unit	Servo motor
		HA-LP
MR-J3-CR55K	MR-J3-DU30KA	30K1・30K1M・30K2
	MR-J3-DU37KA	37K1・37K1M・37K2
MR-J3-CR55K4	MR-J3-DU30KA4	25K14・30K14・30K1M4・30K24
	MR-J3-DU37KA4	37K14・37K1M4・37K24
	MR-J3-DU45KA4	45K1M4・45K24
	MR-J3-DU55KA4	50K1M4・55K24

(2) Installation

The MR-J3 series have been approved as the products which have been installed in the electrical enclosure.

The minimum enclosure size is based on 150% of each MR-J3 combination.

And also, design the enclosure so that the ambient temperature in the enclosure is 55℃ (131℉) or less, refer to the spec manual.

The servo amplifier must be installed in the metal cabinet (control box).

(3) Short circuit rating (SCCR: Short Circuit Current Rating)

Suitable For Use In A Circuit Capable Of Delivering Not More Than 100 kA rms Symmetrical Amperes, 500 Volts Maximum.

(4) Flange

Mount the servo motor on a flange which has the following size or produces an equivalent or higher heat dissipation effect.

Flange size [mm]	Servo motor					
	HF-MP HF-KP	HF-SP	HC-RP	HC-UP	HC-LP	HA-LP
250 × 250 × 6	053 ・ 13 ・ 23					
250 × 250 × 12	43	51 ・ 81 52(4) to 152(4)	103 to 203		52 to 152	
300 × 300 × 12	73					
300 × 300 × 20		121 ・ 201 202(4) ・ 352(4)			202 ・ 302	
550 × 550 × 30			353 ・ 503	72 ・ 152		
650 × 650 × 35		502(4) ・ 702(4)		202 to 502		601 to 12K1 8014 to 12K14 701M(4) to 15K1M(4) 502 to 22K2 11K24 to 22K24
950 × 950 × 35						15K1 to 37K1 15K14 to 20K14 22K1M to 37K1M 22K1M4 to 50K1M4 30K2・37K2 30K24 to 55K24

(5) About wiring protection

For installation in United States, branch circuit protection must be provided, in accordance with the National Electrical Code and any applicable local codes.

For installation in Canada, branch circuit protection must be provided, in accordance with the Canada Electrical Code and any applicable provincial codes.

(6) Options, peripheral devices

Use the UL/C-UL Standard-compliant products.

Use the no-fuse breaker (UL489 Listed MCCB) or a Class T fuse indicated in the table below.

Servo amplifier		No-fuse breaker (Note)		Fuse	
		Current	Voltage AC	Current	Voltage AC
MR-J3-10A(1) ・ 20A		30A frame 5A	240V	10A	300V
MR-J3-40A ・ 20A1		30A frame 10A		15A	
MR-J3-60A to 100A ・ 40A1		30A frame 15A		20A	
MR-J3-200A		30A frame 20A		40A	
MR-J3-350A		30A frame 30A		70A	
MR-J3-500A		50A frame 50A		125A	
MR-J3-700A		100A frame 75A		150A	
MR-J3-11KA		100A frame 100A		200A	
MR-J3-15KA		225A frame 125A		250A	
MR-J3-22KA		225A frame 175A		350A	
MR-J3-CR55K	MR-J3-DU30KA	400A frame 250A		500A	
	MR-J3-DU37KA	400A frame 300A		600A	

Servo amplifier		No-fuse breaker (Note)		Fuse	
		Current	Voltage AC	Current	Voltage AC
MR-J3-60A4		30A frame 5A	600Y/347V	10A	600V
MR-J3-100A4		30A frame 10A		15A	
MR-J3-200A4		30A frame 15A		25A	
MR-J3-350A4		30A frame 20A		35A	
MR-J3-500A4		30A frame 30A		50A	
MR-J3-700A4		50A frame 40A		65A	
MR-J3-11KA4		60A frame 60A		100A	
MR-J3-15KA4		100A frame 75A		150A	
MR-J3-22KA4		225A frame 125A		175A	
MR-J3-CR55K4	MR-J3-DU30KA4	225A frame 125A		250A	
	MR-J3-DU37KA4	225A frame 150A		300A	
	MR-J3-DU45KA4	225A frame 175A		400A	
	MR-J3-DU55KA4	400A frame 225A		450A	

Note. Listed no-fuse breakers are for when the power factor improving reactor is not used.

(7) Capacitor discharge time

The capacitor discharge time is as follows. To ensure safety, do not touch the charging section for 15 minutes (20 minutes in case drive unit is 30kW or more) after power-off.

Servo amplifier	Discharge time (min)
MR-J3-10A ・ 20A	1
MR-J3-40A ・ 60A(4) ・ 10A1 ・ 20A1	2
MR-J3-70A	3
MR-J3-40A1	4
MR-J3-100A(4)	5
MR-J3-200A(4) ・ 350A	9

Servo amplifier	Discharge time (min)
MR-J3-350A4 ・ 500A(4) ・ 700A(4)	10
MR-J3-11KA(4)	4
MR-J3-15KA(4)	6
MR-J3-22KA(4)	8
MR-J3-DU30KA ・ DU37SKA ・ DU30KA4 ・ DU37KA4 ・ DU45KA4 ・ DU55KA4	20

(8) Selection example of wires

To comply with the UL/C-UL Standard, use UL-approved copper wires rated at 60/75℃ (140/167℉) for wiring.

The following table shows the wire sizes [AWG] and the crimping terminal symbols rated at 60℃ (140℉). The sizes and the symbols rated at 75℃ (167℉) are shown in the brackets.

Servo amplifier	Converter unit	(Note 3) Wires (AWG)			
		L_1・L_2・L_3・⏚	L_{11}・L_{21}	U・V・W・ P_1・P_2・⏚	P・P_2・C
MR-J3-10A(1) to 40A(1)・60A・70A		14(14)	16(16)	(Note 4) 14(14)	14(14)
MR-J3-100A・200A					
MR-J3-350A		12(12)		12(12)	
(Note 1) MR-J3-500A		10(10): a(a)	16(16): h(h)	10(10): a(a)	14(14): g(g)
(Note 1) MR-J3-700A		8(8): b(b)		8(8): b(b)	12(12): a(a)
(Note 1) MR-J3-11KA		6(6): c(c)	16(16): g(g)	4(4): d(c)	10(10): j(j)
(Note 1) MR-J3-15KA		4(4): d(d)		2(3): e(d)	
(Note 1) MR-J3-22KA		1/0(1): f(p)		－(1): －(p)	10(10): k(k)
(Note 1) MR-J3-DU30KA	MR-J3-CR55K	－(1): －(t)	14(14)	－(2/0): －(u)	10(10): r(r)
(Note 1) MR-J3-DU37KA		－(2/0): －(u)			
MR-J3-60A4		14(14)	16(16)	14(14)	14(14)
MR-J3-100A4					
MR-J3-200A4					
MR-J3-350A4		14(14): g(g)	16(16): h(h)	14(14): g(g)	14(14): g(g)
(Note 1) MR-J3-500A4		10(12): a(a)		10(12): a(a)	
(Note 1) MR-J3-700A4				10(10): a(a)	
(Note 1) MR-J3-11KA4		8(10): l(j)	16(16): g(g)	8(8): l(l)	12(12): j(j)
(Note 1) MR-J3-15KA4		6(8): c(l)		4(6): d(c)	10(10): j(j)
(Note 1) MR-J3-22KA4		6(6): m(m)		4(6): n(m)	10(10): k(k)
(Note 1) MR-J3-DU30KA4	MR-J3-CR55K4	3(4): s(s)	14(14)	2(3): p(n)	10(10): r(r)
(Note 1) MR-J3-DU37KA4		2(2): t(s)		1(2): p(n)	
(Note 1) MR-J3-DU45KA4		－(2): (t)		－(1/0): －(t)	
(Note 1) MR-J3-DU55KA4		－(2): －(t)		－(1/0): －(t)	

Servo amplifier	Converter Unit	(Note 3) Wires [mm^2]		
		B1・B2	BU・BV・BW	OHS1・OHS2
MR-J3-10A(1) to 40A(1)・60A・70A		16(16)		
MR-J3-100A・200A				
MR-J3-350A				
(Note 1) MR-J3-500A				
(Note 1) MR-J3-700A			(Note 2) 14(14)	(Note 2) 16(16)
(Note 1) MR-J3-11KA			14(14)	16(16)
(Note 1) MR-J3-15KA				
(Note 1) MR-J3-22KA				
(Note 1) MR-J3-DU30KA	MR-J3-CR55K			
(Note 1) MR-J3-DU37KA				
MR-J3-60A4		16(16)		
MR-J3-100A4				
MR-J3-200A4				
MR-J3-350A4				
(Note 1) MR-J3-500A4				
(Note 1) MR-J3-700A4			(Note 2) 14(14)	(Note 2) 16(16)
(Note 1) MR-J3-11KA4			14(14)	16(16)
(Note 1) MR-J3-15KA4				
(Note 1) MR-J3-22KA4				
(Note 1) MR-J3-DU30KA4	MR-J3-CR55K4		16(16)	
(Note 1) MR-J3-DU37KA4				
(Note 1) MR-J3-DU45KA4				
(Note 1) MR-J3-DU55KA4				

Note 1. To connect these models to a terminal block, be sure to use the screws that come with the terminal block.

2. For the servo motor with a cooling fan.

3. Alphabets in the table indicate crimping tools. Refer to the following table for the crimping terminals and crimping tools.

4. To wire the servo amplifier and a HF-MP・KP servo motor, use the MR-PWS1CBL (option). To extend the wiring, use the AWG14 wire size.

Table: Recommended crimping terminals

Symbol	Servo amplifier side crimping terminals				
	(Note 2) Crimping terminal	Applicable tool			Manufacturer
		Body	Head	Dice	
a	FVD5.5-4	YNT-1210S			Japan Solderless Terminals
(Note 1) b	8-4NS	YHT-8S			
C	FVD14-6	YF-1 ・ E-4	YNE-38	DH-122 ・ DH-112	
D	FVD22-6			DH-123 ・ DH-113	
(Note 1) e	38-6	YPT-60-21		TD-124 ・ TD-112	
		YF-1 ・ E-4	YET-60-1		
(Note 1) f	R60-8	YPT-60-21		TD-125 ・ TD-113	
		YF-1 ・ E-4	YET-60-1		
G	FVD2-4	YNT-1614			
H	FVD2-M3				
J	FVD5.5-6	YNT-1210S			
K	FVD5.5-8				
L	FVD8-6	YF-1 ・ E-4	YNE-38	DH-121 ・ DH-111	
M	FVD14-8			DH-122 ・ DH-112	
N	FVD22-8			DH-123 ・ DH-113	
(Note 1) p	R38-8	YPT-60-21		TD-124 ・ TD-112	
		YF-1 ・ E-4	YET-60-1		
Q	FVD2-6	YNT-1614			
R	R38-10	YPT-60-21		TD-124 ・ TD-112	
S		YF-1 ・ E-4	YET-60-1		
(Note 1) t	R60-10	YPT-60-21		TD-125 ・ TD-113	
(Note 1) u		YF-1 ・ E-4	YET-60-1		

Note 1. Coat the part of crimping with the insulation tube.

2. Some crimping terminals may not be mounted depending on the size. Make sure to use the recommended ones or equivalent ones.

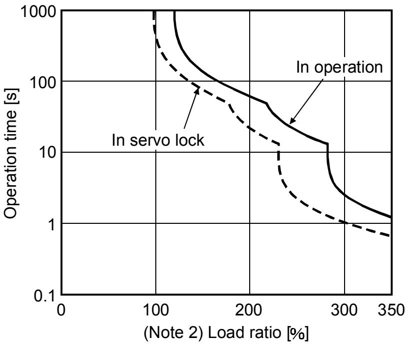
(9) Terminal block tightening torque

Servo amplifier	Tightening torque [N ・ m]								
	TE1	TE2	TE3	PE	L_1/L_2/L_3/U/V/W/P_1/P/C/N	L_{11}/L_{12}	TE1-1 TE1-2	TE2-1	TE2-2
MR-J3-10A(1) to 40A(1) ・ 60A to 100A ・ 60A4 ・ 100A4 ・ 200A(4) ・ 350A				1.2					
MR-J3-350A4 ・ 500A(4) ・ 700A(4)	1.2	0.8	1.2		1.2	0.8			
MR-J3-11KA(4) ・ 15KA(4)				3.0	3.0	1.2			
MR-J3-22KA(4)				6.0	6.0				
MR-J3-DU30KA ・ DU37KA ・ DU45KA4 ・ DU55KA4	10.0		1.2	10.0				3.0	
MR-J3-DU30KA ・ DU37KA4	6.0	3.0		6.0					
MR-J3-CR55KA(4)				10.0			10.0		3.0

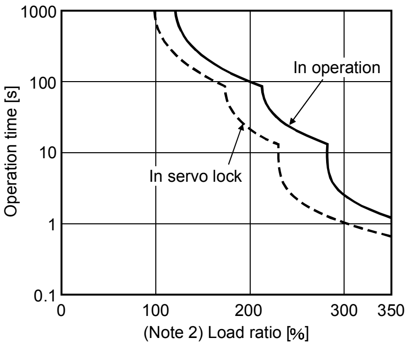
(10) Overload protection characteristics

An electronic thermal relay is built in the servo amplifier to protect the servo motor, servo amplifier and servo motor power line from overloads. The operation characteristics of the electronic thermal relay are shown below. It is recommended to use an unbalanced torque-generated machine, such as a vertical motion shaft, so that unbalanced torque is not more than 70% of the rated torque. When you carry out adhesion mounting of the servo amplifier, make circumference temperature into 0 to 45℃ (32 to 113℉) or use it with 75% or less of effective load torque.

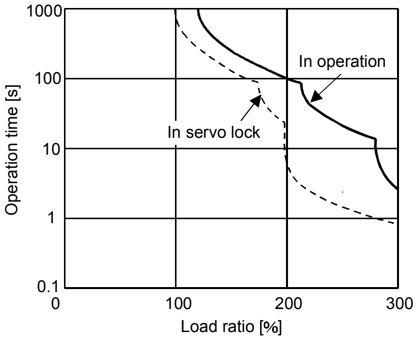
Servo amplifier MR-J3 series have servo motor overload protection. (The motor full load current is 115% rated current.)



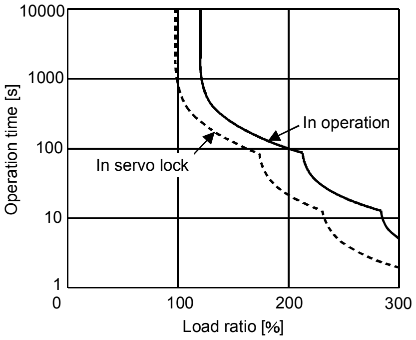
MR-J3-10A(1)



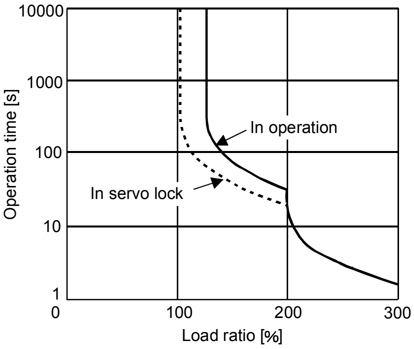
MR-J3-20A(1) · MR-J3-40A(1)
MR-J3-60A(4) to MR-J3-100A(4)



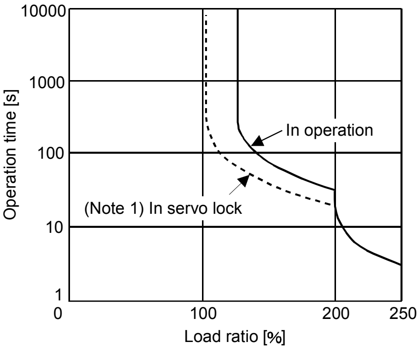
MR-J3-200A(4) · MR-J3-350A(4)



MR-J3-500A(4) · MR-J3-700A(4)



MR-J3-11KA(4) to MR-J3-22KA(4)



MR-J3-DU30KA(4) ·
MR-J3-DU37KA(4)
MR-J3-DU54KA4 ·
MR-J3-DU55KA4
Converter unit MR-J3-CR55KA(4)

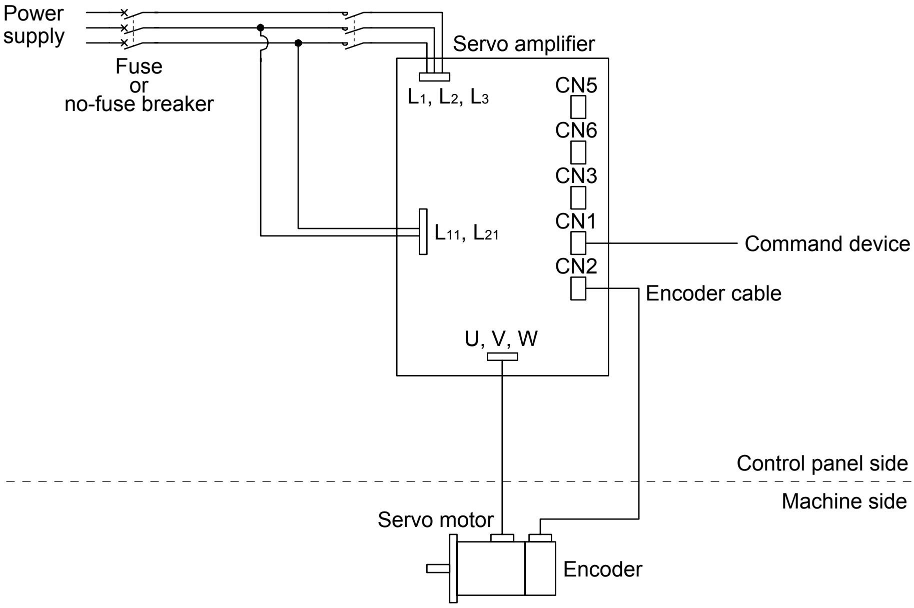
Note 1. The thermal relay protection characteristics for servo lock are not applied to MR-J3-CR55K(4).

2. The operation time at the load ratio of 300 to 350% applies when the maximum torque of HF-KP servo motor is increased to 350%.

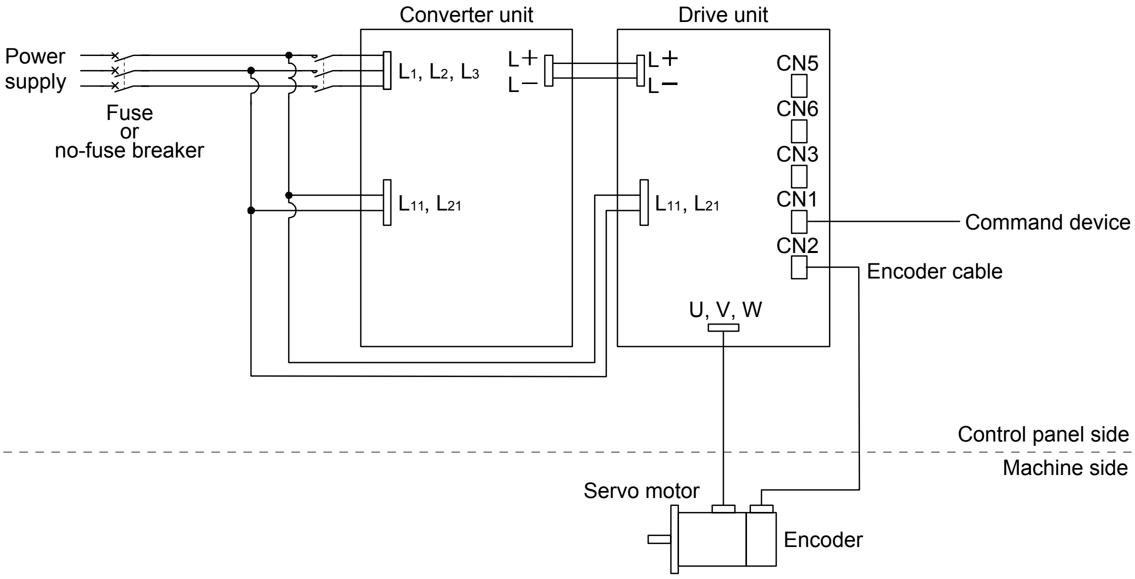
(11) Figure configuration

Representative configuration example to conform to the UL/C-UL standard is shown below. The earth wiring is excluded from the figure configuration.

(a) MR-J3-22KA(4) or less



(b) MR-J3-DU30KA(4) or more



REVISIONS

*The manual number is given on the bottom left of the back cover.

Print Data	*Manual Number	Revision
Oct. 2003	SH(NA)030038-A	First edition
May 2004	SH(NA)030038-B	Safety Instructions: 4. (1) HF-SP Series servo motor is added to the environment conditions. Compliance with EC directives in EU: 2.(1) Servo amplifiers MR-J3-60A/100A/200A/350A are added. HF-SP Series servo motor is added. Conformance with UL/C-UL standard: (1) Servo amplifiers MR-J3-60A/100A/200A/350A are added. HF-SP Series servo motor is added. (4) Servo amplifiers MR-J3-60A/100A/200A/350A are added. Section 1.3: Servo amplifiers MR-J3-60A/100A/200A/350A are added. Note 2. The torque limit is changed to the effective load ratio. Section 1.4: The amplifier diagnosis function is added. Section 1.5 (2): Servo amplifiers MR-J3-60A/100A/200A/350A are added. Section 1.6: Servo amplifiers MR-J3-60A/100A/200A/350A are added. HF-SP Series servo motor is added. Section 1.7 (2): Added. Section 1.8 (2): Added. Section 2.1 (2): Part of the paragraph is changed. Section 3.2.2: Analog torque limit ±10V is changed to 8V. Section 3.3.1: Paragraph is added. Servo amplifiers MR-J3-60A/100A/200A/350A are added. Section 3.3.3 (2) (4): Added. Section 3.4 (1): Error in the CN2 connector signal allotment is corrected. Section 3.5 (1) (b): Description of speed reached is examined. Alarm code AL.47 is added. Section 3.5 (5): Caution is added. Section 3.6.2 (1) (a): Note is added. Section 3.8.2 (3) (a) 2): 0.7μs is changed to 0.35μs. Section 3.10.2 (1): HF-KP Series is added. Section 3.10.2 (2): HF-SP Series is added. Section 3.11.4: "POINT" is added. Section 5.1.4: Parameter No.PA02 MR-RB30 and MR-RB50 is added. Section 5.1.8 (3): The per-revolution pulse count of the servo motor viewed from QD75 is examined. Section 5.2.2: PB01 Paragraph is added. PB02 Paragraph is added. PB23 Paragraph is examined. Section 5.3.1: PC22 Control mode is examined. PC13 Setting is changed to "1000.0". PC23 Part of the paragraph is examined. PC24 The in-position range unit selection setting is changed to the fourth digit. Section 5.4.1: PD08 Initial value is changed to 00202006h. Section 5.4.2: List of details is added. PD24 AL.47 is added. Section 6.4: Amplifier diagnosis is added. Section 6.7 (3) (a) (b): SP2 (CN1-16) is added. Section 8.2 (3): Paragraph is added. Part of the paragraph in "POINT" is examined.

Print Data	*Manual Number	Revision
May 2004	SH(NA)030038-B	Section 9.1: AL.47 is added. AL.E8 is added. Section 9.2: Description of AL.52 is changed. Section 9.3: Paragraph is added. AL.E8 is added. Section 10: Outline drawing is examined. Section 10.1 (4): Added. Section 11.1: c. HF-SP152 to 352 is added. Section 11.2 (1): Servo amplifiers MR-J3-60A/100A/200A/350A are added. Section 11.3: HF-SP Series is added. Section 11.5: Servo amplifiers MR-J3-60A/100A/200A/350A are added. Section 12.1.1: The cable and connector set drawing is added and changed. Section 12.1.2 (1) (a): The CN2 connector signal allotment drawing is changed. Section 12.1.2 (4) (5): Added. Section 12.2 (1) (b): Servo amplifiers MR-J3-60A/100A/200A/350A are added. Section 12.2 (1) (c): MR-RB30 and MR-RB50 are added. Section 12.2 (5): MR-RB30 and MR-0RB50 are added. Section 12.4 (2): The free space of the hard disk is changed to 30MB. Section 12.4 (2) (c): Added. Section 12.6 (1): Servo amplifiers MR-J3-60A/100A/200A/350A are added. Section 12.6 (2): Cable is added. Section 12.7: Servo amplifiers MR-J3-60A/100A/200A/350A are added. Section 12.8: Servo amplifiers MR-J3-60A/100A/200A/350A are added. Section 12.9: Servo amplifiers MR-J3-60A/100A/200A/350A are added. Section 12.12 (2) (d): FR-BLF is added. Section 12.13 (1): Servo amplifiers MR-J3-60A/100A/200A/350A are added. Section 12.14: HF-3030-UN is added. Section 14.8.3: Added. App. 4: Added.
Apr. 2005	SH(NA)030038-C	Servo amplifiers MR-J3-500A/700A are added. Servo motors HF-MP Series・HF-SP1000/min Series・HF-SP502/702 Series are added. Section 1.2 (2): Added. Section 1.3: Power supply capacity column is deleted. Input and inrush current columns are added. Section 1.4: Modified to MRZJW3-SETUP211E. Brake unit and return converter are added. Section 1.7: Format is examined. Section 1.7.1 (3) (4): Added. Section 1.7.2: Added. Section 1.8 (3) (4): Added. Section 2.1 (2): "POINT" is added. Section 3.1 (1) (2) (3) Titles are examined. Note 4. is added. Section 3.1 (4): Added. Section 3.2.1: Note 12. is added. Section 3.2.2: Note 12. is added. Section 3.2.3: Note 10. is added. Section 3.3.1: "POINT" is added. Servo amplifier conceptual diagram is deleted. Regenerative option is separated into each case. Section 3.3.2 (3): Note is added into the drawing.

Print Data	*Manual Number	Revision
Apr. 2005	SH(NA)030038-C	Section 3.3.3: Sentence is added into "POINT". Section 3.5 (1) (a): Servo on and servo off condition is deleted. Part of columns of emergency stop and functions/applications is examined. Section 3.5 (1) (b): Zero speed Example is added. Section 3.5 (3): The minimum pulse width of Encoder Z-phase pulse is changed to 400μs. Section 3.6.2 (1) (a): Note is added. Section 3.6.3 (1) (a): Note is added. Section 3.6.3 (3) (a): Note is added. Section 3.6.4 (3) (a): Note is added. Section 3.6.4 (3) (b): Content is examined. Section 3.6.5 (4) (a): Note is added. Section 3.7 (3): Sentence is examined. Section 3.8.1: Part of connection diagram is modified. Section 3.8.2 (4) (b) 2): Part of drawing is modified. Section 3.8.2 (6): Drawing is examined. Section 3.10.2 (2) (b): Connector signal allotment CE05-2A32-17PD-B is added. Section 3.11.1: Sentence is examined. Section 4.1.2 (1) (c): Examined. Section 5.1.1: PA16 Initial value is modified to 0. PA17・PA18 Initial value is modified to 0000h. PA19 Name is examined. Section 5.1.4: Parameter No.PA02 setting 01・08・09 are added. Section 5.1.10: Feedback pulses are changed to droop pulses. Section 5.2.1: PB14・PB15・PB16・PB18・PB23 are modified to correspond to speed control mode. PB44 Initial value is modified to 0.0. Section 5.2.2: PB02 Sentence is added. PB07 Setting range is modified to 1~2000. PB17 Sentence is examined. PB26 Expression is examined. Section 5.3.1: PC20 Errors in writing are modified. Section 5.3.2: PC12 The case of MR-J3-100A to 700A is added. PC14 Note 2 is added. PC15 Note 2 is added. PC17 Sentence is added. PC22 Sentence is added. Section 5.3.3 (1): Parameters are separated into each case. Section 5.3.3 (2): Note 2 is added. Setting A Horizontal axis is changed to 1Mpulse. Setting B Horizontal axis is changed to 10Mpulse. Setting C Horizontal axis is changed to 100Mpulse. Section 6.6.2 (1) (2): Error in Parameter screen is corrected. Section 8.1: Setting of machine resonance suppression filter 2 is modified to □□□1. Section 8.6.3 (4): Expression for setting parameter is examined. Chapter 9: Sentence in "POINT" is changed. Section 9.1: AL.45・AL.47 Note 1. is added. Section 9.2: AL.33 Causes 1・2 are added. AL.46 Modified to thermal sensor. Section 9.3: Caution is added. AL.E3 Content is added.

Print Data	*Manual Number	Revision
Apr. 2005	SH(NA)030038-C	Section 10.1 (5) (6): Added. Section 11.1: d. HF-SP502・702 is added. Section 11.2 (1): Table is examined. Section 11.3: Dynamic brake time constant is added. Chapter 12: "WARNING" 10 minutes are modified to 15 minutes. Section 12.1.1: Combinations of cable and connector sets diagram is examined. 2) Servo amplifier power supply connector is added. 3) Power supply connector set is added. Section 12.1.2 (1) (a): Encoder connector Crimping tool are added. Section 12.1.2 (2) (a): Note is added. Section 12.2 (1): MR-RB31 and MR-RB51 are added. Section 12.2 (3): Parameter No.PA02 setting 01・08・09 are added. Section 12.2 (4): "POINT" is added. Content is examined. Section 12.2 (5): MR-RB31 and MR-RB51 are added. Section 12.5 (5) (b): Outline drawing is partially modified. Section 12.3: Added. Section 12.4: Added. Section 12.6 (2) (a): The free space of the hard disk is changed to 130MB. Section 12.7 (2): Added. Section 12.8: Part of wiring diagram is added. Table of crimping terminals and applicable tools is added. Section 12.16: HF3040A-UN is added. Section 13.4.1 (5): Current alarm data [0][1]・[0][8]・[0][9] are deleted. Section 13.4.2 (3): Error in reference page No. is corrected. Section 13.4.2 (8): Data No.[2] [0] Content is changed. Data No.[2] [1] The expression of test operation setting is changed. Chapter 14: Caution Sentence is added. Description of AD75□ is deleted. Section 14.2 (2): QD75□ is added. Section 14.3 (2): Added. Section 14.7.3 (2): Part of sentence is examined. Section 17.8.2 (2) (c): Note 2 is added. Section 17.8.2 (2) (f): Note 3 is added. App. 6: Table is examined.
Oct. 2006	SH(NA)030038-D	Servo amplifiers MR-J3-11KA to 22KA・11KA4 to 22KA4 are added. Servo motors HC-RU・HC-UP・HC-LP・HA-LP・HA-LP4 are added. Safety Instructions: 4. (1) Environmental conditions table: Vibration is examined. Safety Instructions: 4. (2) Caution is added. Safety Instructions: 4. (4) Caution is added. Section 1.2: Connection diagram is modified. Addition of Note. Section 1.3: 400VAC class supporting table is added. Section 1.5 (2): Drawings are modified. Section 1.7: Mounting hole is changed into fixing part. Section 1.7.1 (5): Added. Section 1.8 (5): Added. Chapter 2: Caution is added. Section 2.1 (2): Added. Section 3.1 (1) to (4): Modified. Section 3.1 (5): Added.

Print Data	*Manual Number	Revision
Oct. 2006	SH(NA)030038-D	Section 3.2.1: SD (Plate) is added to CN1.
		Section 3.3.3 (2) (b) 1): 2.5mm size ferrule model name (for 2 cables) is modified.
		Section 3.3.3 (3): "POINT" is added. Table for parameter No.PD01 in the functions/applications column of the forward rotation stroke end and reverse rotation stroke end is examined.
		Section 3.5 (1) (a): Functions/Applications column of devices is modified.
		Section 3.5 (1) (b): Dynamic interlock is added. Zero speed detection graph is modified. Variable gain selection is modified.
		Section 3.6 (5) (b): Table is modified.
		Section 3.8.1: Differential line driver is modified to 35mA.
		Section 3.8.1 (4) (b) 2): Explanation is added.
		Section 3.9: Content is examined.
		Section 3.10.2 (2): Content is examined.
		Section 3.11.1: Caution is added.
		Section 3.11.3 (4): 10ms is added to electromagnetic brake interlock invalid.
		Section 3.11.4 (1) (2): Electromagnetic brake interlock (MBR) is added.
		Section 4.1.1: Part of sentence is examined.
		Section 4.2.3: Part of sentence is examined.
		Section 4.3.3: Part of sentence is examined.
		Section 4.4.3: Added.
		Section 4.4.6: Ex-Section 4.4.3 is moved.
		Section 5.1.1: PA13 Name is modified.
		Section 5.1.3: Setting of parameter No.PA02 is added and modified.
		Section 5.1.11: Setting value is modified.
		Section 5.2.1: Parameter No.PB07 is modified. Parameter No.PB17 is modified.
		Section 5.2.2: Sentence of parameter No.PB07 is modified. Sentence of parameter No.PB09 is modified. Sentence of parameter No.PB10 is modified. Sentence of parameter No.PB24 is modified.
		Section 5.3.2: Addition of Note for parameter No.PC14. Modified description for parameter No.PC15.
		Section 5.3.3: Note 3 is added to setting value 1 and 3. Note 4 is added to setting value D.
		Section 5.4.2: PD01 Explanation is modified. PD13 Setting value 06 is modified. PD13 Setting value 09 is modified.
		Section 6.3.3: Change of bus voltage display range.
		Section 7.3 (1) (a): Part of table is added.
		Section 7.3 (1) (b): Table is modified.
		Section 7.3 (2) (b): Table is modified.
		Section 7.4 (2): Sentence in the table is modified.
		Section 9.2: AL.10 Description of 400V class is added. AL.30 Description of 400V class is added. AL.32 Cause 2. IGBT is added to transistor. AL.33 Description of 400V class is added.
		Section 9.3: "POINT" is added.
		Section 10.1: Mounting hole machining drawing is added.
		Section 10.1 (5) (6): Outline drawings are modified.

Print Data	*Manual Number	Revision
Oct. 2006	SH(NA)030038-D	Section 10.1 (7): Added. Section 10.2: Examined. Section 11.1: Table is added. Graph is added. Section 11.3: Graph is added. Section 12.1.1: Motor drawing is added. Connector set is added. Change of connector set model. Section 12.1.2 (1) (a): For CN2 connector: Model name is changed. For CN2 connector: Added. Section 12.1.2 (2) (a) (c): For CN2 connector: Model name is changed. For CN2 connector: Added. Section 12.1.2 (4) (a) (c): For CN2 connector: Model name is changed. For CN2 connector: Added. Section12.1.2 (5) (a): For CN2 connector: Model name is changed. For CN2 connector: Added. Section 12.2 (3): Parameter No.PA02 Selection description of regenerative option is examined. Section 12.2 (4) (b): Sentence is modified. Section 12.2 (4) (c) (d): Added. Section 12.2 (5) (d) (e): Added. Section 12.3: Part of "POINT" is added. Section 12.3: FR-BU-55K・FR-BU-H 1 5K・FR-BU-H30K・FR-BU-H55K are added. Section 12.3 (2): Sentence of Note is modified. Section 12.4: FR-BU-55K・FR-BU-H 1 5K・FR-BU-H30K・FR-BU-H55K are added. Section 12.4 (2): Note 5 is added. Section 12.5: Power regenerative common converter is added. Section 12.6: External dynamic brake is added. Section 12.10: Heat sink outside mounting attachment (MR-J3ACN) is added. Section 12.11 (1): Cooling fan・thermal are added. Section 12.13 (2): 400V class is added. Section 12.14 (2) (e): Radio noise filter FR-BIF-H is added. Section 12.15 (1): 400V class graph is added. Section 12.16: Sentence is modified. Part of drawing is deleted. Section 12.19: Outline drawings are added. Section 12.19 (1): Part of table is added. Section 13.1 (2) (a): Note 2 is added. Section 13.1 (2) (b): Note 7 is added to cable connection diagram. Section 13.4: Part of POINT is modified. Section 13.4.1 (2): Data No.[0] [1] is modified. Section 13.4.1 (6): Part of table is deleted. Section 13.4.2 (2): Data No.[0] [1] is modified. Section 13.5.3 (5): "POINT" is added. Section 13.5.9 (3): Added. Section 14.3 (1): "POINT" is added. APPENDIX: App. 5 is added.
Jul. 2007	SH(NA)030038-E	Servo amplifier MR-J3-60A4 to MR-J3-700A4 added.
Nov. 2007	SH(NA)030038-F	Converter unit MR-J3-CR55K(4), drive unit MR-J3-DU30KA(4) to 37K(4), 45K to 55KA4 are added.

Print Data	*Manual Number	Revision
Nov. 2007	SH(NA)030038-F	"Fan" is changed to "cooling fan". Charge lamp off confirmation point is examined. Fahrenheit is added to temperature notation. Section 2.1 (1) (b): "POINT" content is changed. Section 2.3 (2): Description of cable fixing method is examined. Section 4.1.2 (1): (c)1) Title and content are changed. (c)2) Title and content are changed. Section 6.3.3: "Across P-N" is changed to "between P and N or P＋ and N－" in Description of Bus voltage. Section 6.6: "PD10 to PD18" is corrected to "PD10 to PD16 and PD18" for I/O setting parameter description of POINT. Section 6.9.3 (1) f): Description content is changed. Section 7.4: Description of interpolation mode is changed. Section 9.2: Cause 4 of AL.37 is added. Cause 6 of AL.50 is added. Reference is added to Definition of AL.51. Section 9.3: Definition of AL.E8 is changed. Section 10.1: Outline drawings of MR-J3-60A4, 100A4, 200A4 are added. Section 11.3.1 (2): (a) HC-RP and UP are added. (b) HA-SP is added. Section 12.3: Content of "Brake unit" is changed for "FR-BU2-(H) brake unit". Chapter 15: Chapter of servo amplifiers with a large capacity is newly added. Chapter 16: Chapter of parameter unit is newly added.
Dec. 2007	SH(NA)030038-G	Expression of "misoperate" is changed to "unexpected operation" in Warning. Notation of servo configuration software is deleted. Safety instructions 4 (1) Transportation and installation: Servo motor models are added for item of environmental conditions. Safety instructions 4 (2) Wiring: Description of tightening wires to terminal box with specified torque is added. About the manuals: Reference chapter for servo amplifiers with a large capacity is listed. Section 1.6: Addition of Note. Section 1.8 (1) (a): Descriptions of Note 2 and 3 are changed. Section 1.8 (1) (b): Description of Note 3 is changed. Section 1.8 (2) to (7): Description of Note 3 is changed. Section 3.1 (5): Cooling fan is added to connection diagram and Note 6 is added. Section 3.1 (7), (8): Option notation is added to dynamic brake in connection diagram. Section 3.2.1: Description of Note 10 is changed. Section 3.2.2: Description of Note 10 is changed. Section 3.2.3: Description of Note 9 is changed. Section 3.3.2 (2): Trouble (ALM) is added to timing chart. Section 3.3.3 (4): Connector model in description is changed. Section 3.3.3 (5): Description is changed. Section 3.4 (1): CN2 connector in figure is changed. Section 3.5 (1) (a): "This signal is not designed to make a stop. Do not turn it ON during operation" is added to explanation of Reset (device). Parameter for setting value "0" of second acceleration/deceleration selection (device) is corrected. Section 3.5 (1) (b): Expression of Functions/Applications for speed reached (device) is changed. Section 3.6.1 (1) (b) 1): Addition of Note. Section 3.6.3 (1) (a): "The maximum torque is generated at ± 8V" is changed to "In the initial setting, rated speed is ± 10V" in description.

Print Data	*Manual Number	Revision
Dec. 2007	SH(NA)030038-G	Section 3.8.1 (2): Addition of Note. Section 3.8.1 (3) (b) 1): Addition of Note. Section 3.8.3 (2): Addition of Note. Section 3.10.2 (2) (a) 1), 2): Connection diagram and Note 1 and 2 are changed. Section 3.10.2 (3) (a) 1): Connection diagram and Note 1, 2 and 4 are changed. Section 3.10.2 (3) (a) 2): Connection diagram and Note 1, 2 and 5 are changed. Section 3.10.2 (3) (b): Outline drawing of terminal box is changed. Section 3.11.3 (1): Timing chart and Note are added. Section 3.11.3 (2) to (5): Note for electromagnetic brake interlock is added. Section 3.11.4 (1): Note 3 is added. Section 3.11.4 (2): Note 4 is added. Section 5.1.4: Setting details for drive unit is added to POINT. Section 5.2.1: Initial value of parameter No.PB44 is corrected from "0.0" to "0000h". Section 5.2.2: Initial value of parameter No.PB44 is corrected from "0.0" to "0000h". Section 5.3.1: Initial values of parameter No.PC43 to PC50 are corrected from "0.0" to "0000h". Section 5.3.2: "If this function is enabled for the drive unit, the parameter error (AL.37) occurs." is added for description of when parameter No.PC22 setting is "□□□1". nitial values of parameter No.PC43 to PC50 are changed to "0". Section 5.4.1: Initial values of parameter No.PD25 to PD30 are corrected from "0" to "0000h". Section 5.4.2: Initial values of parameter No.PD25 to PD30 are corrected from "0" to "0000h". Section 13.4.2 (6): Description of data No.[0][3] is changed. Section 13.5.9 (3): Transmission data is added to table. Chapter 14: QD75P1/2/4 and QD75D1/2/4 are deleted from POINT. Section 14.2: "If the encoder cable is disconnected, absolute position data will be lost" is added to POINT. Section 14.3 (1): POINT description is changed. Section 14.7.2 (1) (a): Description of Note 3 is added. Note 5 is added. Section 14.7.2 (1) (b): Description of Note 7 is changed. Section 14.7.2 (2) (a): 4) and 5) are added. Section 14.7.2 (2) (b): Description and timing chart are changed. Section 14.8.1 (2) (b): "T211" is added to T timer and "M4" is added to M contact in device list. Section 14.8.1 (2) (c): Ladder program is corrected. Section 14.8.2 (2) (a): Sentence is added. Section 14.8.2 (2) (a) 1): Sentence is added. Section 14.8.2 (2) (b): "T201" is added to T timer and "M26" is added to M contact in device list. Section 14.8.2 (2) (c): Ladder program is corrected. Section 14.8.2 (2) (f): Note 2 is integrated into Note 1. Section 14.8.3 (2) (a): Sentence is added. Section 14.8.3 (2) (f): Note 2 is integrated into Note 1.
Jun. 2008	SH(NA)030038-H	Conformance with UL/C-UL standard: (3) Changed the description. (5) Deleted the fuse combination list. Cables for wiring: Described the criterion of selecting temperature. Section 1.3 (1): Changed the "2.3", MR-J3-200A in mass, to "2.1". Section 1.5 (2): Made the case of MR-J3-200A be same as MR-J3-200A4.

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Jun. 2008	SH(NA)030038-H	Section 1.7.1 (3) (4): Interchanged the model names (3) and (4). Made the function and configuration be same between MR-J3-200A and MR-J3-200A4 in comment. Added the "Note 4" at (3). Section 1.8 (1) (a), (b): Modified the "FR-BLF" to "FR-BSF01". Section 1.8 (3), (4): Interchanged model names (3) and (4). Made the function and configuration be same between MR-J3-200A and MR-J3-200A4 in comment. Added the "Note 4" at (3). Deleted the "Note 3" at (4). Section 2.1 (1) (b): At "POINT", changed the "Mounting closely is available for a combination of servo amplifier of 3.5kW or less in 200V or 100V class." to "Mounting closely is available for the servo amplifier of 3.5kW or less in 200V or 400W or less in 100V". Section 3.1 (5) to (8): In drawings, added no-fuse breakers (NFB) at the cables of cooling fan power supply. Section 3.3.2 (2): Timing chart is changed. Section 3.3.3 (2), (3): Interchanged the model names (2) and (3). Made the function and configuration be same between MR-J3-200A and MR-J3-200A4 in comment. Section 3.10.2 (3) (a) 1) to 2): In drawings, added no-fuse breakers (NFB) at the cables of cooling fan power supply. Section 10.1 (5), (6): Interchanged the model names (5) and (6). Made the function and configuration be same between MR-J3-200A and MR-J3-200A4 in comment. Added the POINT at (5). Section 11.3.1 (2) (b): Changed the graphs at HA-LP1000r/min and HA-LP1500r/min in dynamic brake characteristics. Section 12.1: POINT for protective structure is added. Section 12.1.1: In use, delete the "2kW" at the upper side in table 2), the "2kW or less in 400V" at down side. Section 12.1.2 (3)(a): "Crimping tool 91529-1" is added to table for junction connector. Section 12.1.3 (2): Added the "Note". Section 12.1.4 (2): Added the "Note". Section 12.2 (5) (a): Changed the tightening torque "3.2" to "3.24". Section 12.3.3 (4) (a): Changed the sentence. Section 12.3.4 (2): Errors in dimension notation are corrected. Section 12.5 (4) (a) 1): Added the "POINT", selection criterion for cable size. Deleted a sentence "The 600V vinyl cables used is standard". Section 12.5 (4) (b) 1): Changed the cross section of cable "5.5 mm^2" used for the 3.5kW servo amplifier, to "3.5mm^2" in connection drawing. Section 12.6 (3) (a): Added the "Note" in table. Section 12.6 (3) (b): Added the "Note" in table. Section 12.8 (2) (a): Changed the position of ® symbol for Windows Vista. RS-422/232C conversion cable is deleted. Section 12.8 (2) (b) 3): Changed the connection configuration. Section 12.11: Changed the "Recommended wires" to "Example of selecting wires". Added the HIV cable. Section 12.13: Added the "Note" in table.

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Jun. 2008	SH(NA)030038-H	Section 13.1 (1): Deleted the connection in RS-422/232C converter.	
		Section 13.1 (2) (a): Deleted the connection in RS-422/232C converter.	
		Section 13.1 (2) (b): Changed the RS-422 output unit. Added "Note 8".	
		Chapter 14: As a "POINT", added the "Taking the detecting cable off will lead to disappear the absolute position data".	
		Section 14.8.2 (1): Note 5 is changed.	
		Section 14.8.3 (1): Note 5 is changed.	
		Section 15.3.7 (1) (b): Timing chart is changed.	
		Section 15.9.3 (2): Added the "Note" in table.	
		Section 15.9.4: Changed the "Recommended wires" to "Example of selecting wires". Added the HIV cable.	
		Section 15.9.5: Note is deleted.	
		Section 15.9.10 (4) (b): Errors in dimension notation are corrected.	
		App. 5: Newly added as an explanation of "MR-J3-200A-RT servo amplifier".	
		App. 6: Newly added "Example of selecting cables of servo motor power supply".	
Aug. 2010	SH(NA)030038-J	HF-JP servo motor is added.	
		HF-KP servo motor becomes compatible with the 350% maximum torque.	
		Electronic symbols are entirely changed. (compliance with JIS C0617)	
		"Servo Motor Instruction Manual" is changed to "Servo Motor Instruction Manual (Vol.2)".	
		"AC reactor" is changed to "power factor improving AC reactor", and "DC reactor" is changed to "power factor improving DC reactor".	
		"Protective structure" is changed to "IP rating".	
		The signal name of ZSP is changed from "Zero speed" to "Zero speed detection".	
		"Japan Solderless Terminal" is changed to "Japan Solderless Terminals".	
		2. To prevent fire, note the following	Description is added.
		4. Additional instructions	Description is partially changed.
		COMPLIANCE WITH THE EUROPEAN EC DIRECTIVES	Description is changed to "Refer to Appendix 9 for the compliance with EC Directives".
		COMPLIANCE WITH UL/C-UL SATNDARD	Description is changed to "Refer to Appendix 10 for the compliance with UL/C-UL standard".
		Section 1.2 (3)	Note 2 is added.
		Section 1.3 (1)	Power supply specifications are added and changed. Environmental conditions are added and changed. Note 3 and Note 4 are added.
		Section 1.3 (2)	Power supply specifications are added and changed. Environmental conditions are added and changed. Note 2 is added.
		Section 1.4	Functions are added.
		Section 1.5 (1)	Description is partially changed.
		Section 1.5 (2)	Description is partially changed.
		Section 1.6	Description in the table is partially added.
		Chapter 2	"WARNING" is added. Description in "CAUTION" is added and changed.
		Section 2.1 (2) (a)	Diagram is partially changed.
		Section 2.5 (1)	Description is changed.
		Chapter 3	"CAUTION" is partially changed.
		Section 3.1 (1), (2), (4) to (8)	"Use only one of power factor improving DC reactor or power factor improving AC reactor." is added at the end of Note 1.

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Aug. 2010	SH(NA)030038-J	Section 3.1 (1) to (3)	Note 6 and Note 7 are added.
		Section 3.1 (4), (5), (7)	Note 7 and Note 8 are added.
		Section 3.1 (6)	Note 8 and Note 9 are added.
		Section 3.1 (7)	Note 7, Note 8 and Note 9 are added.
		Section 3.1 (8)	Note 9, Note 10 and Note 11 are added.
		Section 3.3.2 (2)	The timing chart of Trouble (ALM) is changed.
		Section 3.5 (1) (b)	Description in "Functions/Applications" of DB is partially changed.
		Section 3.5 (2)	Description in "Functions/Applications" of TLA is partially changed.
			Description in "Functions/Applications" of VLA is partially changed.
		Section 3.5 (3)	Description in "Functions/Applications" of MO1 and MO2 is partially changed.
		Section3.5 (5)	Description in "Functions/Applications" of DICOM and DOCOM is partially changed.
			"Control mode" for OPC is changed. Only P is marked by ○.
		Section 3.6.4 (3) (b)	Description is partially changed.
		Section 3.6.5 (4) (b)	Description is partially changed.
		Section 3.7 (3)	Description is partially changed.
		Section 3.10.1	Description in "CAUTION" is partially added.
		Section 3.10.2 (2)	Title is changed.
			"POINT" is partially changed.
		Section 3.10.2 (2) (b)	Partially added.
		Section 3.10.2 (3)	"POINT" is added.
		Section 3.11.1	Description in "CAUTION" is added and changed.
			2) is deleted.
			3)4)5) is changed to 2)3)4).
		Section 3.11.2 2)	"Time delay" is changed to "delay time".
		Section 3.11.3 (5)	Note 2 is deleted.
		Section 3.11.4 (1)	Note 4 is added.
		Section 3.11.4 (2)	Note 2 Description is partially changed.
			Note 5 is added.
		Section 4.1.1	Description is partially changed.
		Section 4.1.2 (1) (b) 4)	"11kW or more" is changed to "11k to 22kW".
		Section 4.1.2 (1) (c) 4)	"11kW or more" is changed to "11k to 22kW".
		Section 4.2.6 (1)	Description in the table is partially added.
		Section 5.1.3	Entire is changed.
		Section 5.1.8	Description is partially changed.
		Section 5.1.12	Description in the table is partially changed.
		Section 5.2.1	Parameter No.PB12 and PB45 are added.
		Section 5.2.2	Description in "Name and function" for parameter No.PB01 is partially changed.
			Description in "Name and function" for parameter No.PB02 is partially changed.
			Description in "Name and function" for parameter No.PB09 is partially added.
			Parameter No.PB12 added.
			Description in "Name and function" for parameter No.PB13 is partially changed.

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Aug. 2010	SH(NA)030038-J	Section 5.2.2	Description in "Name and function" for parameter No.PB14 is partially changed.
			Description in "Name and function" for parameter No.PB26 is partially changed.
			Parameter No.PB45 is added.
		Section 5.3.1	Parameter No.PC27 is added.
		Section 5.3.2	Description in "Name and function" for parameter No.PC17 is partially changed.
			Description in "Name and function" for parameter No.PC19 is partially changed.
			Description in "Name and function" for parameter No.PC22 is partially added and changed.
			Description in "Name and function" for parameter No.PC23 is partially changed.
			Parameter No.PC27 is added.
		Section 5.3.3	Description is partially deleted.
		Section 5.3.4	Description is partially changed.
		Section 5.4.1	Name of parameter No.PD19 is changed to "Input filter setting".
		Section 5.4.2	Description in "Name and function" for parameter No.PD01 is partially changed.
			Description in "Name and function" for parameter No.PD13 is partially added.
			Description in "Name and function" for parameter No.PD14 is partially added.
			Description in "Name and function" for parameter No.PD15 is partially added.
			Description in "Name and function" for parameter No.PD16 is partially added.
			Description in "Name and function" for parameter No.PD18 is partially added.
		Section 6.2	Description in the table is partially changed.
		Section 6.3.3	"POINT" is added.
			Description in the table is partially changed.
		Section 6.4	Description in the table is partially changed.
		Section 6.6.2 (1)	Title is changed.
		Section 6.6.2 (2)	Title is changed.
		Section 6.9.1	Diagram is partially changed.
		Section 6.9.3 (1)	Entire is changed.
		Section 7.1.1 (1)	Description in the table is partially added and changed.
		Section 7.2.2	Title is changed.
		Section 7.2.4	Description is partially changed.
		Section 7.3	"POINT" is partially changed.
		Section 7.3 (1) (b)	Description in the table is partially changed.
		Section 7.3 (2) (b)	Description in the table is partially changed.
		Section 8.2 (1)	"POINT" is partially changed.
		Section 8.2 (2)	Description is partially changed.
		Section 8.2 (3)	Description is partially changed.
			"POINT" is partially changed.
		Section 8.3 (1)	Description is partially changed.
		Section 8.3 (2)	(b) is added.
		Section 8.4 (1)	Description is partially changed.

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Aug. 2010	SH(NA)030038-J	Section 8.4 (2)	Description is partially changed.
		Section 8.4 (3)	Description is partially changed.
		Section 8.4 (4) (a)	Description is partially changed.
		Section 8.4 (4) (b)	"POINT" is partially changed.
		Section 8.5	Description is partially changed.
		Section 8.6.3	Description is partially added in (4).
			(7) is added.
		Section 8.6.4	Entire is changed.
		Section 8.7	Newly added.
		Chapter 9	"POINT" is partially added.
		Section 9.1	Name of AL.20 is changed. AL.21 is added.
		Section 9.2	"POINT" is partially added.
			Cause 3 of AL.20 is deleted.
			AL.21 is added.
			"10" is added in the Cause of AL.33.
		Section 10.1 (3), (5) to (9)	Air intake and exhaust directions are added.
		Section 11.1	Entire is changed.
		Section 11.2	Description in the table is partially added.
			Note 4 is added.
		Section 11.3	"POINT" is added.
		Section 11.3.1 (1)	Description is partially changed.
		Section 11.3.1 (2) (a)	Description is partially added and deleted.
		Section 11.3.1 (2) (b)	Description is partially added.
		Section 11.3.2	Description in the table is partially added.
			Note 3 is added.
		Section 12.1	"POINT" is entirely changed.
		Section 12.1.1	The option configuration diagram is entirely changed.
			Description in the table is partially added.
		Section 12.1.2 (2) (a)	Diagram is partially changed.
		Section 12.1.2 (2) (b)	Diagram is partially changed.
		Section 12.1.2 (2) (c)	Description is partially changed.
		Section 12.1.2 (4)	Title is changed to "(5) MR-J3ENSCBL□M-L(-S06) ・ MR-J3ENSCBL□M-H(-S06)" in section 12.1.2.
			The following contents are added in the new section 12.1.2 (5).
			MR-J3ENSCBL□M-L-S06, MR-J3ENSCBL□M-H-S06
			MR-J3SCNS-S06, MR-J3SCNSA, MR-J3SCNSA-S06
		Section 12.1.2 (4)	"MR-J3JSCBL03M-A1-L ・ MR-J3JSCBL03M-A2-L" is newly added.
		Section 12.1.2 (5)	The section number is changed to section 12.1.2(7).
		Section 12.1.2 (6)	"MR-ENECBL□M-H" is newly added.
		Section 12.1.2 (7)	Description is partially added.
		Section 12.2 (1)	Description in the table is partially added.
		Section 12.2 (3)	Description in the table is partially added.
		Section 12.2 (4) (a) (b)	Description is partially changed.
			Description is partially deleted.
		Section 12.2 (4) (c) (d)	Description is partially changed.
			Description in the table is partially added.
		Section 12.2 (5)	Entire is changed.
		Section 12.3	"POINT" is partially changed.

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Aug. 2010	SH(NA)030038-J	Section 12.3.3 (1) (a)	"Use only one of power factor improving DC reactor or power factor improving AC reactor." is added at the end of Note 3. Note 11 is added.
		Section 12.3.3 (1) (b)	"Use only one of power factor improving DC reactor or power factor improving AC reactor." is added at the end of Note 3. Note 12 is added.
		Section 12.3.3 (2)	"Use only one of power factor improving DC reactor or power factor improving AC reactor." is added at the end of Note 2. "For the servo amplifier of 11kW or more, connect the thermal relay censer of the servo amplifier." is added in Note 7. Note 7, 8, 9 are changed to Note 8, 9, 10. Note 11 is added.
		Section 12.4 (2)	"Use only one of power factor improving DC reactor or power factor improving AC reactor." is added at the end of Note 4. Note 7 is added.
		Section 12.5 (5)	Description is partially changed.
		Section 12.5 (6)	Description in the table is partially changed.
		Section 12.6	"CAUTION" is added. "POINT" is partially added and changed.
		Section 12.6 (2)	"Use only one of power factor improving DC reactor or power factor improving AC reactor." is added at the end of Note 1. Note 6 is added. "RA1" is changed to "Dynamic brake interlock (DB)" in the timing chart.
		Section 12.6 (3) (a)	Outline dimension drawings are changed.
		Section 12.7 (2)	Label is changed to the labels showing assigned signals in each control mode.
		Section 12.7 (4) (b)	Description is partially changed.
		Section 12.8 (1)	Description in the table is partially added.
		Section 12.8 (2)	Resolution of the display is changed from "800 × 600" to "1024 × 768". RS-422/232C converter cable is added.
		Section 12.9	"POINT" is changed.
		Section 12.11	"POINT" is changed.
		Section 12.11 (1)	"POINT" is added.
		Section 12.11 (1) (b)	"POINT" is added. Table 12.3 is added.
		Section 12.11 (1) (c)	Description in the table is partially changed.
		Section 12.11 (2)	Description in the table is partially added. Description is partially changed. Note 7 is added.
		Section 12.12	Entire table is changed. Note 2 is added.
		Section 12.13	"11kW or more" is changed to "11k to 22kW".
		Section 12.17 (2) (a)	Description is partially changed.
		Section 12.17 (2) (b)	Description is partially changed.
		Section 13.3.3	Description in the table is partially changed.
		Section 13.3.5	Title is changed. Description is partially changed.

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Aug. 2010	SH(NA)030038-J	Section 13.3.6	Title is changed. Description is partially changed.
		Section 13.5.3 (4)	Description is partially changed.
		Section 13.5.12	Description is partially changed.
		Chapter 14	"CAUTION" is partially changed. "POINT" is partially changed.
		Section 14.3	Title is changed to "Battery replacement procedure".
		Section 14.3.1	Newly added.
		Section 14.3.2	Newly added.
		Section 14.4	"Battery installation procedure" is newly added.
		Section 14.5	"Procedure to replace battery with the control circuit power OFF" is newly added.
		Section 14.5.1	Newly added.
		Section 14.5.2	Newly added.
		Section 14.4 to Section 14.11	Section numbers are changed to "section 14.6 to section 14.13".
		Section 14.10.3 (2)	"Absolute value restoration" is changed to "Absolute position restoration".
		Section 15.1.1	Note 2 is added.
		Section 15.1.3 (1)	Power supply specifications are added and changed. Environmental conditions are added and changed.
		Section 15.1.3 (2) (a) (b)	Power supply specifications are added and changed. Environmental conditions are added and changed. Note 2 is added.
		Section 15.1.6 (1) to (3)	"POINT" is partially changed.
		Section 15.1.6 (1)	Description in the table is partially changed.
		Section 15.1.8	Description in the diagram is partially changed.
		Section 15.2	"WARNING" is added. "CAUTION" is partially added and partially changed.
		Section 15.2.1 (1)	Description is partially changed.
		Section 15.3.2	"CAUTION" is partially changed. "POINT" is partially changed.
		Section 15.3.2 (1) (a)	Note 5 and Note 6 are added.
		Section 15.3.2 (1) (b)	Note 6 and Note 7 are added.
		Section 15.3.2 (2) (a)	Note 6 and Note 7 are added.
		Section 15.3.2 (2) (b)	Note 7 and Note 8 are added.
		Section 15.3.6 (1)	Description in the table is partially changed.
		Section 15.3.7	Timing chart is entirely changed.
		Section 15.4.4	Description is partially changed.
		Section 15.6.1 (2)	"9" is added in Cause of AL.33.
		Section 15.7.1	Air intake and exhaust directions are added.
		Section 15.7.2	Air intake and exhaust directions are added.
		Section 15.8.1	Description is partially added.
		Section 15.8.3 (1)	"POINT" is added. Description is partially changed.
		Section 15.9.1 (1)	Diagram is partially changed. Description in the table is partially added. Description is partially changed.
		Section 15.9.2 (4)	Description is partially changed.
		Section 15.9.2 (5)	Outline dimension drawings are changed.
		Section 15.9.3	"CAUTION" is added. "POINT" is partially added and partially changed.
		Section 15.9.3 (2)	Description is partially changed.

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Aug. 2010	SH(NA)030038-J	Section 15.9.3 (3)	Outline dimension drawings are changed.
		Section 15.9.4	"POINT" is partially changed.
		Section 15.9.4 (3)	Description in the table is partially added. Description is partially changed.
		Section 15.9.5	Entire is changed.
		Section 15.9.6	Description in the table is partially changed.
		Section 15.9.10	"POINT" is partially changed.
		Section 16.2	Description in the table is partially changed.
		Section 16.5.6	"CAUTION" is partially changed.
		Section 16.5.6 (1) (2)	Description is partially changed.
		Section 16.6 (1)	Description in the table is partially changed.
		App. 1	Description is partially added. Description is partially changed.
		App. 5.4	Air intake and exhaust directions are added.
		App. 6	Description in the table is partially added.
		App. 7	Newly added.
		App. 8	Newly added.
		App. 9	Newly added.
		App. 10	Newly added.
Aug. 2013	SH(NA)030038-K	Section 12.4	POINT is added.
		Section 12.4(2)	Note is added.
		Section 15.9.10	POINT is added.

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Taiwan	Setsuyo Enterprise Co., Ltd. 6F, No.105 Wu-Kung 3rd Rd, Wu-Ku Hsiang, Taipei Hsine, Taiwan	Tel : ＋886-2-2299-2499 Fax : ＋886-2-2299-2509
Korea	Mitsubishi Electric Automation Korea Co., Ltd. 3F, 1480-6, Gayang-dong, Gangseo-gu, Seoul 157-200, Korea	Tel : ＋82-2-3660-9552 Fax : ＋82-2-3664-8372
Singapore	Mitsubishi Electric Asia Pte, Ltd. 307 Alexandra Road #05-01/02, Mitsubishi Electric Building Singapore 159943	Tel : ＋65-6470-2460 Fax : ＋65-6476-7439

Warranty

1. Warranty period and coverage

We will repair any failure or defect hereinafter referred to as "failure" in our FA equipment hereinafter referred to as the "Product" arisen during warranty period at no charge due to causes for which we are responsible through the distributor from which you purchased the Product or our service provider. However, we will charge the actual cost of dispatching our engineer for an on-site repair work on request by customer in Japan or overseas countries. We are not responsible for any on-site readjustment and/or trial run that may be required after a defective unit are repaired or replaced.

[Term]

The term of warranty for Product is twelve (12) months after your purchase or delivery of the Product to a place designated by you or eighteen (18) months from the date of manufacture whichever comes first (“Warranty Period”). Warranty period for repaired Product cannot exceed beyond the original warranty period before any repair work.

[Limitations]

(1) You are requested to conduct an initial failure diagnosis by yourself, as a general rule.
It can also be carried out by us or our service company upon your request and the actual cost will be charged. However, it will not be charged if we are responsible for the cause of the failure.

(2) This limited warranty applies only when the condition, method, environment, etc. of use are in compliance with the terms and conditions and instructions that are set forth in the instruction manual and user manual for the Product and the caution label affixed to the Product.

(3) Even during the term of warranty, the repair cost will be charged on you in the following cases;
  (i) a failure caused by your improper storing or handling, carelessness or negligence, etc., and a failure caused by your hardware or software problem
  (ii) a failure caused by any alteration, etc. to the Product made on your side without our approval
  (iii) a failure which may be regarded as avoidable, if your equipment in which the Product is incorporated is equipped with a safety device required by applicable laws and has any function or structure considered to be indispensable according to a common sense in the industry
  (iv) a failure which may be regarded as avoidable if consumable parts designated in the instruction manual, etc. are duly maintained and replaced
  (v) any replacement of consumable parts (battery, fan, smoothing capacitor, etc.)
  (vi) a failure caused by external factors such as inevitable accidents, including without limitation fire and abnormal fluctuation of voltage, and acts of God, including without limitation earthquake, lightning and natural disasters
  (vii) a failure generated by an unforeseeable cause with a scientific technology that was not available at the time of the shipment of the Product from our company
  (viii) any other failures which we are not responsible for or which you acknowledge we are not responsible for

2. Term of warranty after the stop of production

(1) We may accept the repair at charge for another seven (7) years after the production of the product is discontinued. The announcement of the stop of production for each model can be seen in our Sales and Service, etc.

(2) Please note that the Product (including its spare parts) cannot be ordered after its stop of production.

3. Service in overseas countries

Our regional FA Center in overseas countries will accept the repair work of the Product. However, the terms and conditions of the repair work may differ depending on each FA Center. Please ask your local FA center for details.

4. Exclusion of responsibility for compensation against loss of opportunity, secondary loss, etc.

Whether under or after the term of warranty, we assume no responsibility for any damages arisen from causes for which we are not responsible, any losses of opportunity and/or profit incurred by you due to a failure of the Product, any damages, secondary damages or compensation for accidents arisen under a specific circumstance that are foreseen or unforeseen by our company, any damages to products other than the Product, and also compensation for any replacement work, readjustment, start-up test run of local machines and the Product and any other operations conducted by you.

5. Change of Product specifications

Specifications listed in our catalogs, manuals or technical documents may be changed without notice.

6. Application and use of the Product

(1) For the use of our General-Purpose AC Servo, its applications should be those that may not result in a serious damage even if any failure or malfunction occurs in General-Purpose AC Servo, and a backup or fail-safe function should operate on an external system to General-Purpose AC Servo when any failure or malfunction occurs.

(2) Our General-Purpose AC Servo is designed and manufactured as a general purpose product for use at general industries.
Therefore, applications substantially influential on the public interest for such as atomic power plants and other power plants of electric power companies, and also which require a special quality assurance system, including applications for railway companies and government or public offices are not recommended, and we assume no responsibility for any failure caused by these applications when used
In addition, applications which may be substantially influential to human lives or properties for such as airlines, medical treatments, railway service, incineration and fuel systems, man-operated material handling equipment, entertainment machines, safety machines, etc. are not recommended, and we assume no responsibility for any failure caused by these applications when used.
We will review the acceptability of the abovementioned applications, if you agree not to require a specific quality for a specific application. Please contact us for consultation.

MODEL	MR-J3-A INSTRUCTIONMANUAL
MODEL CODE	1CW203

MITSUBISHI ELECTRIC CORPORATION

HEAD OFFICE : TOKYO BLDG MARUNOUCHI TOKYO 100-8310

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Specifications are subject to change without notice.