



**Allen-Bradley**

# **PowerFlex<sup>®</sup>** **700S**

**High Performance AC Drive**

**Firmware Versions**

x.xx-2.04

**User Manual**

**Rockwell**  
**Automation**

## Important User Information

Solid state equipment has operational characteristics differing from those of electromechanical equipment. *Safety Guidelines for the Application, Installation and Maintenance of Solid State Controls* (Publication SGI-1.1 available from your local Rockwell Automation sales office or online at <http://www.rockwellautomation.com/literature>) describes some important differences between solid state equipment and hard-wired electromechanical devices. Because of this difference, and also because of the wide variety of uses for solid state equipment, all persons responsible for applying this equipment must satisfy themselves that each intended application of this equipment is acceptable.

In no event will Rockwell Automation, Inc. be responsible or liable for indirect or consequential damages resulting from the use or application of this equipment.

The examples and diagrams in this manual are included solely for illustrative purposes. Because of the many variables and requirements associated with any particular installation, Rockwell Automation, Inc. cannot assume responsibility or liability for actual use based on the examples and diagrams.

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Throughout this manual, when necessary we use notes to make you aware of safety considerations.



**WARNING:** Identifies information about practices or circumstances that can cause an explosion in a hazardous environment, which may lead to personal injury or death, property damage, or economic loss.

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**Important:** Identifies information that is critical for successful application and understanding of the product.

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**ATTENTION:** Identifies information about practices or circumstances that can lead to personal injury or death, property damage, or economic loss. Attentions help you:

- identify a hazard
  - avoid the hazard
  - recognize the consequences
- 



**Shock Hazard** labels may be located on or inside the equipment (e.g., drive or motor) to alert people that dangerous voltage may be present.

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**Burn Hazard** labels may be located on or inside the equipment (e.g., drive or motor) to alert people that surfaces may be at dangerous temperatures.

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# Summary of Changes

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This information summarizes the changes to the PowerFlex 700S User Manual, publication 20D-UM001 since the last release.

## Manual Updates

Change	See Page...
Catalog Number Explanation updated.	<a href="#">Preface-5</a>
Terminal Block Table updated.	<a href="#">1-11</a>
External Brake Resistor Circuitry updated.	<a href="#">1-14</a>
Programming and Parameters Chapter updated.	<a href="#">3-1-3-100</a>
High Power Faults added.	<a href="#">4-1</a>
Recommended Protection Devices Tables updated.	<a href="#">A-7-A-12</a>
Control Block Diagrams updated.	<a href="#">B-1</a>
Stegmann High Resolution Encoder Appendix updated.	<a href="#">C-1</a>
Appendix D, Application Notes added.	<a href="#">E-1</a>
Appendix E, Resolver Feedback Option added.	<a href="#">F-1</a>
Appendix F, Access Procedures added.	<a href="#">G-1</a>



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## Overview

The purpose of this manual is to provide you with the basic information needed to install, start-up and troubleshoot the PowerFlex 700S Adjustable Frequency AC Drive.

For information on ...	See page...
<a href="#">Who Should Use This Manual</a>	<a href="#">Preface-1</a>
<a href="#">What Is Not In This Manual</a>	<a href="#">Preface-1</a>
<a href="#">Recommended Documentation</a>	<a href="#">Preface-1</a>
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<a href="#">General Precautions</a>	<a href="#">Preface-4</a>
<a href="#">Catalog Number Explanation</a>	<a href="#">Preface-5</a>

### Who Should Use This Manual

This manual is intended for qualified personnel. You must be able to program and operate Adjustable Frequency AC Drive devices. In addition, you must have an understanding of the parameter settings and functions. You must also understand programmable controllers for the PowerFlex 700S with DriveLogix.

### What Is Not In This Manual

Since this *User Manual* is designed to provide only basic start-up information, the following topic has not been included:

- Spare Parts Information

For detailed drive information, please refer to publication *PowerFlex 700S Reference Manual, Vol 2*. This publication is available online at:

[www.theautomationbookstore.com](http://www.theautomationbookstore.com)

### Recommended Documentation

The following publications provide general drive information.

Title	Publication	Available...
Wiring and Grounding for PWM AC Drives	DRIVES-IN001	<a href="http://www.theautomationbookstore.com">www.theautomationbookstore.com</a>
Safety Guidelines for the Application, Installation and Maintenance of Solid State Control	SGI-1.1	<a href="http://www.ab.com/manuals/dr/index3.html#Safety">www.ab.com/manuals/dr/index3.html#Safety</a>
A Global Reference Guide for Reading Schematic Diagrams	100-2.10	<a href="http://www.theautomationbookstore.com">www.theautomationbookstore.com</a>
Guarding Against Electrostatic Damage	8000-4.5.2	<a href="http://www.ab.com/manuals/dr/index3.html#Safety">www.ab.com/manuals/dr/index3.html#Safety</a>

The following publications provide specific PowerFlex drive information.

Title	Publication	Available...
Installation Instructions - Hi-Resolution Encoder Feedback Option for PowerFlex 700S Drives	20D-IN001	www.ab.com/manuals/dr
Installation Instructions - Resolver Feedback Option for PowerFlex 700S Drives	20D-IN002	
Firmware Release Notes - PowerFlex 700S Drive (firmware revision 2.04)	20D-RN0012	

For detailed PowerFlex 700S information:

Title	Publication	Available...
PowerFlex Reference Manual, Vol. 2	PFLEX-RM002	On CD supplied with drive or www.ab.com/manuals/dr

For Allen-Bradley Drives Technical Support:

Title	Online at...
Allen-Bradley Drives Technical Support	www.ab.com/support/abdrives

The following publications provide necessary information when applying the DriveLogix Controller.

Title	Publication	Available...
DriveLogix Controller User Manual	20D-UM002	On CD supplied with drive or www.ab.com/manuals/dr
Firmware Release Notes - DriveLogix Controller (firmware revision 10.15)	20D-RN001	www.ab.com/manuals/dr
Firmware Release Notes - DriveLogix Controller (firmware revision 10.16)	20D-RN002	www.ab.com/manuals/dr
Firmware Release Notes - DriveLogix Controller (firmware revision 11.14)	20D-RN003	www.ab.com/manuals/dr
Logix5000 Controllers Common Procedures	1756-PM001	www.ab.com/manuals/fl/
Installation Instructions - DriveLogix Controller for PowerFlex 700S Drives	20D-IN003	www.ab.com/manuals/dr
Logix5000 Controllers General Instructions	1756-RM003	www.ab.com/manuals/fl/
ControlNet Daughtercard Installation Instructions	1788-IN002	www.ab.com/manuals/cn
ControlNet Daughtercard Installation Instructions	1788-IN005	www.ab.com/manuals/cn
Logix5000 Controllers Process Control and Drives Instructions	1756-RM006	www.ab.com/manuals/fl/
RSLogix 5000 Getting Results	9399-RLD300GR	www.ab.com/manuals/swrsi/
RSNetworx for ControlNet Getting Results	9398-CNETGR	www.ab.com/manuals/swrsi/
RSLinx Getting Results Guide	9399-LINXGR	www.ab.com/manuals/swrsi/

The following publications provide information that is useful when planning and installing communication networks.

Title	Publication	Available...
ControlNet Coax Tap Installation Instructions	1786-5.7	www.ab.com/manuals/cn/controlnet.html
ControlNet Cable System Planning and Installation Manual	1786-6.2.1	www.ab.com/manuals/cn/controlnet.html
ControlNet Fiber Media Planning and Installation Guide	CNET-IN001	www.ab.com/manuals/cn/controlnet.html
SynchLink Design Guide	1756-TD008	www.ab.com/manuals/cn/

## Manual Conventions

- In this manual we refer to the PowerFlex 700S Adjustable Frequency AC Drive as: drive, PowerFlex 700S or PowerFlex 700S Drive.
- To help differentiate parameter names and LCD display text from other text, the following conventions will be used:
  - Parameter Names will appear in [brackets] after the Parameter Number.  
For example: Parameter 307 [Output Voltage].
  - Display text will appear in “quotes.” For example: “Enabled.”
- The following words are used throughout the manual to describe an action:

Word	Meaning
Can	Possible, able to do something
Cannot	Not possible, not able to do something
May	Permitted, allowed
Must	Unavoidable, you must do this
Shall	Required and necessary
Should	Recommended
Should Not	Not recommended

## Drive Frame Sizes

Similar PowerFlex 700S drive sizes are grouped into frame sizes to simplify spare parts ordering, dimensioning, etc. A cross reference of drive catalog numbers and their respective frame size is provided in [Appendix A](#).

## General Precautions

### Class 1 LED Product



**ATTENTION:** Hazard of permanent eye damage exists when using optical transmission equipment. This product emits intense light and invisible radiation. Do not look into module ports or fiber optic cable connectors.

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**ATTENTION:** This drive contains **ESD** (Electrostatic Discharge) sensitive parts and assemblies. Static control precautions are required when installing, testing, servicing or repairing this assembly. Component damage may result if ESD control procedures are not followed. If you are not familiar with static control procedures, reference A-B publication 8000-4.5.2, “Guarding Against Electrostatic Damage” or any other applicable ESD protection handbook.



**ATTENTION:** An incorrectly applied or installed drive can result in component damage or a reduction in product life. Wiring or application errors, such as, undersizing the motor, incorrect or inadequate AC supply, or excessive ambient temperatures may result in malfunction of the system.



**ATTENTION:** Only **qualified personnel** familiar with the PowerFlex 700S Drive and associated machinery should plan or implement the installation, start-up and subsequent maintenance of the system. Failure to comply may result in personal injury and/or equipment damage.



**ATTENTION:** To avoid an electric shock hazard, verify that the voltage on the bus capacitors has discharged before performing any work on the drive. Measure the DC bus voltage at the +DC & –DC terminals of the Power Terminal Block (refer to [Chapter 1](#) for location). The voltage must be zero.



**ATTENTION:** Risk of injury or equipment damage exists. DPI or SCANport host products must not be directly connected together via 1202 cables. Unpredictable behavior can result if two or more devices are connected in this manner.



**ATTENTION:** Risk of injury or equipment damage exists. Parameters 365 [Encdr0 Loss Cnfg] - 394 [VoltFdbkLossCnfg] let you determine the action of the drive in response to operating anomalies. Precautions should be taken to ensure that the settings of these parameters do not create hazards of injury or equipment damage.



**ATTENTION:** Risk of injury or equipment damage exists. Parameters 383 [SL CommLoss Data] - 392 [NetLoss DPI Cnfg] let you determine the action of the drive if communications are disrupted. You can set these parameters so that the drive continues to run. Precautions should be taken to ensure that the settings of these parameters do not create hazards of injury or equipment damage.

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## Catalog Number Explanation

Position												
1-3	4	5-7	8	9	10	11	12	13	14	15	16	17
20D	D	2P1	A	0	E	Y	N	A	N	N	N	N
Drive	Voltage Rating	Rating	Enclosure	HIM	Documentation	Brake	Brake Resistor	Emission	Comm Slot	I/O	Additional Feedback	Additional Config

**Code Type**

20D PowerFlex 700S

**Code w/Resistor**

Y Yes ❶  
N No

**Code Type**

N None

**Code Voltage Ph. DC Precharge**

Code	Voltage	Ph.	DC Precharge
B	240V AC	3	—
C	400V AC	3	—
D	480V AC	3	—
E ❸	600V AC	3	—
F	690V AC	3	—
H ❹	540V DC	—	—
J ❺	650V DC	—	—
P ❻	540V DC	—	N
R ❼	650V DC	—	Y

**Code Operator Interface**

0	Blank Cover
2	Digital LCD
3	Full Numeric LCD
4	Analog LCD
5	Prog. Only LCD
C	Full Numeric LCD, Door Mount ❷

**Code CE Filter CM Choke**

Code	CE Filter	CM Choke
A	Yes	Yes
B	Yes	No
N ❸	No	No

**Code Option**

N	None
A	Resolver
B	Hi-Resolution Stegman Encoder
C	Multi-Device Interface

**Code Enclosure**

A IP 20, NEMA Type 1

**Code w/Brake IGBT ❹**

Y Yes  
N No

**Code Logix Options**

N	None
A	DriveLogix5720
B	DriveLogix5720 w/ Expanded Memory

**Code Documents**

E	Quick Start Guide and CD
N	No Documentation

**Code Version**

C	DPI ControlNet (Coax)
D	DPI DeviceNet
R	DPI RIO
S	DPI RS-483 DF1
E	DPI EtherNet/IP
1	DriveLogix ControlNet (Coax)
2	DriveLogix ControlNet Redundant (Coax)
3	DriveLogix ControlNet (Fiber)
4	DriveLogix ControlNet Redundant (Fiber)
5	DriveLogix DeviceNet (Open Conn.)
6	DriveLogix EtherNet/IP (Twisted Pair)
N	None

Output Current @ 208/240V

Code	208V Amps	240 Amps	HP
4P2	4.8	4.2	1.0
6P8	7.8	6.8	2.0
9P6	11	9.6	3.0
015	17.5	15.3	5.0
022	25.3	22	7.5
028	32.2	28	10
042	48.3	42	15
052	56	52	20
070	78.2	70	25
80	92	80	30
104	120	104	40
130	130	130	50
154	177	154	60
192	221	192	75

Output Current @ 400V

Code	Amps	HP
2P1	2.1	1.0
3P5	3.5	2.0
5P0	5.0	3.0
8P7	8.7	5.0
011	11.5	7.5
015	15.4	10
022	22	15
030	30	20
037	37	25
043	43	30
056	56	40
072	72	50
085	85	60
105	105	75
125	125	75
140	140	100
170	170	125
205	205	150
248	248	200
261	261	200
300	300	250
385	385	300
460	460	350
500	500	450

Output Current @ 480V

Code	Amps	HP
2P1	2.1	1.0
3P4	3.4	2.0
5P0	5	3.0
8P0	8	5.0
011	11	7.5
014	14	10
022	22	15
027	27	20
034	34	25
040	40	30
052	52	40
065	65	50
096	96	75
125	125	100
156	156	125
180	180	150
248	248	200
261	261	200
300	300	250
385	385	300
460	460	350
500	500	450

Output Current @ 600V ❸

Code	Amps	HP
022	22	20
027	27	25
032	32	30
041	41	40
052	52	50
062	62	60
077	77	75
099	99	100
125	125	125
144	144	150

Output Current @ 690V

Code	Amps	kW-ND
052	52	45
060	60	55
082	82	75
098	98	90
119	119	110
142	142	132

- ❶ Not available for Frame 3 drives or larger.
- ❷ Frame 10 & up only.
- ❸ Brake IGBT is standard on Frames 1-3 and optional on Frames 4-9 ONLY.
- ❹ For use on ungrounded distribution systems (Frame 9 drives only).
- ❺ CE Certification testing has not been performed on 600V class drives.
- ❻ Frames 5 & up Only.

**Important:** This table is not intended for ordering. For a full list of current options refer to publication 20D-PL001, *PowerFlex 700S/700S DriveLogix USA Price List*.

**Notes:**

## Installation/Wiring

### Chapter Objectives

This chapter provides the information needed to mount and wire the PowerFlex 700S AC drive.

For Information on ...	See Page...
<a href="#">Opening the Cover</a>	<a href="#">1-2</a>
<a href="#">Mounting Clearances</a>	<a href="#">1-2</a>
<a href="#">AC Supply Source Considerations</a>	<a href="#">1-3</a>
<a href="#">Grounding Requirements</a>	<a href="#">1-4</a>
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<a href="#">CE Conformity</a>	<a href="#">1-34</a>

Since most start-up difficulties are the result of incorrect wiring, take every precaution to assure the wiring is correct. Read and understand all items in this chapter before beginning installation.

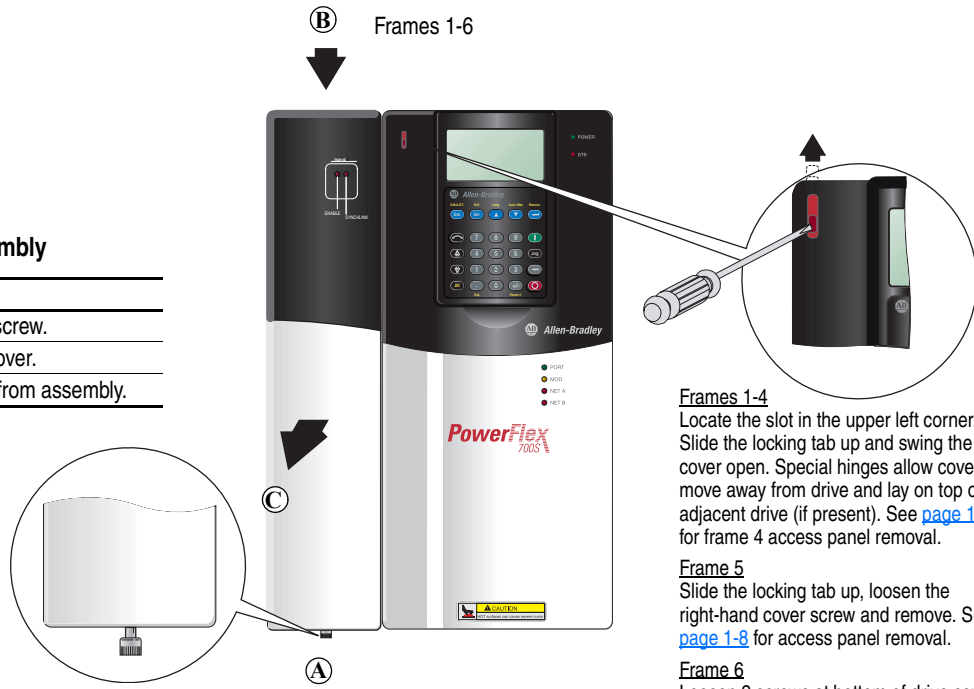


**ATTENTION:** The following information is merely a guide for proper installation. Rockwell Automation, Inc. cannot assume responsibility for the compliance or the noncompliance to any code, national, local or otherwise for the proper installation of this drive or associated equipment. A hazard of personal injury and/or equipment damage exists if codes are ignored during installation.

## Opening the Cover

### Opening Control Assembly

Step	Description
Ⓐ	Loosen captive screw.
Ⓑ	Push down on cover.
Ⓒ	Pull cover away from assembly.

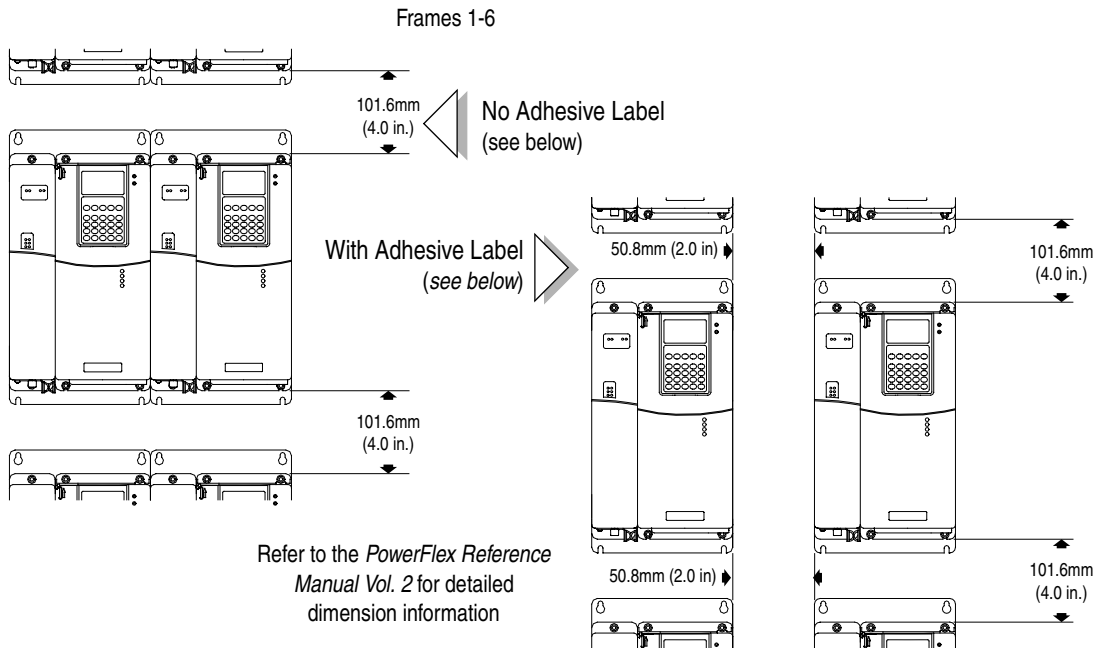


**Frames 1-4**  
 Locate the slot in the upper left corner. Slide the locking tab up and swing the cover open. Special hinges allow cover to move away from drive and lay on top of adjacent drive (if present). See [page 1-8](#) for frame 4 access panel removal.

**Frame 5**  
 Slide the locking tab up, loosen the right-hand cover screw and remove. See [page 1-8](#) for access panel removal.

**Frame 6**  
 Loosen 2 screws at bottom of drive cover. Carefully slide bottom cover down and out. Loosen the 2 screws at top of cover and remove.

## Mounting Clearances





## Operating Temperatures

PowerFlex 700S drives are designed to operate in surrounding air temperature of 0° to 40° C. To operate the drive in installations with surrounding air temperature between 41° and 50° C, remove the adhesive label affixed to the top of the drive enclosure.

**Table 1.A Acceptable Surrounding Air Temperature & Required Actions**

Drive Catalog Number	Required Action . . .		
	IP 20, NEMA Type 1	IP 20, NEMA Type Open	IP 00, NEMA Type Open
	No Action Required	Remove Top Label	Remove Top Label & Vent Plate <sup>(1)</sup>
All <i>Except</i> 20BC072	40° C	50° C	NA
20BC072	40° C	45° C	50° C

<sup>(1)</sup> To remove vent plate (see [page A-15](#) for location), lift top edge of plate from the chassis. Rotate the plate out from the back plate.

**Important:** Removing the adhesive label from the drive changes the NEMA enclosure rating from Type 1 to Open type.

## AC Supply Source Considerations

PowerFlex drives are suitable for use on a circuit capable of delivering up to a maximum of 200,000 rms symmetrical amperes, 600 volts with recommended fuses/circuit breakers. Refer to the *PowerFlex Reference Manual Vol. 2* for actual interrupt ratings based on circuit breaker or fuse choice.



**ATTENTION:** To guard against personal injury and/or equipment damage caused by improper fusing or circuit breaker selection, use only the recommended line fuses/circuit breakers specified in [Appendix A](#).

If a Residual Current Detector (RCD) is used as a system ground fault monitor, only Type B (adjustable) devices should be used to avoid nuisance tripping.

## Unbalanced or Ungrounded Distribution Systems

If phase to ground voltage will exceed 125% of normal or the supply system is ungrounded, refer to the *Wiring and Grounding Guidelines for PWM Drives* for more information.



**ATTENTION:** PowerFlex 700S drives contain protective MOVs and common mode capacitors that are referenced to ground. These devices should be disconnected if the drive is installed on an ungrounded distribution system. See [page 1-17](#) for jumper locations.

## Input Power Conditioning

Certain events on the power system supplying a drive can cause component damage or shortened product life. These conditions are divided into 2 basic categories:

### 1. All Drives

- The power system has power factor correction capacitors switched in and out of the system, either by the user or by the power company.
- The power source has intermittent voltage spikes in excess of 6000 volts. These spikes could be caused by other equipment on the line or by events such as lightning strikes.
- The power source has frequent interruptions.

### 2. 5 HP or Less Drives (in addition to “1” above)

- The nearest supply transformer is larger than 100kVA or the available short circuit (fault) current is greater than 100,000A.
- The impedance in front of the drive is less than 0.5%.

If any or all of these conditions exist, it is recommended that the user install a minimum amount of impedance between the drive and the source. This impedance could come from the supply transformer itself, the cable between the transformer and drive or an additional transformer or reactor. The impedance can be calculated using the information supplied in either the *PowerFlex Reference Manual Vol. 2* or the technical document *Wiring and Grounding Guidelines*, publication DRIVES-IN001.

## Grounding Requirements

**The drive Safety Ground-PE must be connected to system ground.**

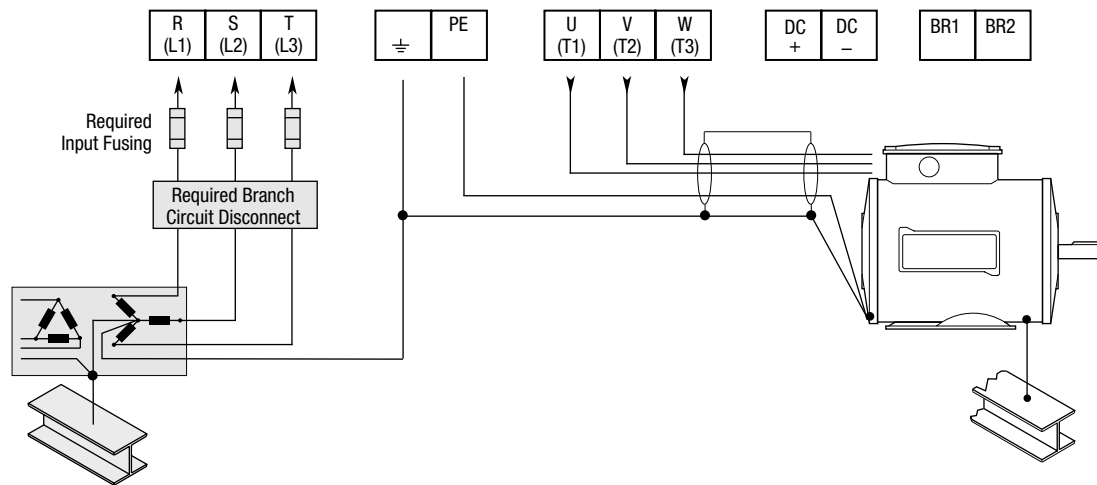
Ground impedance must conform to the requirements of national and local industrial safety regulations and/or electrical codes. The integrity of all ground connections should be periodically checked.

### Recommended Grounding Scheme

A single point (PE only) grounding scheme should be used. Some applications may require alternate grounding schemes, refer to the *Wiring and Grounding Guidelines for PWM AC Drives*, publication number DRIVES-IN001 for more information. These applications include installations with long distances between drives or drive line-ups, which could cause large potential differences between the drive or line-up grounds.

For installations within a cabinet, a single safety ground point or ground bus bar connected directly to building steel should be used. All circuits including the AC input ground conductor should be grounded independently and directly to this point/bar.

Figure 1.1 Typical Grounding



### Shield Termination - SHLD

The Shield terminal (see [Figure 1.3 on page 1-12](#)) provides a grounding point for the motor cable shield. It must be connected to an earth ground by a separate continuous lead. The **motor cable** shield should be connected to this terminal on the drive (drive end) and the motor frame (motor end). Use a shield terminating or EMI clamp to connect shield to this terminal.

### RFI Filter Grounding

Using an optional RFI filter may result in relatively high ground leakage currents. Therefore, the **filter must only be used in installations with grounded AC supply systems and be permanently installed and solidly grounded** (bonded) to the building power distribution ground. Ensure that the incoming supply neutral is solidly connected (bonded) to the same building power distribution ground. Grounding must not rely on flexible cables and should not include any form of plug or socket that would permit inadvertent disconnection. Some local codes may require redundant ground connections. The integrity of all connections should be periodically checked. Refer to the instructions supplied with the filter.

### Fuses and Circuit Breakers

The PowerFlex 700S can be installed with either input fuses or an input circuit breaker. Local/national electrical codes may determine additional requirements for these installations. Refer to [Appendix A](#) for recommended fuses/circuit breakers.



**ATTENTION:** The PowerFlex 700S does not provide input power short circuit protection. Specifications for the recommended fuse or circuit breaker to provide drive input power protection against short circuits are provided in [Appendix A](#).

## Power Wiring

### Power Cable Types Acceptable for 200-600 Volt Installations



**ATTENTION:** National Codes and standards (NEC, BSI etc.) and local codes outline provisions for safely installing electrical equipment. Installation must comply with specifications regarding wire types, conductor sizes, branch circuit protection and disconnect devices. Failure to do so may result in personal injury and/or equipment damage.

A variety of cable types are acceptable for drive installations. For many installations, unshielded cable is adequate, provided it can be separated from sensitive circuits. As an approximate guide, allow a spacing of 0.3 meters (1 foot) for every 10 meters (32.8 feet) of length. In all cases, long parallel runs must be avoided. Do not use cable with an insulation thickness less than or equal to 15 mils (0.4mm/0.015 in.). Use copper wire only. Wire gauge requirements and recommendations are based on 75° C. Do not reduce wire gauge when using higher temperature wire.

#### Unshielded

THHN, THWN or similar wire is acceptable for drive installation in dry environments provided adequate free air space and/or conduit fill rates limits are provided. **Do not use THHN or similarly coated wire in wet areas.** Any wire chosen must have a minimum insulation thickness of 15 Mil and should not have large variations in insulation concentricity.

#### Shielded/Armored Cable

Shielded cable contains all of the general benefits of multi-conductor cable with the added benefit of a copper braided shield that can contain much of the noise generated by a typical AC Drive. Strong consideration for shielded cable should be given in installations with sensitive equipment such as weigh scales, capacitive proximity switches and other devices that may be affected by electrical noise in the distribution system. Applications with large numbers of drives in a similar location, imposed EMC regulations or a high degree of communications/networking are also good candidates for shielded cable.

Shielded cable may also help reduce shaft voltage and induced bearing currents for some applications. In addition, the increased impedance of shielded cable may help extend the distance the motor can be located from the drive without the addition of motor protective devices such as terminator networks. Refer to Reflected Wave in *Wiring and Grounding Guidelines for PWM AC Drives*, publication DRIVES-IN001.

Consideration should be given to all of the general specifications dictated by the environment of the installation, including temperature, flexibility, moisture characteristics and chemical resistance. In addition, a braided shield should be included and specified by the cable manufacturer as having coverage of at least 75%. An additional foil shield can be greatly improve noise containment.

A good example of recommended cable is Belden® 295xx (xx determines gauge). This cable has 4 XLPE insulated conductors with a 100% coverage foil and an 85% coverage copper braided shield (with drain wire) surrounded by a PVC jacket.

Other types of shielded cable are available, but the selection of these types may limit the allowable cable length. Particularly, some of the newer cables twist 4 conductors of THHN wire and wrap them tightly with a foil shield. This construction can greatly increase the cable charging current required and reduce the overall drive performance. Unless specified in the individual distance tables as tested with the drive, these cables are not recommended and their performance against the lead length limits supplied is not known.

**Table 1.B Recommended Shielded Wire**

Location	Rating/Type	Description
Standard (Option 1)	600V, 90° C (194° F) XHHW2/RHW-2 Anixter B209500-B209507, Belden 29501-29507, or equivalent	Four tinned copper conductors with XLPE insulation. Copper braid/aluminum foil combination shield and tinned copper drain wire. PVC jacket.
Standard (Option 2)	Tray rated 600V, 90° C (194° F) RHH/RHW-2 Anixter OLF-7xxxx or equivalent	Three tinned copper conductors with XLPE insulation. 5 mil single helical copper tape (25% overlap min.) with three bare copper grounds in contact with shield. PVC jacket.
Class I & II; Division I & II	Tray rated 600V, 90° C (194° F) RHH/RHW-2 Anixter 7V-7xxx-3G or equivalent	Three bare copper conductors with XLPE insulation and impervious corrugated continuously welded aluminum armor. Black sunlight resistant PVC jacket overall. Three copper grounds on #10 AWG and smaller.

### EMC Compliance

Refer to [CE Conformity on page 1-34](#) for details.

### Cable Trays and Conduit

If cable trays or large conduits are to be used, refer to guidelines presented in the *Wiring and Grounding Guidelines for PWM AC Drives*.



**ATTENTION:** To avoid a possible shock hazard caused by induced voltages, unused wires in the conduit must be grounded at both ends. For the same reason, if a drive sharing a conduit is being serviced or installed, all drives using this conduit should be disabled. This will help minimize the possible shock hazard from “cross coupled” motor leads.

## Motor Cable Lengths

Typically, motor lead lengths less than 30 meters (100 feet) are acceptable. Motor lead lengths of 30 meters (100 feet) to 246 meters (800 feet) require shielded cable. If your application dictates longer lengths, refer to publication 20D-TD001, *Technical Data - PowerFlex 700S Drives*, for details.

## Power Terminal Block

[Figure 1.3](#) shows the typical location of the Power Terminal Block in Frame 1 drives. The terminal block is located in the bottom section of the drive on Frame 2-5 drives.

## Cable Entry Plate Removal

If additional wiring access is needed, the Cable Entry Plate on Frame 1-3 drives can be removed. Simply loosen the screws securing the plate to the chassis. The slotted mounting holes assure easy removal.

**Important:** Removing the Cable Entry Plate limits the maximum surrounding air temperature to 40° C (104° F).

## Power Wiring Access Panel Removal

Frame	Removal Procedure <i>(Replace when wiring is complete)</i>
1, 2 & 6	Part of front cover, see <a href="#">page 1-2</a> .
3	Open front cover and gently tap/slide cover down and out.
4	Loosen the 4 screws and remove.
5	Remove front cover (see <a href="#">page 1-2</a> ), gently tap/slide panel up and out.

## Access Panel Removal

Frame 3 drives utilize a panel/cover over the power wiring terminals. To remove, simply slide it down and out.

## Replace the cover when wiring is complete.



**ATTENTION:** Removing the access panel/cover exposes dangerous voltages on the terminals and negates the enclosure type rating. Replace the access panel/cover when service is complete. Failure to comply may result in personal injury or equipment damage.

## AC Input Phase Selection (Frames 5 & 6 Only)



**ATTENTION:** To avoid a shock hazard, ensure that all power to the drive has been removed before performing the following.

Moving the “Line Type” jumper shown in [Figure 1.2](#) will select single or three-phase operation. Remove plastic guard to access jumper.

**Important:** When selecting single-phase operation, input power must be applied to the R (L1) and S (L2) terminals only.

## Precharge - Common Bus

AC drives have internal precharge. DC fed drives require external precharge consisting of precharge contactors and current limiting resistors. Refer to [Table 1.C](#) for contactor and resistor values.

**Table 1.C Precharge Resistor Values**

Frame	Precharge Contactor	Precharge Resistor Series
9	318 A or greater	(2) 15 $\Omega$ 240 W

## Cooling Fan Voltage

Common Bus drives require user supplied 120 or 240V AC to power the cooling fans. Power source is connected between “0V AC” and the terminal corresponding to your source voltage (see [Figure 1.4 on page 1-13](#)).

**Table 1.D Fan VA Rating**

Frame	Fan Voltage(120V or 240V)
5	100 VA
6	138 VA

## Selecting/Verifying Fan Voltage (Frames 5 & 6 Only)

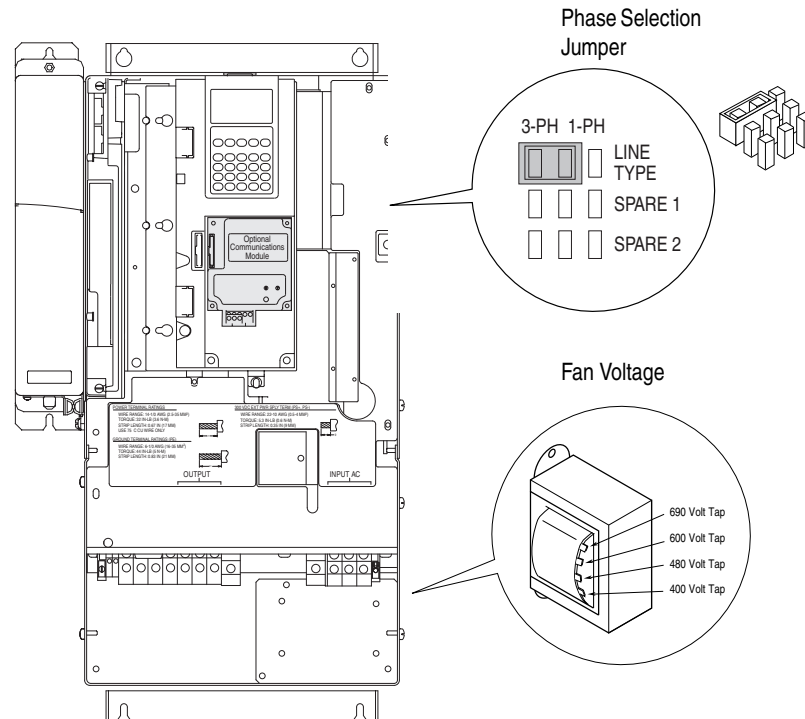


**ATTENTION:** To avoid a shock hazard, ensure that all power to the drive has been removed before performing the following.

Frames 5 & 6 utilize a transformer to match the input line voltage to the internal fan voltage. If your line voltage is different than the voltage class

specified on the drive nameplate, it may be necessary to change the transformer taps. The taps are shown in the insert of frame 5 below.

**Figure 1.2 Frames 5 & 6 Jumper and Transformer Locations (Frame 5 shown)**



#### Frame 6 Transformer Tap Access

The transformer is located behind the Power Terminal Block in the area shown in [Figure 1.2](#). Gain access by releasing the terminal block from the rail. To release terminal block and change tap:

1. Locate the small metal tab at the bottom of the end block.
2. Press the tab in and pull the top of the block out. Repeat for next block if desired.
3. Select appropriate transformer tap.
4. Replace block(s) in reverse order.

#### Important Common Bus (DC Input) Application Notes

1. If drives without internal precharge are used (Frames 5 & 6 only), then:
  - a) precharge capability must be provided in the system to guard against possible damage, and
2. disconnect switches **Must Not** be used between the input of the drive and a common DC bus without the use of an external precharge device.



Table 1.E Power Terminal Block Specifications

No.	Name	Frame	Description	Wire Size Range <sup>(1)</sup>		Torque		Terminal Bolt Size <sup>(2)</sup>		
				Maximum	Minimum	Maximum	Recommended			
①	Power Terminal Block	1	All power terminals	4.0 mm <sup>2</sup> (10 AWG)	0.5 mm <sup>2</sup> (22 AWG)	1.7 N-m (15 lb.-in.)	0.8 N-m (7 lb.-in.)	—		
		2	All power terminals	10.0 mm <sup>2</sup> (6 AWG)	0.8 mm <sup>2</sup> (18 AWG)	1.7 N-m (15 lb.-in.)	1.4 N-m (12 lb.-in.)	—		
		3	All power terminals	25.0 mm <sup>2</sup> (3 AWG)	2.5 mm <sup>2</sup> (14 AWG)	3.6 N-m (32 lb.-in.)	1.8 N-m (16 lb.-in.)	—		
			All power terminals	10.0 mm <sup>2</sup> (6 AWG)	0.8 mm <sup>2</sup> (18 AWG)	1.7 N-m (15 lb.-in.)	1.4 N-m (12 lb.-in.)	—		
		4	All power terminals	35.0 mm <sup>2</sup> (1/0 AWG)	10 mm <sup>2</sup> (8 AWG)	4.0 N-m (24 lb.-in.)	4.0 N-m (24 lb.-in.)	—		
		5 (75 HP) <sup>(3)</sup>	R, S, T, BR1, 2, DC+, DC-, U, V and W	50.0 mm <sup>2</sup> (1/0 AWG)	2.5 mm <sup>2</sup> (14 AWG)	See Note <sup>(4)</sup>	See Note <sup>(3)</sup>	—		
			PE	50.0 mm <sup>2</sup> (1/0 AWG)	4.0 mm <sup>2</sup> (12 AWG)			—		
		5 (100 HP) <sup>(3)</sup>	R, S, T, DC+, DC-, U, V and W	70.0 mm <sup>2</sup> (2/0 AWG)	16.0 mm <sup>2</sup> (6 AWG)			—		
			BR1, 2	50.0 mm <sup>2</sup> (1/0 AWG)	2.5 mm <sup>2</sup> (14 AWG)			—		
			PE	50.0 mm <sup>2</sup> (1/0 AWG)	4.0 mm <sup>2</sup> (12 AWG)			—		
6	All power terminals	120.0 mm <sup>2</sup> (4/0 AWG)	2.5 mm <sup>2</sup> (14 AWG)	6 N-m (52 lb.-in.)	6 N-m (52 lb.-in.)			—		
②	SHLD Terminal	1-6	Terminating point for wiring shields	—	—			1.6 N-m (14 lb.-in.)	1.6 N-m (14 lb.-in.)	M12
③	AUX Terminal Block	1-4	Auxiliary Control Voltage <sup>(5)</sup> PS+, PS-	1.5 mm <sup>2</sup> (16 AWG)	0.2 mm <sup>2</sup> (24 AWG)			—	—	—
		5-6		4.0 mm <sup>2</sup> (10 AWG)	0.5 mm <sup>2</sup> (22 AWG)			0.6 N-m (5.3 lb.-in.)	0.6 N-m (5.3 lb.-in.)	—
④	Fan Terminal Block (Common Bus Only)	5-6	User Supplied Fan Voltage 0V AC, 120V AC, 240V AC	4.0 mm <sup>2</sup> (10 AWG)	0.5 mm <sup>2</sup> (22 AWG)			0.6 N-m (5.3 lb.-in.)	0.6 N-m (5.3 lb.-in.)	M10

(1) Maximum/minimum sizes that the terminal block will accept - these are not recommendations.

(2) Apply counter torque to the nut on the other side of terminations when tightening or loosening the terminal bolt in order to avoid damage to the terminal.

(3) Not all terminals present on all drives.

(4) Refer to the terminal block label inside the drive.

(5) Auxiliary power:

UL Installation - 300V DC,  $\pm 10\%$ , Non UL Installation - 270-600V DC,  $\pm 10\%$ .

Frame 1-6, 100 W

Figure 1.3 Typical Power Terminal Block Location

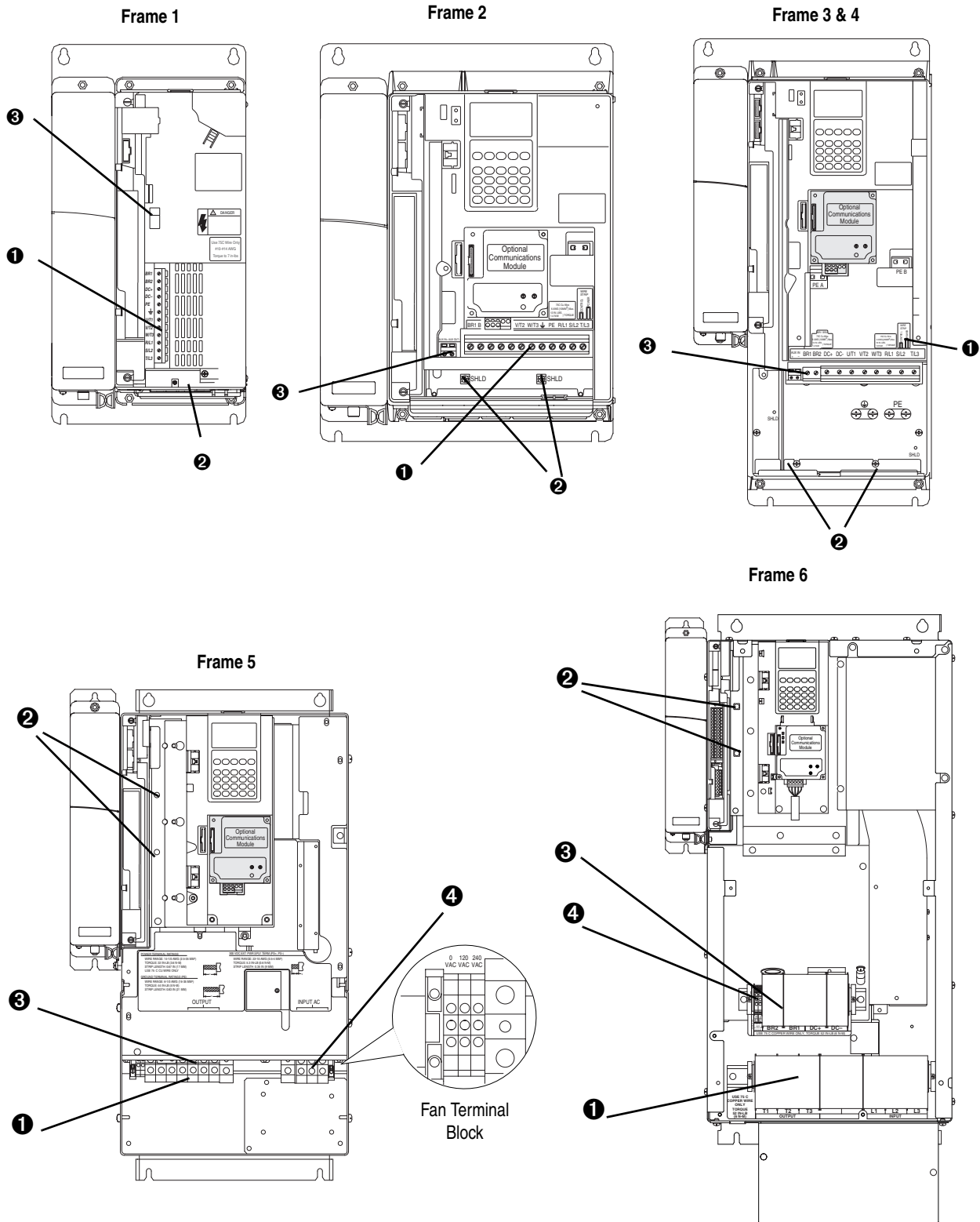
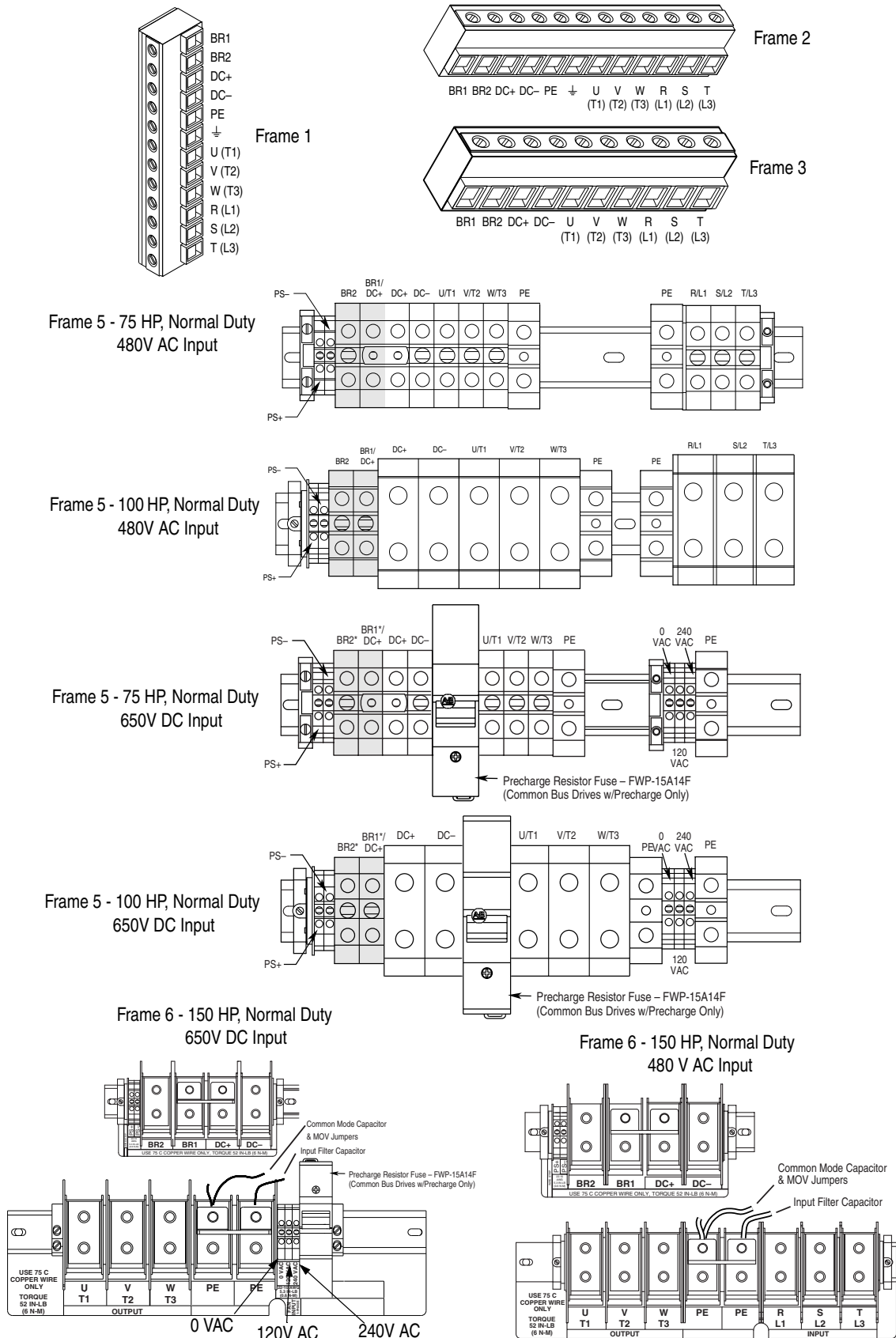


Figure 1.4 Power Terminal Block



Shaded terminals (BR1 & BR2) will only be present on drives ordered with the Brake Option.

**Table 1.F Terminal Block Descriptions**

Terminal	Description	Frame	Notes
BR1	DC Brake (+)	1-6	Dynamic Brake Resistor Connection (+)
DC+		9	DC Input or External Brake ( <i>Internal Brake option not ordered</i> )
BR2	DC Brake (-)	1-6	Dynamic Brake Resistor Connection (-)
DC-		9	DC Input or External Brake ( <i>Internal Brake option not ordered</i> )
DC+	DC Bus (+)	1-6	DC Input Power or Dynamic Brake Chopper
DC+/R+	DC Bus (+)/DC Brake (+)	9	DC Input/Internal Brake Connection ( <i>These terminals present when Internal Brake option is ordered</i> )
DC-		1-6	DC Input Power or Dynamic Brake Chopper
R-	DC Brake (-)	9	DC Input/Internal Brake Connection ( <i>These terminals present when Internal Brake option is ordered</i> )
PE	PE Ground	1-6	Refer to <a href="#">Figure 1.4</a> for location on 3 Frame drives
		9	
PS+	Aux +		Auxiliary Control Voltage. See <a href="#">Table 1.E on page 1-11</a> <sup>(1)</sup>
PS-	Aux -		Auxiliary Control Voltage. See <a href="#">Table 1.E on page 1-11</a> <sup>(1)</sup>
⊥	Motor Ground	1-6	Refer to <a href="#">Figure 1.3</a> for location on 3 Frame drives
		9	
U	U (T1)	1-9	To motor
V	V (T2)	1-9	To motor
W	W (T3)	1-9	To motor
R	R (L1)	1-9	AC Line Input Power
S	S (L2)	1-9	Three-Phase = R, S & T
T	T (L3)	1-9	Single-Phase = R & S

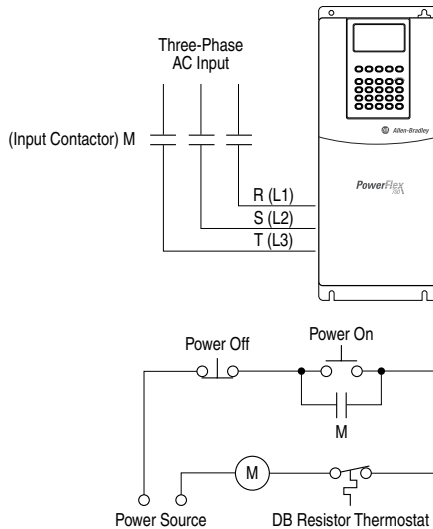
<sup>(1)</sup> Auxiliary power:  
 UL Installation - 300V DC, ±10%, Non UL Installation - 270-600V DC, ±10%.  
 1-3 Frame - 40 W, 165 mA, 5 Frame - 80 W, 90 mA

### Dynamic Brake Resistor Considerations



**ATTENTION:** The drive does not offer protection for externally mounted brake resistors. A risk of fire exists if external braking resistors are not protected. External resistor packages must be self-protected from over temperature or a circuit equivalent to the one shown below must be supplied.

**Figure 1.5 External Brake Resistor Circuitry**



## Using Input/Output Contactors



**ATTENTION:** A contactor or other device that routinely disconnects and reapplies the AC line to the drive to start and stop the motor can cause drive hardware damage. The drive is designed to use control input signals that will start and stop the motor. If an input device is used occasionally, an auxiliary contact on that device should also be wired to a digital input programmed as a “Enable” function. The input device must not exceed one operation per minute or drive damage will occur.



**ATTENTION:** The drive start/stop control circuitry includes solidstate components. If hazards due to accidental contact with moving machinery or unintentional flow of liquid, gas or solids exist, an additional hardwired stop circuit may be required to remove the AC line to the drive. When the AC line is removed, there will be a loss of any inherent regenerative braking effect that might be present - the motor will coast to a stop. An auxiliary braking method may be required.



**ATTENTION:** To guard against drive damage when using output contactors, the following information must be read and understood. One or more output contactors may be installed between the drive and motor(s) for the purpose of disconnecting or isolating certain motors/loads. If a contactor is opened while the drive is operating, power will be removed from the respective motor, but the drive will continue to produce voltage at the output terminals. In addition, reconnecting a motor to an active drive (by closing the contactor) could produce excessive current that may cause the drive to fault. If any of these conditions are determined to be undesirable or unsafe, an auxiliary contact on the output contactor should be wired to a drive digital input that is programmed as “Enable.” This will cause the drive to execute a coast-to-stop (cease output) whenever an output contactor is opened.

## Disconnecting MOVs and Common Mode Capacitors

PowerFlex 700S drives contain protective MOVs and common mode capacitors that are referenced to ground. To guard against drive damage, these devices should be disconnected if the drive is installed on an ungrounded distribution system where the line-to-ground voltages on any phase could exceed 125% of the nominal line-to-line voltage. To disconnect these devices, remove the jumper(s) listed in [Table 1.G](#). Jumpers can be removed by carefully pulling the jumper straight out. See the *Wiring and Grounding Guidelines for Pulse Width Modulated (PWM) AC Drives*, publication DRIVES-IN001 for more information on ungrounded system installation.



**ATTENTION:** To avoid an electric shock hazard, verify that the voltage on the bus capacitors has discharged before removing/ installing jumpers. Measure the DC bus voltage at the +DC & – DC terminals of the Power Terminal Block. The voltage must be zero.

**Table 1.G Jumper Removal**

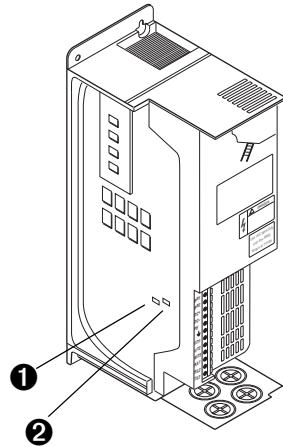
Frames	Jumper	Component	Jumper Location	No.
1	PEA	Common Mode Capacitors	Remove the Control Assembly and Cassette. Jumpers are located on the drive Power Board (see <a href="#">Figure 1.6</a> ).	①
	PEB	MOV's		②
2-4	PEA	Common Mode Capacitors	Jumpers are located above the Power Terminal Block (see <a href="#">Figure 1.6</a> ).	③
	PEB	MOV's		④
5	Wire	Common Mode Capacitors	Remove the I/O Cassette. The green/yellow jumper is located on the back of chassis in the area shown (see <a href="#">Figure 1.6</a> ). Disconnect, insulate and secure the wire to guard against unintentional contact with chassis or components.	⑤
		MOV's Input Filter Capacitors		⑥
6	Wire	Common Mode Capacitors	Remove the wire guard from the Power Terminal Block. Disconnect the three green/yellow wires from the two "PE" terminals shown in <a href="#">Figure 1.4</a> . Insulate and secure the wires to guard against unintentional contact with chassis or components.	Please refer to Power Terminal Blocks, Frame 6 on page <a href="#">1-12</a> .
		MOV's		
		Input Filter Capacitors		



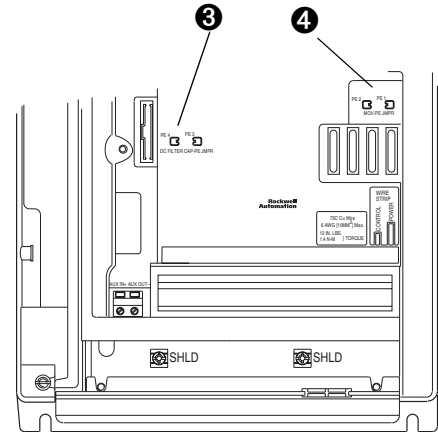
**ATTENTION:** The disconnecting MOV must be used on a grounded system.

Figure 1.6 Typical Jumper Locations

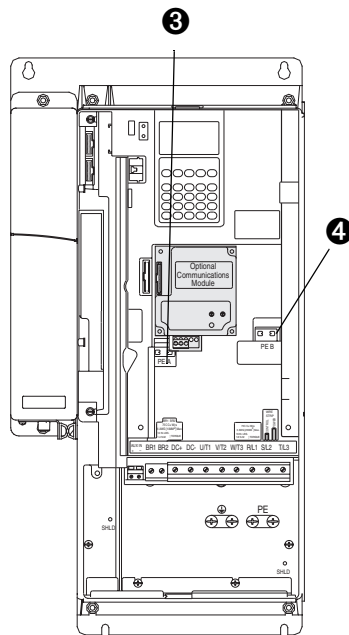
Frame 1  
(Control Assembly and I/O  
Cassette Removed)



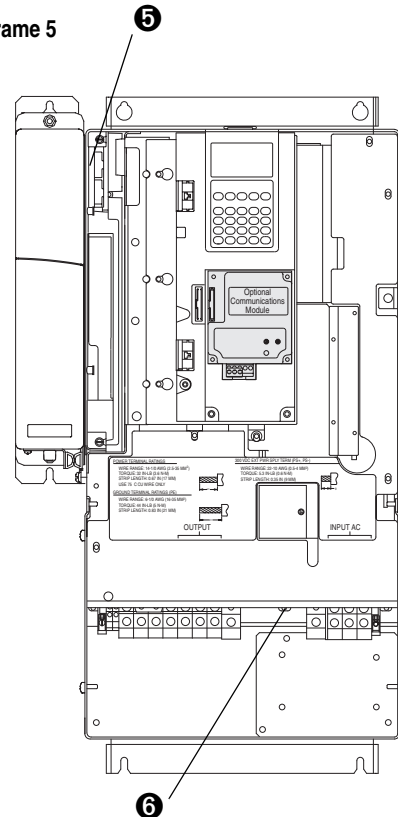
Frame 2



Frames 3 & 4



Frame 5



## I/O Wiring

Important points to remember about I/O wiring:

- Always use copper wire.
- Wire with an insulation rating of 600V or greater is recommended.
- Control and signal wires should be separated from power wires by at least 0.3 meters (1 foot).

**Important:** I/O terminals labeled “(-)” or “Common” are not referenced to earth ground and are designed to greatly reduce common mode interference. Grounding these terminals can cause signal noise.



**ATTENTION:** Configuring an analog input for 0-20mA operation and driving it from a voltage source could cause component damage. Verify proper configuration prior to applying input signals.



**ATTENTION:** Hazard of personal injury or equipment damage exists when using bipolar input sources. Noise and drift in sensitive input circuits can cause unpredictable changes in motor speed and direction. Use speed command parameters to help reduce input source sensitivity.

**Table 1.H Recommended Control Wire**

Type	Wire Type(s)	Description	Insulation Rating	
<b>Signal</b>	Standard Analog I/O	Belden 8760/9460 (or equiv.)	300V, 75-90° C (167-194° F), Minimum	
		Belden 8770 (or equiv.)		
	Encoder/Pulse I/O	Less than or equal to 30 m (98 ft.) – Belden 9728 (or equiv.)		0.750 mm <sup>2</sup> (18 AWG), twisted pair, shielded.
		Greater than 30 m (98 ft.) – Belden 9388 (or equiv.)		0.750 mm <sup>2</sup> (18 AWG), twisted pair, shielded.
<b>Digital I/O</b>	Unshielded	Per US NEC or applicable national or local code	300V, 60° C (140° F), Minimum	
	Shielded	Multi-conductor shielded cable such as Belden 8770 (or equiv.)		0.750 mm <sup>2</sup> (18 AWG), 3 conductor, shielded.
<b>EMC Compliance</b>	Refer to <a href="#">CE Conformity on page 1-34</a> for details.			

New Table via Wiring/  
Grounding

(1) If the wires are short and contained within a cabinet which has no sensitive circuits, the use of shielded wire may not be necessary, but is always recommended.



### Wiring the Main Control Board I/O Terminals

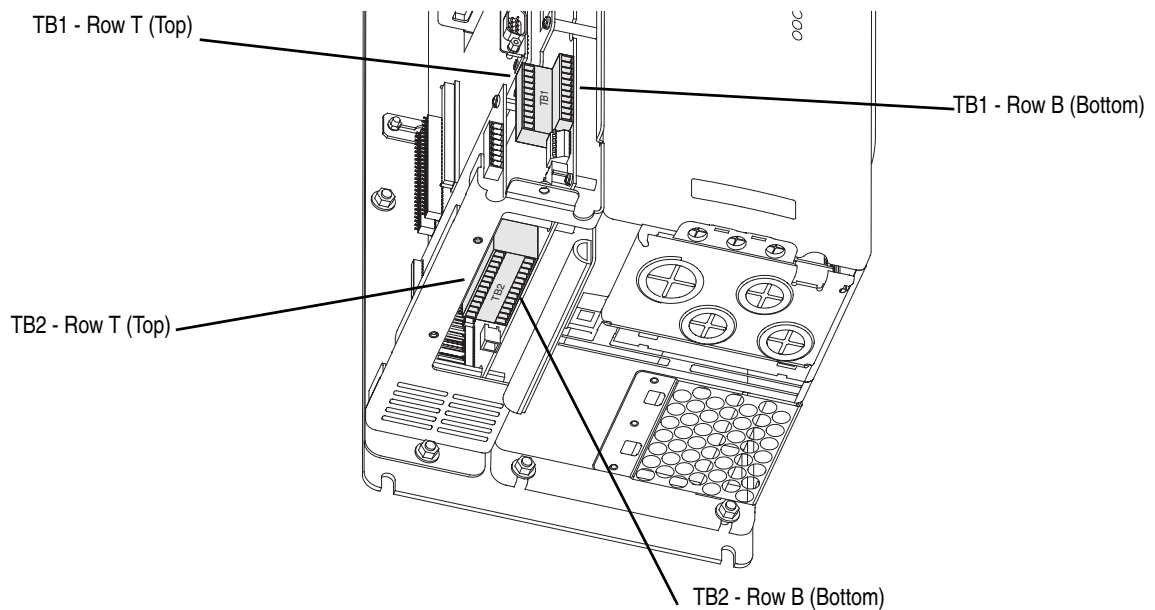
Terminal blocks TB1 and TB2 contain connection points for all inputs, outputs and standard encoder connections. Both terminal blocks reside on the Main Control Board.

Remove the terminal block plug from the socket, and make connections.

► **TIP:** Remember to route wires through the sliding access panel at the bottom Control Assembly.

Reinstall the plug, when wiring is complete. The terminal blocks have keys, which make it difficult to insert a terminal plug into the wrong socket.

**Table 1.I Main Control Board I/O Terminal Locations**



**Table 1.J Main Control Board I/O Terminal Block Specifications**

Name	Frame	Description	Wires Size Range <sup>(1)</sup>		Torque	
			Maximum	Minimum	Maximum	Recommended
I/O & Encoder Blocks	1-6	Signal & Encoder power connections	1.5 mm <sup>2</sup> (16 AWG)	.14 mm <sup>2</sup> (28 AWG)	.25 N-m (2.2 lb.-in.)	.22 N-m (1.9 lb.-in.)

<sup>(1)</sup> Maximum/minimum sizes the terminal block will accepts - these are not recommendations.

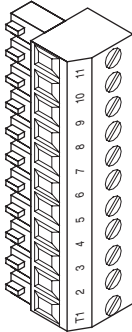
### Auxiliary Power Supply

You may use an auxiliary power supply to keep the 700S Control Assembly energized when output power is de-energized. This allows the Main Control Board, DriveLogix controller and any feedback option cards to continue operation. Connect auxiliary power to terminal block. See [Table 1.E on page 1-11](#). You must set Par 153 [Control Options]/bit 7 [Aux Pwr Sply] to enable this feature.

### Hard Enable Circuitry

A dedicated hardware enable input is provided for applications that require the drive to be disabled without software interpretation.

**Table 1.K TB1 - Row T (Top) Terminals**



Terminal	Signal	Description	Related Parameter
T11	Power Supply 24V DC Return (-)	Power and common for pre charge and enable inputs. <sup>(1)</sup> Inputs may sink or source. <sup>(2)</sup> Rating: 100 mA maximum.	
T10	Power Supply 24V DC (+)		
T9	Logic Common		
T8	Digital Input #1  Default = Precharge	For common DC bus drives. Must be high, for drive to complete the pre charge cycle. Load: 20 mA at 24V DC.	824, 826, 827, 828, 829, 838
T7	Enable Input	Must be high for drive to run. Load: 20 mA at 24V DC.	824, 825
T6	Digital Output #1	24V DC open collector (sinking logic) output. Rating: 25 mA maximum.	824, 843, 844
T5	Digital Output #2	24V DC open collector (sinking logic) output. Rating: 25 mA maximum.	824, 845, 846
T4	Digital Output Return	Return for Digital outputs 1 and 2.	
T3	Thermistor Input	Used only in FOC2 mode with approved motor for temperature adaptation. Refer to Appendix A, Specifications for approved motors.	485
T2	Thermistor Input Return		
T1	Thermistor Shield		

<sup>(1)</sup> The drive's 24V DC power supply supports only on-board digital inputs. Do not use it to power circuits outside of the drive.

<sup>(2)</sup> Refer to wiring examples of sinking and sourcing outputs.

**Table 1.L TB1 - Row T (Top) Wiring Examples**

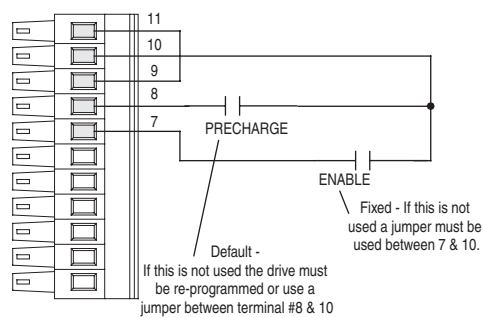
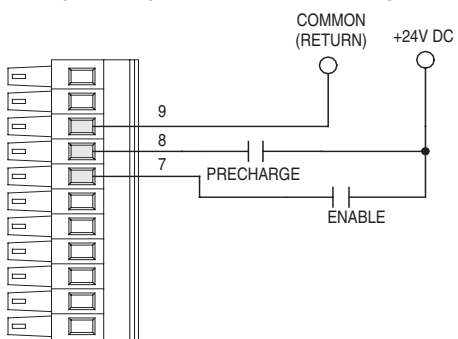
The following definitions are used throughout this section:

**Source**

- A. Apply positive voltage through the device to the input or output.
- B. Connect the input or output common (return) directly to the power supply common.

**Sinking**

- A. Apply the positive voltage directly to the input or output common (return).
- B. Connect the input or output to the power supply common through the device

Input/Output	Connection Example	Required Parameter Changes
<p>Digital Inputs used for enable and precharge control.</p> <p><i>Note:</i>  <b>24V DC Supply</b> - supports only on-board digital inputs. Do not use for circuits outside the drive.</p>	<p>Sourcing Precharge and Enable Inputs - using internal power supply</p>  <p>Sourcing Precharge and Enable Inputs - using external power</p> 	<p><b>Enable</b> - In sourcing configuration, this circuit must connect to 24V DC power for drive to run.</p> <p><b>Precharge</b>  Precharge control is used in common bus configurations and is not required for AC fed drives.</p> <p>If precharge control is not required, reprogram <i>Par 838 [DigIn 1 Sel]</i> to a value of zero or replace the contact shown with a jumper from Terminal 8 to Terminal 10.</p> <p>If precharge is needed, in sourcing configuration, this circuit must connect to 24V DC power for drive to complete the precharge cycle.</p>

**Table 1.L TB1 - Row T (Top) Wiring Examples**

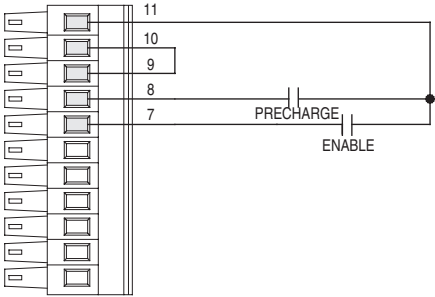
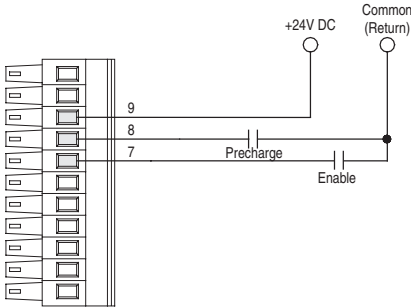
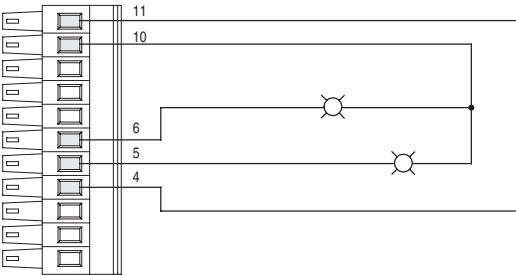
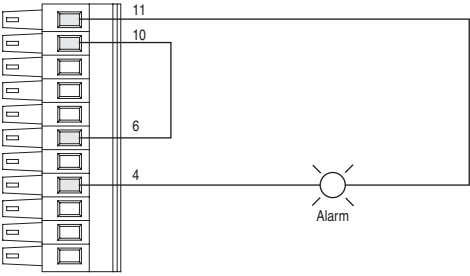
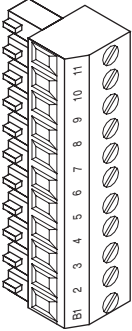
Input/Output	Connection Example	Required Parameter Changes
	<p>Sinking Precharge and Enable Inputs - using internal power supply</p>  <p>Sinking Precharge and Enable Inputs - using external power supply</p> 	<p><b>Enable</b> - In sinking configuration, this circuit must connect to 24V DC return for drive to run.</p> <p><b>Precharge</b> Precharge control is used in common bus configurations and is not required for AC fed drives.</p> <p>If precharge control is not required, reprogram <i>Par 838</i> [DigIn 1 Sel] to a value of zero or replace the contact shown with a jumper from Terminal 8 to Terminal 11.</p> <p>If precharge is needed, in sinking configuration, this circuit must connect to 24V DC return for drive to complete the precharge cycle.</p>
<p><b>Digital Outputs</b> - 24V DC outputs 25 mA maximum per output</p>	<p>Digital Output 1 Indicating Alarm and Digital Output 2 Indicating Fault - in sourcing configuration</p> 	<ul style="list-style-type: none"> <li>• Link Parameter 155 [Logic Status], the source, to Parameter 843 [DigOut 1 Data], the sink</li> <li>• Set Parameter 844 [DigOut 1 Bit] to a value of eight, so that parameter 155 [Logic Status] / bit 8 "Alarm" will control the output</li> <li>• Link Parameter 155 [Logic Status], the source, to Parameter 845 [DigOut 2 Data], the sink</li> <li>• Set Parameter 846 [DigOut 2 Bit] to a value of seven, so that Parameter 155 [Logic Status] / bit 7 [Faulted] will control the output</li> </ul>
<p><b>Digital Output</b> - 24V DC output 25 mA maximum per output.</p> <p>If one (1) output is configured in sinking, the other output is not available.</p>	<p>Digital Output 1 Indicating Alarm Fault - in sinking configuration</p> 	<ul style="list-style-type: none"> <li>• Link Parameter 155 [Logic Status], the source, to Parameter 843 [DigOut 1 Data], the sink</li> <li>• Set Parameter 844 [DigOut 1 Bit] to a value of 8, so that Parameter 155 [Logic Status] / bit 8 "Alarm" will control the output</li> </ul>

Table 1.M TB1 - Row B (Bottom) Terminals



Terminal	Signal	Description	Related Parameter
B11	Analog Input #1 (-)	+/-10.0V DC or +/-1.0V DC bipolar, differential input. <sup>(1)</sup> 13 bit + sign, 20k ohm input impedance	800, 802, 803, 804, 805
B10	Analog Input #1 (+)		
B9	Analog Input Shield	Optional connection point for analog input shield. <sup>(2)</sup>	
B8	Analog Input #2 (-)	+/-10.0V DC or +/-1.0V DC bipolar, differential input. <sup>(1)</sup> 13 bit + sign, 20k ohm input impedance	806, 808, 809, 810, 811
B7	Analog Input #2 (+)		
B6	Analog Output #1 (+)	+/-10.0V DCDC bipolar, differential output, 11 bit + sign, 2k ohm minimum load	812, 814, 815, 817, 818
B5	Analog Output #1 Return (-)		
B4	Analog Output Shield	Optional connection point for analog output shield. <sup>(2)</sup>	
B3	Analog Output #2 (+)	+/-10.0V DC bipolar, differential output, 11 bit + sign, 2k ohm minimum load	813, 819, 820, 822, 823,
B2	Analog Output #2 Return (-)		
B1	Analog Output Shield	Optional connection point for analog shields.	

<sup>(1)</sup> Refer to [Analog Input Settings on page 1-31](#) for necessary dip switch settings.

<sup>(2)</sup> Analog shields should connect to common at the signal source, if possible. Shields for signals from ungrounded devices, such as analog tachometers, should connect to an analog shield terminal point at the drive.

**Table 1.N TB1 - Row B (Bottom) Wiring Examples**

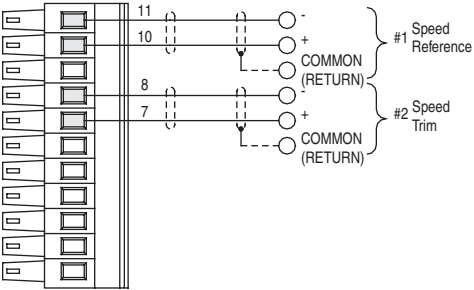
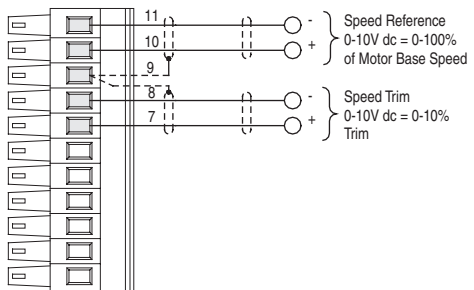
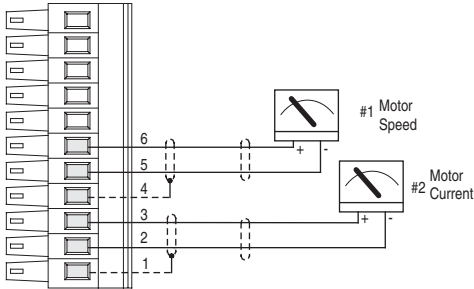
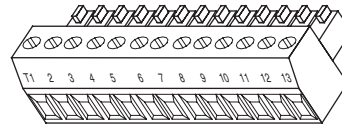
Input/Output	Connection Example	Required Parameter Changes
<p><b>Analog Inputs</b>                      +/-10V DC or +/-1.0V DC                      (DIP switch selectable)                      Terminate shields at the analog source if analog common is available</p> <p>Used for Speed Reference and Speed Trim</p>	<p>Analog Inputs for Speed Reference and Speed Trim - shield terminated at source</p> 	<p><b>Using Analog In1 as 0-10V speed reference</b></p> <ul style="list-style-type: none"> <li>Adjust Parameter 803 [Anlg In1 Offset] so that the minimum analog signal creates the minimum speed reference (if the minimum input is 0V DC and the minimum speed reference is zero, enter a value of zero)</li> <li>Adjust the Parameter 802 [Anlg In1 Offset] so that the maximum analog signal creates the maximum speed reference (if the maximum input is 10V DC and the maximum speed reference is motor base speed, enter a value of 0.1)</li> <li>Send the data to the Speed Reference parameter  <i>Par 10</i> [Speed Ref1] (the destination) linked to <i>Par 800</i> [Anlg In1 Data] (the source)</li> <li>Select Ref 1 as the active speed ref <i>Par 16</i> [Speed Ref Sel] = 1</li> <li><i>Par 153</i> [Control Option]/bit 0 = 0 Unipolar Speed Reference</li> </ul>
<p><b>Analog Outputs</b>                      +/-10V DC or +/-1.0V DC</p> <p>Used to drive analog meters displaying speed and current</p>	<p>Analog Inputs for Speed Reference and Speed Trim - shield terminated at drive</p> 	<p><b>Using Analog In2 as -10 to +10V speed trim @ 10%:</b></p> <ul style="list-style-type: none"> <li>Adjust Parameter 809 [Anlg In2 Offset] so that the minimum analog signal creates the minimum speed trim (if the minimum input is 0V DC and the minimum trim is zero, enter a value of zero)</li> <li>Adjust Parameter 808 [Anlg In2 Offset] so that the maximum analog signal creates the maximum speed trim (if the maximum input is 10V DC and the maximum speed trim is 10%, enter a value of 0.01)</li> <li>Send the data to the speed Reference parameter  <i>Par 13</i> [Speed Ref2] (the destination) linked to <i>Par 806</i> [Anlg In2 Data] (the source)</li> <li>Select Ref 1 as the active speed ref and Ref2 as trim [Speed Ref Sel] = 3</li> </ul>
<p><b>Analog Outputs</b>                      +/-10V DC</p>	<p>Analog Outputs Indicating Motor Speed and Motor Current</p> 	<p><b>Using Analog Out 1, -10V to +10V to meter Motor RPM and direction:</b></p> <ul style="list-style-type: none"> <li>Adjust Parameter 812 [Anlg Out1 Offset] so that minimum speed creates a minimum signal (if the minimum speed is zero and the minimum signal is zero, enter a zero)</li> <li>Adjust Parameter 817 [Anlg Out1 Scale] so that the maximum speed creates a maximum signal (if the maximum speed is 100% of motor base speed and the maximum signal is 10V DC, enter a value of 0.1)</li> <li>Send the data to the Analog Output  <i>Par 815</i> [Anlg Out1 Real] (the destination) linked to <i>Par 300</i> [Motor Spd Fdbk] (the source)</li> </ul> <p><b>Using Analog Out 2, -10V to +10V to meter Motor Current</b></p> <ul style="list-style-type: none"> <li>Adjust Parameter 813 [Anlg Out2 Offset] so that minimum current creates a minimum signal (if the minimum current is zero and the minimum signal is zero, enter a zero)</li> <li>Adjust Parameter 822 [Anlg Out2 Scale] so that the maximum current creates a maximum signal (if the maximum current is 200% of motor NP FLA and the maximum signal is 10V DC, enter a value of 2.0)</li> <li>Send the data to the Analog Output  <i>Par 820</i> [Anlg Out2 Real] (the destination) linked to <i>Par 308</i> [Output Current] (the source)</li> <li>Scale the Output to the source parameter  <i>Par 822</i> [Anlg Out2 Scale] = xx (<i>Par 2</i> [Motor NP FLA]/10V Output</li> </ul>

Table 1.O TB2 - Row T (Top) Terminals



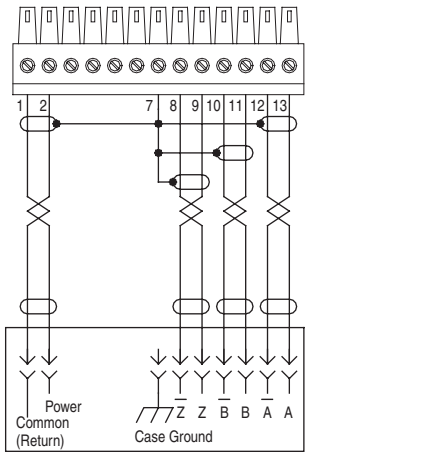
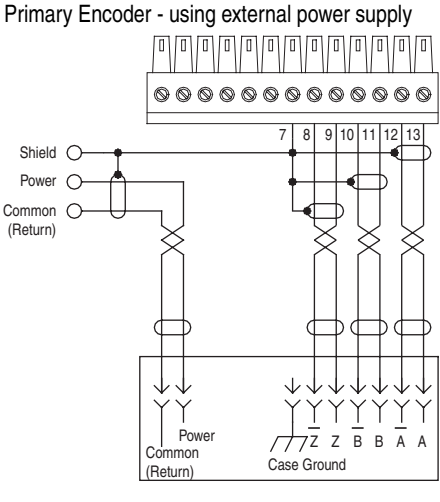
Terminal	Signal	Description	Related Parameter
T13	Encoder Signal A	Primary encoder interface. 5 or 12V DC switch selectable <sup>(1)</sup> , Nominal current draw per channel @ 12V DC 45 mA, @5V DC 32 mA Maximum input frequency for Encoders 0 & 1 is 500 kHz.	222, 230, 231, 232, 233, 234, 235, 236, 237, 238
T12	Encoder Signal Not A		
T11	Encoder Signal B		
T10	Encoder Signal Not B		
T9	Encoder Signal Z		
T8	Encoder Signal Not Z		
T7	Shield	Connection point for encoder shield.	
T6	Digital Input #2	High speed 12-24V DC sinking digital input.	824, 830, 831, 832, 833, 839
T5	Digital Input #2 Return		
T4	Digital Input #3	High speed 12-24V DC sinking digital input.	824, 834, 835, 836, 837, 840
T3	Digital Input #3 Return		
T2	Power Supply +12V DC (A) (+)	5/12V DC power supply for primary encoder interface and high speed inputs. Rating 300 mA <sup>(2)</sup> <sup>(3)</sup>	
T1	Power Supply +12V DC Return (A) (-)		

<sup>(1)</sup> Refer to [Encoder Input Settings on page 1-31](#) for necessary dip switch settings.

<sup>(2)</sup> This power supply supports only the primary encoder interface and digital inputs. Do not use it to power circuits outside of the drive.

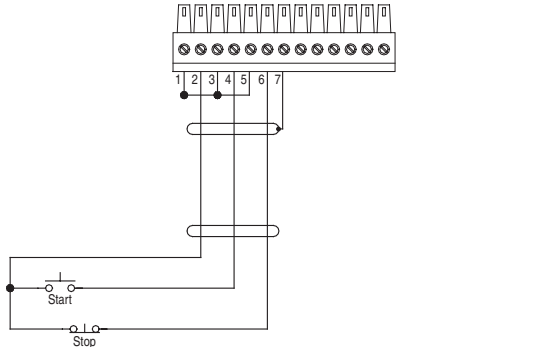
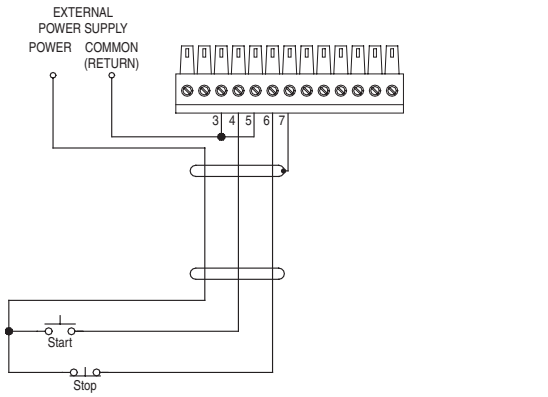
<sup>(3)</sup> To enable 5V supply, set Jumper J6 (located in the Main Control Board) to positions T2 and T3. Default 12V supply is set to T1 and T2.

**Table 1.P TB2 - Row T (Top) Wiring Examples**

Input/Output	Connection Examples	Required Parameter Changes
<p><b>Primary Encoder Interface -</b> Supports 12V DC differential encoders with internal power supply.</p> <p>5V DC differential encoders may require external power supply and special jumper settings. Refer to <a href="#">Main Control Board I/O Configuration Settings on page 1-31</a> for external power supply and jumper settings.</p> <p>For 5V DC differential encoders with internal power supply, set Jumper J6 to positions T2 and T3.</p>	<p><b>Primary Encoder - using internal power supply</b></p>  <p><b>Primary Encoder - using external power supply</b></p> 	<ul style="list-style-type: none"> <li>• Set the value of Parameter 222 [Motor Fdbk Sel] to a value of 0 - Encoder 0, so the drive will use this encoder as the primary motor speed feedback device.</li> <li>• Set the value of Parameter 232 [Encoder0 PPR] to match the encoder's resolution.</li> </ul>



**Table 1.P TB2 - Row T (Top) Wiring Examples**

Input/Output	Connection Examples — 3-Wire Control	Required Parameter Changes
<p><b>High Speed Inputs</b> 12 or 24V DC</p>	<p>Sourcing High Speed Inputs, Used for 3 Wire Control - using the internal power supply</p> 	<ul style="list-style-type: none"> <li>• Set the value of Parameter 839 [DigIn 2 Sel] to a value of 1 - Normal Stop</li> <li>• Set the value of Parameter 840 [DigIn 3 Sel] to a value of 2 - Start</li> <li>• Set Parameter 153 [Control Options] / bit 8 "3WireControl"</li> </ul>
	<p>Sourcing High Speed Inputs, Used for 3 Wire Control - using an external power supply</p> 	<p><b>Note:</b> +12V and +24V are also available from TB1 Top 10 &amp; 11.</p>

**Table 1.P TB2 - Row T (Top) Wiring Examples**

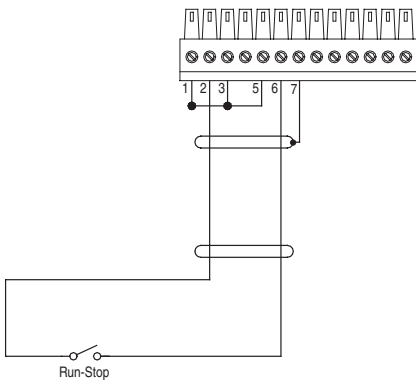
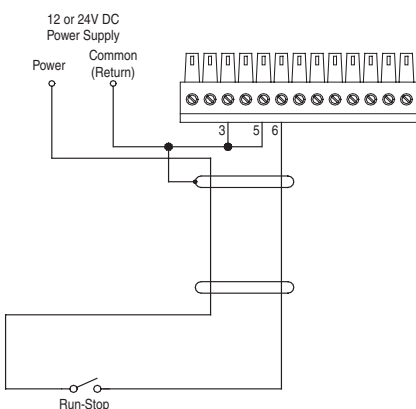
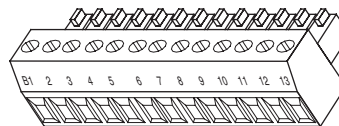
Input/Output	Connection Examples — 2-Wire Control	Required Parameter Changes
<p><b>High Speed Inputs</b> 12 or 24V DC</p>	<p>Sourcing High Speed Inputs, Used for 2 Wire Control - using the internal power supply</p> 	<ul style="list-style-type: none"> <li>• Set the value of Parameter 839 [DigIn 2 Sel] to a value of 3 - Run</li> <li>• Set Parameter 153 [Control Options] / bit 9 "2W Coast Stop" to make the drive coast stop when input 2 goes low</li> <li>• Reset Parameter 153 [Control Options] / bit 9 "2W Coast Stop" to make the drive ramp stop when input 2 goes low</li> <li>• Reset Parameter 153 [Control Opt]/bit 8 "3Wire Control" for two wire control</li> </ul>
	<p>Sourcing High Speed Inputs, Used for 2 Wire Control - using an external power supply</p> 	<p><b>Note:</b> +12V and +24V are also available from TB1 Top 10 &amp; 11.</p>

Table 1.Q TB2 - Row B (Bottom) Terminals



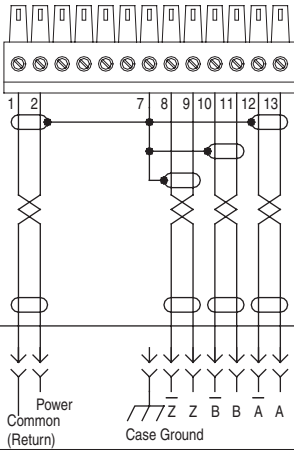
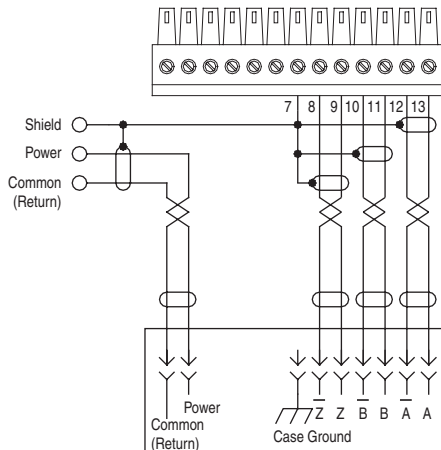
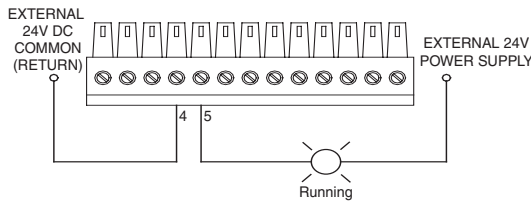
Terminal	Signal	Description	Related Parameter
B13	Encoder Signal A	Secondary encoder interface. 5 or 12V DC switch selectable <sup>(1)</sup> , Nominal current draw per channel @ 12V DC 45 mA, @5V DC 32 mA Maximum input frequency for Encoders 0 & 1 is 500 kHz.	222, 240, 241, 242, 243, 244, 245, 246, 247, 248
B12	Encoder Signal Not A		
B11	Encoder Signal B		
B10	Encoder Signal Not B		
B9	Encoder Signal Z		
B8	Encoder Signal Not Z		
B7	Shield	Connection point for encoder shield.	
B6	Unused		
B5	Relay Output	Relay contact output. Rating: 5A @ 24V DC Resistive, 2A 24V DC Inductive	824, 841, 842
B4	Relay Output Return		
B3	Unused		
B2	Power Supply +12V DC (B) (+)	15/2V DC power supply for secondary encoder interface. Rating 300 mA <sup>(2)</sup> <sup>(3)</sup>	
B1	Power Supply +12V DC Return (B) (-)		

<sup>(1)</sup> Refer to [Encoder Input Settings on page 1-31](#) for necessary dip switch settings.

<sup>(2)</sup> This power supply supports only the secondary encoder interface. Do not use it to power circuits outside of the drive

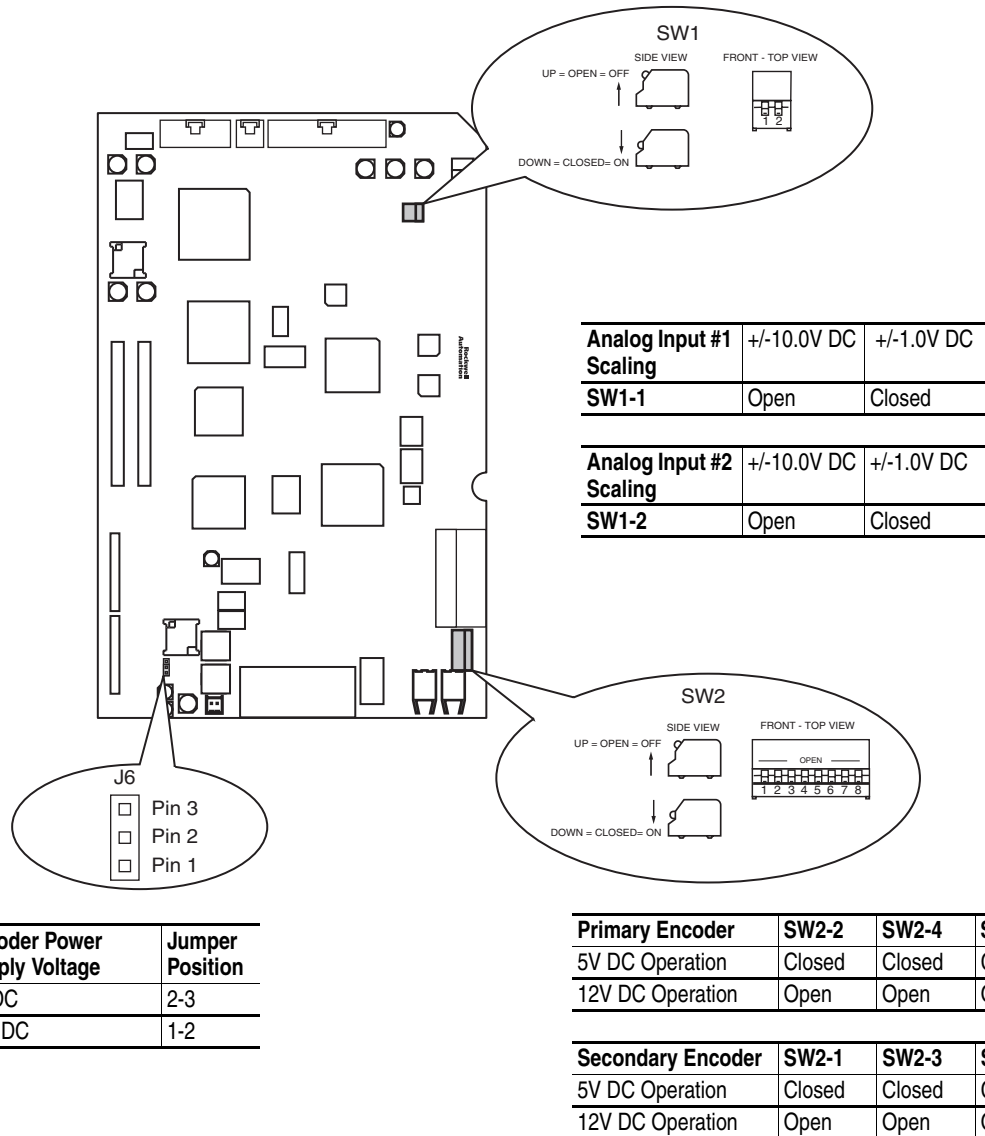
<sup>(3)</sup> To enable 5V supply, set Jumper J6 (located in the Main Control Board) to positions T2 and T3. Default 12V supply is set to T1 and T2.

Table 1.R TB2 - Row B (Bottom) Wiring Examples

Input/Output	Connection Example	Required Parameter Changes
<p><b>Secondary Encoder Interface</b> - Supports 12V DC differential encoders with internal power supply.</p> <p>5V DC differential encoders require external power supply and special jumper settings. Refer to <a href="#">Main Control Board I/O Configuration Settings on page 1-31</a> for external power supply and jumper settings.</p> <p>For 5V DC differential encoders with internal power supply, set Jumper J6 to positions T2 and T3.</p>	<p><b>Secondary Encoder - using internal power supply</b></p> 	<ul style="list-style-type: none"> <li>• Set the value of Parameter 222 [Motor Fdbk Sel] to a value of 1 - Encoder 1, so the drive will use this encoder as the primary motor speed feedback device</li> <li>• Set the value of Parameter 242 [Encoder1 PPR] to match the encoder's resolution</li> </ul>
	<p><b>Secondary Encoder - using external power supply</b></p> 	
<p><b>Auxiliary Output - Relay contact output</b></p>	<p><b>Auxiliary Output, Used to Indicate Running</b></p> 	<ul style="list-style-type: none"> <li>• Link Parameter 155 [Logic Status], the source, to Parameter 841 [Relay Out Data], the sink</li> <li>• Set Parameter 842 [Relay Out Bit] to a value of one, so that Parameter 155 [Logic Status] / bit 1 "Running" will control the output.</li> </ul>

## Main Control Board I/O Configuration Settings

Figure 19 Main Control Board Dip Switches



### Analog Input Settings

Switch SW1-1 configures the scaling of Analog Input #1. Switch SW1-2 configures the scaling of Analog Input #2. Open the switch for +/-10.0V DC operation. Close the switch for +/-1.0V DC operation.

### Encoder Input Settings

Dip switch SW2 on the main control board configures the encoder inputs for 5V DC or 12V DC operation. Switches SW2-2, 4, and 6 are for the primary encoder. Set these switches to match the encoder output specifications. Open these switches for 12V DC operation, close them for 5V DC operation.

Switches SW2-1, 3, and 5 are for the secondary encoder. Set these switches to match the encoder output specifications. Open these switches for 12V DC operation, close them for 5V DC operation.

## Connecting SynchLink

SynchLink provides high-speed synchronization and communication between multiple PowerFlex 700S drives (or other products with SynchLink capability).

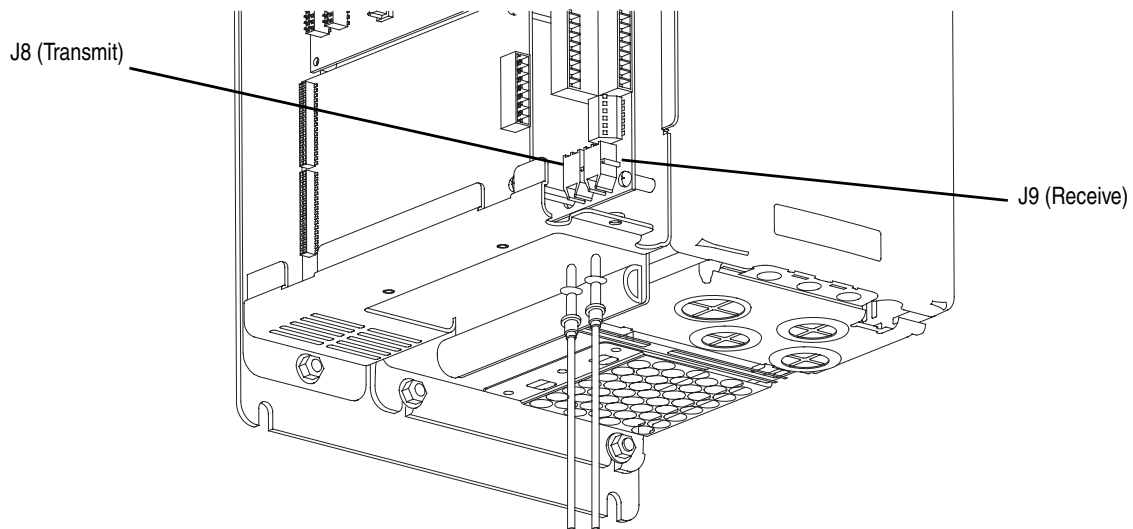
Refer to *The SynchLink Design Guide*, publication # 1756-TD008 when planning and connecting the SynchLink network.

### Class 1 LED Product



**ATTENTION:** Hazard of permanent eye damage exists when using optical transmission equipment. This product emits intense light and invisible radiation. Do not look into module ports or fiber optic cable connectors.

Figure 1.1 SynchLink Connections



Connect cables to J9 (receive) and J8 (transmit) connectors on the bottom of the Main Control Board. Push the plug into the socket until it produces an audible click.

**Important:** Do not overtighten tie-wraps.

**Table 1.T SynchLink Cables and Accessories**

Description	Cat. No.
2 x 25 cm Fiber Optic Link	1403-CF000
2 x 1 M Fiber Optic Link	1403-CF001
2 x 3 M Fiber Optic Link	1403-CF003
2 x 5 M Fiber Optic Link	1403-CF005
10 M Fiber Optic Link	1403-CF010
20 M Fiber Optic Link	1403-CF020
50 M Fiber Optic Link	1403-CF050
100 M Fiber Optic Link	1403-CF100
250 M Fiber Optic Link	1403-CF250
500 M Fiber Optic Bulk	1403-CFBLK
SynchLink Fiber-Hub, 1 input, Base	1751-SLBA
SynchLink Fiber-Hub, 4 output, "Star" Splitter	1751-SL4SP
SynchLink Bypass Switch	1751-SLBP/A

**Table 1.U Fiber Optic Cable Assembly**

Specification	
Connecting Cables	200/230 micron HCS (Hard Clad Silica) <ul style="list-style-type: none"> <li>• Versalink V-System</li> <li>• Lucent Technologies,</li> <li>• Specialty Fibers Technology Division</li> </ul>
Maximum Cable Length	300 meters with no more than one splice or one adapter
Minimum Cable Length	1 meter
Minimum inside bend radius	25.4mm (1 in.) Any bends with a shorter inside radius can permanently damage the fiber optic cable. Signal attenuation increases with decreased inside bend radius.
Operating Wavelength	650 nm (Red)
Data Rate	5 Mbps
Maximum Node Count	<ul style="list-style-type: none"> <li>• 10 - Daisy Chain</li> <li>• 256 - Star Configuration</li> </ul>

## CE Conformity

Conformity with the Low Voltage (LV) Directive and Electromagnetic Compatibility (EMC) Directive has been demonstrated using harmonized European Norm (EN) standards published in the Official Journal of the European Communities. PowerFlex Drives comply with the EN standards listed below when installed according to the User and Reference Manual.

Declarations of Conformity are available online at:  
**<http://www.ab.com/certification/ce/docs>**.

### Low Voltage Directive (73/23/EEC)

- EN50178 Electronic equipment for use in power installations.

### EMC Directive (89/336/EEC)

- EN61800-3 Adjustable speed electrical power drive systems Part 3: EMC product standard including specific test methods.

### General Notes

- If the adhesive label is removed from the top of the drive, the drive must be installed in an enclosure with side openings less than 12.5 mm (0.5 in.) and top openings less than 1.0 mm (0.04 in.) to maintain compliance with the LV Directive.
- The motor cable should be kept as short as possible in order to avoid electromagnetic emission as well as capacitive currents.
- Use of line filters in ungrounded systems is not recommended.
- PowerFlex drives may cause radio frequency interference if used in a residential or domestic environment. The user is required to take measures to prevent interference, in addition to the essential requirements for CE compliance listed below, if necessary.
- Conformity of the drive with CE EMC requirements does not guarantee an entire machine or installation complies with CE EMC requirements. Many factors can influence total machine/installation compliance.
- PowerFlex drives can generate conducted low frequency disturbances (harmonic emissions) on the AC supply system. More information regarding harmonic emissions can be found in the *PowerFlex Reference Manual Vol. 2*.



## Essential Requirements for CE Compliance

Conditions 1-6 listed below must be satisfied for PowerFlex drives to meet the requirements of EN61800-3.

3. Standard PowerFlex 700S CE compatible Drive.
4. Review important precautions/attentions statements throughout this document before installing drive.
5. Grounding as described on [page 1-4](#).
6. Output power, control (I/O) and signal wiring must be braided, shield cable with a coverage of 75% or better, metal conduit or equivalent attenuation.
7. All shielded cables should terminate with proper shielded connector.
8. Conditions in [Table 1.V on page 35](#)

**Table 1.V PowerFlex 700S EN61800-3 EMC Compatibility**

Frame	Second Environment <i>Restrict Motor Cable to 30 m (98 ft.)</i>	First Environment Restricted Distribution
	<i>Any Drive and Option</i>	
1	✓	<i>Refer to PowerFlex Reference Manual Vol. 2</i>
2	✓	
3	✓	
4	✓	
5	✓	
6	✓	



## Start-Up

This chapter describes how you start-up the PowerFlex 700S Drive. Refer to [Appendix D](#) for a brief description of the HIM (Human Interface Module).

For Information on ...	See Page...
<a href="#">Prepare for Drive Start-Up</a>	<a href="#">2-1</a>
<a href="#">Status Indicators</a>	<a href="#">2-3</a>
<a href="#">Assisted Start-Up</a>	<a href="#">2-3</a>



**ATTENTION:** Power must be applied to the drive to perform the following start-up procedure. Some of the voltages present are at incoming line potential. To avoid electric shock hazard or damage to equipment, only qualified service personnel should perform the following procedure. Thoroughly read and understand the procedure before beginning. If an event does not occur while performing this procedure, **Do Not Proceed**. **Remove Power** including user supplied control voltages. User supplied voltages may exist even when main AC power is not applied to then drive. Correct the malfunction before continuing.

### Prepare for Drive Start-Up

#### Before Applying Power to the Drive

**Important:** If you have a DriveLogix application, you must first connect the battery before starting this section.

- 1. Confirm that motor wires are connected to the correct terminals and are secure. Confirm Frame 5 transformer connections (refer to [page 1-9](#)).
- 2. Confirm that encoder wires are connected to the correct terminals and are secure.
- 3. Confirm that all control inputs are connected to the correct terminals and are secure.
- 4. Verify that AC line power at the disconnect device is within the rated value of the drive.
- 5. Verify that control power voltage is correct.

The remainder of this procedure requires that a HIM be installed. If an operator interface is not available, remote devices should be used to start-up the drive.

### Applying Power to the Drive

- ❑ 6. Apply AC power and control voltages to the drive. Examine the *Power (PWR)* LED.

#### Steady Green

Power has been applied to the drive and no faults are present.

- ❑ 7. Examine the *Status (STS)* LED. Verify that it is flashing green. If it is not in this state, check the following possible causes and take the necessary corrective action.

#### Flashing Yellow

A run inhibit exists in the drive. Refer to [Chapter 4](#) to correct the problem.

#### Flashing Red

A fault has occurred. Refer to [on page 4-4](#) for drive faults and actions to correct the problem.

If any digital input is configured to Stop – CF (CF = Clear Fault) or Enable, verify that signals are present or the drive will not start. Refer to [Chapter 4](#) for a list of potential digital input conflicts.

If a fault code appears, refer to [Chapter 4](#).

If the STS LED is not flashing green at this point, refer to the Status Indicators descriptions in [Table 2.A on page 2-3](#).

- ❑ 8. Proceed to Start-Up Routine.

Status Indicators

Figure 2.1 Drive Status Indicators

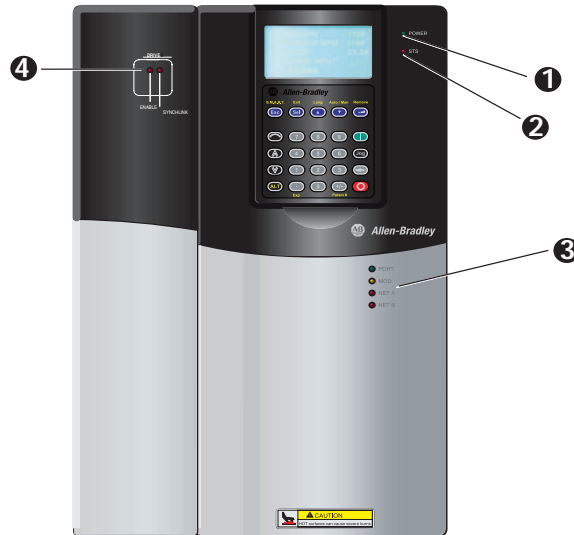


Table 2.A Drive Status Indicator Descriptions


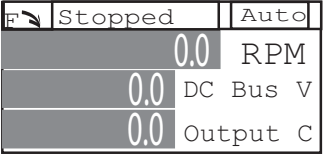
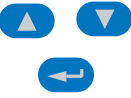
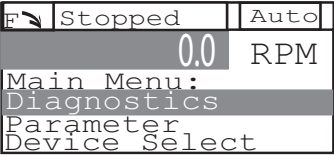

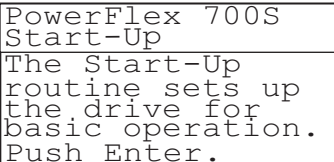
#	Name	Color	State	Description		
DRIVE	Power Structure	1	PWR (Power)	Green	Steady	Illuminates when power is applied to the drive.
		2	STS (Status)	Green	Flashing	Drive ready, but not running & no faults are present.
				Green	Steady	Drive running, no faults are present.
			Yellow	Flashing	A type 2 (non-configurable) alarm condition exists, drive continues to run.	
				Steady	A type 1 (user configurable) alarm condition exists, but drive continues to run.	
		Red	Flashing	A fault has occurred.		
	Steady		A non-resettable fault has occurred.			
	Control Assembly	Control	3	PORT	Refer to the <i>Communication Adapter User Manual</i>	Status of DPI port internal communications (if present).
				MOD		Status of communications module (when installed).
				NET A		Status of network (if connected).
NET B				Status of secondary network (if connected).		
Control Assembly	Control	4	SYNCHLINK	Green	Steady	<ul style="list-style-type: none"> <li>The module is configured as the time keeper or</li> <li>The module is configured as a follower and synchronization is complete.</li> </ul>
				Green	Flashing	The follower(s) are not configured with the time keeper.
				Red	Flashing	<ul style="list-style-type: none"> <li>The module is configured as a time master on SynchLink and has received time information from another time master on SynchLink.</li> </ul>
		ENABLE	Green	On	The drive's enable input is high.	
			Green	Off	The drive's enable input is low.	

Assisted Start-Up

This routine prompts you for information needed to start-up a drive for most applications, such as line and motor data, commonly adjusted parameters and I/O.

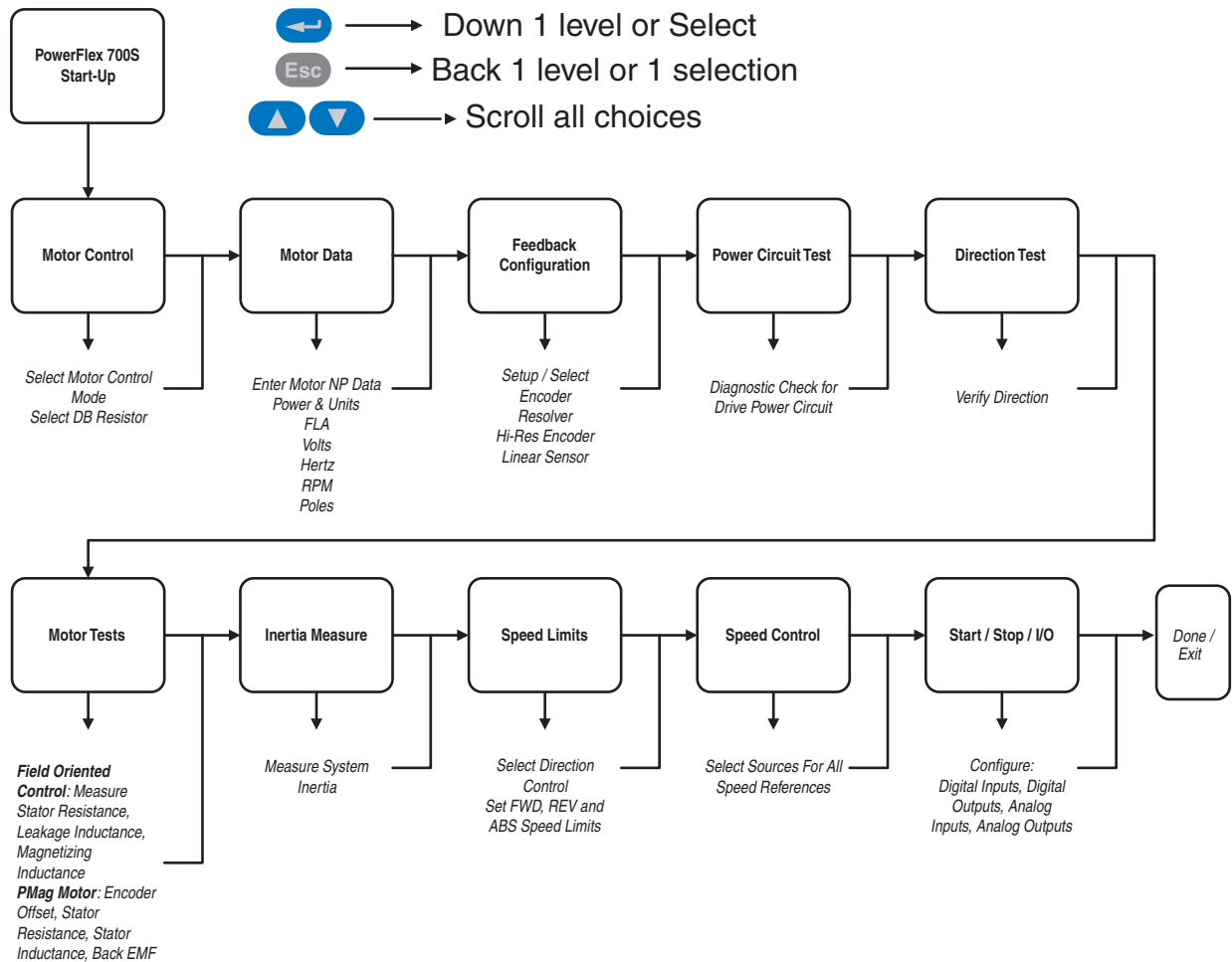
- ▶ **Important:** This start-up routine requires a HIM. If the drive is configured for 2-wire control, the HIM installed on the drive will also act as a 2-wire device. In 2-wire mode, the drive will start when the HIM “Start” is pressed and stop when the HIM “Start” is released. The recommended mode of use for the Start-Up Routine is 3-wire control, Parameter 153 [Control Options], Bit 8 set to “1”.

The assisted start-up routine asks simple yes or no questions and prompts you to input required information. Access Assisted Start-Up by selecting “Start-Up” from the Main Menu.

Step	Key(s)	Example LCD Displays
1. To exit the User Display screen, Press Esc.		
1. In the Main Menu, use the Down Arrow to scroll to “Start Up” 2. Press Enter. ▶ <b>TIP:</b> Throughout the Start-Up Routine many screens have more selection than shown. Use the arrow keys to scroll through all the menu options.		
1. Follow the instructions on the screen to complete the Start-Up.		

- ▶ **Important:** If using a HIM the following functions are not available.
  - Alt-Man
  - Alt-Lang
  - Alt-SMART

**Table 2.B Start-Up Menu**



**Note:** In 2-wire mode, the drive will start when the HIM “Start” is pressed and stop when the HIM “Start” is released. The recommended mode of use for the Start-Up Routine is 3-wire control, Parameter 153 [Control Options], Bit 8 set to “1”.





## Programming and Parameters

Chapter 3 provides a complete listing and description of the PowerFlex 700S parameters. The parameters can be programmed (viewed/edited) using a HIM (Human Interface Module). As an alternative, programming can also be performed using DriveTools 2000™ software and a personal computer.

For information on...	See page
<a href="#">About Parameters</a>	<a href="#">3-1</a>
<a href="#">How Parameters are Organized</a>	<a href="#">3-3</a>
<a href="#">Parameter Data in Linear List Format</a>	<a href="#">3-16</a>
<a href="#">Parameter Cross Reference By Name</a>	<a href="#">3-96</a>

### About Parameters

To configure a Drive module to operate in a specific way, drive parameters may have to be set. Three types of parameters exist:

- **ENUM Parameters**

These parameters allow a selection from 2 or more items

- **Bit Parameters**


These parameters have individual bits associated with features or conditions. If the bit is 0, the feature is off or the condition is false. If the bit is 1, the feature is on or the condition is true.

- **Numeric Parameters**

These parameters have a single numeric value (i.e. 0.1 Volts).

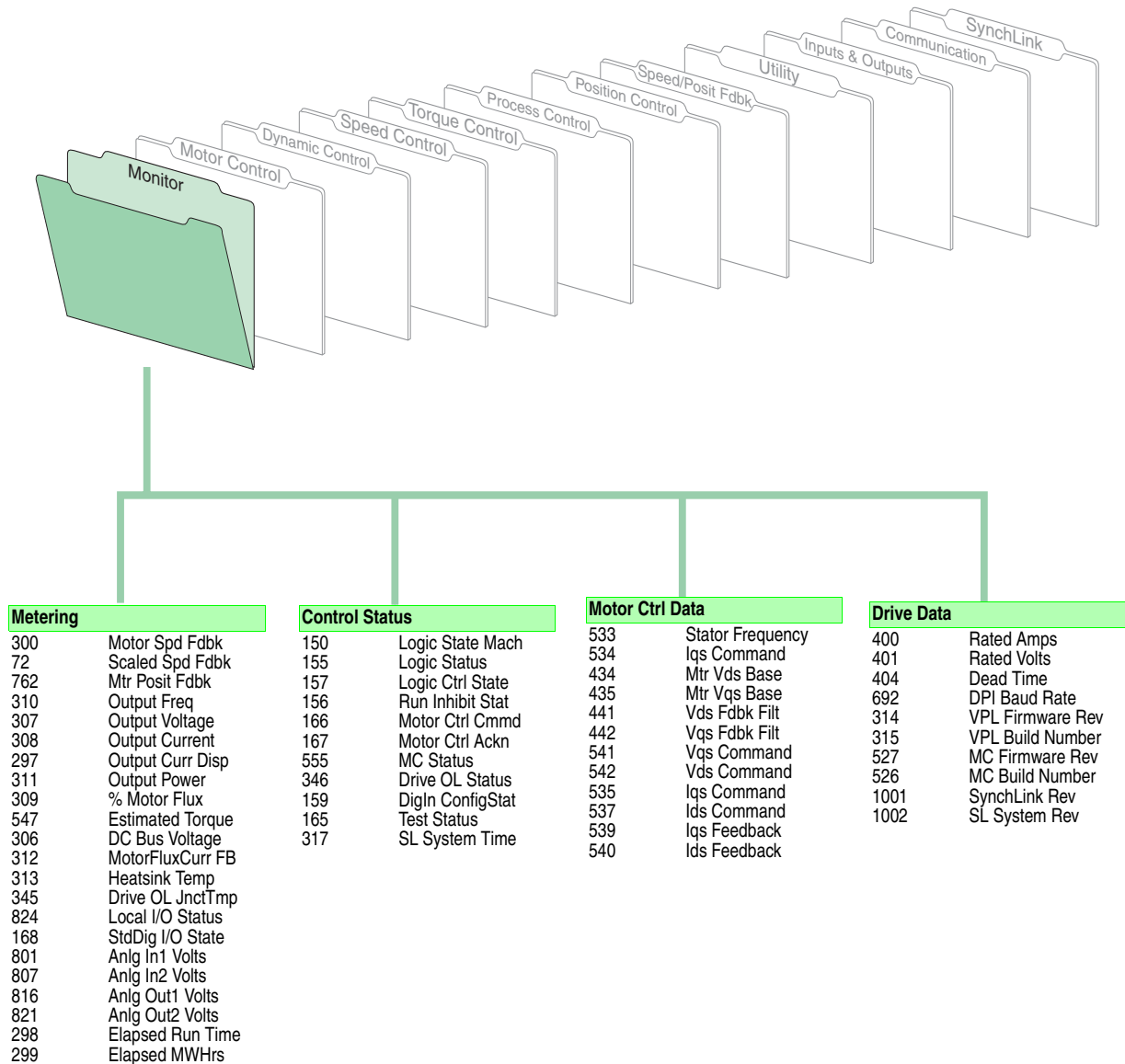
The example on the following page shows how each parameter type is presented in this manual.

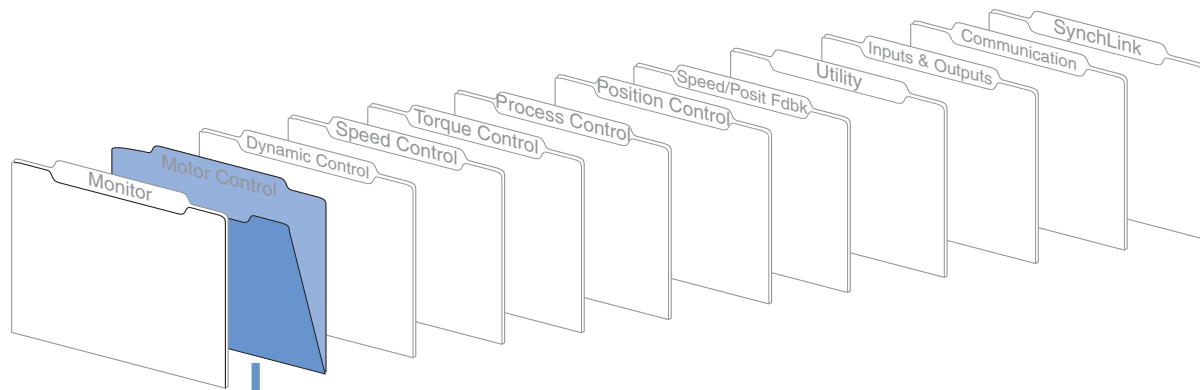
1	2	3																																																			
No.	Name Description	Values																																																			
151	<p><b>Logic Command</b> The controller-drive interface (as defined by the Controller Communication Format) sets bits to enable and disable various functions and algorithms. Bits that are changed here are reflected in Parameter 152 [Applied LogicCmd]. Note: Bits 4 through 9 in Logic Command are NOT recalled from Control EEPROM. They will be cleared upon drive powerup or following an EEPROM recall operation.</p> <p>Options</p> <table border="1" data-bbox="212 443 813 625"> <thead> <tr> <th></th> <th>Reserved</th> <th>Reserved</th> <th>PositionEnbl</th> <th>ProcsTrim En</th> <th>Fric Comp</th> <th>Inertia Comp</th> <th>Sys Inert En</th> <th>Mtr Inert En</th> <th>PM Offset En</th> <th>Dir Sel En</th> <th>Pwr Diag En</th> <th>MC Atune En</th> <th>Time Axis En</th> <th>TachLoss Rst</th> <th>Spd S Crv En</th> <th>SpdRamp Dsbl</th> </tr> </thead> <tbody> <tr> <td>Default</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> </tr> <tr> <td>Bit</td> <td>15</td> <td>14</td> <td>13</td> <td>12</td> <td>11</td> <td>10</td> <td>9</td> <td>8</td> <td>7</td> <td>6</td> <td>5</td> <td>4</td> <td>3</td> <td>2</td> <td>1</td> <td>0</td> </tr> </tbody> </table> <p>0 = True 1 = False</p>		Reserved	Reserved	PositionEnbl	ProcsTrim En	Fric Comp	Inertia Comp	Sys Inert En	Mtr Inert En	PM Offset En	Dir Sel En	Pwr Diag En	MC Atune En	Time Axis En	TachLoss Rst	Spd S Crv En	SpdRamp Dsbl	Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0	<p style="text-align: right;">Linkable Read-Write Data Type</p>
	Reserved	Reserved	PositionEnbl	ProcsTrim En	Fric Comp	Inertia Comp	Sys Inert En	Mtr Inert En	PM Offset En	Dir Sel En	Pwr Diag En	MC Atune En	Time Axis En	TachLoss Rst	Spd S Crv En	SpdRamp Dsbl																																					
Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0																																					
Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0																																					
110	<p><b>Spd/Torq ModeSel</b> Selects the source for the drive torque reference.</p>	<p>Default: 1 "Speed Reg"</p> <p>Options:</p> <table border="0"> <tr> <td>0</td> <td>"Zero Torque"</td> <td>4</td> <td>"Max Spd/Torq"</td> </tr> <tr> <td>1</td> <td>"Speed Reg"</td> <td>5</td> <td>"Sum Spd/Torq"</td> </tr> <tr> <td>2</td> <td>"Torque Ref"</td> <td>6</td> <td>"AbsMn Spd/Tq"</td> </tr> <tr> <td>3</td> <td>"Min Spd/Torq"</td> <td></td> <td></td> </tr> </table>	0	"Zero Torque"	4	"Max Spd/Torq"	1	"Speed Reg"	5	"Sum Spd/Torq"	2	"Torque Ref"	6	"AbsMn Spd/Tq"	3	"Min Spd/Torq"																																					
0	"Zero Torque"	4	"Max Spd/Torq"																																																		
1	"Speed Reg"	5	"Sum Spd/Torq"																																																		
2	"Torque Ref"	6	"AbsMn Spd/Tq"																																																		
3	"Min Spd/Torq"																																																				
4	<p><b>Motor NP RPM</b> Set to the motor nameplate rated RPM.</p>	<p>Units: RPM</p> <p>Default: Calculated</p> <p>Min/Max: 1/30000</p> <p>Comm Scale: Parameter 4 [Motor NP RPM] = 1.0</p> <p style="text-align: right;">✓ 16-bit Integer</p>																																																			

No.	Name Description									
p	<p>No. - Parameter Number</p> <p> Parameter value cannot be changed until the drive is stopped.</p>									
A	<p>Name - Parameter name as it appears in DriveExecutive software.</p> <p>Description - Brief description of parameter function.</p>									
A	<p>Values - Define the various operating characteristics of the parameter. <i>There are 3 types of Values.</i></p> <table border="1" data-bbox="240 1163 1398 1457"> <tbody> <tr> <td data-bbox="240 1163 488 1220">ENUM</td> <td data-bbox="488 1163 659 1220">Default: Options:</td> <td data-bbox="659 1163 1398 1220">Lists the value assigned at the factory. Displays the selections available.</td> </tr> <tr> <td data-bbox="240 1226 488 1283">Bit</td> <td data-bbox="488 1226 659 1283">Default: Options:</td> <td data-bbox="659 1226 1398 1283">Lists the value assigned at the factory. Displays the selections available.</td> </tr> <tr> <td data-bbox="240 1289 488 1457">Numeric</td> <td data-bbox="488 1289 659 1457">Default Min. Max. Type Comm Scale:</td> <td data-bbox="659 1289 1398 1457">Lists the value assigned at the factory. Displays lowest possible setting. Displays highest possible setting. Indicates if parameter is linkable, read-write, read-only, and data type (i.e. integer, floating point, boolean). Value sent from Controller or Comm Device = Drive Parameter Value x Comm Scale</td> </tr> </tbody> </table>	ENUM	Default: Options:	Lists the value assigned at the factory. Displays the selections available.	Bit	Default: Options:	Lists the value assigned at the factory. Displays the selections available.	Numeric	Default Min. Max. Type Comm Scale:	Lists the value assigned at the factory. Displays lowest possible setting. Displays highest possible setting. Indicates if parameter is linkable, read-write, read-only, and data type (i.e. integer, floating point, boolean). Value sent from Controller or Comm Device = Drive Parameter Value x Comm Scale
ENUM	Default: Options:	Lists the value assigned at the factory. Displays the selections available.								
Bit	Default: Options:	Lists the value assigned at the factory. Displays the selections available.								
Numeric	Default Min. Max. Type Comm Scale:	Lists the value assigned at the factory. Displays lowest possible setting. Displays highest possible setting. Indicates if parameter is linkable, read-write, read-only, and data type (i.e. integer, floating point, boolean). Value sent from Controller or Comm Device = Drive Parameter Value x Comm Scale								

## How Parameters are Organized

DriveExecutive programming software displays parameters in “Linear List” or “File Group Parameter” format. Viewing the parameters in “File Group Parameter” format simplifies programming by grouping parameters that are used for similar functions. There are twelve files. Each file is divided into multiple groups of parameters.





**Motor Data**

1	Motor NP Volts
2	Motor NP FLA
3	Motor NP Hertz
4	Motor NP RPM
5	Motor NP Power
6	Mtr NP Pwr Units
7	Motor Poles
8	Motor Inertia
9	Total Inertia
336	Service Factor

**Drive Config**

485	Motor Ctrl Mode
402	PWM Frequency
403	Voltage Class
405	Dead Time Comp
409	Line Undervolts
410	PreChrg TimeOut
411	PreChrg Control
510	FOC Mode Config
511	FOC2 Mode Config
514	Test Mode Config
512	PMag Mode Cnfg
505	PM TestWait Time
506	PM Test Idc Ramp
507	PM Test FreqRamp
508	PM Test Freq Ref
509	PM Test I Ref
424	Flux Ratio Ref

**Tuning**

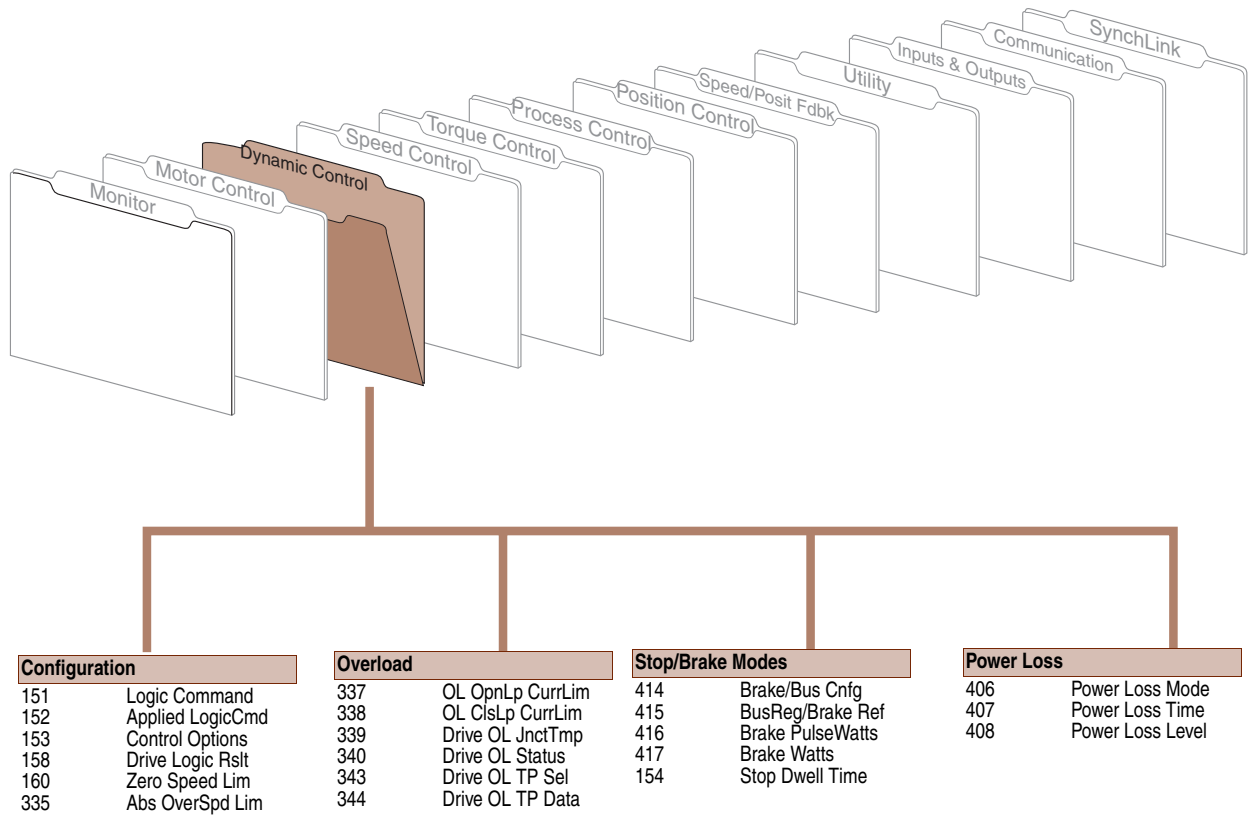
423	Iqs Rate Limit
453	Iu Offset
454	Iw Offset
425	Flux Rate Limit
426	Flux Satur Coef
443	Flux Reg P Gain1
470	Flux Reg P Gain2
444	Flux Reg I Gain
500	Bus Util Limit
501	Torque En Dly
437	Vqs Max
438	Vds Max
439	Vqs Min
440	Vds Min
469	StatorInduc Gain
473	Freq Reg FF Gain
449	Freq Reg I Gain
450	Freq Reg P Gain
451	Freq Track Filt
474	Freq Reg Wr BW
475	Freq Reg Wr BW
447	Slip Reg P Gain
448	Slip Reg I Gain
446	Slip Gain Min
445	Slip Gain Max
476	Slip Gain Comp
472	PreCharge Delay
431	Test Current Ref
432	Test Freq Ref
433	Test Freq Rate
477	Est Theta Delay

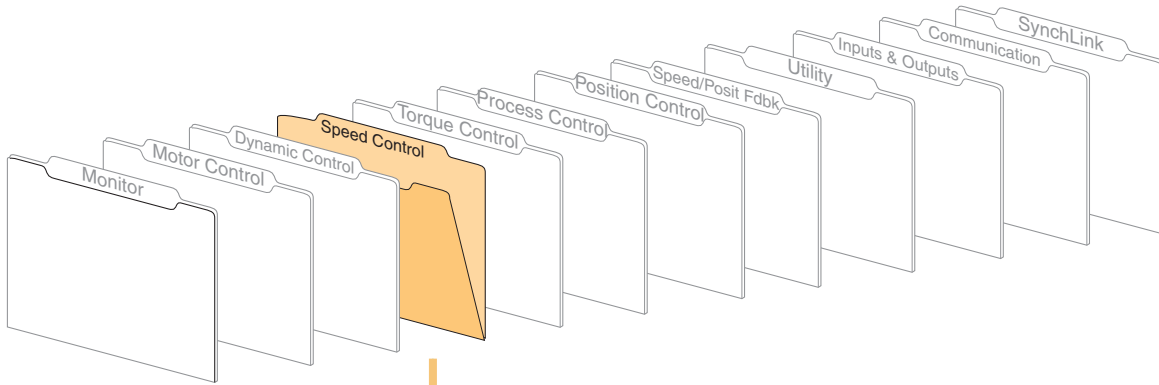
**Autotune Results**

421	Iqs Integ Freq
422	Iqs Reg P Gain
429	Ids Integ Freq
430	Ids Reg P Gain
486	Rated Slip Freq
487	Motor NTC Coef
488	Flux Current
490	StatorInductance
491	StatorResistance
492	Leak Inductance
502	Rotor Resistance
503	Current Reg BW
504	PM AbsEncd Offst

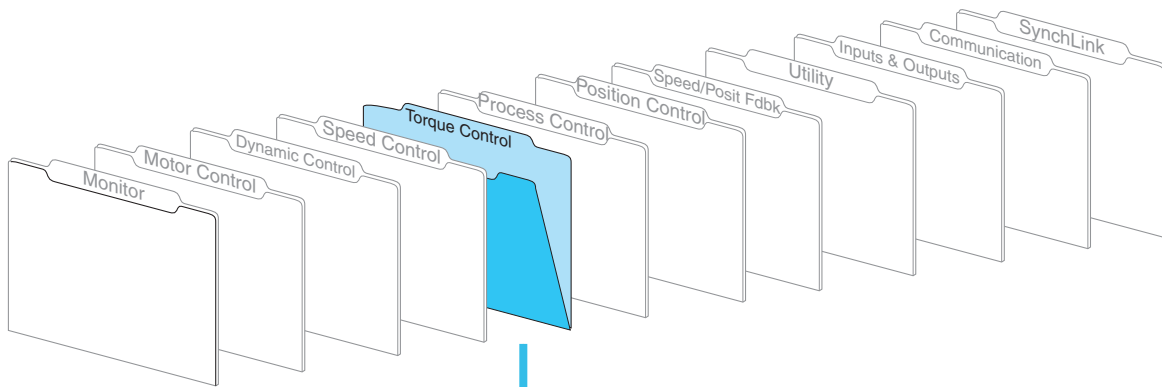
**PM Motor**

427	PM Mtr CEMF Comp
520	PM Q Inductance
521	PM D Inductance
522	PM Stator Resist
523	PM Mtr CEMF Coef





Reference		Regulator		Setpoint Monitor	
16	Speed Ref Sel	47	Spd Trim1 SpdRef	171	Set Speed Lim
10	Speed Ref 1	22	Speed Trim 2	172	Setpt 1 Data
11	Spd Ref1 Divide	25	STrim2 Filt Gain	173	Setpt1 TripPoint
12	Speed Ref 2	26	SpdTrim2 Filt BW	174	Setpt 1 Limit
13	Spd Ref2 Multi	23	Speed Trim 3	175	Setpt 2 Data
14	Speed Ref 4	24	SpdTrim 3 Scale	176	Setpt2 TripPoint
15	Speed Ref 5	19	Atune Spd Ref	177	Setpt 2 Limit
20	Speed Ref DPI	30	Rev Speed Limit		
17	Jog Speed 1	31	Fwd Speed Limit		
18	Jog Speed 2	301	Motor Speed Ref		
40	Selected Spd Ref	300	Motor Spd Fdbk		
30	Rev Speed Limit	93	SRegFB Filt Gain		
31	Fwd Speed Limit	94	SReg FB Filt BW		
41	Limited Spd Ref	71	Filtered SpdFdbk		
32	Accel Time	100	Speed Error		
33	Decel Time	89	Spd Err Filt BW		
42	Ramped Spd Ref	85	Servo Lock Gain		
34	S Curve Time	84	SpdReg AntiBckup		
43	S Curve Spd Ref	80	Speed Reg Ctrl		
37	Spd Ref Bypass	81	Spd Reg P Gain		
35	SpdRef Filt Gain	82	Spd Reg I Gain		
36	SpdRef Filt BW	87	SReg Torq Preset		
44	Filtered Spd Ref	8	Motor Inertia		
38	Speed Ref Scale	9	Total Inertia		
46	Scaled Spd Ref	90	Spd Reg BW		
21	Speed Trim 1	97	Act Spd Reg BW		
47	Spd Trim1 SpdRef	91	Spd Reg Damping		
45	Delayed Spd Ref	92	SpdReg P Gain Mx		
61	Virt Encoder EPR	101	SpdReg Integ Out		
62	Virt Encdr Posit	102	Spd Reg Pos Lim		
63	Virt Encdr Dlyed	103	Spd Reg Neg Lim		
56	Inertia SpeedRef	86	Spd Reg Droop		
55	Speed Comp	95	SRegOut FiltGain		
57	InertiaAccelGain	96	SReg Out Filt BW		
58	InertiaDecelGain	302	Spd Reg PI Out		
59	Inertia Torq Add				
60	DeltaSpeedScale				
140	FricComp Spd Ref				
141	FricComp Setup				
142	FricComp Stick				
143	FricComp Slip				
144	FricComp Rated				
145	FricComp TorqAdd				

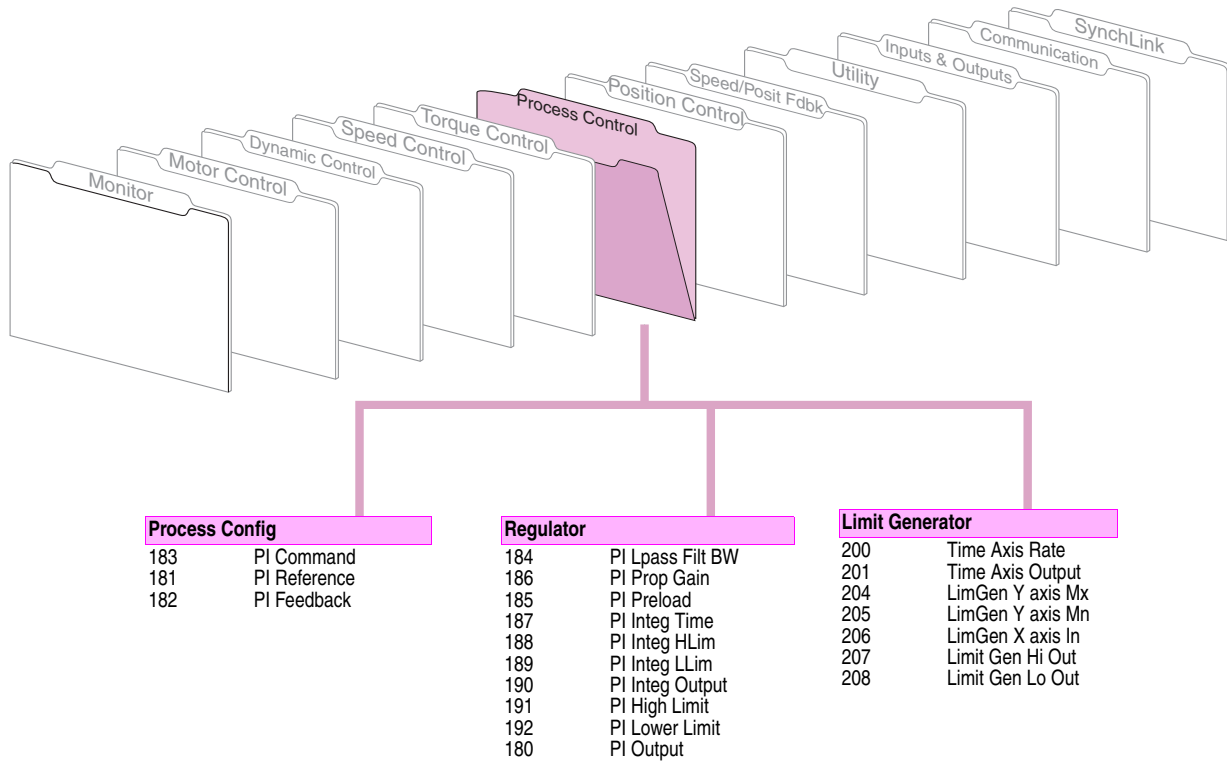


**Torque**

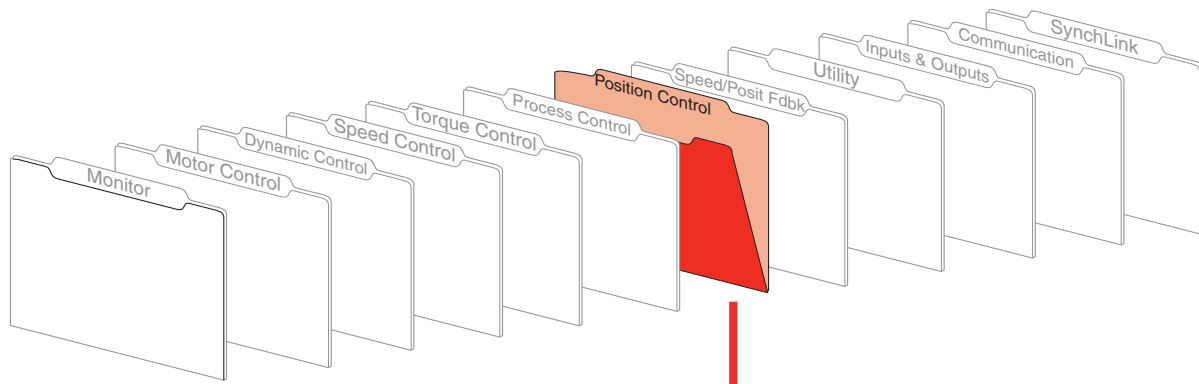
110	Spd/Torq ModeSel
302	Spd Reg PI Out
59	Inertia Torq Add
145	FricComp TorqAdd
111	Torque Ref 1
112	Torq Ref1 Div
113	Torque Ref 2
114	Torq Ref2 Mult
115	Torque Trim
116	Torque Step
129	Atune Torq Ref
117	Notch Filt Mode
118	Notch Filt Freq
306	DC Bus Voltage
401	Rated Volts
127	Mtring Power Lim
128	Regen Power Lim
300	Motor Spd Fdbk
125	Torque Pos Limit
126	Torque Neg Limit
123	Torq PosLim Actl
124	Torq NegLim Actl
303	Motor Torque Ref

**Current**

309	% Motor Flux
360	Min Flux
361	Flx LpassFilt BW
350	Iq Actual Ref
351	Iq Ref Trim
343	OL OpnLp CurrLim
356	Mtr Current Lim
352	Is Actual Lim
313	Heatsink Temp
345	Drive OL JnctTmp







**Position Config**

740	Position Control
741	Position Status
742	Posit Ref Sel

**Interp / Diret**

743	Aux Posit Ref
745	PositRef EGR Mul
746	PositRef EGR Div
744	PositRef EGR Out
757	Abs Posit Offset
753	Posit Offset 1
754	Posit Offset 2
755	Posit Offset Spd
756	X Offst SpdFilt
747	Position Cmmd
762	Mtr Posit Fdbk
764	Posit Load Fdbk
766	Posit FB EGR Mul
767	Posit FB EGR Div
763	Act Motor Posit
765	Posit Actl Load
769	Position Error
768	PositReg P Gain
770	PositReg Integ
772	XReg Integ LoLim
773	XReg Integ HiLim
774	XReg Integ Out
771	PositReg Droop
775	XReg Spd LoLim
776	XReg Spd HiLim
318	Posit Spd Output

**Point to Point**

758	Pt-Pt Posit Ref
745	PositRef EGR Mul
746	PositRef EGR Div
744	PositRef EGR Out
753	Posit Offset 1
754	Posit Offset 2
755	Posit Offset Spd
756	X Offst SpdFilt
747	Position Cmmd
762	Mtr Posit Fdbk
763	Act Motor Posit
769	Position Error
768	PositReg P Gain
761	Pt-Pt Filt BW
759	Pt-Pt Accel Time
760	Pt-Pt Decel Time
775	XReg Spd LoLim
776	XReg Spd HiLim
318	Posit Spd Output

**Posit Detection**

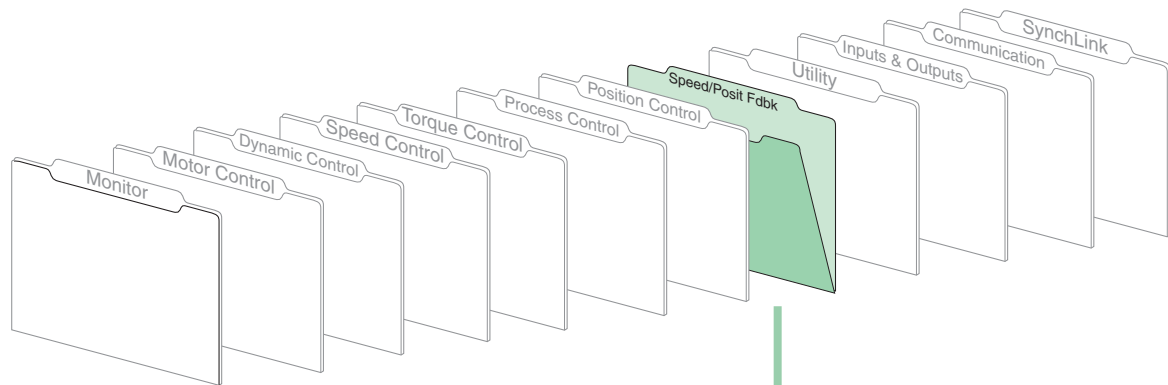
784	Posit Detct1 In
785	Posit Detct2 In
780	PositDetct1 Stpt
781	PositDetct2 Stpt
769	Position Error
782	In Posit BW
783	In Posit Dwell

**Sync Generator**

786	Xsync Status
787	Xsync Gen Period
317	SL System Time
788	Xsync In 1
789	Xsync Out 1
790	Xsync In 2
791	Xsync Out 2
792	Xsync Out 2 Dly
793	Xsync In 3
794	Xsync Out 3

**Posit Indexer**

796	Posit Index Ctrl
797	Posit Index Step
798	PositIndexPreset
799	PositIndexOutput



**Feedback Config**

72	Scaled Spd Fdbk
73	Spd Fdbk Scale
222	Motor Fdbk Sel
223	Virtual Edge/Rev
227	Spd Obs Trq Gain
220	Spd Observer BW
221	Load Estimate
300	Motor Spd Fdbk

**Encoder Port 0**

233	Encdr0 Config
234	Encdr0 Error
232	Encoder0 PPR
231	Encdr0 Spd Fdbk
230	Encdr0 Position
236	Port0 Regis Cnfg
237	Port0 Regis Ctrl
238	Port0 Regis Stat
235	Port0 Regis Ltch

**Encoder Port 1**

243	Encdr1 Config
244	Encdr1 Error
242	Encoder1 PPR
241	Encdr1 Spd Fdbk
240	Encdr1 Position
246	Port1 Regis Cnfg
247	Port1 Regis Ctrl
248	Port1 Regis Stat
245	Port1 Regis Ltch

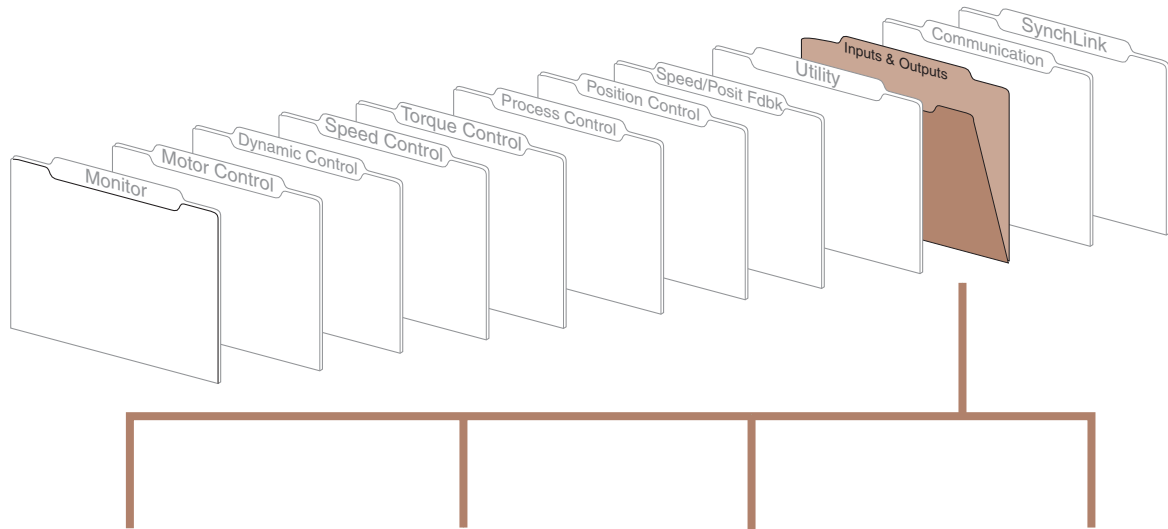
**Feedback Opt 0**

249	Fdbk Option ID
250	FB Opt0 Posit

**Calculated Fdbk**

548	Est Speed Fdbk
74	Motor Spd Est
226	Virtual Edge/Rev
75	MtrSpd Est Posit
76	MtrSpd Simulated
70	MtrSpd Sim Posit



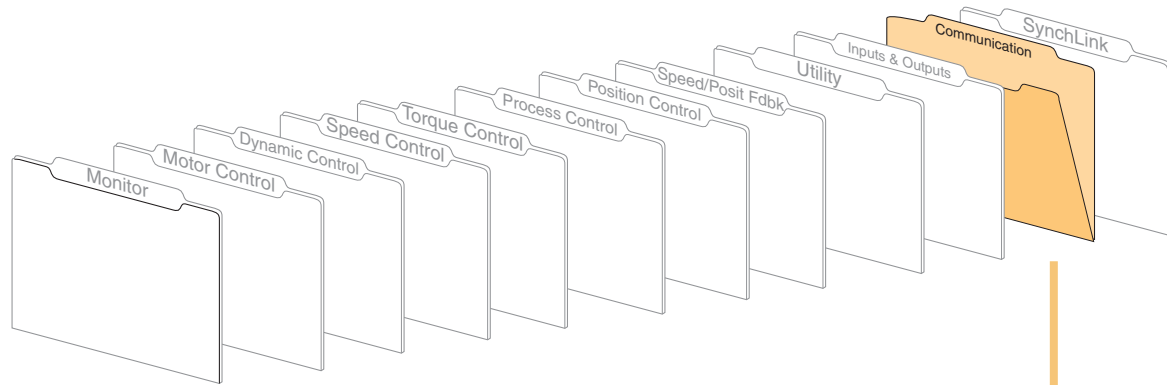


Analog Inputs	
800	Anlg In1 Data
802	Anlg In1 Scale
803	Anlg In1 Offset
804	AI 1 Filt Gain
805	Anlg In1 Filt BW
806	Anlg In2 Data
808	Anlg In2 Scale
809	Anlg In2 Offset
810	AI 2 Filt Gain
811	Anlg In2 Filt BW

Analog Outputs	
814	AnlgOut1 Integer
815	Anlg Out1 Real
817	Anlg Out1 Scale
812	Anlg Out1 Offset
818	Anlg Out1 Zero
819	AnlgOut2 Integer
820	Anlg Out2 Real
822	Anlg Out2 Scale
813	Anlg Out2 Offset
823	Anlg Out2 Zero

Digital Inputs	
825	En In Debounce
838	DigIn1 Sel
829	DigIn1 Debounce
826	DigIn1 Data
827	DigIn1 Bit
828	DigIn1 User Data
839	DigIn2 Sel
833	DigIn2 Debounce
830	DigIn2 Data
831	DigIn2 Bit
832	DigIn2 User Data
840	DigIn3 Sel
837	DigIn3 Debounce
834	DigIn3 Data
835	DigIn3 Bit
836	DigIn3 User Data

Digital Outputs	
(1)	Relay Out Data
843	Relay Out Bit
844	Dig Out 1 Data
845	Dig Out 1 Bit
846	Dig Out 2 Data
	Dig Out 2 Bit



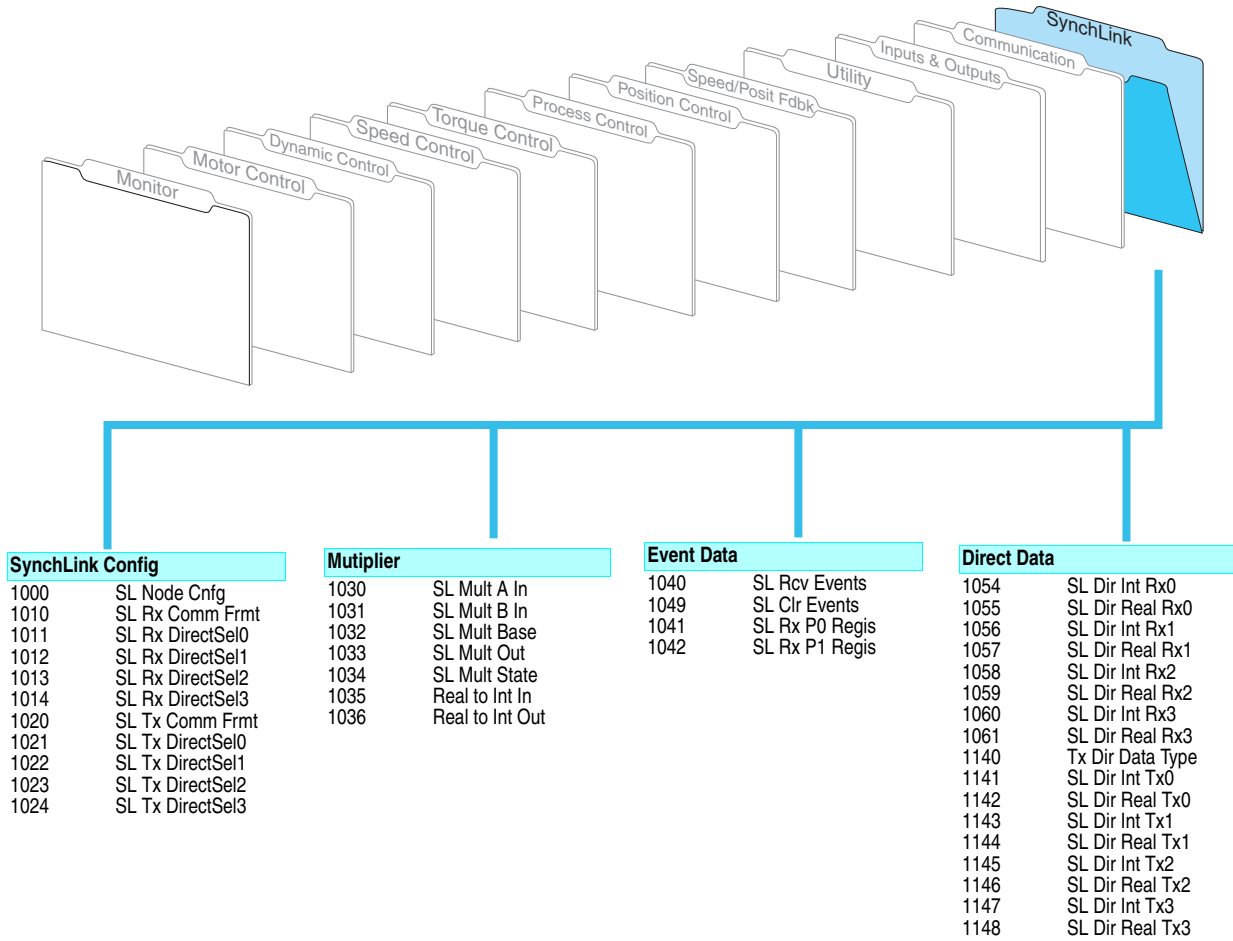
Commands	
691	DPI Ref Select
664	Lgx Comm Format

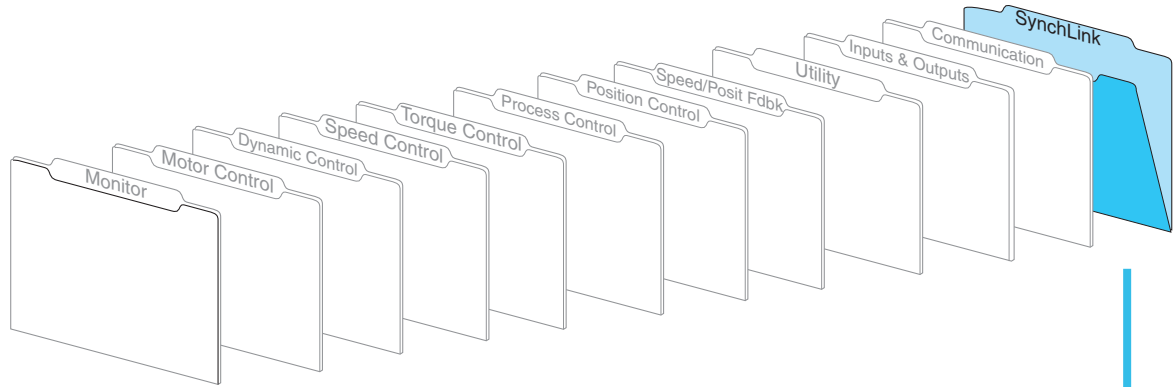
Masks & Owners	
693	Logic Mask
694	Start Mask
695	Jog Mask
696	Direction Mask
697	Fault Clr Mask
700	Stop Owner
701	Start Owner
702	Jog Owner
703	Direction Owner
704	Fault Clr Owner

DPI Data Links	
707	Data In A1 Int
708	Data In A1 Real
709	Data In A2 Int
710	Data In A2 Real
711	Data In B1 Int
712	Data In B1 Real
713	Data In B2 Int
714	Data In B2 Real
715	Data In C1 Int
716	Data In C1 Real
717	Data In C2 Int
718	Data In C2 Real
719	Data In D1 Int
720	Data In D1 Real
721	Data In D2 Int
722	Data In D2 Real
723	DLink OutDataTyp
724	Data Out A1 Int
725	Data Out A1 Real
726	Data Out A2 Int
727	Data Out A2 Real
728	Data Out B1 Int
729	Data Out B1 Real
730	Data Out B2 Int
731	Data Out B2 Real
732	Data Out C1 Int
733	Data Out C1 Real
734	Data Out C2 Int
735	Data Out C2 Real
736	Data Out D1 Int
737	Data Out D1 Real
738	Data Out D2 Int
739	Data Out D2 Real

Logix Inputs	
600	Integer In00
601	Real In00
602	Integer In01
603	Real In01
604	Integer In02
605	Real In02
606	Integer In03
607	Real In03
608	Integer In04
609	Real In04
610	Integer In05
611	Real In05
612	Integer In06
613	Real In06
614	Integer In07
615	Real In07
616	Integer In08
617	Real In08
618	Integer In09
619	Real In09
620	Integer In10
621	Real In10
622	Integer In11
623	Real In11
624	Integer In12
625	Real In12
626	Integer In13
627	Real In13
628	Integer In14
629	Real In14
630	Integer In15
631	Real In15

Logix Outputs	
632	Integer Out00
633	Real Out00
634	Integer Out01
635	Real Out01
636	Integer Out02
637	Real Out02
638	Integer Out03
639	Real Out03
640	Integer Out04
641	Real Out04
642	Integer Out05
643	Real Out05
644	Integer Out06
645	Real Out06
646	Integer Out07
647	Real Out07
648	Integer Out08
649	Real Out08
650	Integer Out09
651	Real Out09
652	Integer Out10
653	Real Out10
654	Integer Out11
655	Real Out11
656	Integer Out12
657	Real Out12
658	Integer Out13
659	Real Out13
660	Integer Out14
661	Real Out14
662	Integer Out15
663	Real Out15













**Buffered Data In**

1073	SL Buf Int Rx00	1103	SL Buf Int Rx15
1074	SL Buf Real Rx00	1104	SL Buf Real Rx15
1075	SL Buf Int Rx01	1105	SL Buf Int Rx16
1076	SL Buf Real Rx01	1106	SL Buf Real Rx16
1077	SL Buf Int Rx02	1107	SL Buf Int Rx17
1078	SL Buf Real Rx02	1108	SL Buf Real Rx17
1079	SL Buf Int Rx03	1109	SL Buf Int Rx18
1080	SL Buf Real Rx03	1110	SL Buf Real Rx18
1081	SL Buf Int Rx04	1111	SL Buf Int Rx19
1082	SL Buf Real Rx04	1112	SL Buf Real Rx19
1083	SL Buf Int Rx05	1113	SL Buf Int Rx20
1084	SL Buf Real Rx05	1114	SL Buf Real Rx20
1085	SL Buf Int Rx06	1115	SL Buf Int Rx21
1086	SL Buf Real Rx06	1116	SL Buf Real Rx21
1087	SL Buf Int Rx07	1117	SL Buf Int Rx22
1088	SL Buf Real Rx07	1118	SL Buf Real Rx22
1089	SL Buf Int Rx08	1119	SL Buf Int Rx23
1090	SL Buf Real Rx08	1120	SL Buf Real Rx23
1091	SL Buf Int Rx09	1121	SL Buf Int Rx24
1092	SL Buf Real Rx09	1122	SL Buf Real Rx24
1093	SL Buf Int Rx10	1123	SL Buf Int Rx25
1094	SL Buf Real Rx10	1124	SL Buf Real Rx25
1095	SL Buf Int Rx11	1125	SL Buf Int Rx26
1096	SL Buf Real Rx11	1126	SL Buf Real Rx26
1097	SL Buf Int Rx12	1127	SL Buf Int Rx27
1098	SL Buf Real Rx12	1128	SL Buf Real Rx27
1099	SL Buf Int Rx13	1129	SL Buf Int Rx28
1100	SL Buf Real Rx13	1130	SL Buf Real Rx28
1101	SL Buf Int Rx14	1131	SL Buf Int Rx29
1102	SL Buf Real Rx14	1132	SL Buf Real Rx29

**Buffered Data Out**



1160	Tx Buf Data Type	1190	SL Buf Real Tx14
1161	SL Buf Int Tx00	1191	SL Buf Int Tx15
1162	SL Buf Real Tx00	1192	SL Buf Real Tx15
1163	SL Buf Int Tx01	1193	SL Buf Int Tx16
1164	SL Buf Real Tx01	1194	SL Buf Real Tx16
1165	SL Buf Int Tx02	1195	SL Buf Int Tx17
1166	SL Buf Real Tx02	1196	SL Buf Real Tx17
1167	SL Buf Int Tx03	1197	SL Buf Int Tx18
1168	SL Buf Real Tx03	1198	SL Buf Real Tx18
1169	SL Buf Int Tx04	1199	SL Buf Int Tx19
1170	SL Buf Real Tx04	1200	SL Buf Real Tx19
1171	SL Buf Int Tx05	1201	SL Buf Int Tx20
1172	SL Buf Real Tx05	1202	SL Buf Real Tx20
1173	SL Buf Int Tx06	1203	SL Buf Int Tx21
1174	SL Buf Real Tx06	1204	SL Buf Real Tx21
1175	SL Buf Int Tx07	1205	SL Buf Int Tx22
1176	SL Buf Real Tx07	1206	SL Buf Real Tx22
1177	SL Buf Int Tx08	1207	SL Buf Int Tx23
1178	SL Buf Real Tx08	1208	SL Buf Real Tx23
1179	SL Buf Int Tx09	1209	SL Buf Int Tx24
1180	SL Buf Real Tx09	1210	SL Buf Real Tx24
1181	SL Buf Int Tx10	1211	SL Buf Int Tx25
1182	SL Buf Real Tx10	1212	SL Buf Real Tx25
1183	SL Buf Int Tx11	1213	SL Buf Int Tx26
1184	SL Buf Real Tx11	1214	SL Buf Real Tx26
1185	SL Buf Int Tx12	1215	SL Buf Int Tx27
1186	SL Buf Real Tx12	1216	SL Buf Real Tx27
1187	SL Buf Int Tx13	1217	SL Buf Int Tx28
1188	SL Buf Real Tx13	1218	SL Buf Real Tx28
1189	SL Buf Int Tx14	1219	SL Buf Int Tx29
		1220	SL Buf Real Tx29

## Parameter Data in Linear List Format

No.	Name Description	Values	Linkable	Read-Write	Data Type
1	 <b>Motor NP Volts</b> Set to the motor nameplate rated volts.	Units: Volt Default: Calculated Min/Max: 75/705		✓	16-bit Integer
2	 <b>Motor NP FLA</b> Set to the motor nameplate rated full load amps. Range limited by three-second inverter rating.	Units: Amps Default: Calculated Min/Max: Calculated/Calculated		✓	Real
3	 <b>Motor NP Hertz</b> Set to the motor nameplate rated frequency.	Units: Hz Default: Calculated Min/Max: 2.0000/500.0000		✓	Real
4	 <b>Motor NP RPM</b> Set to the motor nameplate rated RPM.	Units: RPM Default: Calculated Min/Max: 1/30000		✓	16-bit Integer
5	 <b>Motor NP Power</b> Set to the motor nameplate rated power.	Units: Hp Default: Calculated Min/Max: 0.2500/3500.0000		✓	Real
6	 <b>Mtr NP Pwr Units</b> The power units shown on the motor nameplate.	Default: 0 Hp Options: 0 Hp 1 W			
7	 <b>Motor Poles</b> Set to the number of motor poles indicated on the motor nameplate. Only even numbers are allowed.	Units: Pole Default: 4 Min/Max: 2/40		✓	16-bit Integer
8	<b>Motor Inertia</b> Time, in seconds, for an uncoupled motor to accelerate from zero to base speed, at rated motor torque. Calculated during auto-tune.	Units: Sec Default: 0.400 Min/Max: 0.0100/655.0000	✓	✓	Real
9	<b>Total Inertia</b> Time, in seconds, for a motor coupled to a load to accelerate from zero to base speed, at rated motor torque. Calculated during auto-tune.	Units: Sec Default: 2.0000 Min/Max: 0.0100/655.0000	✓	✓	Real
10	<b>Speed Ref 1</b> Sets the speed reference that the drive should use when selected by Par 16 [Speed Ref Sel]. A value of 1.0 represents base speed of the motor.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
11	<b>Spd Ref1 Divide</b> Par 10 [Speed Ref 1] is divided by this number. This number can be used to scale the value of Par 10 [Speed Ref 1].	Default: 1.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
12	<b>Speed Ref 2</b> Sets the speed reference that the drive should use when selected by Par 16 [Speed Ref Sel]. A value of 1.0 represents base speed of the motor.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
13	<b>Spd Ref2 Multi</b> Par 12 [Speed Ref 2] is multiplied by this number. This number can be used to scale the value of Par 12 [Speed Ref 2].	Default: 1.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
14	<b>Speed Ref 4</b> Sets the speed reference that the drive should use when selected by Par 16 [Speed Ref Sel].	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0	✓	✓	Real
15	<b>Speed Ref 5</b> Sets the speed reference that the drive should use when selected by Par 16 [Speed Ref Sel].	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0	✓	✓	Real
16	<b>Speed Ref Sel</b> Selects the source of the speed reference to the drive.	Default: 1 "Spd Ref DPI" Options: 0 "Zero Speed" 4 ""Spd Ref 4" 1 "Spd Ref 1" 5 "Spd Ref 5" 2 "Spd Ref 2" 6 "Spd Ref DPI" 3 "Spd Ref 3"			
17	<b>Jog Speed 1</b> Sets the speed reference that the drive should use when responding to bit 18 [Jog 1] of Par 152 [Applied LogicCmd].	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0	✓	✓	Real
18	<b>Jog Speed 2</b> Sets the speed reference that the drive should use when responding to bit 23 [Jog 2] of Par 152 [Applied LogicCmd].	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0	✓	✓	Real
19	 <b>Atune Spd Ref</b> Sets the maximum speed of the motor during the Flux current and inertia tests.	Units: RPM Default: 1499.4000 Min/Max: 176.4000/1764.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0		✓	Real



No.	Name Description	Values	Linkable	Read-Write	Data Type
20	<b>Speed Ref DPI</b> Sets the speed reference that the drive should use when selected in Par 16 [Speed Ref Sel]. A device communicating on a DPI port (typically a HIM) provides this value.	Units: RPM Default: 0.00000 Min/Max: -/+14112.00000 Comm Scale: Par 4 [Motor NP RPM] = 1.0			Real
21	<b>Speed Trim 1</b> Provides an additive trim value to the Par 46 [Scaled Speed Reference].	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0	✓	✓	Real
22	<b>Speed Trim 2</b> Provides an additive speed trim value to Par 47 [Spd Trim1 SpdRef] with a Lead/Lag filter. The Position regulator output is linked to this parameter by default. This speed trim value affects the speed reference input to the speed regulator.	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0	✓	✓	Real
23	<b>Speed Trim 3</b> Provides a scalable speed trim value that will be added to Par 47 [Spd Trim1 SpdRef]. [SpdTrim3 Scale] scales this value prior to the trim value affecting the speed reference.	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0	✓	✓	Real
24	<b>SpdTrim 3 Scale</b> Par 23 [Speed Trim 3] is multiplied by this number. This number can be used to scale the value of Par 23 [Speed Trim 3].	Default: 1.0000 Min/Max: -/+1000.0000	✓	✓	Real
25	<b>STrim2 Filt Gain</b> Sets the lead term for the Par 22 [Speed Trim 2] filter. Values greater than 1 will result in a lead function and value less than 1 will result in a lag function. A value of 1 will disable the filter.	Default: 1.0000 Min/Max: -/+15.0000	✓	✓	Real
26	<b>SpdTrim2 Filt BW</b> Sets the frequency for the Speed Trim 2 filter.	Units: R/S Default: 200.0000 Min/Max: 0.0000/1000.0000	✓	✓	Real
30	 <b>Rev Speed Limit</b> Sets a limit on the speed reference in the negative direction. This value can be entered as a negative value or zero.	Units: RPM Default: -2205.0000 Min/Max: -14112.0000/0.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0		✓	Real
31	 <b>Fwd Speed Limit</b> Sets a limit on the speed reference in the positive direction. This value can be entered as a positive value or zero.	Units: RPM Default: 2205.0000 Min/Max: 0.0000/14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0		✓	Real
32	<b>Accel Time</b> Sets the rate of acceleration for all speed increases, with time in seconds to base speed. Accel Rate = Par 4 [Motor NP RPM] / Par 32 [Accel Time]	Units: Sec Default: 10.0000 Min/Max: 0.0100/6553.5000	✓	✓	Real
33	<b>Decel Time</b> Sets the rate of deceleration for all speed decreases, with time in seconds to base speed. Decel Rate = Par 4 [Motor NP RPM] / Par 33 [Decel Time]	Units: Sec Default: 10.0000 Min/Max: 0.0100/6553.5000	✓	✓	Real
34	<b>S Curve Time</b> Sets the S time (Round In and Round Out ) in seconds. This time is added to the beginning and to the end of the applied ramp. The S time is independent of speed and results in a trapezoidal torque profile.	Units: Sec Default: 0.5000 Min/Max: 0.0000/4.0000	✓	✓	Real
35	<b>SpdRef Filt Gain</b> Sets the lead term for the Speed Reference filter. Values greater than 1 will result in a lead function and value less than 1 will result in a lag function. A value of 1 will disable the filter.	Default: 1.0000 Min/Max: -/+5.0000	✓	✓	Real
36	<b>SpdRef Filt BW</b> Sets the frequency for the Speed Reference filter.	Units: R/S Default: 0.0000 Min/Max: 0.0000/500.0000	✓	✓	Real
37	<b>Spd Ref Bypass</b> The speed command after the limit, ramp and s-curve blocks. Link a source directly to this parameter to bypass these blocks.	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0	✓	✓	Real
38	<b>Speed Ref Scale</b> This parameter is multiplied with the value in Par 44 [Filtered Spd Ref] to produce the value in Par 46 [Scaled Spd Ref].	Default: 1.0000 Min/Max: -/+1000.0000 x 1	✓	✓	Real
40	<b>Selected Spd Ref</b> Displays the speed command before the speed reference limit block.	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0			Real
41	<b>Limited Spd Ref</b> Displays the speed command after the limit block, limited by Par 30 [Rev Speed Limit] and Par 31 [Fwd Speed Limit].	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0			Real
42	<b>Ramped Spd Ref</b> Displays the speed command after the linear ramp block, modified by Par 32 [Accel Time] and Par 33 [Decel Time].	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0			Real

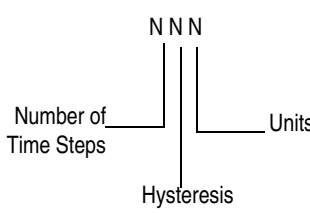
No.	Name Description	Values	Linkable	Read-Write	Data Type
43	<b>S Curve Spd Ref</b> Displays the speed command after the s-curve block, modified by Par 34 [S Curve Time].	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0			Real
44	<b>Filtered Spd Ref</b> Displays the speed reference value output from the reference Lead/Lag filter.	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0			Real
45	<b>Delayed Spd Ref</b> One sample period delayed output of Par 43 [S Curve Spd Ref]. Used in some applications to synchronize the speed reference value through SynchLink. This master drive [S Curve Spd Ref] would then be transmitted to the slave drives over SynchLink.	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4[Motor NP RPM] = 1.0			Real
46	<b>Scaled Spd Ref</b> Displays the speed command after scaling (the product of Par 44 [Filtered Spd Ref] and Par 38 [Speed Ref Scale].	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0			Real
47	<b>Spd Trim1 SpdRef</b> Displays the final speed command used by the Speed Regulator. It is the sum of the Par 46 [Scaled Spd Ref] and Par 21 [Speed Trim1].	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0			Real
50	<b>Spd Ref TP Sel</b> Enter or write a value to select speed reference data displayed in Par 52 [Spd TP Data] and Par 51 [Spd Ref TP RPM].	Default: 0 "Zero" Options: 0 "Zero" 11 "Ramp Match" 1 "User Ref" 12 "S Crv Match" 2 "Logic Select" 13 "S Array size" 3 "Lgc Sel Ref" 14 "S Array Indx" 4 "Reserved" 15 "VE Pos Diff" 5 "Logic En Ref" 16 "Scl Ext Trim" 6 "Rev Spd Lim" 17 "Trim FiltOut" 7 "Fwd Spd Lim" 18 "Ref w/Trim" 8 "Rev Lim Stat" 19 "Amp Lim2 In" 9 "Fwd Lim Stat" 20 "Amp LimStat2" 10 "Amp Lim Stat" 21 "FTD Ramp Out"			
51	<b>Spd Ref TP RPM</b> Displays the value selected by Par 50 [Spd Ref TP Sel] in RPM. This display should only be used if the selected value is floating point data.	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4[Motor NP RPM] = 1.0			Real
52	<b>Spd Ref TP Data</b> Displays the value selected by Par 50 [Spd Ref TP Sel]. A value of 1.0 represents base speed of the motor.	Default: 0 Min/Max: -/+32768			16-bit Integer
53	<b>Drive Ramp Rslt</b> Displays the speed reference value, after the limit function. This is the input to the error calculator and speed regulator. Available for use in peer-to-peer data links (DPI interface). This number is scaled so that rated motor speed will read 32768.	Default: 0 Min/Max: -/+262144/262144			16-bit Integer
55	 <b>Speed Comp</b> Displays the derivative or change in Par 56 [Inertia SpeedRef] on a per second basis. Link this parameter to Par 23 [Speed Trim 3] and set Par 24 [SpeedTrim 3 Scale] to 0.002 to reduce position error in following applications.	Default: 0.0000 Min/Max: -/+2200000000.0000			16-bit Integer
56	<b>Inertia SpeedRef</b> The speed input of the inertia compensator. Link this parameter to the output of an internal ramp or s-curve block. The inertia compensator generates a torque reference that is proportional to the rate of change of speed input and total inertia.	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0	✓	✓	Real
57	<b>InertiaAccelGain</b> Sets the acceleration gain for the Inertia Compensation function. A value of 1 produces 100% compensation.	Default: 1.0000 Min/Max: 1.0000/2.0000	✓	✓	Real
58	<b>InertiaDecelGain</b> Sets the deceleration gain for the Inertia Compensation function. A value of 1 produces 100% compensation.	Default: 1.0000 Min/Max: 1.0000/2.0000	✓	✓	Real
59	<b>Inertia Torq Add</b> The torque reference output generated by the inertia compensator. This torque level is modified by Par 57 [InertiaAccelGain] and Par 58 [InertiaDecelGain]. A value of 1.0 represents rated torque of the motor.	Units: P.U. Default: 1.0000 Min/Max: -/+8.0000			Real
60	<b>DeltaSpeedScale</b> Multiplier in the Inertia Compensation function - affects the value of Par 59 [Inertia Torq Add]. Use in center winder and unwind applications to compensate for roll diameter build-up.	Default: 1.0000 Min/Max: -/+1000.0000	✓	✓	Real
61	 <b>Virt Encoder EPR</b> Equivalent Edges Per Revolution (EPR) or line count of a virtual encoder. A virtual encoder is a position reference whose input comes from speed reference. It accumulates pulses at the same rate as a real encoder of identical PPR. Enter the equivalent Pulses Per Revolution (PPR). For example: enter 1024 EPR to match an encoder with 1024 PPR.	Units: EPR Default: 4096 Min/Max: 10/67108864		✓	32-bit Integer

No.	Name Description	Values	Linkable	Read-Write	Data Type																								
62	<b>Virt Encdr Posit</b> A 32 bit pulse accumulator of the virtual encoder. The accumulated pulse count is equivalent to the hardware accumulator of a real encoder. It accumulates at a rate of 4x the value placed in Par 61 [Virt Encoder PPR]. The accumulator starts at zero upon position enable.	Default: 0 Min/Max: -/+2147483648			32-bit Integer																								
63	<b>Virt Encdr Delay</b> One sample period delayed output of Par 62 [Virt Encdr Posit]. Used in some applications to phase synchronize position reference through synchLink. The master is delayed one sample while the downstream drives update their position references – then all drives sample position simultaneously. The downstream drives do not select a delay.	Default: 0 Min/Max: -/+2147483648			32-bit Integer																								
70	<b>MtrSpd Sim Posit</b> The motor position output of the motor simulator. The simulator provides motor position information during setup and troubleshooting when actual motor control is not desired or possible. To use the motor simulator, enter a value of 4 in Par 222 [Motor Fdbk Sel].	Default: 0 Min/Max: -/+2147483648			32-bit Integer																								
71	<b>Filtered SpdFdbk</b> Displays the motor speed feedback value output from the feedback Lead/Lag filter.	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0			Real																								
72	<b>Scaled Spd Fdbk</b> Displays the product of the speed feedback and Par 73 [Spd Fdbk Scale]. This parameter is for display only.	Default: 0.0000 Min/Max: -/+2200000000.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0			Real																								
73	<b>Spd Fdbk Scale</b> A user adjustable scale factor (multiplier) for speed feedback. It is multiplied with speed feedback to produce Par 72 [Scaled Spd Fdbk].	Default: 1.0000 Min/Max: -/+2200000000.0000 x 1	✓	✓	Real																								
74	<b>Motor Spd Est</b> Displays estimated motor speed, calculated when the selected feedback is sensorless or when encoderless ridethrough is enabled, in RPM.	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0			Real																								
75	<b>MtrSpd Est Posit</b> Summation (or integration) of Par 74 [Motor Spd Est] scaled by the value in Par 226 [Virtual Edge/Rev].	Default: 0 Min/Max: -/+2147483648			32-bit Integer																								
76	<b>MtrSpd Simulated</b> The motor speed output of the motor simulator. The simulator provides motor speed information during setup and troubleshooting when actual motor control is not desired or possible. To use the motor simulator, enter a value of 4 in Par 222 [Motor Fdbk Sel].	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0			Real																								
77	<b>Spd Fdbk TP Sel</b> Enter or write a value to select the data displayed in Par 78 [Spd Fdbk TP RPM] and Par 79 [Spd Fdbk TP data].	Default: 0 "Zero" Options: 0 "Zero" 20 "E0 dTime" 1 "Clock Time" 21 "E0 EPR" 2 "InactvFbkDev" 22 "E0 PU Mult" 3 "ActiveFbkDev" 23 "E0 dTheta" 4 "MCP Fdbk Dev" 24 "E0 Error" 5 "Observer Err" 25 "E0 Qloss pk" 6 "UnFilt Load" 26 "E0 Ploss pk" 7 "Pri Actl Spd" 27 "E0 PlevlHist" 8 "Alt Actl Spd" 28 "E1 Edge Time" 9 "Pri Actl Pos" 29 "E1 dEdge" 10 "Alt Actl Pos" 30 "E1 dTime" 11 "Obser dp in" 31 "E1 EPR" 12 "Obser dp" 32 "E1 Edge Modet" 13 "Obser dperr" 33 "E1 dTheta" 14 "Obser accel" 34 "E1 Error" 15 "Obser K3/S" 35 "E1 Qloss pk" 16 "MCP PPR" 36 "E1 Ploss pk" 17 "MCP 2^n" 37 "E1 PlevlHist" 18 "E0 Edge Time" 38 "E1 Delta2Err" 19 "E0 dEdge" 39 "E1 Delta2Err"																											
78	<b>Spd Fdbk TP RPM</b> Displays the value selected in Par 77 [Spd Fdbk TP Sel] in RPM. This display should only be used if the selected value is floating point data.	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0			Real																								
79	<b>Spd Fdbk TP Data</b> Displays the value selected in Par 77 [Spd Fdbk TP Sel]. This display should only be used if the selected value is integer data.	Default: 0 Min/Max: -/+32768			16-bit Integer																								
80	<b>Speed Reg Ctrl</b> Enter or write a value to configure the speed regulator integrator. Refer to Appendix B, Speed Control, page B-4.																												
<table border="1"> <thead> <tr> <th>Options</th> <th>Reserved</th> <th>Presel Sel</th> <th>Integ Hold</th> <th>Integ Reset</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> </tr> </thead> <tbody> <tr> <td>Default</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> </tr> <tr> <td>Bit</td> <td>0</td> <td>1</td> <td>2</td> <td>3</td> <td>4</td> <td>5</td> <td>6</td> </tr> </tbody> </table> <p>0 = False 1 = True</p>						Options	Reserved	Presel Sel	Integ Hold	Integ Reset	Reserved	Reserved	Reserved	Default	0	0	0	0	0	0	0	Bit	0	1	2	3	4	5	6
Options	Reserved	Presel Sel	Integ Hold	Integ Reset	Reserved	Reserved	Reserved																						
Default	0	0	0	0	0	0	0																						
Bit	0	1	2	3	4	5	6																						

No.	Name Description	Values	Linkable	Read-Write	Data Type
81	<b>Spd Reg P Gain</b> Sets the proportional gain of the speed regulator. It's value is automatically calculated based on the bandwidth setting in Par 90 [Spd Reg BW]. Proportional gain may be manually adjusted by setting Par 90 to a value of zero. Units are (per unit torque) / (per unit speed).  Adjustments to Pars 474 [Freq Reg We BW] and 475 Freq Reg Wr BW] may be necessary when using sensorless feedback.	Default: 20.0000 Min/Max: 0.0000/600.0000	✓	✓	Real
82	<b>Spd Reg I Gain</b> Sets the integral gain of the speed regulator. It's value is automatically calculated based on the bandwidth setting in Par 90 [Spd Reg BW]. Integral gain may be manually adjusted by setting Par 90 to a value of zero. Units are (per unit torque/sec) / (per unit speed).  Adjustments to Pars 474 [Freq Reg We BW] and 475 Freq Reg Wr BW] may be necessary when using sensorless feedback.	Units: /Sec Default: 50.0000 Min/Max: 0.0000/100000.0000	✓	✓	Real
84	<b>SpdReg AntiBckup</b> By setting this to 0.3, the drive will not over-shoot to a step response. This Par has no affect on the drive's response to load changes. Recommended setting is 0.1000 to 0.5000.	Default: 0.0000 Min/Max: 0.0000/0.5000	✓	✓	Real
85	<b>Servo Lock Gain</b> Sets the gain of an additional integrator in the speed regulator. The effect of Servo Lock is to increase stiffness of the speed response to a load disturbance. It behaves like a position regulator with velocity feed forward, but without the pulse accuracy of a true position regulator. The units of Servo Lock are rad/sec. Gain should normally be set to less than 1/3 speed regulator bandwidth, or for the desired response. Set to zero to disable Servo Lock.	Units: /Sec Default: 0.0000 Min/Max: 0.0000/300.0000	✓	✓	Real
86	<b>Spd Reg Droop</b> Specifies the amount of base speed that the speed reference is reduced when at full load torque. Use the droop function to cause the motor speed to decrease with an increase in load. The units are per unit speed / per unit torque.	Units: P.U. Default: 0.0000 Min/Max: 0.0000/0.2500	✓	✓	Real
87	<b>SReg Torq Preset</b> When the drive is not enabled, this parameter presets integrator output Par 101 [SpdReg Integ Out] to specified a torque level. This ensures that the torque command will be at the preset value when the drive is enabled and run. Par 80 [Speed Reg Ctrl] bit 1 [Preset Sel] = 0 enables this preset.	Units: P.U. Default: 0.0000 Min/Max: -/+8.0000	✓	✓	Real
89	<b>Spd Err Filt BW</b> Sets the bandwidth of a 2nd order Butterworth low pass filter, which reduces quantization noise. The units are rad/sec. A value of 0 will disable the filter. The value should be greater than 5 times the value of Par 90 [Spd Reg BW].	Units: R/S Default: 200.0000 Min/Max: 0.0000/2000.0000	✓	✓	Real
90	<b>Spd Reg BW</b> Sets the bandwidth of the speed regulator in rad/sec. Bandwidth is also referred to as the crossover frequency. Small signal time response is approximately 1/BW and is the time to reach 63% of set point. A change to this parameter will cause an automatic update of Pars 81 [Spd Reg P Gain] and 82 [Spd Reg I Gain]. To disable the automatic gain calculation, set this parameter to a value of zero.  Adjustments to Pars 474 [Freq Reg We BW] and 475 Freq Reg Wr BW] may be necessary when using sensorless feedback.	Units: R/S Default: 10.0000 Min/Max: 0.0000/500.0000  Min/Max limited by AutoTune calculations.	✓	✓	Real
91	<b>Spd Reg Damping</b> Sets the damping factor of the drive's characteristic equation and factors in the calculation of the integral gain. A damping factor of 1.0 is considered critical damp. Lowering the damping will produce faster load disturbance rejection, but may cause a more oscillatory response. When Par 90 [Spd Reg BW] is set to zero, damping factor has no effect.	Default: 1.0000 Min/Max: 0.5000/3.0000	✓	✓	Real
92	<b>SpdReg P Gain Mx</b> Places a limit on the maximum value of proportional gain in Par 81 [Spd Reg P Gain]. When gains are automatically calculated, this parameter is necessary to limit the amplification of noise with increased inertia.	Default: 100.0000 Min/Max: 0.0000/600.0000	✓	✓	Real

No.	Name Description	Values	Linkable	Read-Write	Data Type
93	<b>SRegFB Filt Gain</b> Sets the lead term for the speed feedback filter. Values greater than 1 will result in a lead function and value less than 1 will result in a lag function. A value of 1 will disable the filter.	Default: 1.0000 Min/Max: -5.0000/20.0000	✓	✓	Real
94	<b>SReg FB Filt BW</b> Sets the frequency for the Speed feedback filter.	Units: R/S Default: 35.0000 Min/Max: 0.0000/3760.0000	✓	✓	Real
95	<b>SRegOut FiltGain</b> Sets the lead term for the Speed Regulator output filter. Values greater than 1 will result in a lead function and value less than 1 will result in a lag function. A value of 1 will disable the filter.	Default: 0.7000 Min/Max: -/+5.0000	✓	✓	Real
96	<b>SReg Out Filt BW</b> Sets the frequency for the Speed Regulator output filter.	Units: R/S Default: 30.0000 Min/Max: 0.0000/3760.0000	✓	✓	Real
97	<b>Act Spd Reg BW</b> Displays the actual speed regulator bandwidth or crossover frequency. The value represents the bandwidth in Par 90 [Spd Reg BW] after the maximum bandwidth limits have been applied.	Units: R/S Default: 10.0000 Min/Max: 0.0000/500.0000			Real
98	<b>Spd Gain TP Sel</b> Enter or write a value to select the speed gain data displayed in Par 99 [Spd Gain TP Data].	Default: 0 "Zero" Options: 0 "Zero" 12 "I Rate Limit" 1 "Iq Rate BW" 13 "I RtLim Stat" 2 "Reserved" 14 "PGain Max" 3 "PGain Max BW" 15 "GnMx LimStat" 4 "BW Limit" 16 "Damping" 5 "InertiaMaxBW" 17 "Dmp Lim Stat" 6 "BW Lim Stat" 18 Reserved 7 "BW Select" 19 Srls KpMxBW 8 "Totl Inertia" 20 Srls BWLimit 9 "TI Lim Stat" 21 SrlsInrtMxBW 10 "Mtr Inertia" 22 SrlsBWSelect 11 "M InrtLStat" 23 Srls BW Calc 24 Snsr BW Calc			
99	<b>Spd Gain TP Data</b> Displays the value selected by Par 98 [Spd Gain TP Sel].	Default: 0.0000 Min/Max: 0.0000/500.0000			Real
100	<b>Speed Error</b> The error (difference) between the motor speed reference (+) and the filtered motor speed feedback (-).	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0			Real
101	<b>SpdReg Integ Out</b> The output value of the Speed Regulator Intergal channel.	Units: P.U. Default: 0.0000 Min/Max: -/+8.0000 Comm Scale: 1.0 PU Torque			Real
102	<b>Spd Reg Pos Lim</b> Sets the positive limit of the Speed regulator output value. The output of the Speed regulator is limited by adjustable high and low limits.	Units: P.U. Default: 3.0000 Min/Max: 0.0000/6.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0	✓	✓	Real
103	<b>Spd Reg Neg Lim</b> Sets the negative limit of the Speed regulator output value. The output of the Speed regulator is limited by adjustable high and low limits.	Units: P.U. Default: -3.0000 Min/Max: -6.0000/0.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0	✓	✓	Real
104	<b>SrLss Spd Reg Kp</b> Sets the proportional gain of the speed regulator when sensorless motor speed feedback is used. Value is automatically calculated based on the bandwidth set in Par 106 [SrLss Spd Reg BW]. Proportional gain may be manually adjusted by setting Par 106 to zero. This gain setting has no units (per unit torque) / (per unit speed error).	Default: 8.0000 Min/Max: 0.0000/200.0000		✓	Real
105	<b>SrLss Spd Reg Ki</b> Sets the integral gain of the speed regulator when sensorless motor speed feedback is used. Value is automatically calculated based on the bandwidth set in Par 106 [SrLss Spd Reg BW]. Integral gain may be manually adjusted by setting Par 106 to zero. Units are /Sec (per unit torque/sec) / (per unit speed error).	Units: /Sec Default: 8.0000 Min/Max: 0.0000/4095.8000		✓	
106	<b>SrLss Spd Reg BW</b> Sets the bandwidth of the speed regulator when sensorless motor speed feedback is used. Units are in rad/sec. Bandwidth is also referred to as the crossover frequency. Small integral time response is approximately 1/BW and is the time to reach 63% of set point. A change to this parameter will cause an automatic update of Pars 104 [SrLss Spd Reg Kp] and 105 [SrLss Spd Reg Ki]. To disable the automatic gain calculation, set this parameter to zero. The maximum limit for this parameter is determined by Par 354 [Iq Rate Limit], the ratio of Par 8 [Motor Inertia] to Par 9 [Total Inertia], and Par 107 [SrLss Kp Max].	Units: R/S Default: 10.0000 Min/Max: 0.0000/30.0000		✓	

No.	Name Description	Values	Linkable	Read-Write	Data Type
107	<b>SrLss Kp Max</b> Places a limit on the maximum value of proportional gain in Par 104 [SrLss Spd Reg Kp], for use when sensorless motor speed feedback is used. When gains are automatically calculated, this parameter is necessary to limit the amplification of noise with increased inertia.	Default: 20.0000 Min/Max: 20.0000/35.0000			
108	<b>Spd Reg TP Sel</b> Enter or write a value to select speed regulator data displayed in Par 109 [Spd Reg TP Data].	Default: 0 "Zero" Options: 0 "Zero" 10 "Intg Hold" 1 "Spd FiltOut" 11 "Reserved" 2 "Servo Lock" 12 "I GainParLim" 3 "Spd+ServLock" 13 "P GainParLim" 4 "Prop Output" 14 "SrvLck ParLm" 5 "Intg Input" 15 "AntiBkup PLm" 6 "SclD Int Pre" 16 "Droop ParLim" 7 "Sel Int Pre" 17 "Pos Lim Stat" 8 "Droop Output" 18 "Neg Lim Stat" 9 "Out Lim Stat" 19 "Active Igain"			
109	<b>Spd Reg TP Data</b> Displays the data selected by Par 108 [Spd Reg TP Sel].	Units: P.U. Default: 0.0000 Min/Max: +/-8.0000			Real
110	<b>Spd/Torq ModeSel</b> Selects the source for the drive torque reference.	Default: 1 "Speed Reg" Options: 0 "Zero Torque" 4 "Max Spd/Torq" 1 "Speed Reg" 5 "Sum Spd/Torq" 2 "Torque Ref" 6 "AbsMn Spd/Tq" 3 "Min Spd/Torq"			
111	<b>Torque Ref 1</b> Supplies an external motor torque reference to the drive. This parameter is divided by the value in Par 112 [Torq Ref1 Div]. A value of 1.0 represents rated torque of the motor.	Default: 0.0000 Min/Max: -/+2200000000.0000 Comm Scale: 1.0 Rated Motor Torque	✓	✓	Real
112	<b>Torq Ref1 Div</b> Par 111 [Torque Ref 1] is divided by this number. Use this parameter to scale the value of Par 111 [Torque Ref 1].	Default: 1.0000 Min/Max: -/+2200000000.0000		✓	Real
113	<b>Torque Ref 2</b> Supplies an external motor torque reference to the drive. This parameter is multiplied by the value in Par 114 [Torq Ref2 Mult]. A value of 1.0 represents rated torque of the motor.	Default: 0.0000 Min/Max: -/+2200000000.0000 Comm Scale: 1.0 Rated Motor Torque	✓	✓	Real
114	<b>Torq Ref2 Mult</b> Par 113 [Torque Ref 2] is multiplied by this number. Use this parameter to scale the value of Par 113 [Torque Ref 2].	Default: 1.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
115	<b>Torque Trim</b> The amount added to the Torque Ref 1 & 2 before the Speed/Torque Mode Selector. A value of 1.0 represents rated torque of the motor.	Units: P.U. Default: 0.0000 Min/Max: -/+8.0000 Comm Scale: 1.0 Rated Motor Torque	✓	✓	Real
116	<b>Torque Step</b> The amount added to the selected Torque Reference before notch filtering or limits are applied. A value of 1.0 represents rated torque of the motor.	Units: P.U. Default: 0.0000 Min/Max: -/+8.0000 Comm Scale: 1.0 Rated Motor Torque	✓	✓	Real
117	<b>Notch Filt Mode</b> Notch enabled.	Default: 0 "No Filter" Options: 0 "No Filter" 2 "IIR Notch" 1 "Reserved"			
118	<b>Notch Filt Freq</b> The center frequency for Notch filter.	Units: Hz Default: 135.0000 Min/Max: 0.0000/500.0000	✓	✓	Real
123	<b>Torq PosLim Actl</b> Sets the internal torque limit for positive torque reference values. The positive internal motor torque will not be allowed to exceed this value.	Units: P.U. Default: 1.0000 Min/Max: 0.0000/8.0000			Real
124	<b>Torq NegLim Actl</b> Sets the internal torque limit for negative torque reference values. The internal negative motor torque will not be allowed to exceed this value.	Units: P.U. Default: -1.0000 Min/Max: -8.0000/0.0000			Real
125	<b>Torque Pos Limit</b> Sets the external torque limit for positive torque reference values. The external positive motor torque will not be allowed to exceed this value.	Units: P.U. Default: 2.0000 Min/Max: 0.0000/8.0000	✓	✓	Real
126	<b>Torque Neg Limit</b> Sets the external torque limit for negative torque reference values. The external negative motor torque will not be allowed to exceed this value.	Units: P.U. Default: -2.0000 Min/Max: -8.0000/0.0000	✓	✓	Real
127	<b>Mtring Power Lim</b> Sets the maximum motoring (positive) power of the drive. This can be calculated by multiplying the desired maximum motor torque and the maximum motor speed. A value of 1.0 = nominal motor power	Units: P.U. Default: 8.0000 Min/Max: 0.0000/8.0000	✓	✓	Real
128	<b>Regen Power Lim</b> Sets the maximum regenerative (negative) power of the drive. This can be calculated by multiplying the desired maximum motor torque and the maximum motor speed. A value of 1.0 = nominal motor power	Units: P.U. Default: -1.0000 Min/Max: -8.0000/0.0000	✓	✓	Real

No.	Name Description	Values	Linkable	Read-Write	Data Type											
129	<b>Atune Torq Ref</b> Sets the motor torque that is applied to the motor during the flux current and inertia tests	Units: P.U. Default: 0.5000 Min/Max: 0.2500/1.0000 Comm Scale: 1.0 = P.U. Motor to Torque	✓	✓	Real											
130	<b>Torq Ref TP Sel</b> Enter or write a value to select torque reference data displayed in Par 131 [Torq Ref TP Data].	Default: 0 "Zero" Options: 0 "Zero" 16 "Neg Lim Src" 1 "Scale Output" 17 "MPwr Par Lim" 2 "Spd Torque" 18 "RPwr Par Lim" 3 "Trq Mode Out" 19 "+Trq ParLim" 4 "Actv TrqMode" 20 "-Trq ParLim" 5 "Actv Mod Out" 21 "Nom Bus Volt" 6 "Trq En Input" 22 "Bus Volt Hys" 7 "NotchFiltOut" 23 "Bus Reg Ref" 8 "NotchFilt In" 24 "Bus Reg Err" 9 "Trq Lim In" 25 "Bus Reg Intg" 10 "Bus Reg Out" 26 "BusReg Clamp" 11 "Pos Pwr Lim" 27 "BusRegOutput" 12 "Neg Pwr Lim" 28 "IAA Filt Out" 13 "Pos Atun Trq" 29 "IAA dV/dt" 14 "Neg Atun Trq" 30 "MC Trq Lim" 15 "Pos Lim Src" 31 "IqActTrqLim"														
131	<b>Torq Ref TP Data</b> Displays the data selected by Par 130 [Torq Ref TP Sel].	Units: P.U. Default: 0.0000 Min/Max: -/+8.0000 Comm Scale: 1.0 = P.U. Motor to Torque			Real											
132	<b>Inert Adapt Sel</b> Configures the Inertia Adaption Algorithm (IAA Function). Contains the following selections: <table border="1"> <thead> <tr> <th>Bit</th> <th>Name</th> <th>Current Function</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>Inertia Adaption</td> <td>When set to 1 (on), the Inertia Adaption function will effect enhanced stability, higher bandwidths and dynamic stiffness. Useful when systems with a gear-box becomes disconnected from the load. Also used with motors that have very little inertia that otherwise lack dynamic stiffness, even at high bandwidths.</td> </tr> <tr> <td>1</td> <td>Load Estimate</td> <td>When set to 1 (on), the Load Estimate option removes or greatly reduces load disturbances and gives quicker system response.</td> </tr> <tr> <td>0 &amp; 1</td> <td></td> <td>This mode enhances stability as well as removing load disturbances.</td> </tr> </tbody> </table>	Bit	Name	Current Function	0	Inertia Adaption	When set to 1 (on), the Inertia Adaption function will effect enhanced stability, higher bandwidths and dynamic stiffness. Useful when systems with a gear-box becomes disconnected from the load. Also used with motors that have very little inertia that otherwise lack dynamic stiffness, even at high bandwidths.	1	Load Estimate	When set to 1 (on), the Load Estimate option removes or greatly reduces load disturbances and gives quicker system response.	0 & 1		This mode enhances stability as well as removing load disturbances.	Default: 00000000 Min/Max: 00000000/00000011	✓	Real
Bit	Name	Current Function														
0	Inertia Adaption	When set to 1 (on), the Inertia Adaption function will effect enhanced stability, higher bandwidths and dynamic stiffness. Useful when systems with a gear-box becomes disconnected from the load. Also used with motors that have very little inertia that otherwise lack dynamic stiffness, even at high bandwidths.														
1	Load Estimate	When set to 1 (on), the Load Estimate option removes or greatly reduces load disturbances and gives quicker system response.														
0 & 1		This mode enhances stability as well as removing load disturbances.														
133	<b>Inert Adapt BW</b> This parameter sets the bandwidth of the Inertia Adaption function when the IAA function is selected (Par 132, bit 0). Typical IAA bandwidths range from 70 to 150 rad/sec with 100 rad/sec nominal best.  If the Load Estimate (Par 132, bit 1) function is selected, then this parameter sets the natural frequency of a filter in rad/sec. Typical values range from 10 to 150 rad/sec with higher values being more responsive to disturbances but with increased system noise. There is no nominal best value, but 40 rad/sec is a suggested starting point. This adjustment may not function well in 'sloppy' geared systems  If both Inertia Adaption and Load Estimate functions are active, use a bandwidth setting of 100 rad/sec.	Units: R/S Default: 100.0000 Min/Max: 10.0000/250.0000		✓	Real											
134	<b>Inert Adapt Gain</b> This parameter sets a multiplier of system inertia when the Inertia Adaption function is selected (Par 132 bit 0). Higher values may cause high frequency ringing, while smaller values may cause fundamental load instability. A typical value is 0.5 This parameter has no affect on the Load Estimate function.	Default: 0.500 Min/Max: 0.300/1.000		✓	Real											
140	<b>FricComp Spd Ref</b> Supplies a speed input to the Friction Compensation algorithm. This input is normally a speed reference from a motion planner or ramped speed reference. It will trigger a torque feed forward response depending on its value.	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0	✓	✓	Real											
141	<b>FricComp Setup</b> Enter or write a value to configure the friction compensation algorithm. This is a packed word of 3 digits. Each digit has a possible selection of 10 levels. <ul style="list-style-type: none"> <li>The least significant digit sets the speed threshold in intervals of 0.0005 pu speed.</li> <li>The next (middle) digit sets the hysteresis band for the "units" digit in intervals of 0.0005 pu velocity.</li> <li>The most significant digit sets the number of time steps from stick to slip, each step is 0.002 sec.</li> </ul> <p>Example: Fsetup = 524 means: 5 time steps between stick and slip, each of 0.002 sec. duration, 2 counts of hysteresis or 0.001 pu_speed (each count is 0.0005 pu speed), and 4 counts or 0.002 pu_speed is the trigger threshold (each count is 0.0005 pu speed).</p>	Default: 325 Min/Max: 0/999Integer  		✓	16-bit Integer											

No.	Name Description	Values	Linkable	Read-Write	Data Type																												
142	<b>FricComp Stick</b> The torque needed to break away from zero speed. By nature of friction, the break away sticktion will always be greater than the running friction.	Units: P.U. Default: 0.1500 Min/Max: 0.0000/8.0000 Comm Scale: Motor P.U. Torque	✓	✓	Real																												
143	<b>FricComp Slip</b> The torque level to sustain very low speed – once “break away” has been achieved. By nature of friction, viscous friction will always be less than sticktion.	Units: P.U. Default: 0.1000 Min/Max: 0.0000/8.0000 Comm Scale: Motor P.U. Torque	✓	✓	Real																												
144	<b>FricComp Rated</b> The torque needed to a base friction at base motor speed and with no process loading. The friction compensation algorithm assumes a linear or viscous component of friction between [FricComp Slip] and FricComp Rated].	Units: P.U. Default: 0.2000 Min/Max: 0.0000/8.0000 Comm Scale: Motor P.U. Torque	✓	✓	Real																												
145	<b>FricComp TorqAdd</b> The torque reference output of the Friction Compensation function. A value of 1.0 represents rated torque of the motor.	Units: P.U. Default: 0.0000 Min/Max: -/+8.0000 Comm Scale: Motor P.U. Torque			Real																												
150	<b>Logic State Mach</b> Indicates the logical state of the drive.  Value 0- Stopped indicates zero speed has been detected and the speed and torque regulators are disabled.	Default: 0 “Stopped” Options: 0 “Stopped” 4 “Inertia Test” 1 “Starting” 5 “MC Diag” 2 “Running” 6 “Test Done” 3 “Stopping”																															
151	<b>Logic Command</b> The controller-drive interface (as defined by the Controller Communication Format) sets bits to enable and disable various functions and algorithms. Bits that are changed here are reflected in Par 152 [Applied LogicCmd]. Note: Bits 4 through 9 in Logic Command are NOT recalled from Control EEprom. They will be cleared upon drive powerup or following an EEprom recall operation.																																
	Options																																
	Reserved	Reserved	PositionEnbl	ProcsTrim En	Fric Comp	Inertia Comp	Sys Inert En	Mtr Inert En	PM Offset En	Dir Sel En	Pwr Diag En	MC Atune En	Time Axis En	TachLoss Rst	Spd S Crv En	SpdRamp Dsbl																	
Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0 = False															
Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0		1 = True															
152	<b>Applied LogicCmd</b> Displays Logic Command that is applied to the Regulators and Control Algorithms within the drive. Logic Commands come from the 32-bit Logic Command found in a connection with the Logix Controller.																																
	Options																																
	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Coast Stop	CurrLim Stop	Jog 2	Reserved	UniPol Rev	UniPol Fwd	Clear Fault	Jog 1	Start	Normal Stop	Reserved	Reserved	PositionEnbl	ProcsTrim En	Fric Comp	Inertia Comp	Sys Inert En	Mtr Inert En	PM Offset En	Dir Sel En	Pwr Diag En	MC Atune En	Time Axis En	TachLoss Rst	Spd S Crv En	SpdRamp Dsbl	
Default	0	1	0	1	1	0	0	0	0	1	0	0	0	0	1	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0 = False
Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0	1 = True



No.	Name Description	Values																										Linkable	Read-Write	Data Type							
153	<b>Control Options</b>																																				
	Set bits to configure the options for operating the drive.																																				
	Options	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Aux Pwr Sply	Auto Tach Sw	Reserved	Reserved	OL ClsLpDsbl	Jog -NoInteg	Iq Delay	Motor Dir	2W CoastStop	3WireControl	Stop Cndt Tq	Stop in Torq	Jog - NoRamp	Jog in Torq	2WCurLimSip	Sreg LPF 1	SRef Filt En	Bipolar SRef		
Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	1	0	0	0	0	0	0	0	1	0 = False		
Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0	1 = True				

Bit Name	Current Function
0 Bipolar SRef	Uses a bipolar speed reference. Resetting the bit configures for a unipolar speed reference determined by <i>Par 152</i> [Applied LogicCmd]/ bits 20 [UniPol Fwd] and 21 [UniPol Rev].
1 SRef LdLg En	Enables Speed Reference Lead Lag Filter-reset disables
2 SErrFilt1Stg	
4 Jog in Torq	Overrides <i>Par 110</i> [Spd/Torq ModeSel] setting when jog command received
5 Job-NoRamp	Bypasses the Speed Reference Ramp and S-Curve
6 Trq StopRamp	Overrides <i>Par 110</i> [Spd/Torq ModeSel] setting when stopping
7 Trq DsblZSpd	Configures how drive uses stop dwell time
8 3WireControl	Configures for 3-wire control
10 SReg IntgRst	
11 Iq Delay	Enables Torque Current Delay option
12 Jog-NoInteg	Configures speed regulator's integrator to hold when jogging
13 OL ClsLpDsbl	
14 Reserved DM	Reserved for use by the Drive Module for "Invert Speed Feedback"
15 Reserved DM	Reserved for use by the Drive Module for "Invert Motor Torque Current"
16 Auto Tach Sw	
17 Aux Pwr Sply	Enables use of Aux. Power Supply. When set to 1, Main Control Board examines internal 12V DC power to see when energized. When set to 0, examines voltage of DC Bus. This bit enables Main Control Board and DriveLogix Controller to remain energized when 3-Ø voltage is de-energized.
18 SpdRegPreset	
23 Enable	
24 Time Lim En	
25 MC Atune En	
26 MC Atune En	

No.	Name Description	Values	Linkable	Read-Write	Data Type
154	<b>Stop Dwell Time</b> Sets an adjustable delay time between detecting zero speed and disabling the speed and torque regulators, when responding to a stop command. For more information, please see <a href="#">Stop Dwell Time on page E-6</a> . <b>Important:</b> Consult industry and local codes when setting the value of this parameter.	Units: Sec Default: 0.0000 Min/Max: 0.0000/10.0000	✓	✓	Real

Options		Reserved	Reserved	Reserved	Reserved	Reserved	Command Run	Start Active	Position Mode	Speed Mode	Torque Mode	Reserved	Spd Commis	MC Commis	MC En Ack	Above Setpt2	At Setpt 1	Reserved	At Setpt Spd	At Zero Spd	Tach Loss Sw	At Limit	Run Ready	Flash Mode	Alarm	Faulted	Jogging	Decelerating	Accelerating	Actual Dir	Command Dir	Running	Enabled
Default		0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0
Bit		31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
																		0 = False 1 = True															
Bit Name	Current Function																	Bit	Name	Current Function													
0	Enabled	Drive is controlling motor																14	At Setpt Spd	Speed feedback is within limits defined in <i>Par 41</i> and <i>171</i>													
1	Running	Run command received & controlling motor																15	Reserved														
2	Command Dir	Commanded direction is forward																16	At Setpt 1	<i>Par 172</i> value is within limits defined by <i>Par 173</i> and <i>174</i>													
3	Actual Dir	Actual motor direction is forward																17	Above Setpt 2	<i>Par 175</i> value is within limits defined by <i>Par 176</i> and <i>177</i>													
4	Accelerating	Motor is increasing speed																18	MC En Ack	Drive is controlling motor (same as enabled)													
5	Decelerating	Motor is decreasing speed																19	MC Commis	Motor control commissioning in progress													
6	Jogging	Jog command received & controlling motor																20	Spd Commis	Speed control commissioning in progress													
7	Faulted	Exception event that causes a fault has occurred																21	Reserved														
8	Alarm	Exception event that causes an alarm has occurred																22	Torque Mode	<i>Par 110</i> value is 2, 3, 4, 5 or 6													
9	Flash Mode	Flash upgrade in progress																23	Speed Mode	<i>Par 110</i> value is 1 & position control is not enabled													
10	Run Ready	Enable input is high & drive is fault free																24	Position Mode	Position control active & <i>Par 110</i> value is not 2, 3, 4, 5 or 6													
11	At Limit	Speed, Power, Current or Torque is being limited, refer to <i>Par 304</i>																25	Start Active	Start command received & controlling motor													
12	Tach Loss SW	Failure is detected in primary speed or position feedback device & drive has switched to secondary device																26	Command Run	Run command received													
13	At Zero Spd	Speed feedback is within limits defined in <i>Par 160</i>																27-31	Reserved														

Options		Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	PM Mtr Fdbk	Reserved	DigIn Config	Bus PreChrg	Encoder PPR	Jog	Start	Flash Upgrd	Power EE	Power Loss	SW Lim Slip	SW Coast Slip	SW Ramp Stop	No Enable	Faulted
Default		0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	
Bit		31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0	
																		0 = False 1 = True																



Options		ProcsTrim En	Cmd Dir Upol	Lgx I/O Cnx	Lgx Run Mode	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	PM Offset Rq	Mtr Dir Req	Pwr Diag Req	MC Atune Req	Reserved	MC En Req	RThru Flux	DC Brake En	Mtr Sim Mode	RThru Coast	CurrRef En	Forced Spd	Torq Ref En	Spd Reg En	SRReg InHid	SRReg InLHid	J Tst FullSpd	Inert Tst En	PositionEnbl	SRRef SCrv En	SRRef Ramp En	Spd Ref En
Default		0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0
Bit		31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
																		0 = False 1 = True															

No.	Name Description	Values	Linkable	Read-Write	Data Type																																																																																																					
158	<b>Drive Logic Rslt</b> This is the logic output of the logic parser that combines the outputs from the DPI ports and the DriveLogix controller to determine drive control based on the masks and owners. The control bits are reflected in Par 152 [Applied LogicCmd] bits 16-31.  Options <table border="1"> <tr> <td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Coast Stop</td><td>CurrLim Stop</td><td>Jog 2</td><td>Reserved</td><td>UnlPol Rev</td><td>UnlPol Fwd</td><td>Clear Fault</td><td>Jog 1</td><td>Start</td><td>Normal Stop</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Coast Stop</td><td>CurrLim Stop</td><td>Jog 2</td><td>Reserved</td><td>UnlPol Rev</td><td>UnlPol Fwd</td><td>Clear Fault</td><td>Jog 1</td><td>Start</td><td>Normal Stop</td> </tr> <tr> <td>Default</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td> </tr> <tr> <td>Bit</td><td>31</td><td>30</td><td>29</td><td>28</td><td>27</td><td>26</td><td>25</td><td>24</td><td>23</td><td>22</td><td>21</td><td>20</td><td>19</td><td>18</td><td>17</td><td>16</td><td>15</td><td>14</td><td>13</td><td>12</td><td>11</td><td>10</td><td>9</td><td>8</td><td>7</td><td>6</td><td>5</td><td>4</td><td>3</td><td>2</td><td>1</td><td>0</td> </tr> </table>	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Coast Stop	CurrLim Stop	Jog 2	Reserved	UnlPol Rev	UnlPol Fwd	Clear Fault	Jog 1	Start	Normal Stop	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Coast Stop	CurrLim Stop	Jog 2	Reserved	UnlPol Rev	UnlPol Fwd	Clear Fault	Jog 1	Start	Normal Stop	Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0				0 = False 1 = True		
Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Coast Stop	CurrLim Stop	Jog 2	Reserved	UnlPol Rev	UnlPol Fwd	Clear Fault	Jog 1	Start	Normal Stop	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Coast Stop	CurrLim Stop	Jog 2	Reserved	UnlPol Rev	UnlPol Fwd	Clear Fault	Jog 1	Start	Normal Stop																																																																										
Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0																																																																										
Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0																																																																										
159	<b>DigIn ConfigStat</b> This parameter indicates the status of the Digital Inputs.	Default: 0 "DigIn Ok" Options: 0 "DigIn Ok" 4 "Strt+UnLatch" 1 "2 Run/Starts" 5 "2 Jog1's" 2 "Start NoStop" 6 "2 Jog2's" 3 "Run+Latched" 7 "2 FwdRevs's"																																																																																																								
160	<b>Zero Speed Lim</b> Establishes a band around zero speed that is used to determine when the drive considers the motor to be at zero speed.	Units: RPM Default: 17.6400 Min/Max: 0.0000/882.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0	✓	✓	Real																																																																																																					
161	<b>Logic TP Sel</b> Enter or write a value to select logic status indication displayed in Par 162 [Logic TP Data].	Default: 0 "Reserved" Options: 0 "Reserved" 15 "2ms time" 1 "Avg Spd Ref" 16 "2ms max" 2 "Avg Spd Fdbk" 17 "8ms time" 3 "LastStopMode" 18 "8ms max" 4 "Spd Ref Sel" 19 "BkGnd Time" 5 "Start State" 20 "BkGnd Max" 6 "Run State" 21 "500us %" 7 "Stop State" 22 "2ms %" 8 "PrChrg Logic" 23 "8ms %" 9 "Meas State" 24 "BkGnd %" 10 "Data State" 25 "RThru State" 11 "Diag State" 26 "RThru Timer" 12 "MC CalcState" 27 "Mtr Friction" 13 "500us time" 28 "Sys Friction" 14 "500us max" 29 "Iq proc time"																																																																																																								
162	<b>Logic TP Data</b> Displays the indication selected by Par 161 [Logic TP Sel].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real																																																																																																					
163	<b>Stop Oper TP Sel</b> Enter or write a value to select data displayed in Par 164 [StpOper TPData] at the time of the last initiated stop.	Default: 0 "Zero" Options: 0 "Zero" 14 "ZM1 Spd Fdbk" 1 "Logic State" 15 "Speed Ref" 2 "Logic Input" 16 "Avg Spd Ref" 3 "Lcl In State" 17 "ZM1 Spd Ref" 4 "Logic Status" 18 "SReg PI Out" 5 "Run Inhibit" 19 "Torq Ref" 6 "Logic Ctrl" 20 "TorqRef Stat" 7 "Mtr Ctrl Cmd" 21 "DC Bus Volts" 8 "Mtr Ctrl Ack" 22 "Motor Volts" 9 "Reserved" 23 "Mtr Current" 10 "Flt Status 1" 24 "Motor Flux" 11 "Flt Status 2" 25 "Motor Freq" 12 "Motor Speed" 26 "Motor Power" 13 "Avg Spd Fdbk" 27 "Flt Status 3"																																																																																																								
164	<b>StopOper TP Data</b> Displays the data selected by Par 163 [Stop Oper TP Sel].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real																																																																																																					
165	<b>Test Status</b> Indicates which test (if any) is in progress.	Default: 0 "None" Options: 0 "None" 4 "PM Offset" 1 "MC Autotune" 5 "Mtr Inertia" 2 "Power Diag" 6 "Sys Inertia" 3 "Motor Direct" 7 "Mtr+Sys J"																																																																																																								
166	<b>Motor Ctrl Cmmnd</b> Displays the command bits to the Motor Control Processor from the Velocity Processor.	Options <table border="1"> <tr> <td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Base Block</td><td>Reserved</td><td>Reserved</td><td>Torque Run</td><td>Flux Run</td><td>CP Enable</td> </tr> <tr> <td>Default</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td> </tr> <tr> <td>Bit</td><td>31</td><td>30</td><td>29</td><td>28</td><td>27</td><td>26</td><td>25</td><td>24</td><td>23</td><td>22</td><td>21</td><td>20</td><td>19</td><td>18</td><td>17</td><td>16</td><td>15</td><td>14</td><td>13</td><td>12</td><td>11</td><td>10</td><td>9</td><td>8</td><td>7</td><td>6</td><td>5</td><td>4</td><td>3</td><td>2</td><td>1</td><td>0</td> </tr> </table>	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Base Block	Reserved	Reserved	Torque Run	Flux Run	CP Enable	Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0			0 = False 1 = True
Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Base Block	Reserved	Reserved	Torque Run	Flux Run	CP Enable																																																																									
Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0																																																																									
Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0																																																																										

No.	Name Description	Values	Linkable	Read-Write	Data Type
167	<b>Motor Ctrl Ackn</b> Displays the Motor Control Processor's acknowledgment to the Velocity Processor for the Motor Control Command bits.	Options Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Fault Reset Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Power Diag Precharge Torque Run Flux Run CP Enable Default 0 Bit 31 30 29 28 27 26 25 24 23 22 21 20 19 18 17 16 15 14 13 12 11 10 9 8 7 6 5 4 3 2 1 0			0 = False 1 = True
169	<b>SrLss ZeroSpdLim</b> Functionally equivalent to Par 160, but is used exclusively in Sensorless speed mode. The value is automatically set from Par 3 [Motor NP Hertz], Par 4 [Motor NP RPM] or Par 7 [Motor Poles]. The automatic setting corresponds to the rated slip speed of the motor (synchronous speed - nameplate speed). The value can be manually set.	Units: RPM Default: 49.9975 Min/Max: 0.0000/875.0000		✓	Real
171	<b>Set Speed Lim</b> Creates a tolerance - hysteresis band around the value in Par 41 [Limited Spd Ref] for comparison to average speed feedback. The comparison controls bit 14 [At Setpt Spd] of Par 155 [Logic Status]. In general bit 14 [At Setpt Spd] turns on when the feedback is within the tolerance of the reference. Technically - Turn-on level for rising feedback = Limited Spd Ref - Limit. Turn-off level for rising feedback = Limited Spd Ref + 2(Limit). Turn-on level for falling feedback = Limited Spd Ref + Limit. Turn-off level for falling feedback = Limited Spd Ref - 2(Limit).	Units: RPM Default: 17.6400 Min/Max: 0.0000/882.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0		✓	Real
172	<b>Setpt 1 Data</b> Provides data for comparison to Par 173 [Setpt1 TripPoint], driving bit 16 [At Setpt 1] of Par 155 [Logic Status]. For more information, please see <a href="#">Setpt 1 Data on page E-7</a> .	Units: P.U. Default: 0.0000 Min/Max: +/-8.0000		✓	Real
173	<b>Setpt1 TripPoint</b> Provides the midpoint for operation of bit 16 [At Setpt 1] of Par 155 [Logic Status].	Units: P.U. Default: 0.1000 Min/Max: +/-8.0000		✓	Real
174	<b>Setpt 1 Limit</b> Creates a tolerance - hysteresis band around the value in Par 173 [Setpt1 TripPoint]. Turn-on level for ascending data = TripPoint - Limit. Turn-off level for ascending data = TripPoint + 2(Limit). Turn-on level for descending data = TripPoint + Limit. Turn-off level for descending data = TripPoint - 2(Limit).	Units: P.U. Default: 0.0100 Min/Max.: 0.0000/0.5000		✓	Real
175	<b>Setpt 2 Data</b> Provides data for comparison to Par 177 [Setpt2 TripPoint], driving bit 17 [Above Setpt 2] of Par 155 [Logic Status]. For more information, please see <a href="#">Setpt 2 Data on page E-8</a> .	Units: P.U. Default: 0.0000 Min/Max: +/-8.0000		✓	Real
176	<b>Setpt2 TripPoint</b> Provides the midpoint for operation of bit 16 [At Setpt 1] of Par 155 [Logic Status].	Units: P.U. Default: 0.2000 Min/Max: +/-8.0000		✓	Real
177	<b>Setpt 2 Limit</b> Creates a tolerance - hysteresis band around the value in Par 176 [Setpt2 TripPoint]. For positive setpoints: Turn-on level = TripPoint, Turn-off level = TripPoint - Limit. For negative setpoints: Turn-on level = TripPoint, Turn-off level = TripPoint + Limit.	Units: P.U. Default: 0.0100 Min/Max: 0.0000/0.5000		✓	Real
180	<b>PI Output</b> The final output of the Process Control regulator. A value of 1 can represent either base motor speed, motor rated torque, or 100% for some external function.	Units: P.U. Default: 0.0000 Min/Max: +/-8.0000			Real
181	<b>PI Reference</b> The reference input for the process control regulator. A value of 1 can represent either base motor speed, motor rated torque, or 100% for some external function.	Units: P.U. Default: 0.0000 Min/Max: +/-8.0000		✓	Real
182	<b>PI Feedback</b> The feedback input for the process control regulator. A value of 1 can represent either base motor speed, motor rated torque, or 100% for some external function.	Units: P.U. Default: 0.0000 Min/Max: +/-8.0000		✓	Real
183	<b>PI Command</b> Set bits to configure the process control regulator -enable or disable the regulator, enable or disable the time function generator and limit generator.	Options Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Time Lim En Enable Default 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 Bit 15 14 13 12 11 10 9 8 7 6 5 4 3 2 1 0	0 = False 1 = True		
184	<b>PI Lpass Filt BW</b> Sets the bandwidth of a single pole filter applied to the error input of the Process Control regulator. The input to the filter is the difference between Par 181 [PI Reference] and Par 182 [PI Feedback]. The output of this filter is used as the input to the process control regulator.	Units: R/S Default: 0.0000 Min/Max: 0.0000/500.0000		✓	Real
185	<b>PI Preload</b> Presets the integrator of the Process Control regulator.	Units: P.U. Default: 0.0000 Min/Max: +/-8.0000		✓	Real

No.	Name Description	Values	Linkable	Read-Write	Data Type
186	<b>PI Prop Gain</b> Controls the proportional gain of the Process Control regulator. If the proportional gain is 1.0, the regulator output equals 1 pu for 1 pu error.	Default: 8.0000 Min/Max: 0.0000/200.0000	✓	✓	Real
187	<b>PI Integ Time</b> Controls the integral gain of the Process Control regulator. If the integrator time is 1.0, the regulator output equals 1 pu in 1 second for 1 pu error.	Units: /Sec Default: 8.0000 Min/Max: 0.0000/4000.0000	✓	✓	Real
188	<b>PI Integ HLim</b> The high limit of the integral gain channel for the Process Control regulator. A value of 1 can represent either base motor speed, motor rated torque, or 100% for some external function.	Units: P.U. Default: 0.1000 Min/Max: 0.0000/8.0000	✓	✓	Real
189	<b>PI Integ LLim</b> The low limit of the integral gain channel for the Process Control regulator. A value of 1 can represent either base motor speed, motor rated torque, or 100% for some external function.	Units: P.U. Default: -0.1000 Min/Max: -8.0000/0.0000	✓	✓	Real
190	<b>PI Integ Output</b> Displays the output value of the integral channel of the Process Control regulator. A value of 1 can represent either base motor speed, motor rated torque, or 100% for some external function.	Units: P.U. Default: 0.0000 Min/Max: +/-8.0000			Real
191	<b>PI High Limit</b> The high limit of the Process Control regulator output. A value of 1 can represent either base motor speed, motor rated torque, or 100% for some external function.	Units: P.U. Default: 0.1000 Min/Max: 0.0000/8.0000	✓	✓	Real
192	<b>PI Lower Limit</b> The low limit of the Process Control regulator output. A value of 1 can represent either base motor speed, motor rated torque, or 100% for some external function.	Units: P.U. Default: -0.1000 Min/Max: -8.0000/0.0000	✓	✓	Real
193	<b>PI TP Sel</b> Enter or write a value to select Process Control PI data displayed by Par 194 [PI TP Data].	Default: 0 "Zero" Options: 0 "Zero" 6 "On Out Limit" 1 "PI Error" 7 "Extern Hold" 2 "LPF Output" 8 "Hold Status" 3 "P Gain Term" 9 "Enbl Status" 4 "Reg Output" 10 "Time Axis En" 5 "On Intg Lim"			
194	<b>PI TP Data</b> Displays the data selected by Par 193 [PI TP Sel].	Units: P.U. Default: 0.0000 Min/Max: +/-8.0000			Real
200	<b>Time Axis Rate</b> Sets rate (1/sec) for the Time Function Generator to ramp from and output of 0 to 1 and from 1 to 0.	Units: /Sec Default: 1.0000 Min/Max: 0.0100/20.0000	✓	✓	Real
201	<b>Time Axis Output</b> The output of the Time Function Generator. When the Time Function Generator is enabled by Par 183 [PI Command] bit 1 or Par 151 [Logic Command] bit 3, the value of this parameter ramps from 0 to 1 at a rate determined by Par 200 [Time Axis Rate]. Conversely, when the Function Generator is disabled, the value of this parameter ramps from 1 to 0.	Default: 0.0000 Min/Max: 0.0000/1.0000			Real
204	<b>LimGen Y axis Mx</b> Sets Par 207 [Limit Gen Hi Out] and Par 208 [Limit Gen Lo Out] when the absolute value of Par 206 [LimGen X axis in] is greater than or equal to 1.	Units: P.U. Default: 0.2500 Min/Max: 0.0000/8.0000	✓	✓	Real
205	<b>LimGen Y axis Mn</b> Sets Par 207 [Limit Gen Hi Out] and Par 208 [Limit Gen Lo Out] when the absolute value of Par 206 [LimGen X axis in] is equal to 0.	Units: P.U. Default: 0.0500 Min/Max: 0.0000/8.0000	✓	✓	Real
206	<b>LimGen X axis In</b> The x axis input to the Limit Generator. Typically this parameter is linked to a speed reference or to Par 201 [Time Axis Output].	Default: 0.0000 Min/Max: +/-8.0000	✓	✓	Real
207	<b>Limit Gen Hi Out</b> Displays the positive output of the Limit Generator. When Par 206 [Limit Gen X Axis In] is greater than or equal to 1, this value equals Par 204 [Limit Gen Y axis Mx]. When Par 206 [Limit Gen X Axis In] is equal to 0, this value equals Par 205 [Limit Gen Y axis Mn]. For values of x Axis input between 0 and 1, the value of this parameter is interpolated from Y axis min and max values. Typically it is linked to Par 188 [PI High Limit].	Units: P.U. Default: 8.0000 Min/Max: 0.0000/8.0000			Real
208	<b>Limit Gen Lo Out</b> Displays the negative output of the Limit Generator. The value of this parameter is the negative of Par 207 [Limit Gen Hi Out]. Typically it is linked to Par 189 [PI Lower Limit].	Units: P.U. Default: -8.0000 Min/Max: -8.0000/0.0000			Real

No.	Name Description	Values	Linkable	Read-Write	Data Type																																																					
210	<b>PeakDct Ctrl In</b> Sets configuration of the two peak/level detectors. <ul style="list-style-type: none"> <li>• Set mode is a level detector which causes the output to match the preset when the set bit is set.</li> <li>• Hold mode is a level detector which causes the output to hold its present min/max.</li> <li>• Regular peak detection (when set and hold are off) causes the output to capture the peak min/max.</li> <li>• Sel determines if the peak/level detector is positive or negative. If the bit is set the detector detects positive peaks or levels above the preset. If the bit is not set the detector detects "valleys" or levels below the preset. The output shows the min or max peak.</li> </ul>	<table border="1"> <tr> <td>Options</td> <td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Peak 2 Sel</td><td>Peak 2 Hold</td><td>Peak 2 Set</td><td>Reserved</td><td>Peak 1 Sel</td><td>Peak 1 Hold</td><td>Peak 1 Set</td> </tr> <tr> <td>Default</td> <td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td> </tr> <tr> <td>Bit</td> <td>15</td><td>14</td><td>13</td><td>12</td><td>11</td><td>10</td><td>9</td><td>8</td><td>7</td><td>6</td><td>5</td><td>4</td><td>3</td><td>2</td><td>1</td><td>0</td> </tr> </table> <p>0 = False 1 = True</p>	Options	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Peak 2 Sel	Peak 2 Hold	Peak 2 Set	Reserved	Peak 1 Sel	Peak 1 Hold	Peak 1 Set	Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0			
Options	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Peak 2 Sel	Peak 2 Hold	Peak 2 Set	Reserved	Peak 1 Sel	Peak 1 Hold	Peak 1 Set																																									
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Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0																																										
211	<b>Peak Ctrl Status</b> Status of peak/level detectors. A peak detector sets its bit when it detects a peak or when its input exceeds its preset - depending on mode.	<table border="1"> <tr> <td>Options</td> <td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Reserved</td><td>Peak 2 Chng</td><td>Peak 1 Chng</td> </tr> <tr> <td>Default</td> <td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td> </tr> <tr> <td>Bit</td> <td>15</td><td>14</td><td>13</td><td>12</td><td>11</td><td>10</td><td>9</td><td>8</td><td>7</td><td>6</td><td>5</td><td>4</td><td>3</td><td>2</td><td>1</td><td>0</td> </tr> </table> <p>0 = False 1 = True</p>	Options	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Peak 2 Chng	Peak 1 Chng	Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0					
Options	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Peak 2 Chng	Peak 1 Chng																																										
Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0																																										
Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0																																										
212	<b>PeakDct1 In Int</b> Integer input to the first peak/level detector.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer																																																					
213	<b>PkDct1 In Real</b> Floating point input to the first peak/level detector	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real																																																					
214	<b>PeakDct1 Preset</b> The first detector (in set or hold modes) compares this value to its input for level detection. When the detector trips (in set mode) it transfers the value of this parameter to its output.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real																																																					
215	<b>PeakDetect1 Out</b> Output from the first peak/level detector.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real																																																					
216	<b>PeakDct2 In Int</b> Integer input to second peak/level detector.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer																																																					
217	<b>PkDct2 In Real</b> Floating point input to second peak/level detector	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real																																																					
218	<b>PeakDct2 Preset</b> The second detector (in set or hold modes) compares this value to its input for level detection. When the detector trips (in set mode) it transfers the value of this parameter to its output.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real																																																					
219	<b>PeakDetect2 Out</b> Output from the second peak/level detector.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real																																																					
220	<b>Spd Observer BW</b> Sets the internal bandwidth for the speed feedback observer. The setting should be as high a possible, preferably at least 6 times the value of Par 90 [Spd Reg BW]. A setting of 1000 rad/sec is reasonable for most applications. The speed observer is bypassed when set to zero.	Units: R/S Default: 0.0000 Min/Max: 0.0000/1200.0000	✓	✓	Real																																																					
221	<b>Load Estimate</b> Displays the estimated load torque, which is the side effect of the speed observer and does not include torque to accelerate or decelerate the motor if the inertia input is correct. The value is provided for display purposes.	Units: P.U. Default: 0.0000 Min/Max: -/+8.0000			Real																																																					
222	<b>Motor Fdbk Sel</b> Enter or write a value to select the primary motor speed feedback device.	Default: 0 "Encoder 0" Options: 0 "Encoder 0" 4 "Motor Sim" 1 "Encoder 1" 5 "FB Opt Port0" 2 "Sensorless" 6 "FB Opt Port1" 3 "Reserved"																																																								
223	<b>Mtr Fdbk Alt Sel</b> Selects alternate feedback device if the feedback selected from Par 122 fails.	Default: 0 "Encoder 0" Options: 0 "Encoder 0" 4 "Motor Sim" 1 "Encoder 1" 5 "FB Opt Port0" 2 "Sensorless" 6 "FB Opt Port1" 3 "Reserved"																																																								

No.	Name Description	Values	Linkable	Read-Write	Data Type
224	<b>TachSwitch Level</b> Sets the detection level for the automatic tach loss switchover routine. A drop in feedback speed at this percent of rated speed over 0.5 msec will cause a tach switch from primary to alternate feedback device. This feature is enabled when bit 16 'Auto Tach Sw' in Par 153 [Control Options] is selected.  Setting this level lower will make the tach switch detection more sensitive and lower the minimum speed at which a tach switch can occur. Setting this level higher will make the tach switch less sensitive and raise the minimum speed for tach switch detection.	Units: % Default: 10.0000 Min/Max: 5.0000/25.0000		✓	
226	 <b>Virtual Edge/Rev</b> Set the EPR (Edges Per Revolution) scaling for calculating motor position. Used in the calculation of the position feedback such as Par 70 [MtrSpd Sim Pos].	Units: EPR Default: 4096 Min/Max: 10/16777216		✓	32-bit Integer
227	<b>Spd Obs Trq Gain</b> Multiplication factor for the inertia input to the Speed Observer. If the specified inertia differs from actual, this is used to fine tune the inertia value input to the observer. Normally set to 1.	Default: 1.0000 Min/Max: 0.0000/2.0000	✓	✓	Real
230	<b>Encdr0 Position</b> Displays the position feedback (accumulator) from encoder 0. The value changes by a value of 4 times the Pulses Per Revolution (PPR) rating of the encoder for each full revolution of the encoder shaft. Used by the VPL to close the position loop if the position control is selected.	Default: 0 Min/Max: -/+2147483648			32-bit Integer
231	<b>Encdr0 Spd Fdbk</b> Displays the speed feedback from encoder 0. Calculated from the change of Par 230 [Encdr0 Position] and Par 232 [Encoder0 PPR].	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0			Real
232	 <b>Encoder0 PPR</b> Sets the pulse per revolution rating of the feedback device connected to the Encoder 0 input.	Units: PPR Default: 1024 Min/Max: 10/20000		✓	16-bit Integer

No.	Name Description	Values	Linkable	Read-Write	Data Type																																																																																																																																																																																																																																																																																																																																															
233	<p><b>Encdr0 Config</b> Specifies the configuration options for the encoder 0.</p> <ul style="list-style-type: none"> <li>Bits 0 [Encdr Filt 0], 1 [Encdr Filt 1], 2 [Encdr Filt 2], and 3 [Encdr Filt 3] configure encoder input filter (see Table 233A). The filter requires the input signal to be stable for the specified time period. Input transitions within the filter time setting will be ignored.</li> <li>Bits 4 [Encdr 4x] and 5 [Encdr A Phs] determine how the encoder channel A and B signals will be interpreted. Typically, both encoder phases A and B are used so that direction information is available. The Par 230 [Encdr0 Position] counts up for forward rotation and down for reverse rotation. If bit 5 is set, then the B phase signal is ignored. As a result, the encoder position will only increase, regardless of rotation direction. Bits 4 and 5 together also determine the number of edges counted per encoder pulse (see Table 233B). "4x" sampling counts both rise and fall of both A and B encoder phases, hence 4 edges per pulse. In 4x mode, the encoder position will change by four times the encoder pulses per revolution rating (PPR) per encoder revolution (e.g., it increments the value in Par 230 [Encdr0 Position] by 4096 for one revolution of a 1024 PPR encoder).</li> <li>Bit 6 [Encdr Dir] inverts the channel A input, thus reversing the direction of the feedback.</li> <li>Bit 9 [Edge Time] configures the method of sampling used by the Velocity Position Loop (VPL). Setting the bit chooses "Edge to Edge" sampling, while resetting the bit to zero chooses "Simple Difference" sampling. "Simple Difference" sampling calculates speed by examining the difference between pulse counts over a fixed sample time. "Edge to Edge" sampling adjusts the sample time to synchronize with the position count updates from the daughter card - improving the accuracy of the speed calculation.</li> <li>Bits 12 [SmplRate bit0] through 15 [SmplRate bit3] configure the sample interval for measuring speed (see Table 233C). Increasing the encoder sample interval improves speed measurement near zero speed. Decreasing allows the speed control regulator to perform with high gains at high speeds.</li> </ul> <p>Options</p> <table border="1"> <thead> <tr> <th></th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>SmplRate bit3</th> <th>SmplRate bit2</th> <th>SmplRate bit1</th> <th>SmplRate bit0</th> <th>Reserved</th> <th>Reserved</th> <th>Edge Time</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Encdr Dir</th> <th>Encdr A Phs</th> <th>Encdr 4x</th> <th>Encdr Filt 3</th> <th>Encdr Filt 2</th> <th>Encdr Filt 1</th> <th>Encdr Filt 0</th> </tr> </thead> <tbody> <tr> <td>Default</td> <td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>1</td><td>0</td><td>0</td><td>0</td><td>1</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>1</td><td>1</td><td>0</td><td>1</td><td>0</td> </tr> <tr> <td>Bit</td> <td>31</td><td>30</td><td>29</td><td>28</td><td>27</td><td>26</td><td>25</td><td>24</td><td>23</td><td>22</td><td>21</td><td>20</td><td>19</td><td>18</td><td>17</td><td>16</td><td>15</td><td>14</td><td>13</td><td>12</td><td>11</td><td>10</td><td>9</td><td>8</td><td>7</td><td>6</td><td>5</td><td>4</td><td>3</td><td>2</td><td>1</td><td>0</td> </tr> </tbody> </table> <p>0 = False 1 = True</p> <p>Bits 0-3, please refer to <a href="#">Table 233A: Encoder Input Filter Settings</a>. Bits 4 and 5, please refer to <a href="#">Table 233B: Multiplier and Direction Settings</a>. Bits 12-15, please refer to <a href="#">Table 233C: Encoder Sample Interval Settings</a>.</p> <table border="1"> <caption>Table 233A: Encoder Input Filter Settings</caption> <thead> <tr> <th>Bit</th> <th>3</th> <th>2</th> <th>1</th> <th>0</th> <th>Encoder Bit Filter Settings</th> </tr> </thead> <tbody> <tr><td></td><td>0</td><td>0</td><td>0</td><td>0</td><td>Filter disabled</td></tr> <tr><td></td><td>0</td><td>0</td><td>0</td><td>1</td><td>100 ns filter</td></tr> <tr><td></td><td>0</td><td>0</td><td>1</td><td>0</td><td>200 ns filter</td></tr> <tr><td></td><td>0</td><td>0</td><td>1</td><td>1</td><td>300 ns filter</td></tr> <tr><td></td><td>0</td><td>1</td><td>0</td><td>0</td><td>400 ns filter</td></tr> <tr><td></td><td>0</td><td>1</td><td>0</td><td>1</td><td>500 ns filter</td></tr> <tr><td></td><td>0</td><td>1</td><td>1</td><td>0</td><td>600 ns filter</td></tr> <tr><td></td><td>0</td><td>1</td><td>1</td><td>1</td><td>700 ns filter</td></tr> <tr><td></td><td>1</td><td>0</td><td>0</td><td>0</td><td>800 ns filter (default setting)</td></tr> <tr><td></td><td>1</td><td>0</td><td>0</td><td>1</td><td>900 ns filter</td></tr> <tr><td></td><td>1</td><td>0</td><td>1</td><td>0</td><td>1000 ns filter</td></tr> <tr><td></td><td>1</td><td>0</td><td>1</td><td>1</td><td>1100 ns filter</td></tr> <tr><td></td><td>1</td><td>1</td><td>0</td><td>0</td><td>1200 ns filter</td></tr> <tr><td></td><td>1</td><td>1</td><td>0</td><td>1</td><td>1300 ns filter</td></tr> <tr><td></td><td>1</td><td>1</td><td>1</td><td>0</td><td>1400 ns filter</td></tr> <tr><td></td><td>1</td><td>1</td><td>1</td><td>1</td><td>1500 ns filter</td></tr> </tbody> </table> <table border="1"> <caption>Table 233B: Multiplier and Direction Settings</caption> <thead> <tr> <th>Bit</th> <th>5</th> <th>4</th> <th>Mult</th> <th>Directions</th> <th>Comments</th> </tr> </thead> <tbody> <tr><td></td><td>0</td><td>0</td><td>2x</td><td>fwd/rev</td><td>Counts rise/fall of phase A, phase B only used to find direction</td></tr> <tr><td></td><td>0</td><td>1</td><td>4x</td><td>fwd/rev</td><td>Counts rise/fall of both A and B phases (default setting)</td></tr> <tr><td></td><td>1</td><td>0</td><td>1x</td><td>fwd only</td><td>Counts rise of phase A. Phase B ignored.</td></tr> <tr><td></td><td>1</td><td>1</td><td>2X</td><td>fwd only</td><td>Counts rise of phase A. Phase B ignored.</td></tr> </tbody> </table> <table border="1"> <caption>Table 233C: Encoder Sample Interval Settings</caption> <thead> <tr> <th>Bit</th> <th>15</th> <th>14</th> <th>13</th> <th>12</th> <th>Encoder Sample Interval Settings</th> </tr> </thead> <tbody> <tr><td></td><td>0</td><td>0</td><td>0</td><td>0</td><td>0.5 ms</td></tr> <tr><td></td><td>0</td><td>0</td><td>0</td><td>1</td><td>0.5 ms (min. setting)</td></tr> <tr><td></td><td>0</td><td>0</td><td>1</td><td>0</td><td>1.0 ms</td></tr> <tr><td></td><td>0</td><td>0</td><td>1</td><td>1</td><td>1.5 ms</td></tr> <tr><td></td><td>0</td><td>1</td><td>0</td><td>0</td><td>2.0 ms (default setting)</td></tr> <tr><td></td><td>0</td><td>1</td><td>0</td><td>1</td><td>2.5 ms</td></tr> <tr><td></td><td>0</td><td>1</td><td>1</td><td>0</td><td>3.0 ms</td></tr> <tr><td></td><td>0</td><td>1</td><td>1</td><td>1</td><td>3.5 ms</td></tr> <tr><td></td><td>1</td><td>0</td><td>0</td><td>0</td><td>4.0 ms</td></tr> <tr><td></td><td>1</td><td>0</td><td>0</td><td>1</td><td>4.5 ms</td></tr> <tr><td></td><td>1</td><td>0</td><td>1</td><td>0</td><td>5.0 ms</td></tr> <tr><td></td><td>1</td><td>0</td><td>1</td><td>1</td><td>5.5 ms</td></tr> <tr><td></td><td>1</td><td>1</td><td>0</td><td>0</td><td>6.0 ms (max. setting)</td></tr> <tr><td></td><td>1</td><td>1</td><td>0</td><td>1</td><td>6.0 ms</td></tr> <tr><td></td><td>1</td><td>1</td><td>1</td><td>0</td><td>6.0 ms</td></tr> <tr><td></td><td>1</td><td>1</td><td>1</td><td>1</td><td>6.0 ms</td></tr> </tbody> </table>		Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	SmplRate bit3	SmplRate bit2	SmplRate bit1	SmplRate bit0	Reserved	Reserved	Edge Time	Reserved	Reserved	Reserved	Encdr Dir	Encdr A Phs	Encdr 4x	Encdr Filt 3	Encdr Filt 2	Encdr Filt 1	Encdr Filt 0	Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	1	0	0	0	1	0	0	0	0	0	1	1	0	1	0	Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0	Bit	3	2	1	0	Encoder Bit Filter Settings		0	0	0	0	Filter disabled		0	0	0	1	100 ns filter		0	0	1	0	200 ns filter		0	0	1	1	300 ns filter		0	1	0	0	400 ns filter		0	1	0	1	500 ns filter		0	1	1	0	600 ns filter		0	1	1	1	700 ns filter		1	0	0	0	800 ns filter (default setting)		1	0	0	1	900 ns filter		1	0	1	0	1000 ns filter		1	0	1	1	1100 ns filter		1	1	0	0	1200 ns filter		1	1	0	1	1300 ns filter		1	1	1	0	1400 ns filter		1	1	1	1	1500 ns filter	Bit	5	4	Mult	Directions	Comments		0	0	2x	fwd/rev	Counts rise/fall of phase A, phase B only used to find direction		0	1	4x	fwd/rev	Counts rise/fall of both A and B phases (default setting)		1	0	1x	fwd only	Counts rise of phase A. Phase B ignored.		1	1	2X	fwd only	Counts rise of phase A. Phase B ignored.	Bit	15	14	13	12	Encoder Sample Interval Settings		0	0	0	0	0.5 ms		0	0	0	1	0.5 ms (min. setting)		0	0	1	0	1.0 ms		0	0	1	1	1.5 ms		0	1	0	0	2.0 ms (default setting)		0	1	0	1	2.5 ms		0	1	1	0	3.0 ms		0	1	1	1	3.5 ms		1	0	0	0	4.0 ms		1	0	0	1	4.5 ms		1	0	1	0	5.0 ms		1	0	1	1	5.5 ms		1	1	0	0	6.0 ms (max. setting)		1	1	0	1	6.0 ms		1	1	1	0	6.0 ms		1	1	1	1	6.0 ms				
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234	<p><b>Encdr0 Error</b> Indicates the error status of the encoder 0.</p> <p>Options</p> <table border="1"> <thead> <tr> <th></th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Phase Level</th> <th>Phase Loss</th> <th>Quad Loss</th> <th>Encdr Missing</th> </tr> </thead> <tbody> <tr> <td>Default</td> <td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td> </tr> <tr> <td>Bit</td> <td>31</td><td>30</td><td>29</td><td>28</td><td>27</td><td>26</td><td>25</td><td>24</td><td>23</td><td>22</td><td>21</td><td>20</td><td>19</td><td>18</td><td>17</td><td>16</td><td>15</td><td>14</td><td>13</td><td>12</td><td>11</td><td>10</td><td>9</td><td>8</td><td>7</td><td>6</td><td>5</td><td>4</td><td>3</td><td>2</td><td>1</td><td>0</td><td></td><td></td><td></td><td></td> </tr> </tbody> </table> <p>0 = False 1 = True</p>		Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Phase Level	Phase Loss	Quad Loss	Encdr Missing	Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0																																																																																																																																																																																																																																							
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235	<p><b>Port0 Regis Latch</b> Displays the registration data of port 0. Indicates the position reference counter value latched by the external strobes. The strobe signal used to trigger the latch is configurable by Par 236 [Port0 Regis Cnfg].</p>	Default: 0 Min/Max: +/-2147483648			32-bit Integer																																																																																																																																																																																																																																																																																																																																															



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236	<p><b>Port0 Regis Cnfg</b> Configures the registration latch at port 0.</p> <ul style="list-style-type: none"> <li>Bit 0 [RL Encdr1 Sel] selects the encoder for the input source of latched data. Setting bit 0 selects encoder 1, resetting the bit to zero selects encoder 0.</li> <li>Bits 1 [RL Trig Src0] and 2 [RL Trig Src1] select the trigger source (see Table 236A).</li> <li>Bits 3 [RL Trig Edg0] and 4 [RL Trig Edg1] select which edges signal the the position (see Table 236B).</li> <li>Bits 5 [RL Dir Rev] and 6 [RL Dir Fwd] set the direction of position capture (see Table 236C).</li> <li>Bits 8 [Ext Filt 1], 9 [Ext Filt 2], 10 [Ext Filt 3], and 11 [Ext Filt 4] configure a filter for for the digital input 1 and 2 (see Table 236D). The filter requires the input signal to be stable for the specified time period. Input transitions within the filter time setting will be ignored.</li> </ul>																																																																																																																															
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	<p><b>Table 236A: Trigger Source Settings</b></p> <table border="1"> <thead> <tr> <th>Bit</th><th>2</th><th>1</th><th>Description</th> </tr> </thead> <tbody> <tr> <td>0</td><td>0</td><td>Digital Input 2 AND Encoder 0 (Primary Encoder) Z Phase</td> </tr> <tr> <td>0</td><td>1</td><td>Digital Input 3 (default setting)</td> </tr> <tr> <td>1</td><td>0</td><td>Digital Input 2</td> </tr> <tr> <td>1</td><td>1</td><td>Encoder 0 (Primary Encoder) Z Phase</td> </tr> </tbody> </table>	Bit	2	1	Description	0	0	Digital Input 2 AND Encoder 0 (Primary Encoder) Z Phase	0	1	Digital Input 3 (default setting)	1	0	Digital Input 2	1	1	Encoder 0 (Primary Encoder) Z Phase	<p><b>Table 236D: Filter Settings</b></p> <table border="1"> <thead> <tr> <th>Bit</th><th>11</th><th>10</th><th>9</th><th>8</th><th>Input Filter Setting</th> </tr> </thead> <tbody> <tr> <td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>Filter disabled</td> </tr> <tr> <td>0</td><td>0</td><td>0</td><td>1</td><td>1</td><td>100 ns filter</td> </tr> <tr> <td>0</td><td>0</td><td>1</td><td>0</td><td>0</td><td>200 ns filter</td> </tr> <tr> <td>0</td><td>0</td><td>1</td><td>1</td><td>1</td><td>300 ns filter</td> </tr> <tr> <td>0</td><td>0</td><td>1</td><td>1</td><td>1</td><td>300 ns filter</td> </tr> <tr> <td>0</td><td>1</td><td>0</td><td>0</td><td>0</td><td>400 ns filter</td> </tr> <tr> <td>0</td><td>1</td><td>0</td><td>1</td><td>0</td><td>500 ns filter</td> </tr> <tr> <td>0</td><td>1</td><td>1</td><td>0</td><td>0</td><td>600 ns filter</td> </tr> <tr> <td>0</td><td>1</td><td>1</td><td>1</td><td>1</td><td>700 ns filter</td> </tr> <tr> <td>1</td><td>0</td><td>0</td><td>0</td><td>0</td><td>800 ns filter (default setting)</td> </tr> <tr> <td>1</td><td>0</td><td>0</td><td>1</td><td>0</td><td>900 ns filter</td> </tr> <tr> <td>1</td><td>0</td><td>1</td><td>0</td><td>0</td><td>1000 ns filter</td> </tr> <tr> <td>1</td><td>0</td><td>1</td><td>1</td><td>1</td><td>1100 ns filter</td> </tr> <tr> <td>1</td><td>1</td><td>0</td><td>0</td><td>0</td><td>1200 ns filter</td> </tr> <tr> <td>1</td><td>1</td><td>0</td><td>1</td><td>1</td><td>1300 ns filter</td> </tr> <tr> <td>1</td><td>1</td><td>1</td><td>0</td><td>0</td><td>1400 ns filter</td> </tr> <tr> <td>1</td><td>1</td><td>1</td><td>1</td><td>1</td><td>1500 ns filter</td> </tr> </tbody> </table>	Bit	11	10	9	8	Input Filter Setting	0	0	0	0	0	Filter disabled	0	0	0	1	1	100 ns filter	0	0	1	0	0	200 ns filter	0	0	1	1	1	300 ns filter	0	0	1	1	1	300 ns filter	0	1	0	0	0	400 ns filter	0	1	0	1	0	500 ns filter	0	1	1	0	0	600 ns filter	0	1	1	1	1	700 ns filter	1	0	0	0	0	800 ns filter (default setting)	1	0	0	1	0	900 ns filter	1	0	1	0	0	1000 ns filter	1	0	1	1	1	1100 ns filter	1	1	0	0	0	1200 ns filter	1	1	0	1	1	1300 ns filter	1	1	1	0	0	1400 ns filter	1	1	1	1	1	1500 ns filter		
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237	<p><b>Port0 Regis Ctrl</b> Configures the registration control for port 0.</p> <ul style="list-style-type: none"> <li>Set bit 0 [Arm Request] to arm the registration logic for the next trigger event. The particular latch will be armed and ready to be strobed on the next occurrence of the trigger input.</li> <li>Set bit 1 [DisArm Req] to disarm the registration logic for next trigger event.</li> </ul>																																																																																																																															
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238	<p><b>Port0 Regis Stat</b> Indicates the registration control status of port 0.</p> <ul style="list-style-type: none"> <li>Bit 0 [Armed] indicates the registration latch is armed.</li> <li>Bit 1 [Found] indicates the registration event has triggered the latch.</li> </ul>																																																																																																																															
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No.	Name Description	Values	Linkable	Read-Write	Data Type
240	<b>Encdr1 Position</b> Displays the position feedback (accumulator) from encoder 0. The value changes by a value of 4 times the Pulses Per Revolution (PPR) rating of the encoder for each full revolution of the encoder shaft. Used by the VPL to close the position loop if the position control is selected.	Default: 0 Min/Max: +/-2147483648			32-bit Integer
241	<b>Encdr1 Spd Fdbk</b> Displays the speed feedback from encoder 1. Calculated from the change of Par 240 [Encdr1 Position] and Par 242 [Encoder1 PPR].	Units: RPM Default: 0 Min/Max: +/-14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0			Real
242	<b>Encoder1 PPR</b> Sets the pulse per revolution rating of the feedback device connected to the Encoder 1 input.	Units: PPR Default: 1024 Min/Max: 10/20000			16-bit Integer

**243 Encdr1 Config**  
Specifies the configuration options for the encoder 1.

- Bits 0 [Encdr Filt 0], 1 [Encdr Filt 1], 2 [Encdr Filt 2], and 3 [Encdr Filt 3] configure encoder input filter (see Table 243A). The filter requires the input signal to be stable for the specified time period. Input transitions within the filter time setting will be ignored.
- Bits 4 [Encdr 4x] and 5 [Encdr A Phs] determine how the encoder channel A and B signals will be interpreted. Typically, both encoder phases A and B are used so that direction information is available. The Par 240 [Encdr1 Position] counts up for forward rotation and down for reverse rotation. If bit 5 is set, then the B phase signal is ignored. As a result, the encoder position will only increase, regardless of rotation direction. Bits 4 and 5 together also determine the number of edges counted per encoder pulse (see Table 243B). "4x" sampling counts both rise and fall of both A and B encoder phases, hence 4 edges per pulse. In 4x mode, the encoder position will change by four times the encoder pulses per revolution rating (PPR) per encoder revolution (e.g., it increments the value in Par 240 [Encdr1 Position] by 4096 for one revolution of a 1024 PPR encoder).
- Bit 6 [Encdr Dir] inverts the channel A input, thus reversing the direction of the feedback.
- Bit 9 [Edge Time] configures the method of sampling used by the Velocity Position Loop (VPL). Setting the bit chooses "Edge to Edge" sampling, while resetting the bit to zero chooses "Simple Difference" sampling. "Simple Difference" sampling calculates speed by examining the difference between pulse counts over a fixed sample time. "Edge to Edge" sampling adjusts the sample time to synchronize with the position count updates from the daughter card - improving the accuracy of the speed calculation.

Bits 12 [SmplRate bit0] through 15 [SmplRate bit3] configure the sample interval for measuring speed (see Table 223C). Increasing the encoder sample interval improves speed measurement near zero speed. Decreasing allows the speed control regulator to perform with high gains at high speeds.

Options	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	SmplRate bit3	SmplRate bit2	SmplRate bit1	SmplRate bit0	Reserved	Reserved	Edge Time	Reserved	Reserved	Encdr Dir	Encdr A Phs	Encdr 4x	Encdr Filt 3	Encdr Filt 2	Encdr Filt 1	Encdr Filt 0
Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	1	0	0	0	1	0	0	0	0	1	1	0	1	0
Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0

Bits 0-3, please refer to [Table 243A: Trigger Source Settings](#). Bits 4 and 5, please refer to [Table 243B: Encoder Sample Interval Settings](#). 0 = False  
Bits 10-13, please refer to [Table 243C: Channel Interpretation Settings](#). 1 = True

**Table 243A: Trigger Source Settings**

Bit	3	2	1	0	Input Filter Setting
0	0	0	0	0	Filter disabled
0	0	0	1	0	100 ns filter
0	0	1	0	0	200 ns filter
0	0	1	1	0	300 ns filter
0	0	1	1	1	300 ns filter
0	1	0	0	0	400 ns filter
0	1	0	1	0	500 ns filter
0	1	1	0	0	600 ns filter
0	1	1	1	0	700 ns filter
1	0	0	0	0	800 ns filter (default setting)
1	0	0	1	0	900 ns filter
1	0	1	0	0	1000 ns filter
1	0	1	1	0	1100 ns filter
1	1	0	0	0	1200 ns filter
1	1	0	1	0	1300 ns filter
1	1	1	0	0	1400 ns filter
1	1	1	1	0	1500 ns filter

**Table 243C: Channel Interpretation Settings**

Bit	15	14	13	12	Encoder Sample Interval Settings
0	0	0	0	0	0.5 ms
0	0	0	1	0	0.5 ms (min. setting)
0	0	1	0	0	1.0 ms
0	0	1	1	0	1.5 ms
0	1	0	0	0	2.0 ms (default setting)
0	1	0	1	0	2.5 ms
0	1	1	0	0	3.0 ms
0	1	1	1	0	3.5 ms
1	0	0	0	0	4.0 ms
1	0	0	1	0	4.5 ms
1	0	1	0	0	5.0 ms
1	0	1	1	0	5.5 ms
1	1	0	0	0	6.0 ms (max. setting)
1	1	0	1	0	6.0 ms
1	1	1	0	0	6.0 ms
1	1	1	1	0	6.0 ms

**Table 243B: Encoder Sample Interval Settings**

Bit	5	4	Mult	Directions	Comments
0	0	2x	fwd/rev		Counts rise/fall of phase A, phase B only used to find direction
0	1	4x	fwd/rev		Counts rise/fall of both A and B phases (default setting)
1	0	1x	fwd only		Counts rise of phase A. Phase B ignored.
1	1	2X	fwd only		Counts rise of phase A. Phase B ignored.







No.	Name Description	Values	Linkable	Read-Write	Data Type																																																																																																					
260	<p><b>Hi Res0 Status</b> Indicates faults on the Hi-Resolution Encoder Feedback Option.</p> <ul style="list-style-type: none"> <li>Bit 8 [Open Wire] indicates an open wire fault. The feedback option card checks for a pre-determined constant value. If this value is not within tolerances, an open wire fault is declared. A quadrature check also is done. If an error occurs during the check, the open wire check is aborted. If 3 quadrature errors occur in succession, the open wire check will complete and the constant value checked again. If this value is not within tolerances, the fault is declared.</li> <li>Bit 9 [Power Fail] indicates the failure of the power supply.</li> <li>Bit 10 [Diag Fail] indicates the option board failed its power-up diagnostic test. The pattern on the FPGA must be identical to the pattern written from the DSP, or the board status test will fail.</li> <li>Bit 11 [Msg Checksum] indicates a message checksum fault. The check sum associated with the Heidenhain encoder must be correct and acknowledged by the feedback option card.</li> <li>Bit 12 [Time Out Err] indicates a RS-485 time-out fault. This check requires information to be sent from the encoder to the feedback option card within a specified time. Typical times are about 10 clock cycles before and error is detected. This check is done only at power-up.</li> </ul> <p>Options</p> <table border="1"> <thead> <tr> <th></th> <th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Time Out Err</th><th>Msg Checksum</th><th>Diag Fail</th><th>Power Fail</th><th>Open Wire</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th> </tr> </thead> <tbody> <tr> <td>Default</td> <td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td> </tr> <tr> <td>Bit</td> <td>31</td><td>30</td><td>29</td><td>28</td><td>27</td><td>26</td><td>25</td><td>24</td><td>23</td><td>22</td><td>21</td><td>20</td><td>19</td><td>18</td><td>17</td><td>16</td><td>15</td><td>14</td><td>13</td><td>12</td><td>11</td><td>10</td><td>9</td><td>8</td><td>7</td><td>6</td><td>5</td><td>4</td><td>3</td><td>2</td><td>1</td><td>0</td> </tr> </tbody> </table> <p style="text-align: right;">0 = False 1 = True</p>		Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Time Out Err	Msg Checksum	Diag Fail	Power Fail	Open Wire	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0				
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261	<p><b>Hi Res0 TP Sel</b> Selects data displayed by Par 262 [Hi Res0 TP Data].</p> <ul style="list-style-type: none"> <li>H0 Edge Time - Latency counter value, not used for Hi-Resolution Feedback Option.</li> <li>H0 dEdge - Change in edge counts for one 500 microsecond update. At constant speed, this value should be constant.</li> <li>H0 dTime - Change in update time. This value should be constant, 500 microseconds.</li> <li>H0 EPR - This value should be 1,048,576 counts per revolution-this is a constant value.</li> <li>H0 dTheta - This is a scaled value of 2.</li> <li>Ho Delta2Err - Derivative of value 2.</li> </ul>	<p>Default: 0 "Zero"</p> <p>Options:</p> <ul style="list-style-type: none"> <li>0 "Zero"</li> <li>1 "H0 Edge Time"</li> <li>2 "H0 dEdge"</li> <li>3 "H0 dTime"</li> <li>4 "H0 EPR"</li> <li>5 "H0 Edge Mode"</li> <li>6 "H0 dTheta"</li> <li>7 "H0 Delta2Err"</li> </ul>																																																																																																								
262	<p><b>Hi Res0 TP Data</b> Displays data selected by Par 260 [Hi Res0 TP Sel].</p>	<p>Default: 0</p> <p>Min/Max: -/+32768</p>			16-bit Integer																																																																																																					

No.	Name Description	Values	Linkable	Read-Write	Data Type																																																																																																																																																																																																																														
266	<p><b>Reslvr0 Config</b> Configures options for the resolver option card at port 0.</p> <ul style="list-style-type: none"> <li>Setting bit 0 [Cable Tune] enables the cable tuning test, resetting the bit to zero disables the test.</li> <li>Bit 1 [Tune Param] has been disabled.</li> <li>Bits 2 [Resolution 0] and 3 [Resolution 1] select the resolver resolution (see Table 266A).</li> <li>Setting bit 4 [Energize] energizes the resolver, resetting the bit to zero de-energizes it.</li> <li>Bit 5 [Resolver Dir] determines counting direction . If clear, direction is forward or up. If set, the direction is reverse or down.</li> <li>Bit 9 [Edge Time] configures the method of sampling used by the Velocity Position Loop (VPL). Setting the bit chooses "Edge to Edge" sampling, while resetting the bit to zero chooses "Simple Difference" sampling. "Simple Difference" sampling calculates speed by examining the difference between pulse counts over a fixed sample time. "Edge to Edge" sampling adjusts the sample time to synchronize with the position count updates from the daughter card - improving the accuracy of the speed calculation.</li> <li>Bits 10 [Low Speed 0] through 13 [Low Speed 3] configure the sample interval for measuring speed (See Table 266B). Increasing the encoder sample interval improves speed measurement near zero speed. Decreasing allows the speed control regulator to perform with high gains at high speeds.</li> </ul> <p>Options</p> <table border="1"> <thead> <tr> <th></th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>SmpIRate bit3</th> <th>SmpIRate bit2</th> <th>SmpIRate bit1</th> <th>SmpIRate bit0</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Resolver Dir</th> <th>Energize</th> <th>Resolution 1</th> <th>Resolution 0</th> <th>Reserved</th> <th>Cable Tune</th> </tr> </thead> <tbody> <tr> <td>Default</td> <td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>1</td><td>0</td><td>1</td><td>0</td><td>0</td><td>0</td><td>0</td><td>1</td><td>0</td><td>0</td><td>0</td><td>1</td><td>0</td><td>0</td><td>0</td><td>0</td> </tr> <tr> <td>Bit</td> <td>31</td><td>30</td><td>29</td><td>28</td><td>27</td><td>26</td><td>25</td><td>24</td><td>23</td><td>22</td><td>21</td><td>20</td><td>19</td><td>18</td><td>17</td><td>16</td><td>15</td><td>14</td><td>13</td><td>12</td><td>11</td><td>10</td><td>9</td><td>8</td><td>7</td><td>6</td><td>5</td><td>4</td><td>3</td><td>2</td><td>1</td><td>0</td> </tr> </tbody> </table> <p>Bits 2 and 3, please refer to <a href="#">Table 266A: Resolution Settings</a>. Bits 3 and 4, please refer to <a href="#">Table 266B: Encoder Sample Interval</a>.</p> <table border="1"> <thead> <tr> <th colspan="3">Table 266A: Resolution Settings</th> </tr> <tr> <th>Bit 3</th> <th>2</th> <th></th> </tr> </thead> <tbody> <tr> <td>0</td> <td>0</td> <td>10 bit resolution</td> </tr> <tr> <td>0</td> <td>1</td> <td>12 bit resolution (default setting)</td> </tr> <tr> <td>1</td> <td>0</td> <td>14 bit resolution</td> </tr> <tr> <td>1</td> <td>1</td> <td>16 bit resolution</td> </tr> </tbody> </table> <table border="1"> <thead> <tr> <th colspan="5">Table 266B: Encoder Sample Interval</th> </tr> <tr> <th>Bit</th> <th>14</th> <th>13</th> <th>12</th> <th>11</th> <th>Encoder Sample Interval Settings</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0.5 ms</td> </tr> <tr> <td>0</td> <td>0</td> <td>0</td> <td>1</td> <td>0</td> <td>0.5 ms (min. setting)</td> </tr> <tr> <td>0</td> <td>0</td> <td>1</td> <td>0</td> <td>0</td> <td>1.0 ms</td> </tr> <tr> <td>0</td> <td>0</td> <td>1</td> <td>1</td> <td>0</td> <td>1.5 ms</td> </tr> <tr> <td>0</td> <td>1</td> <td>0</td> <td>0</td> <td>0</td> <td>2.0 ms (default setting)</td> </tr> <tr> <td>0</td> <td>1</td> <td>0</td> <td>1</td> <td>0</td> <td>2.5 ms</td> </tr> <tr> <td>0</td> <td>1</td> <td>1</td> <td>0</td> <td>0</td> <td>3.0 ms</td> </tr> <tr> <td>0</td> <td>1</td> <td>1</td> <td>1</td> <td>0</td> <td>3.5 ms</td> </tr> <tr> <td>1</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>4.0 ms</td> </tr> <tr> <td>1</td> <td>0</td> <td>0</td> <td>1</td> <td>0</td> <td>4.5 ms</td> </tr> <tr> <td>1</td> <td>0</td> <td>1</td> <td>0</td> <td>0</td> <td>5.0 ms</td> </tr> <tr> <td>1</td> <td>0</td> <td>1</td> <td>1</td> <td>0</td> <td>5.5 ms</td> </tr> <tr> <td>1</td> <td>1</td> <td>0</td> <td>0</td> <td>0</td> <td>6.0 ms (max. setting)</td> </tr> <tr> <td>1</td> <td>1</td> <td>0</td> <td>1</td> <td>0</td> <td>6.0 ms</td> </tr> <tr> <td>1</td> <td>1</td> <td>1</td> <td>0</td> <td>0</td> <td>6.0 ms</td> </tr> <tr> <td>1</td> <td>1</td> <td>1</td> <td>1</td> <td>0</td> <td>6.0 ms</td> </tr> </tbody> </table>		Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	SmpIRate bit3	SmpIRate bit2	SmpIRate bit1	SmpIRate bit0	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Resolver Dir	Energize	Resolution 1	Resolution 0	Reserved	Cable Tune	Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	1	0	1	0	0	0	0	1	0	0	0	1	0	0	0	0	Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0	Table 266A: Resolution Settings			Bit 3	2		0	0	10 bit resolution	0	1	12 bit resolution (default setting)	1	0	14 bit resolution	1	1	16 bit resolution	Table 266B: Encoder Sample Interval					Bit	14	13	12	11	Encoder Sample Interval Settings	0	0	0	0	0	0.5 ms	0	0	0	1	0	0.5 ms (min. setting)	0	0	1	0	0	1.0 ms	0	0	1	1	0	1.5 ms	0	1	0	0	0	2.0 ms (default setting)	0	1	0	1	0	2.5 ms	0	1	1	0	0	3.0 ms	0	1	1	1	0	3.5 ms	1	0	0	0	0	4.0 ms	1	0	0	1	0	4.5 ms	1	0	1	0	0	5.0 ms	1	0	1	1	0	5.5 ms	1	1	0	0	0	6.0 ms (max. setting)	1	1	0	1	0	6.0 ms	1	1	1	0	0	6.0 ms	1	1	1	1	0	6.0 ms				
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267	<p><b>Reslvr0 Status</b> Indicates status of the resolver option card port 0.</p> <ul style="list-style-type: none"> <li>Bit 0 [Cable Status] ?</li> <li>Bit 1 [Tune Result] indicates the tuning parameter type. When set, it indicates the tuning is using the parameter database. When cleared, it indicates the tuning is using derived data.</li> <li>Bit 2 [Mtr Turning] indicates that the motor is turning.</li> <li>Bit 4 [Energized] indicates the resolver is energized.</li> <li>Bit 8 [Open Wire] indicates a problem with the cable (open circuit).</li> <li>Bit 9 [Power Supply] indicates problem with the option card's power supply.</li> <li>Bit 10 [Diag Fail] indicates the option card has failed its power-up diagnostics.</li> </ul> <p>Options</p> <table border="1"> <thead> <tr> <th></th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Select OK</th> <th>Diag Fail</th> <th>Power Supply</th> <th>Open Wire</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Energized</th> <th>Cable Comp</th> <th>Mtr Turning</th> <th>Tune Result</th> <th>Cable Status</th> </tr> </thead> <tbody> <tr> <td>Default</td> <td>0</td><td>0</td><td>0</td><td>0</td><td>1</td><td>1</td><td>1</td><td>1</td><td>1</td><td>1</td><td>1</td><td>1</td><td>1</td><td>1</td><td>1</td><td>1</td> </tr> <tr> <td>Bit</td> <td>15</td><td>14</td><td>13</td><td>12</td><td>11</td><td>10</td><td>9</td><td>8</td><td>7</td><td>6</td><td>5</td><td>4</td><td>3</td><td>2</td><td>1</td><td>0</td> </tr> </tbody> </table>		Reserved	Reserved	Reserved	Reserved	Select OK	Diag Fail	Power Supply	Open Wire	Reserved	Reserved	Reserved	Energized	Cable Comp	Mtr Turning	Tune Result	Cable Status	Default	0	0	0	0	1	1	1	1	1	1	1	1	1	1	1	1	Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0																																																																																																																																																																															
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268	<p><b>Reslvr0 TP Sel</b> Enter or write a value to select Fault data data displayed in Par 269 [Reslvr0 TP Data].</p>	<p>Default: 0 "Zero"</p> <p>Options:</p> <table border="1"> <tr> <td>0</td> <td>"Zero"</td> <td>4</td> <td>"R0 EPR"</td> </tr> <tr> <td>1</td> <td>"R0 Edge Time"</td> <td>5</td> <td>"R0 Edge Mode"</td> </tr> <tr> <td>2</td> <td>"R0 dEdge"</td> <td>6</td> <td>"R0 dTheta"</td> </tr> <tr> <td>3</td> <td>"R0 dTime"</td> <td>7</td> <td>"R0 Delta2Err"</td> </tr> </table>	0	"Zero"	4	"R0 EPR"	1	"R0 Edge Time"	5	"R0 Edge Mode"	2	"R0 dEdge"	6	"R0 dTheta"	3	"R0 dTime"	7	"R0 Delta2Err"																																																																																																																																																																																																																	
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269	<p><b>Reslvr0 TP Data</b> Displays the data selected by Par 268 [Reslvr0 TP Sel].</p>	<p>Default: 0</p> <p>Min/Max: -/+2147483648</p>			32-bit Integer																																																																																																																																																																																																																														







No.	Name Description	Values	Linkable	Read-Write	Data Type																																																																																																		
303	<b>Motor Torque Ref</b> Displays the reference value of motor torque. The actual value of the motor torque is within 5% of this value.	Units: P.U. Default: 0.0000 Min/Max: -/+8.0000			Real																																																																																																		
304	<b>Limit Status</b> Displays the limit status of conditions that may be limiting the current reference or torque reference. <ul style="list-style-type: none"> <li>• Bit 0 [+MCS Iq Lim] indicates that torque producing current is at its positive limit.</li> <li>• Bit 1 [+MCS Ws Lim] indicates that flux producing torque is at its positive limit.</li> <li>• Bit 2 [0 Ia from +] indicates that torque producing current is limited to zero from the positive direction - refer to Par 353 [Iq Actual Lim].</li> <li>• Bit 3 [+Iq Calc] indicates the calculation for torque producing current has reached its positive limit.</li> <li>• Bit 4 [+Current Lim] indicates that the current reference has reached the positive Motor Current Limit set by Par 356 [Mtr Current Lim].</li> <li>• Bit 5 [+DriveProtOL] indicates that the current reference has reached the positive current limit set by the Open Loop Inverter Overload, shown in Par 343 [OL OpnLp CurrLim].</li> <li>• Bit 6 [+DriveProtCL] indicates that the current reference has reached the positive current limit set by the Closed Loop Inverter Overload, shown in Par 344 [OL ClsLp CurrLim].</li> <li>• Bit 8 [+Torq Limit] indicates that the torque reference has reached the Positive Torque Limit set by Par 125 [Torque Pos Limit].</li> <li>• Bit 9 [Mtrng PwrLim] indicates that the torque reference is being limited by the Motoring Power Limit set by Par 127 [Mtring Power Lim].</li> <li>• Bit 10 [+Torq CurLim] indicates that current reference has reached the Actual Torque Producing Current Limit set by Par 353 [Iq Actual Lim].</li> <li>• Bit 11 [Atune Tq Lim] indicates that the torque reference is being limited by Par 129 [Atune Torq Ref].</li> <li>• Bit 12 [+0 Torq Ena] indicates that the torque reference is limited to zero because Par 157 [Logic Ctrl State] bit 9 [Torq Ref En] is off.</li> <li>• Bit 13 [+0 Curr Ena] indicates that the current reference is limited to zero because Par 157 [Logic Ctrl State] bit 11 [CurrRef En] is off.</li> <li>• Bit 16 [-MCS Iq Lim] indicates that torque producing current is at its negative limit.</li> <li>• Bit 17 [-MCS Ws Lim] indicates that flux producing torque is at its negative limit.</li> <li>• Bit 18 [0 Ia from -] indicates that torque producing current is limited to zero from the negative direction - refer to Par 353 [Iq Actual Lim].</li> <li>• Bit 19 [-Iq Calc] indicates the calculation for torque producing current has reached its negative limit.</li> <li>• Bit 20 [-Current Lim] indicates that the current reference has reached the negative Motor Current Limit set by Par 356 [Mtr Current Lim].</li> <li>• Bit 21 [-DriveProtOL] indicates that the current reference has reached the negative current limit set by the Open Loop Inverter Overload, shown in Par 343 [OL OpnLp CurrLim].</li> <li>• Bit 22 [-DriveProtCL] indicates that the current reference has reached the negative current limit set by the Closed Loop Inverter Overload, shown in Par 344 [OL ClsLp CurrLim].</li> <li>• Bit 24 [-Torq Limit] indicates that the torque reference has reached the Negative Torque Limit set by Par 126 [Torque Neg Limit].</li> <li>• Bit 25 [Regen PwrLim] indicates that the torque reference is being limited by the Regenerative Power Limit set by Par 128 [Regen Power Lim].</li> <li>• Bit 26 [-Torq CurLim] indicates that current reference has reached the Actual Torque Producing Current Limit set by Par 353 [Iq Actual Lim].</li> <li>• Bit 27 [Bus Reg Tq Lim] indicates the bus voltage regulator is active and limiting the regenerative torque.</li> <li>• Bit 28 [-0 Torq Ena] indicates that the torque reference is limited to zero because Par 157 [Logic Ctrl State] bit 9 [Torq Ref En] is off.</li> <li>• Bit 29 [-0 Curr Ena] indicates that the current reference is limited to zero because Par 157 [Logic Ctrl State] bit 11 [CurrRef En] is off.</li> </ul> Options <table border="1" style="width: 100%; border-collapse: collapse; text-align: center;"> <tr> <td></td> <td>Reserved</td><td>Reserved</td><td>-0 Curr Ena</td><td>-0 Torq Ena</td><td>Bus Reg Lim</td><td>-Torq CurLim</td><td>Regen PwrLim</td><td>-Torq Lim</td><td>Reserved</td><td>-DriveProtCL</td><td>-DriveProtOL</td><td>-Current Lim</td><td>-Iq Calc</td><td>0 Iq from -</td><td>-MCS Ws Lim</td><td>-MCS Iq Lim</td><td>Reserved</td><td>Reserved</td><td>+0 Curr Ena</td><td>+0 Torq Ena</td><td>Atune Tq Lim</td><td>+Torq CurLim</td><td>Mtrng PwrLim</td><td>+Torq Limit</td><td>Reserved</td><td>+DriveProtCL</td><td>+DriveProtOL</td><td>+Current Lim</td><td>+Iq Calc</td><td>0 Iq from +</td><td>+MCS Ws Lim</td><td>+MCS Iq Lim</td> </tr> <tr> <td>Default</td> <td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td> </tr> <tr> <td>Bit</td> <td>31</td><td>30</td><td>29</td><td>28</td><td>27</td><td>26</td><td>25</td><td>24</td><td>23</td><td>22</td><td>21</td><td>20</td><td>19</td><td>18</td><td>17</td><td>16</td><td>15</td><td>14</td><td>13</td><td>12</td><td>11</td><td>10</td><td>9</td><td>8</td><td>7</td><td>6</td><td>5</td><td>4</td><td>3</td><td>2</td><td>1</td><td>0</td> </tr> </table> 0 = False 1 = True		Reserved	Reserved	-0 Curr Ena	-0 Torq Ena	Bus Reg Lim	-Torq CurLim	Regen PwrLim	-Torq Lim	Reserved	-DriveProtCL	-DriveProtOL	-Current Lim	-Iq Calc	0 Iq from -	-MCS Ws Lim	-MCS Iq Lim	Reserved	Reserved	+0 Curr Ena	+0 Torq Ena	Atune Tq Lim	+Torq CurLim	Mtrng PwrLim	+Torq Limit	Reserved	+DriveProtCL	+DriveProtOL	+Current Lim	+Iq Calc	0 Iq from +	+MCS Ws Lim	+MCS Iq Lim	Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0			
	Reserved	Reserved	-0 Curr Ena	-0 Torq Ena	Bus Reg Lim	-Torq CurLim	Regen PwrLim	-Torq Lim	Reserved	-DriveProtCL	-DriveProtOL	-Current Lim	-Iq Calc	0 Iq from -	-MCS Ws Lim	-MCS Iq Lim	Reserved	Reserved	+0 Curr Ena	+0 Torq Ena	Atune Tq Lim	+Torq CurLim	Mtrng PwrLim	+Torq Limit	Reserved	+DriveProtCL	+DriveProtOL	+Current Lim	+Iq Calc	0 Iq from +	+MCS Ws Lim	+MCS Iq Lim																																																																							
Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0																																																																							
Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0																																																																							
305	<b>Mtr TorqCurr Ref</b> Displays the torque current reference present at the output of the current rate limiter. 100% is equal to 1 per unit (pu) rated motor torque.	Units: P.U. Default: 0.0000 Min/Max: -/+8.0000			Real																																																																																																		
306	<b>DC Bus Voltage</b> Displays measured bus voltage.	Units: Volt Default: 0.0000 Min/Max: 0.0000/1000.0000			Real																																																																																																		
307	<b>Output Voltage</b> Displays RMS line-to-line fundamental motor voltage. This data is averaged and updated every 50 milliseconds.	Units: Volt Default: 0.00 Min/Max: 0.00/3000.00			Real																																																																																																		
308	<b>Output Current</b> Displays measured RMS motor current.	Units: Amps Default: 0.00 Min/Max: 0.00/10000.00			Real																																																																																																		
309	<b>% Motor Flux</b> Displays the motor flux in % of nominal.	Units: % Default: 100.0 Min/Max: 0.0/100.0 Comm Scale: 100 = 4096			16-bit Integer																																																																																																		
310	<b>Output Freq</b> Displays the motor stator frequency.	Units: Hz Default: 0.00 Min/Max: -/+250.00			Real																																																																																																		
311	<b>Output Power</b> Motor Power is the calculated product of the torque reference and motor speed feedback. A 125mS filter is applied to this result. Positive values indicate motoring power; negative values indicate regenerative power.	Units: Hp Default: 0.00 Min/Max: -/+9999.00			Real																																																																																																		

No.	Name Description	Values	Linkable	Read-Write	Data Type																											
312	<b>MotorFluxCurr FB</b> Displays the measured per unit motor flux producing current.	Units: P.U. Default: 0.0000 Min/Max:: 0.0000/1.0000			Real																											
313	<b>Heatsink Temp</b> Displays the measured temperature of the drive's heatsink.	Units: degC Default: 0.0000 Min/Max: -30.0000/200.0000			Real																											
314	<b>VPL Firmware Rev</b> Displays the major and minor revision levels of the drive's Velocity Position Loop (VPL) software.	Default: 1.16 Min/Max: 0.01/99.99 Comm Scale: x 100			16-bit Integer																											
315	<b>VPL Build Number</b> Displays the build number of the drive's Velocity Position Loop (VPL) software.	Default: 2 Min/Max: 1/10000			16-bit Integer																											
316	<b>SynchLink Status</b> Indicates status of SynchLink functions. <ul style="list-style-type: none"> <li>• Bit 0 [FB Opt Prsnt] indicates the presence of an optional feedback daughter card.</li> <li>• Bit 1 [Encdr0 Prsnt] indicates the presence of encoder 0.</li> <li>• Bit 2 [Encdr1 Prsnt] indicates the presence of encoder 1.</li> <li>• Bit 3 [In Sync] indicates SynchLink communications is synchronized.</li> <li>• Bit 4 [Tx Active] indicates TX frames are being transmitted downstream from this node.</li> <li>• Bit 5 [Rx Active] indicates RX frames are being received from nodes upstream.</li> <li>• Bit 15 [Rx Data Enbl] indicates received data is being updated.</li> </ul>																															
Options																																
	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Rx Data Enbl	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Open Wire	Reserved	Reserved	Rx Active	Tx Active	In Sync	Encdr1 Prsnt	Encdr0 Prsnt	FB Opt Prsnt		
Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0		
Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
						0 = False 1 = True																										
317	<b>SL System Time</b> Displays the SynchLink system time counter.	Units: μSec Default: 0 Min/Max: 0/1048575			32-bit Integer																											
318	<b>Posit Spd Output</b> Final output of the position regulator.	Units: RPM Default: 0.0000 Min/Max: +/-14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0			Real																											
320	<b>Exception Event1</b> Indicates the presence of certain drive anomalies. Configure the drive's response to these events by entering values in the parameters of the fault/alarm configuration group of the utility file.																															
Options																																
	PWM Asynchro	Precharge Er	MC Firmware	PWM Short	VPL/MC Comm	OverCurrent	Ground Fault	Trans Desat	Bus OverVolt	MC Commissn	Over Freq	Inertia Test	DSP Error	DSP Mem Err	Ext Fault In	Inv OL Trip	Inv OL Pend	Inv OTempTrip	Inv OTempPend	Motor Stall	Mtr OL Pend	Mtr OL Trip	Power Loss	SLink Comm	SLink HW	Ctrl EE Mem	FB Opt1 Loss	FB Opt0 Loss	Encdr1 Loss	Encdr0 Loss	SpdRef Decel	Abs OverSpd
Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0
Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
						0 = False 1 = True																										
321	<b>Exception Event2</b> Indicates the presence of certain drive anomalies. Configure the drive's response to these events by entering values in the parameters of the fault/alarm configuration group of the utility file.																															
Options																																
	Lgx LinkChng	Lgx Closed	Lgx Timeout	Lgx OutOfRun	NetLoss DPI6	NetLoss DPI5	NetLoss DPI4	NetLoss DPI3	NetLoss DPI2	NetLoss DPI1	DPI Loss P6	DPI Loss P5	DPI Loss P4	DPI Loss P3	DPI Loss P2	DPI Loss P1	No Ctrl Devc	Reserved	Reserved	HlHP Drv Flt	NonCnfgAlarm	VoltFbkLoss	BusUnderVolt	RideThruTime	SLink Mult	PowerEE Cksm	BrakeOL Trip	PSC Sys Flt2	PSC Sys Flt1	Ctrl EE Cksm	MC Command	+/- 12v Pwr
Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0
Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
						0 = False 1 = True																										









No.	Name Description	Values	Linkable	Read-Write	Data Type																																																		
344	<b>OL ClsLp CurrLim</b> Displays the current limit set by the Closed Loop Inverter Overload (OL) function. This function will set a current limit level based on the values in Par 358 [Iq Ref Limited], Par 313 [Heatsink Temp] and the thermal characteristics of the drive. Under normal operating conditions, the function typically sets the limit at 250% of the continuous drive rating. If the function determines that the power device junction temperature is approaching maximum, it will reduce this limit to the level required to prevent additional heating of the inverter. This level could be as low as the continuous rating of the drive. If the inverter temperature decreases, the function will raise the limit to a higher level. Disable this protection by setting bit 13 [OL ClsLpDsb] of Par 153 [Control Options].	Units: P.U. Default: 8.0000 Min/Max: 0.0000/8.0000			Real																																																		
345	<b>Drive OL JnctTmp</b> Displays the calculated junction temperature of the power semiconductors in the inverter. The calculation uses the values of Par 313[Heatsink Temp], Par 358 [Iq Ref Limited], and inverter thermal characteristics contained in the power EE memory. If this value exceeds the maximum junction temperature (visible in Par 348 [Drive OL TP Data] when Par 347 [Drive OL TP Sel] bit 12 [fJunTmpMax] is set), two faults occur: Inverter Overtemperature Fault (fault code 15), and Junction Overtemperature Fault - indicated by bit 7 [Jnc OverTemp] of Par 346 [Drive OL Status].	Units: degC Default: 0.0000 Min/Max: -50.0000/300.0000			Real																																																		
346	<b>Drive OL Status</b> Indicates the status of various overload (OL) conditions. <ul style="list-style-type: none"> <li>• Bit 0 [NTC Shorted] indicates the Negative Temperature Coefficient (NTC) device has a short circuit.</li> <li>• Bit 1 [NTC Open] indicates the NTC has an open circuit.</li> <li>• Bit 2 [HS OverTemp] indicates heatsink temperature is above 105C for ratings 1.1-11.0A, 115C for 14-34A, 100C for 40-52A.</li> <li>• Bit 3 [HS Pending] indicates heatsink temperature is above 95C for ratings 1.1 -11A, 105C for 14- 34A, 90C for 40- 52A.</li> <li>• Bit 4 [IT Trip] indicates the drive has exceed the 3 second rating of either the 150% normal duty rating or 200% of the heavy duty rating.</li> <li>• Bit 5 [IT Pending] indicates the drive OL integrator is at 50% of the time out time.</li> <li>• Bit 6 [IT Foldback] indicates the drive closed loop current limit is in a fold back condition. The value of the fold back is proportional to the calculated junction temperature.</li> <li>• Bit 7 [Jnc Over Temp] indicates the junction temperature has exceeded the maximum temperature for the power semiconductor device.</li> </ul> Options <table border="1" style="display: inline-table; margin-right: 20px;"> <thead> <tr> <th></th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Jnc OverTemp</th> <th>IT Foldback</th> <th>IT Pending</th> <th>IT Trip</th> <th>HS Pending</th> <th>HS OverTemp</th> <th>NTC Open</th> <th>NTC Shorted</th> </tr> </thead> <tbody> <tr> <td>Default</td> <td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td> </tr> <tr> <td>Bit</td> <td>15</td><td>14</td><td>13</td><td>12</td><td>11</td><td>10</td><td>9</td><td>8</td><td>7</td><td>6</td><td>5</td><td>4</td><td>3</td><td>2</td><td>1</td><td>0</td> </tr> </tbody> </table> 0 = False 1 = True		Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Jnc OverTemp	IT Foldback	IT Pending	IT Trip	HS Pending	HS OverTemp	NTC Open	NTC Shorted	Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0			
	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Jnc OverTemp	IT Foldback	IT Pending	IT Trip	HS Pending	HS OverTemp	NTC Open	NTC Shorted																																							
Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0																																							
Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0																																							
347	<b>Drive OL TP Sel</b> Enter or write a value to select the drive overload data displayed in Par 348 [Drive OL TP Data].	Default: 0 "Zero" Options: 0 "Zero" 22 "flgbtEnergy" 1 "fAbsIsCurr" 23 "flgbtJuncase" 2 "fDelta" 24 "flgbtWatts" 3 "fAbsIqCurr" 25 "flgbtPerMod" 4 "fOL_m" 26 "fFdThres" 5 "fOL_m" 27 "fFdSlope" 6 "fOL_k" 28 "fFdJunCase" 7 "fOL_g" 29 "fFdWatts" 8 "fOL_intg" 30 "fMaxHsDegc" 9 "fCL_intg" 31 "fCsImp" 10 "fInvOLClim" 32 "fCsFltr" 11 "fJuncDegc" 33 "fPwmHz" 12 "fJunTmpMax" 34 "fElecHz" 13 "f60sPUCur" 35 "fModIdx" 14 "f60sAmp" 36 "fBoost" 15 "f3sPUCur" 37 "fTotalWatts" 16 "f3sAmp" 38 "fHSDegc" 17 "fRatioInvMtr" 39 "fAdconv" 18 "fRatioMtrInv" 40 "fJct Temp" 19 "fConvertStat" 41 "fJct Tmp HiHp" 20 "flgbtThres" 42 "fJct Tmp Fwd" 21 "flgbtSlope" 43 "fHH Loss Intg" 44 "fHH PwrBdTemp"																																																					
348	<b>Drive OL TP Data</b> Displays the value selected by Par 347 [Drive OL TP Sel].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real																																																		
350	<b>Iq Actual Ref</b> Displays the value of motor current reference that is present at the output of the divide by flux calculation.	Units: P.U. Default: 0.0000 Min/Max: -/+8.0000			Real																																																		
351	<b>Iq Ref Trim</b> Provides an external source to command, trim or offset the internal motor current reference. This value is summed with Par 351 [Current Actl Ref] before the current limit is applied. Scaling is in per unit motor current.	Units: P.U. Default: 0.0000 Min/Max: -/+8.0000	✓	✓	Real																																																		
352	<b>Is Actual Lim</b> Displays the largest allowable stator motor current. The range of allowable motor current is limited by the maximum drive current. Scaling is in per unit motor current.	Units: P.U. Default: 1.0000 Min/Max: 0.0000/8.0000			Real																																																		




No.	Name Description	Values	Linkable	Read-Write	Data Type
353	<b>Iq Actual Lim</b> Displays the largest allowable torque producing (Iq) motor current. The range of allowable Iq motor current is limited by the maximum drive current and is adjusted by the motor flux current. Scaling is in per unit Iq motor current.	Units: P.U. Default: 1.0000 Min/Max: 0.0000/8.0000			Real
354	<b>Iq Rate Limit</b> Enter the maximum rate of change for Current Reference, in per unit current/ sec. Par 90 [Spd Reg BW] will be limited to 2/3 of this value.	Units: /Sec Default: 1000.0000 Min/Max: 5.0000/10000.0000	✓	✓	Real
355	<b>Iq Rate Limited</b> Displays the current reference output of the rate limiter.	Units: P.U. Default: 0.0000 Min/Max: +/-8.0000			Real
356	<b>Mtr Current Lim</b> Sets the largest allowable motor stator current. The online maximum value of this parameter is Par 2 [Motor NP FLA]. The online minimum value is 105% of the current indicated in Par 488 [Flux Current].	Units: P.U. Default: 1.5000 Min/Max: 0.0000/24.0000	✓	✓	Real
358	<b>Iq Ref Limited</b> Sets the limit value for the motor torque producing current.	Units: P.U. Default: 0.0000 Min/Max: +/-8.0000			Real
359	<b>Motor Flux Est</b> Q-axis motor voltage is divided by the motor frequency while field weakening is active. This is used to convert the torque command to a motor current (Iqs) command.	Units: P.U. Default: 0.0000 Min/Max: +/-8.0000			Real
360	<b>Min Flux</b> Sets the smallest level of flux used to convert Par 303 [Motor Torque Ref] to a current reference above base speed.	Units: P.U. Default: 0.2500 Min/Max: 0.2500/1.0000	✓	✓	Real
361	<b>Flx LpassFilt BW</b> Sets bandwidth of filter which adjusts the response of the flux estimate used in the torque to current conversion. Since the field time constant varies between motors a better control response may be obtained by adjusting the filter time constant. Normally this parameter is not changed unless a significant disturbance occurs as the motor enters field weakening AND Par 360 [Min Flux] is less than 1 per unit.	Units: R/S Default: 12.0000 Min/Max: 0.5000/100.0000	✓	✓	Real
363	<b>Curr Ref TP Sel</b> Enter or write a value to select current reference data displayed in Par 364 [Curr Ref TP Data].	Default: 0 "Zero" Options: 0 "Zero" 10 "Min Lim Stat" 1 "Iq Sum" 11 "Iq Prescale" 2 "Iq Lim In" 12 "Iqtols Stat" 3 "Iq Lim Out" 13 "Flux Status" 4 "Iq Rate Stat" 14 "Flux LPF Out" 5 "Limited Flux" 15 "Is Per Unit" 6 "MtrCrLimStat" 16 "Iq Actl +Lim" 7 "Lim'dMtrCrLm" 17 "Iq Actl -Lim" 8 "Iq Act Limit" 18 "Flx Filt Hld" 9 "Iq Cal Gain"			
364	<b>Curr Ref TP Data</b> Displays the data selected by Par 363 [Curr Ref TP Sel].	Units: P.U. Default: 0.0000 Min/Max: +/-8.0000			Real
365	<b>Encdr0 Loss Cnfg</b> Enter a value to configure the drive's response to an Encoder 0 Loss exception event. • Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs • Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs • Value 2 - FitCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.	Default: 2 "FitCoastStop" Options: 0 "Ignore" 1 "Alarm" 2 "FitCoastStop"			
366	<b>Encdr1 Loss Cnfg</b> Enter a value to configure the drive's response to an Encoder 1 Loss exception event. • Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs • Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs • Value 2 - FitCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.	Default: 0 "FitCoastStop" Options: 0 "Ignore" 1 "Alarm" 2 "FitCoastStop"			
367	<b>FB Opt0 LossCnfg</b> Enter a value to configure the drive's response to a Feedback Option 0 Loss exception event. • Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs • Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs • Value 2 - FitCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.	Default: 0 "FitCoastStop" Options: 0 "Ignore" 1 "Alarm" 2 "FitCoastStop"			




No.	Name Description	Values	Linkable	Read-Write	Data Type
368	<b>FB Opt1 LossCnfg</b> Enter a value to configure the drive's response to a Feedback Option 1 Loss exception event. <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FltCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> </ul>	Default: 0 "FltCoastStop" Options: 0 "Ignore" 1 "Alarm" 2 "FltCoastStop"			
369	<b>Brake OL Cnfg</b> Enter a value to configure the drive's response to a Brake Overload (OL) Trip exception event. This event is triggered when a Dynamic Brake (DB) overload condition occurs. <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FltCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> <li>Value 3 - Flt RampStop configures the drive to perform a ramp stop and set the appropriate fault bit, in response this event.</li> <li>Value 4 - FltCurLimStp configures the drive to perform a current-limit stop and set the appropriate fault bit, in response this event.</li> </ul>	Default: 0 "Alarm" Options: 0 "Alarm" 1 "FltCoastStop" 2 "Flt RampStop" 3 "FltCurLimStp"			
370	<b>HiHp InPhsLs Cfg</b> Selector for the input phase loss configuration. <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FltCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> <li>Value 3 - Flt RampStop configures the drive to perform a ramp stop and set the appropriate fault bit, in response this event.</li> <li>Value 4 - FltCurLimStp configures the drive to perform a current-limit stop and set the appropriate fault bit, in response this event.</li> </ul>	Default: 1 "Alarm" Options: 0 "Ignore" 1 "Alarm" 2 "FltCoastStop" 3 "Flt RampStop" 4 "FltCurLimStp"			
371	<b>Mtr OL Trip Cnfg</b> Enter a value to configure the drive's response to a Motor Overload (OL) Trip exception event. <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FltCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> <li>Value 3 - Flt RampStop configures the drive to perform a ramp stop and set the appropriate fault bit, in response this event.</li> <li>Value 4 - FltCurLimStp configures the drive to perform a current-limit stop and set the appropriate fault bit, in response this event.</li> </ul>	Default: 2 "FltCoastStop" Options: 0 "Ignore" 1 "Alarm" 2 "FltCoastStop" 3 "Flt RampStop" 4 "FltCurLimStp"			
372	<b>Mtr OL Pend Cnfg</b> Enter a value to configure the drive's response to a Motor Overload (OL) Pending exception event. <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FltCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> <li>Value 3 - Flt RampStop configures the drive to perform a ramp stop and set the appropriate fault bit, in response this event.</li> <li>Value 4 - FltCurLimStp configures the drive to perform a current-limit stop and set the appropriate fault bit, in response this event.</li> </ul>	Default: 1 "Alarm" Options: 0 "Ignore" 1 "Alarm" 2 "FltCoastStop" 3 "Flt RampStop" 4 "FltCurLimStp"			
373	<b>Motor Stall Time</b> Enter a value to specify the time delay between when the drive detects a Motor Stall condition and when it declares the exception event.	Units: Sec Default: 1.0000 Min/Max: 0.1000/3000.0000	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>	Real
374	<b>Motor Stall Cnfg</b> Enter a value to configure the drive's response to a Motor Stall exception event. <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FltCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> <li>Value 3 - Flt RampStop configures the drive to perform a ramp stop and set the appropriate fault bit, in response this event.</li> <li>Value 4 - FltCurLimStp configures the drive to perform a current-limit stop and set the appropriate fault bit, in response this event.</li> </ul>	Default: 0 "Ignore" Options: 0 "Ignore" 1 "Alarm" 2 "FltCoastStop" 3 "Flt RampStop" 4 "FltCurLimStp"			







No.	Name Description	Values	Linkable	Read-Write	Data Type
375	<b>Inv OT Pend Cnfg</b> Enter a value to configure the drive's response to a Inverter Over-Temperature (OT) Pending exception event. This event is triggered when the Inverter NTC (Temperature protection) function detects the heat-sink temperature reaches to the overload warning level. <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FltCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> <li>Value 3 - Flt RampStop configures the drive to perform a ramp stop and set the appropriate fault bit, in response this event.</li> <li>Value 4 - FltCurLimStp configures the drive to perform a current-limit stop and set the appropriate fault bit, in response this event.</li> </ul>	Default: 1 "Alarm" Options: 0 "Ignore" 1 "Alarm" 2 "FltCoastStop" 3 "Flt RampStop" 4 "FltCurLimStp"			
376	<b>Inv OL Pend Cnfg</b> Enter a value to configure the drive's response to an Inverter Overload (OL) Pending exception event. This event is triggered when one of the Inverter Protection Current-Over-Time functions (Open Loop or Closed Loop) detects current and temperature at warning levels. <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FltCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> <li>Value 3 - Flt RampStop configures the drive to perform a ramp stop and set the appropriate fault bit, in response this event.</li> <li>Value 4 - FltCurLimStp configures the drive to perform a current-limit stop and set the appropriate fault bit, in response this event.</li> </ul>	Default: 1 "Alarm" Options: 0 "Ignore" 1 "Alarm" 2 "FltCoastStop" 3 "Flt RampStop" 4 "FltCurLimStp"			
377	<b>Inv OL Trip Cnfg</b> <ul style="list-style-type: none"> <li>Enter a value to configure the drive's response to an Inverter Overload (OL) Trip exception event. This event is triggered when one of the Inverter Protection Current-Over-Time functions (Open Loop or Closed Loop) detects current and temperature at a fault level.</li> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FltCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> </ul>	Default: 1 "Alarm" Options: 0 "Ignore" 1 "Alarm" 2 "FltCoastStop"			
378	<b>Interp Flt Cnfg</b> Synchronization input to the Interpolator has been lost or has become excessively irregular.	Default: 2 "FltCoastStop" Options: 0 "Ignore" 1 "Alarm" 2 "FltCoastStop" 3 "Flt RampStop" 4 "FltCurLimStp"			
379	<b>Ext Flt/Alm Cnfg</b> Enter a value to configure the drive's response to an External Input exception event. The event is triggered by a digital input that is configured for auxiliary fault or auxiliary aux fault by setting bit 11 [Aux Fault] or bit 12 [AuxFault Inv] in Pars 838[ DigIn 1 Sel] 839 [DigIn 2 Sel] or 840 [DigIn 3 Sel]. <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FltCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> <li>Value 3 - Flt RampStop configures the drive to perform a ramp stop and set the appropriate fault bit, in response this event.</li> <li>Value 4 - FltCurLimStp configures the drive to perform a current-limit stop and set the appropriate fault bit, in response this event.</li> </ul>	Default: 2 "FltCoastStop" Options: 0 "Ignore" 1 "Alarm" 2 "FltCoastStop" 3 "Flt RampStop" 4 "FltCurLimStp"			
381	<b>PreChrg Err Cnfg</b> Enter a value to configure the drive's response to a Precharge Error exception event. <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FltCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event</li> </ul>	Default: 2 "Alarm" Options: 0 "Ignore" 1 "Alarm" 2 "FltCoastStop"			

No.	Name Description	Values	Linkable	Read-Write	Data Type
382	<b>MC Cmd Lim Cnfg</b> Enter a value to configure the drive's response to a Motor-Controller (MC) Command Limitation exception event. This event is triggered when the motor-controller detects limit of the command values used in the motor-controller, and returns the exception event to the Velocity Position Loop (VPL). <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FitCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> </ul>	Default: 2 "Alarm" Options: 0 "Ignore" 1 "Alarm" 2 "FitCoastStop"			
383	<b>SL CommLoss Data</b> Enter a value to configures the drive's response to SynchLink communication loss. Refer to Par 1229 [SL Error Status] for possible causes of communication loss. <ul style="list-style-type: none"> <li>Value 0 - Zero Data Resets data to zero</li> <li>Value 1 - Last State Holds data in its last state</li> </ul>	Default: 1 "Last State" Options: 0 "Zero Data" 1 "Last State"			
 <b>ATTENTION:</b> Risk of injury or equipment damage exists. Parameter 383 [SL CommLoss Data] lets you determine the action of the drive if communications are disrupted. By default this parameter causes the drive to hold the data in its last state. You can set this parameter so that the drive resets the data to zero. Precautions should be taken to ensure that the setting of this parameter does not create hazards of injury or equipment damage.					
384	<b>SL CommLoss Cnfg</b> Enter a value to determine what is done with the data received from SynchLink when a communication loss occurs. <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FitCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> <li>Value 3 - Fit RampStop configures the drive to perform a ramp stop and set the appropriate fault bit, in response this event.</li> <li>Value 4 - FitCurLimStp configures the drive to perform a current-limit stop and set the appropriate fault bit, in response this event.</li> </ul>	Default: 2 "FitCoastStop" Options: 0 "Ignore" 1 "Alarm" 2 "FitCoastStop" 3 "Fit RampStop" 4 "FitCurLimStp"			
 <b>ATTENTION:</b> Risk of injury or equipment damage exists. Parameter 384 [SL CommLoss Cnfg] lets you determine the action of the drive if communications are disrupted. By default this parameter causes the drive fault and coast to a stop. You can set this parameter so that the drive continues to run. Precautions should be taken to ensure that the setting of this parameter does not create hazards of injury or equipment damage.					
385	<b>Lgx CommLossData</b> Enter a value to configure what drive does with the data received from the DriveLogix controller when the connection is closed or times out. <ul style="list-style-type: none"> <li>Value 0 - Zero Data Resets data to zero</li> <li>Value 1 - Last State Holds data in its last state</li> </ul>	Default: 1 "Last State" Options: 0 "Zero Data" 1 "Last State"			
 <b>ATTENTION:</b> Risk of injury or equipment damage exists. Parameter 385 [Lgx CommLossData] lets you determine the action of the drive if communications are disrupted. By default this parameter causes the drive to hold the data in its last state. You can set this parameter so that the drive resets the data to zero. Precautions should be taken to ensure that the setting of this parameter does not create hazards of injury or equipment damage.					
386	<b>Lgx OutOfRunCnfg</b> Enter a value to configure the drive's response to the DriveLogix processor being in Non-Run mode. Non-Run modes include Program, Remote-Program and Faulted. <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FitCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> <li>Value 3 - Fit RampStop configures the drive to perform a ramp stop and set the appropriate fault bit, in response this event.</li> <li>Value 4 - FitCurLimStp configures the drive to perform a current-limit stop and set the appropriate fault bit, in response this event.</li> </ul>	Default: 2 "FitCoastStop" Options: 0 "Ignore" 1 "Alarm" 2 "FitCoastStop" 3 "Fit RampStop" 4 "FitCurLimStp"			
 <b>ATTENTION:</b> Risk of injury or equipment damage exists. Parameter 386 [Lgx OutOfRunCnfg] lets you determine the action of the drive if communications are disrupted. By default this parameter causes the drive fault and coast to a stop. You can set this parameter so that the drive continues to run. Precautions should be taken to ensure that the setting of this parameter does not create hazards of injury or equipment damage.					


No.	Name Description	Values	Linkable	Read-Write	Data Type
387	<p><b>Lgx Timeout Cnfg</b> Enter a value to configure the drive's response to a Controller to Drive connection timeout, as detected by the drive.</p> <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FltCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> <li>Value 3 - Flt RampStop configures the drive to perform a ramp stop and set the appropriate fault bit, in response this event.</li> <li>Value 4 - FltCurLimStp configures the drive to perform a current-limit stop and set the appropriate fault bit, in response this event.</li> </ul>	<p>Default: 2 "FltCoastStop"</p> <p>Options: 0 "Ignore" 1 "Alarm" 2 "FltCoastStop" 3 "Flt RampStop" 4 "FltCurLimStp"</p>			
<div style="display: flex; align-items: center;">  <p><b>ATTENTION:</b> Risk of injury or equipment damage exists. Parameter 387 [Lgx Timeout Cnfg] lets you determine the action of the drive if communications are disrupted. By default this parameter causes the drive fault and coast to a stop. You can set this parameter so that the drive continues to run. Precautions should be taken to ensure that the setting of this parameter does not create hazards of injury or equipment damage.</p> </div>					
388	<p><b>Lgx Closed Cnfg</b> Enter a value to configure the drive's response to the controller closing the Controller to Drive connection.</p> <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FltCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> <li>Value 3 - Flt RampStop configures the drive to perform a ramp stop and set the appropriate fault bit, in response this event.</li> <li>Value 4 - FltCurLimStp configures the drive to perform a current-limit stop and set the appropriate fault bit, in response this event.</li> </ul>	<p>Default: 2 "FltCoastStop"</p> <p>Options: 0 "Ignore" 1 "Alarm" 2 "FltCoastStop" 3 "Flt RampStop" 4 "FltCurLimStp"</p>			
<div style="display: flex; align-items: center;">  <p><b>ATTENTION:</b> Risk of injury or equipment damage exists. Parameter 388 [Lgx Closed Cnfg] lets you determine the action of the drive if communications are disrupted. By default this parameter causes the drive fault and coast to a stop. You can set this parameter so that the drive continues to run. Precautions should be taken to ensure that the setting of this parameter does not create hazards of injury or equipment damage.</p> </div>					
389	<p><b>Lgx LinkChngCnfg</b> Enter a value to configure the drive's response to Controller to Drive default links being removed. A default link is a link automatically set up when a communication format is selected for the Controller to Drive connection.</p> <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FltCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> <li>Value 3 - Flt RampStop configures the drive to perform a ramp stop and set the appropriate fault bit, in response this event.</li> <li>Value 4 - FltCurLimStp configures the drive to perform a current-limit stop and set the appropriate fault bit, in response this event.</li> </ul>	<p>Default: 2 "FltCoastStop"</p> <p>Options: 0 "Ignore" 1 "Alarm" 2 "FltCoastStop" 3 "Flt RampStop" 4 "FltCurLimStp"</p>			
<div style="display: flex; align-items: center;">  <p><b>ATTENTION:</b> Risk of injury or equipment damage exists. Parameter 389 [Lgx LinkChngCnfg] lets you determine the action of the drive if communications are disrupted. By default this parameter causes the drive fault and coast to a stop. You can set this parameter so that the drive continues to run. Precautions should be taken to ensure that the setting of this parameter does not create hazards of injury or equipment damage.</p> </div>					

No.	Name Description	Values	Linkable	Read-Write	Data Type
390	<p><b>SL MultErr Cnfg</b> Enter a value to configure the Drive Module's response to SynchLink Multiplier error. Refer to Par 1034 [SL Mult State] for possible causes for multiplier errors.</p> <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FitCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> <li>Value 3 - Fit RampStop configures the drive to perform a ramp stop and set the appropriate fault bit, in response this event.</li> <li>Value 4 - FitCurLimStp configures the drive to perform a current-limit stop and set the appropriate fault bit, in response this event.</li> </ul>	<p>Default: 2 "FitCoastStop"</p> <p>Options: 0 "Ignore" 1 "Alarm" 2 "FitCoastStop" 3 "Fit RampStop" 4 "FitCurLimStp"</p>			
<div style="display: flex; align-items: center;">  <p><b>ATTENTION:</b> Risk of injury or equipment damage exists. Parameter 390 [SL MultErr Cnfg] lets you determine the action of the drive if communications are disrupted. By default this parameter causes the drive fault and coast to a stop. You can set this parameter so that the drive continues to run. Precautions should be taken to ensure that the setting of this parameter does not create hazards of injury or equipment damage.</p> </div>					
391	<p><b>DPI CommLoss Cfg</b> Enter a value to configure the drive's response to the failure of a DPI port.</p> <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FitCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> <li>Value 3 - Fit RampStop configures the drive to perform a ramp stop and set the appropriate fault bit, in response this event.</li> <li>Value 4 - FitCurLimStp configures the drive to perform a current-limit stop and set the appropriate fault bit, in response this event.</li> </ul>	<p>Default: 2 "FitCoastStop"</p> <p>Options: 0 "Ignore" 1 "Alarm" 2 "FitCoastStop" 3 "Fit RampStop" 4 "FitCurLimStp"</p>			
<div style="display: flex; align-items: center;">  <p><b>ATTENTION:</b> Risk of injury or equipment damage exists. Parameter 391 [DPI CommLoss Cfg] lets you determine the action of the drive if communications are disrupted. By default this parameter causes the drive fault and coast to a stop. You can set this parameter so that the drive continues to run. Precautions should be taken to ensure that the setting of this parameter does not create hazards of injury or equipment damage.</p> </div>					
392	<p><b>NetLoss DPI Cnfg</b> Enter a value to configure the drive's response to communication fault from a network card at a DPI port.</p> <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FitCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> <li>Value 3 - Fit RampStop configures the drive to perform a ramp stop and set the appropriate fault bit, in response this event.</li> <li>Value 4 - FitCurLimStp configures the drive to perform a current-limit stop and set the appropriate fault bit, in response this event.</li> </ul>	<p>Default: 2 "FitCoastStop"</p> <p>Options: 0 "Ignore" 1 "Alarm" 2 "FitCoastStop" 3 "Fit RampStop" 4 "FitCurLimStp"</p>			
<div style="display: flex; align-items: center;">  <p><b>ATTENTION:</b> Risk of injury or equipment damage exists. Parameter 392 [NetLoss DPI Cnfg] lets you determine the action of the drive if communications are disrupted. By default this parameter causes the drive fault and coast to a stop. You can set this parameter so that the drive continues to run. Precautions should be taken to ensure that the setting of this parameter does not create hazards of injury or equipment damage.</p> </div>					
393	<p><b>BusUndervoltCnfg</b> Enter a value to configure the drive's response to DC Bus voltage falling below the minimum value.</p> <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FitCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> <li>Value 3 - Fit RampStop configures the drive to perform a ramp stop and set the appropriate fault bit, in response this event.</li> <li>Value 4 - FitCurLimStp configures the drive to perform a current-limit stop and set the appropriate fault bit, in response this event.</li> </ul>	<p>Default: 1 "Alarm"</p> <p>Options: 0 "Ignore" 1 "" 2 "FitCoastStop" 3 "Fit RampStop" 4 "FitCurLimStp"</p>			










No.	Name Description	Values	Linkable	Read-Write	Data Type
394	<b>VoltFdbkLossCnfg</b> Enter a value to configure the drive's response to a communication error between Motor Control (MC) and the motor voltage feedback board. <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FitCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> </ul>	Default: 2 "FitCoastStop" Options: 0 "Ignore" 1 "Alarm" 2 "FitCoastStop"			
396	<b>User Data Int 01</b> General purpose parameter available for storage of 32 bit enumerated data by the operator. This value will be retained through a power cycle.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
397	<b>User Data Int 02</b> General purpose parameter available for storage of 32 bit enumerated data by the operator. This value will be retained through a power cycle.	Default: 0 Min/Max: -/+2147483648		✓	32-bit Integer
398	<b>User Data Int 03</b> General purpose parameter available for storage of 32 bit enumerated data by the operator. This value will be retained through a power cycle.	Default: 0 Min Max: -/+2147483648		✓	32-bit Integer
399	<b>User Data Int 04</b> General purpose parameter available for storage of 32 bit enumerated data by the operator. This value will be retained through a power cycle.	Default: 0 Min/Max: -/+2147483648		✓	32-bit Integer
400	<b>Rated Amps</b> This displays the currenting rating of the inverter. The drive automatically sets this at power up.	Units: Amps Default: 22.0000 Min/Max: 0.1000/1000.0000			Real
401	<b>Rated Volts</b> This displays the name plate voltage rating of the inverter. The drive automatically sets this at power up.	Units: Volt Default: 480 Min/Max: 75/690			16-bit Integer
402	<b>PWM Frequency</b> Sets the carrier frequency for the PWM output of the drive. Drive derating may occur at higher carrier frequencies. For derating information, refer to the PowerFlex Reference Manual. Default is dependant on power structure of the 'drive.	Units: kHz Default: 2.0000 (Fr 5, 6, 9) 4.0000 (Fr 1-4) Min/Max: 1.0000/15.0000 (10.0000 Fr 5, 6, 9)			Real
403	<b>Voltage Class</b> Sets the drive configuration for high or low voltage class (I.e. a 400 or 480V ac drive). Allows choice of configuration and affects many drive parameters including drive rated current, voltage, power, over loads and maximum PWM carrier frequency.  <b>Note:</b> Frame 5 & 6 Drives - The internal fan voltage may have to be changed when using option 4 or 5. See "Selecting/Verifying Fan Voltage" on page 1-9.	Default: 3 "High Voltage" Options: 2 "Low Voltage" 3 "High Voltage"			
404	<b>Dead Time</b> The time delay between turning off and turning on an upper device and a lower device in the power structure. This parameter is set at power up and is not user adjustable.	Units: µSec Default: 5.0000 Min/Max: 2.0000/100.0000			Real
405	 <b>Dead Time Comp</b> The amount of voltage correction used to compensate for the loss of voltage during dead time. Do not adjust. Contact factory for alternative settings.	Units: % Default: 0 Min/Max: 0/200		✓	16-bit Integer
406	 <b>Power Loss Mode</b> Enter a value to configure the drive's response to a loss of input power. Input voltage below the value specified in Par 408 [Power Loss Level]. Enter a value of 0 to make the drive coast (supply no current to the motor) during the power loss time (specified by Par 407 [Power Loss Time]). Enter a value of 2 to make the drive continue "normal" operation during the power loss time. Enter a value of 5 to make the drive provide only motor flux current during the power loss time.	Default: 0 "Coast" Options: 0 "Reserved" 1 "Continue" 2 "Reserved" 3 "Reserved" 4 "Flux Only"			
407	<b>Power Loss Time</b> Sets the time that the drive will remain in power loss mode before a fault is detected.	Units: Sec Default: 2.0000 Min/Max: 0.0000 60.0000		✓	Real
408	<b>Power Loss Level</b> Sets the bus voltage level at which ride-through begins and modulation ends. When bus voltage falls below this level, the drive prepares for an automatic reset. Enter a percentage of the bus voltage derived from the high voltage setting for the voltage class For example: on a 400-480V drive,  $0.221 \times 480V_{ac} \times \sqrt{2} = 150V_{dc}$	Units: % Default: 22.1 Min/Max: 15/95		✓	16-bit Integer
409	 <b>Line Undervolts</b> Controls the level of bus voltage that is needed to complete precharge and sets the level for undervoltage alarm/fault detection. Enter a percentage of the bus voltage derived from the value in Par 401 [Rated Volts]. For example: on a 480V drive,  $0.615 \times 480V_{ac} \times \sqrt{2} = 418V_{dc}$	Units: % Default: 61.5000 Min/Max: 10.0000/90.0000		✓	Real
410	 <b>PreChrg TimeOut</b> Sets the time duration of precharge. If bus voltage does not stabilize within this amount of time, a Precharge Error exception event occurs.	Units: Sec Default: 30.0000 Min/Max: 10.0000 180.0000		✓	Real

No.	Name Description	Values	Linkable	Read-Write	Data Type																																																																																																
411	<b>PreChrg Control</b> Must equal 1 to allow drive to exit precharge and begin to run. Link this parameter to a controller output word to coordinate the precharge of multiple drives.	Default: 1 "Enbl PrChrg" Options: 0 "Hold PrChrg" 1 "Enbl PrChrg"																																																																																																			
412	<b>Power EE TP Sel</b> Enter or write a value to select drive power EEPROM data displayed in Par 413 [Power EE TP Data].	Default: 0 Zero																																																																																																			
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413	<b>Power EE TP Data</b> Displays the data selected by Par 412 [Power EE TP Sel].	Default: 0 Min/Max: -/+2200000000			Real																																																																																																
414	<b>Brake/Bus Cnfg</b> Configures the brake and bus operation of the drive. <ul style="list-style-type: none"> <li>Set bit 0 [Brake Enable] to enable the operation of the internal brake transistor.</li> <li>Set bit 1 [Brake Extern] to configure the brake to use an external resistor.</li> <li>Set bit 2 [BusRef High] to select the "high" voltage setting as the turn-on point for the Bus Voltage Regulator. With the "high" setting brake operation starts when bus voltage reaches the value of Par 415 [BusReg/Brake Ref], and Bus Voltage Regulator operation starts when bus voltage reaches the value of 415 [BusReg/Brake Ref] plus 4.5%. With the "low" setting both brake and regulator operation start when bus voltage reaches the value of 415 [BusReg/Brake Ref].</li> <li>Set bit 3 [Bus Reg En] to enable the Bus Voltage Regulator. The output of the Bus Voltage Regulator is summed with Par 12 [Regen Power Lim] and fed into the Power Limit Calculator. It, in effect, reduces negative torque references when the bus voltage is too high.</li> </ul>	Options																																																																																																			
<table border="1"> <thead> <tr> <th></th> <th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Reserved</th><th>Bus Reg En</th><th>BusRef High</th><th>Brake Extern</th><th>Brake Enable</th> </tr> </thead> <tbody> <tr> <td>Default</td> <td>0</td><td>0</td><td>1</td><td>1</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td> </tr> <tr> <td>Bit</td> <td>15</td><td>14</td><td>13</td><td>12</td><td>11</td><td>10</td><td>9</td><td>8</td><td>7</td><td>6</td><td>5</td><td>4</td><td>3</td><td>2</td><td>1</td><td>0</td><td></td><td></td> </tr> </tbody> </table>							Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Bus Reg En	BusRef High	Brake Extern	Brake Enable	Default	0	0	1	1	0	0	0	0	0	0	0	0	0	0	0	0	0	0	Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0																																									
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0 = False 1 = True																																																																																																					
415	<b>BusReg/Brake Ref</b> Sets the "turn-on" voltage for the bus regulator and brakes. Enter a percentage of the high volatge setting for the voltage class (e.g., on a 400-480V drive, $111 \times \sqrt{2} \times 480 = \text{VDC}$	Units: % Default: 111.0000 Min/Max: 110.5000/117.8000		✓	Real																																																																																																
416	<b>Brake PulseWatts</b> Limits the power delivered to the external Dynamic Brake (DB) resistor for one second, without exceeding the rated element temperature. You may change the value of this parameter only if you have selected and external DB resistor (set bit 1 [Brake Extern] of Par 414 [Brake/Bus Cnfg]. If this rating is not available from the resistor vendor, you can approximate it with this equation: Par 416 [Brake PulseWatts] = 75,000 x Weight, where Weight equals the weight of resistor wire element in pounds (not the entire weight of the resistor). Another equation you can use is: Par 416 [Brake PulseWatts] = Time Constant x Brake Watts; where Time Constant equals the amount of time to reach 63% of its rated temperature the maximum power applied, and Brake Watts is the maximum power rating of the resistor.	Units: Watt Default: 2000.0000 Min/Max: 1.0000/1000000.0000		✓	Real																																																																																																
417	<b>Brake Watts</b> Sets the maximum continuous power reference for the Dynamic Brake (DB). You may change the value of this parameter only if you have selected and external DB resistor (set bit 1 [Brake Extern] of Par 414 [Brake/Bus Cnfg].	Units: Watt Default: 100.0000 Min/Max: 0.0000/5000.0000		✓	Real																																																																																																

No.	Name Description	Values	Linkable	Read-Write	Data Type
418	<b>Brake TP Sel</b> Enter or write a value to select the drive overload data displayed in Par 419 [Brake TP Data].	Default: 0 "Zero" Options: 0 "Zero" 10 "Data State" 1 "Duty Cycle" 11 "MC BrakeEnbl" 2 "Power Actual" 12 "1/rdb" 3 "Max BodyTemp" 13 "1/th_eb" 4 "Max ElemTemp" 14 "1/ce" 5 "BodyTemp Act" 15 "tamax" 6 "ElemTemp Act" 16 "1/th_ba" 7 "BTmpTripStat" 17 "1/cb" 8 "ETmpTripStat" 18 "DB IGBT Amp" 9 "Int DB Ohms"			
419	<b>Brake TP Data</b> Displays the data selected by Par 418 [Brake TP Sel].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
421	<b>Iqs Integ Freq</b> Sets the break frequency of the torque producing (q-axis) current regulator. This and Par 422 [Iqs Reg P Gain] determine the integral gain for the q-axis current regulator. Set by the autotune procedure. Do not change this value.	Units: R/S Default: 10 Min/Max: 0/32767		✓	16-bit Integer
422	<b>Iqs Reg P Gain</b> Sets the proportional gain of the torque producing (q-axis) current regulator. Set by the autotune procedure. Do not change this value.	Default: 1.0 Min/Max: 0.0/100.0 Comm Scale: x 10		✓	16-bit Integer
423	<b>Iqs Rate Limit</b> Sets the limit of the rate of change for the torque producing (q-axis) current regulator. Do not change this parameter. Use Par 355 [Iq Rate Limited] to control the q-axis current rate limit.	Units: %/mS Default: 800.0 Min/Max: 0.0/800.0 Comm Scale: x 10		✓	16-bit Integer
424	<b>Flux Ratio Ref</b> Active only in the FOC 2 control mode (when Par 485 [Motor Ctrl Mode] equals 2 - FOC 2), when activated (Par 511 [FOC2 Mode Config] / bit 28 [FluxRatioRef] is set). Provides scaling factor for the flux producing (d-axis) current reference. • When active (Par 511 [FOC2 Mode Config] / bit 28 [FluxRatioRef] is set), Flux Producing (d-axis) Current Reference = Par 488 [Flux Current] x Par 424 [Flux Ratio Ref] • When inactive (Par 511 [FOC2 Mode Config] / bit 28 [FluxRatioRef] is cleared) Flux Producing (d-axis) Current Reference = Par 488 [Flux Current] below base speed and Flux Producing (d-axis) Current Reference = Par 488 [Flux Current] x motor base speed/motor speed above base speed.	Units: % Default: 99.99 Min/Max: 12.50/399.99 Comm Scale: 100 = 32767		✓	16-bit Integer
425	<b>Flux Rate Limit</b> Sets the limit of the rate of change for flux producing (d-axis) current.	Units: %/mS Default: 1.0 Min/Max: 0.0/195.3 Comm Scale: x 10		✓	16-bit Integer
426	<b>Flux Satur Coef</b> This represents the amount of flux current required to compensate for the flux saturation effect of the motor.	Units: %/ Default: 0.0 Min/Max: 0.0/51.3 Comm Scale: x 10		✓	
427	<b>PM Mtr CEMF Comp</b> Provides CEMF compensation for the torque producing (q-axis) current in the permanent magnet motor mode.	Units: % Default: 0 Min/Max: 0/100		✓	16-bit Integer
428	<b>IReg IGainFctr</b> Adjustment for current regulator integral frequency factor (gain).	Default: 1 Min/Max: 1/20			
429	<b>Ids Integ Freq</b> Sets the break frequency of the flux producing (d-axis) current regulator. This and Par 430 [Ids Reg P Gain] determine the integral gain for the d-axis current regulator. Set by the autotune procedure. Do not change this value.	Units: R/S Default: 10 Min/Max: 0/32767		✓	16-bit Integer
430	<b>Ids Reg P Gain</b> Sets the proportional gain of the flux producing (d-axis) current regulator. Set by the autotune procedure. Do not change this value.	Default: 1.0 Min/Max: 0.0/100.0 Comm Scale: x 10		✓	16-bit Integer
431	<b>Test Current Ref</b> Sets the current reference used for Motor Control (MC) Test Mode.	Units: % Default: 50.0 Min/Max: 0.0/799.9 Comm Scale: x 10		✓	16-bit Integer
432	<b>Test Freq Ref</b> Sets the frequency reference used for Motor Control (MC) Test Mode.	Units: % Default: 10.0 Min/Max: -/+799.9 Comm Scale: x 10		✓	16-bit Integer
433	<b>Test Freq Rate</b> Sets the rate of change of frequency reference used for Motor Control (MC) Test Mode.	Units: %/S Default: 5.0 Min/Max: 0.0/1000.0 Comm Scale: x 10		✓	16-bit Integer
434	<b>Mtr Vds Base</b> Displays the motor flux producing (d-axis) voltage command when running at nameplate motor speed and load. This value is determined during the auto-tune procedure. Do not change this value.	Default: 0 Min/Max: -8192/0			16-bit Integer

No.	Name Description	Values	Linkable	Read-Write	Data Type
435	<b>Mtr Vqs Base</b> Displays the motor torque producing (q-axis) voltage command when running at nameplate motor speed and load. This value is determined during the auto-tune procedure. Do not change this value.	Default: 0 Min/Max: 0/8192			16-bit Integer
437	<b>Vqs Max</b> Displays the maximum torque producing (q-axis) voltage allowed on the motor. Adaption is disabled below this voltage. This value is determined during the auto-tune procedure. Do not change this value.	Default: 7971 Min/Max: 0/32767		✓	16-bit Integer
438	<b>Vds Max</b> Displays the maximum flux producing (d-axis) voltage allowed on the motor. Adaption is disabled below this voltage. This value is determined during the auto-tune procedure. Do not change this value.	Default: 5793 Min/Max: 0/32767		✓	16-bit Integer
439	<b>Vqs Min</b> Displays the minimum torque producing (q-axis) voltage required for motor control adaption. Adaption is disabled below this voltage. This value is determined during the auto-tune procedure. Do not change this value.	Default: 246 Min/Max: -/+32767		✓	16-bit Integer
440	<b>Vds Min</b> Displays the minimum flux producing (d-axis) voltage required for motor control adaption. Adaption is disabled below this voltage. This value is determined during the auto-tune procedure. Do not change this value.	Default: 246 Min/Max: -/+32767		✓	16-bit Integer
441	<b>Vds Fdbk Filt</b> Displays measured filtered motor flux producing (d-axis) voltage.	Default: 0 Min/Max: -/+32767			16-bit Integer
442	<b>Vqs Fdbk Filt</b> Displays measured filtered motor torque producing (q-axis) voltage.	Default: 0 Min/Max: -/+32767			16-bit Integer
443	<b>Flux Reg P Gain1</b> Sets the Proportional (P) gain for the flux regulator. Do not change this value.	Default: 150 Min/Max: 0/32767		✓	16-bit Integer
444	<b>Flux Reg I Gain</b> Sets the Integral (I) gain for the flux regulator. Do not change this value.	Default: 350 Min/Max: 0/32767		✓	16-bit Integer
445	<b>Slip Gain Max</b> Displays the maximum slip frequency allowed in the motor control. Scaling is in hertz x 256. This value is determined during the auto-tune procedure. Do not change this value.	Units: % Default: 300 Min/Max: 100/10000		✓	16-bit Integer
446	<b>Slip Gain Min</b> Displays the minimum slip frequency allowed in the motor control. Scaling is in hertz x 256. This value is determined during the auto-tune procedure. Do not change this value.	Units: % Default: 50 Min/Max: 0/100		✓	16-bit Integer
447	<b>Slip Reg P Gain</b> Sets the Proportional (P) gain for the slip regulator. Do not change this value.	Default: 35 Min/Max: 0/32767 Comm Scale: x 1		✓	16-bit Integer
448	<b>Slip Reg I Gain</b> Sets the Integral (I) gain for the slip regulator. Do not change this value.	Default: 100 Min/Max: 0/32767		✓	16-bit Integer
449	<b>Freq Reg I Gain</b> Sets the integral gain of the Frequency Regulator, which estimates motor speed when sensorless feedback is selected. Do not change this value.	Default: 250 Min/Max: 0/32767	✓	✓	16-bit Integer
450	<b>Freq Reg P Gain</b> Sets the proportional gain of the Frequency Regulator, which estimates motor speed when sensorless feedback is selected. Do not change this value.	Default: 350 Min/Max: 0/32767	✓	✓	16-bit Integer
451	<b>SrLss Preset Spd</b> Motor speed at which to start the sensorless frequency search.	Units: RPM Default: 1750.0 Min/Max: -/+13999.6			
453	<b>Iu Offset</b> Sets the current offset correction for the phase U current. Value is set automatically when the drive is not running and Motor Control (MC) is not faulted. Do not change this value.	Default: 0 Min/Max: -/+32767		✓	16-bit Integer
454	<b>Iw Offset</b> Sets the current offset correction for the flux producing (d-axis) current regulator. This value is set automatically when the drive is not running and Motor Control (MC) is not faulted. Do not change this value.	Default: 0 Min/Max: -/+32767		✓	16-bit Integer
469	<b>StatorInduc Gain</b> Displays the current regulator feedforward compensation. Do not change this value.	Units: % Default: 0 Min/Max: 0/100		✓	16-bit Integer
470	<b>Flux Reg P Gain2</b> Displays the additional proportional gain used at the start of Bus voltage limited field weakening. Do not change this value.	Default: 1000 Min/Max: 0/32767		✓	16-bit Integer
472	 <b>PreCharge Delay</b> Adjusts a delay between the time all other precharge conditions have been met and the time the drive leaves the precharge state. Can be used to control the sequence of precharge completion in a drive system.	Units: Sec Default: 0.2 Min/Max: 00.0/29.0		✓	16-bit Integer
473	<b>Freq Reg FF Gain</b> Provides feed forward gain to the Frequency Regulator, which estimates motor speed when sensorless feedback is selected. Higher gains make operation at low speeds smoother. However, higher gains may make operation at high speeds less stable.	Default: 300 Min/Max: 0/32767		✓	16-bit Integer



No.	Name Description	Values	Linkable	Read-Write	Data Type
474	<b>Freq Reg We BW</b> Sets the electrical (stator) frequency bandwidth for the Frequency Regulator, which estimates motor speed when sensorless feedback is selected.  Must always be set to a value higher than Par 475 [Freq Reg Wr BW].	Default: 150 Min/Max: 0/32767		✓	16-bit Integer
475	<b>Freq Reg Wr BW</b> Sets the rotor (speed) frequency bandwidth for the Frequency Regulator, which estimates motor speed when sensorless feedback is selected.  Must always be set to a value higher than Par 97 [Act Spd Reg BW]. Normal applications should use a value approximately 50% greater than Par 97. Applications with large dynamic ranges can use values 200-300% greater than Par 97. However large values can result in pull-outs and unstable operation.	Default: 30 Min/Max: 0/32767		✓	16-bit Integer
476	<b>Slip Gain Comp</b> Provides slip gain compensation for sensorless speed adjustment.	Units: % Default: 100.00 Min/Max: 0.00/400.00		✓	16-bit Integer
477	<b>Est Theta Delay</b> Active only in Permanent Magnet motor mode (when Par 485 [Motor Ctrl Mode] equals 4 - PMag Motor). Provides a delay for the function that compares the estimated rotor position and the data from the position sensor.	Units: mSec Default: 10 Min/Max: 2/1024		✓	16-bit Integer
485	 <b>Motor Ctrl Mode</b> Enter a value to select the operating mode for the Motor Control (MC). <ul style="list-style-type: none"> <li>Value 0 - FOC is Field Oriented Control (FOC) is induction motor control with voltage adaption.</li> <li>Value 1 - FOC 2 is Field Oriented Control 2 (FOC 2) is induction motor control with temperature adaption.</li> <li>Value 2 - Pmag Motor is Permanent Magnet Motor Control (Pmag Motor) is permanent magnet motor operation.</li> <li>Value 4 - Test is the test mode.</li> </ul>	Default: 0 "FOC" Options: 0 "FOC" 3 "Reserved" 1 "FOC 2" 4 "Test" 2 "PMag Motor"			
486	 <b>Rated Slip Freq</b> Displays the control slip frequency, determined from Par 3 [Motor NP Hertz] and Par 4 [Motor NP RPM]. Measured by the autotune procedure. Do not change this value.	Units: Hz Default: 0.470 Min/Max: 0.000/32.000 Comm Scale: x 1000		✓	16-bit Integer
487	 <b>Motor NTC Coef</b> Defines a coefficient used to calculate the rotor temperature from the measured stator temperature. Used only in Field Oriented Control - 2 (FOC2) mode.	Units: % Default: 100 Min/Max: 50/200		✓	16-bit Integer
488	 <b>Flux Current</b> Specifies the magnetizing current that produces rated flux in the motor in a per unit (percent representation). Measured by the auto-tune procedure. Do not change this value.	Units: % Default: 30.00 Min/Max: 0.00/75.00 Comm Scale: x 100		✓	16-bit Integer
490	 <b>StatorInductance</b> Displays the sum of the stator and cable inductances of the motor in per unit (percent representation), as determined by the auto-tune procedure. Scaled to percent of rated motor impedance. Do not change this value.	Units: % Default: 100.00 Min/Max: 0.00/799.99 Comm Scale: 100 = 8192\		✓	16-bit Integer
491	 <b>StatorResistance</b> Displays the sum of the stator and cable resistances of the motor in per unit (percent representation), as determined by the auto-tune procedure. Scaled to percent of rated motor impedance. Do not change this value.	Units: % Default: 1.00 Min/Max: 0.00/100.00 Comm Scale: 100 = 8192		✓	16-bit Integer
492	 <b>Leak Inductance</b> Displays the sum of the motor stator, rotor leakage, and motor cable inductances in per unit (percent representation), as determined by the auto-tune procedure. Scaled to percent of rated motor impedance. Do not change this value.	Units: % Default: 20.00 Min/Max: 0.00/100.00 Comm Scale: 100 = 8192		✓	16-bit Integer
493	<b>Leak Indc Satur1</b> Displays the leakage inductance correction for the first overload level as determined by the autotune procedure.	Units: % Default: 100.00 Min/Max: 25.00/100.00			16-bit Integer
494	<b>Leak Indc Satur2</b> Displays the leakage inductance correction for the first overload level as determined by the auto-tune procedure.	Units: % Default: 100.00 Min/Max: 25.00/100.00			16-bit Integer
500	<b>Bus Util Limit</b> Sets the maximum allowed bus voltage utilization for the Motor Control. Do not change this value. Higher values may result in control instability or over-current faults.	Units: % Default: 90.0 Min/Max: 0.0/100.0 Comm Scale: 100 = 8192		✓	16-bit Integer
501	 <b>Torque En Dly</b> Sets the delay between the time the drive is enabled and the time the Motor Control applies torque.	Units: mSec Default: 100 Min/Max: 0/32767 Comm Scale: 100 = 8192		✓	16-bit Integer
502	 <b>Rotor Resistance</b> Displays rotor resistance, as determined by the auto-tune procedure. Scaled to percent of rated motor impedance. Do not change this value.	Units: % Default: 1.00 Min/Max: 0.00/100.00 Comm Scale: 100 = 8192		✓	16-bit Integer

No.	Name Description	Values	Linkable	Read-Write	Data Type
503	<b>Current Reg BW</b> Sets the bandwidth for the current regulator. Par 402 [PWM Frequency] limits the maximum value. Reducing the value reduces current regulator over-shoot.	Units: R/S Default: 600 Min/Max: 100/30000		✓	16-bit Integer
504	<b>PM AbsEncd Offst</b> Determined by auto-tune procedure.	Default: 0 Min/Max: 0/65535		✓	16-bit Integer
505	<b>PM TestWait Time</b> Defines the time interval used for the automated measurement of Par 504 [PM AbsEncd Offst] for a Permanent Magnet (PM) motor.	Units: mSec Default: 2000 Min/Max: 500/5000		✓	16-bit Integer
506	<b>PM Test Idc Ramp</b> Defines the ramp rate of the Flux Producing (d-axis) current reference that is used for the automated measurement of Par 504 [PM AbsEncd Offst] for a Permanent Magnet (PM) motor.	Units: %/mS Default: 0.1 Min/Max: 0.0/195.3 Comm Scale: x 10		✓	16-bit Integer
507	<b>PM Test FreqRamp</b> Defines the ramp rate of the frequency reference that is used for the automated measurement of Par 504 [PM AbsEncd Offst] for a Permanent Magnet (PM) motor.	Units: %/mS Default: 0.1 Min/Max: 0.0/195.3 Comm Scale: x 10		✓	16-bit Integer
508	<b>PM Test Freq Ref</b> Defines the frequency reference that is used for the automated measurement of Par 504 [PM AbsEncd Offst] for a Permanent Magnet (PM) motor.	Units: % Default: 10.0 Min/Max: -/+799.9 Comm Scale: x 10		✓	16-bit Integer
509	<b>PM Test I Ref</b> Defines the amplitude of the Flux Producing (d-axis) current reference that is used for the automated measurement of Par 504 [PM AbsEncd Offst] for a Permanent Magnet (PM) motor.	Units: % Default: 30.0 Min/Max: 0.0/799.9 Comm Scale: x 10		✓	16-bit Integer

**510 FOC Mode Config**  
Configures Field Oriented Control (FOC) operation.



**ATTENTION:** Do not modify this parameter. Motor/Drive instabilities and damage could result.

Options	Reserved	Reserved	Reserved	Reserved	Reserved	FS PresetSpd	Reserved	Reserved	SlLssStartEn	SlLss Rd Thru	SlLssWeLimit	SlLss WeHold	Reserved	Reserved	Reserved	Reserved	Reserved	Slip Reg En	SlipGain Est	RsEst Update	RsEst Ratio	RsEst Adapt	RefWaveComp	BusGain Comp	LwSpd VqsReg	Flux Reg Use	Flux Reg En	Reserved	Reserved	Reserved	Reserved	Reserved
Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	1	1	1	0	0	1	1	0	1	1	0	0	0	0	0
Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0

0 = False  
1 = True

Bit	Definition
23	Enables Sensorless Flying start
26	Sensorless Flying start function will use the speed set in Par 451.





**511 FOC2 Mode Config**  
Configures Field Oriented Control - 2 (FOC2) operation.



**ATTENTION:** Do not modify this parameter. Motor/Drive instabilities and damage could result.

Options	LmSnsr Dir	LrSnsr Use	Reserved	FixRatRF Use	NTC Active	Reserved	Reserved	CEMF We Use	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	RefWaveComp	BusGain Comp	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	
Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	1	10	0	1	1	0	0	0	0	0	
Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0

0 = False  
1 = True


No.	Name Description	Values	Linkable	Read-Write	Data Type																											
512	<b>PMag Mode Cnfg</b> Configures Permanent Magnet (PM) operation.																															
	 <b>ATTENTION:</b> Do not modify this parameter. Motor/Drive instabilities and damage could result.																															
	Options																															
	Reserved	LmSnsr Use	Reserved	FixRatRf Use	NTC Active	Reserved	Reserved	CEMF We Use	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	RefWaveComp	BusGain Comp	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved				
Default	0	0	0	0	1	0	0	0	0	0	0	0	0	0	0	0	0	0	1	0	0	0	0	0	0	0	0	0				
Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
	0 = False 1 = True																															
514	<b>Test Mode Config</b> Configures the Motor Control (MC) test mode.																															
	 <b>ATTENTION:</b> Do not modify this parameter. Motor/Drive instabilities and damage could result.																															
	Options																															
	Reserved	Reserved	Reserved	BusGain Comp	RefWave Comp	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved
Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0
Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
	0 = False 1 = True																															
515	<b>FOC Tune Config</b>																															
	 <b>ATTENTION:</b> Do not modify this parameter. Motor/Drive instabilities and damage could result.																															
	Options																															
	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	NoRotate Tune	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	
Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	
Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0																
	0 = False 1 = True																															
516	<b>FOC2 Tune Config</b>																															
	 <b>ATTENTION:</b> Do not modify this parameter. Motor/Drive instabilities and damage could result.																															
	Options																															
	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	PwrStrct md1	PwrStrct md0	
Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0		
Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
	0 = False 1 = True																															



No.	Name Description	Values	Linkable	Read-Write	Data Type																																																																																																																																																																																																																																																																																																																																																																																																																																																
544	<p><b>MC TP Select</b> Enter or write a value to select Motor Control (MC) data displayed in Pars 545 [MC TP Value], and 546 [MC TP Bit], Pars 545 [MC TP Value], and 546 [MC TP Bit] are diagnostic tools you can use to view internal drive Pars.</p> <p>Options:</p> <table border="0"> <tr> <td>0</td><td>MulqsRef2</td><td>36</td><td>DcBus</td><td>72</td><td>ThetaEcor</td><td>108</td><td>VqsFluxPl</td><td>144</td><td>VbusFdbkFiltr</td><td>180</td><td>SrLssIntMon</td> </tr> <tr> <td>1</td><td>SlipRatio</td><td>37</td><td>AGnd</td><td>73</td><td>SinThtaEcor1</td><td>109</td><td>VqsIntegral</td><td>145</td><td>VbusMemory</td><td>181</td><td>SLWeNegLmt</td> </tr> <tr> <td>2</td><td>Ws</td><td>38</td><td>Wr2</td><td>74</td><td>SinThtaEcor2</td><td>110</td><td>VqsPrportl1</td><td>146</td><td>VpEnc0VelFbk</td><td>182</td><td>SLWrScale</td> </tr> <tr> <td>3</td><td>WrEst2</td><td>39</td><td>FluxRatio1</td><td>75</td><td>SinThtaEcor3</td><td>111</td><td>VqsPrportnl2</td><td>147</td><td>VpEnc1VelFbk</td><td>183</td><td>SLErrNoCoher</td> </tr> <tr> <td>4</td><td>We</td><td>40</td><td>VbusFdbk</td><td>76</td><td>SinThtaEcor4</td><td>112</td><td>TestMark70</td><td>148</td><td>VPOpt0VelFbk</td><td>184</td><td>SLIntLmtPosM</td> </tr> <tr> <td>5</td><td>VdsCmd</td><td>41</td><td>FluxRatio2</td><td>77</td><td>DeltaCounts</td><td>113</td><td>TestMark71</td><td>149</td><td>VPOpt1VelFbk</td><td>185</td><td>SLIntLmtNegM</td> </tr> <tr> <td>6</td><td>VqsCmd</td><td>42</td><td>FluxRatio3</td><td>78</td><td>MulRef2B</td><td>114</td><td>TestMark72</td><td>150</td><td>BitSelect1</td><td>186</td><td>RsEst</td> </tr> <tr> <td>7</td><td>VuCmd1</td><td>43</td><td>FluxRatio4</td><td>79</td><td>SpdCount</td><td>115</td><td>TestMark73</td><td>151</td><td>BitSelect2</td><td>187</td><td>RsEstCosPhi</td> </tr> <tr> <td>8</td><td>VvCmd1</td><td>44</td><td>MuFlxRtioRef</td><td>80</td><td>SpdError</td><td>116</td><td>TestMark74</td><td>152</td><td>SrLssWeEst2</td><td>188</td><td>RsEstCosPhi</td> </tr> <tr> <td>9</td><td>VwCmd1</td><td>45</td><td>RcpFlxRatio1</td><td>81</td><td>SpdFdbk</td><td>117</td><td>TestMark75</td><td>153</td><td>SrLssPrportl</td><td>189</td><td>RsEstIqsCmdP</td> </tr> <tr> <td>10</td><td>IuFdbk</td><td>46</td><td>MulfluxRef</td><td>82</td><td>SpdIntegral</td><td>118</td><td>TestMark76</td><td>154</td><td>SrLssPI</td><td>190</td><td>RsEstPhi</td> </tr> <tr> <td>11</td><td>IwFdbk</td><td>47</td><td>MultestRef</td><td>83</td><td>SpdPrportnal</td><td>119</td><td>TestMark76</td><td>155</td><td>SrLssQAWeEst</td><td>191</td><td>RsEstSinPhi</td> </tr> <tr> <td>12</td><td>IdsFdbk</td><td>48</td><td>MotVntc</td><td>84</td><td>SpdPI</td><td>120</td><td>TestMark78</td><td>156</td><td>SrLssQAWeEst</td><td>192</td><td>RsEstVqsFbkP</td> </tr> <tr> <td>13</td><td>IqsFdbk</td><td>49</td><td>BaseSlip</td><td>85</td><td>SpdRef</td><td>121</td><td>TestMark79</td><td>157</td><td>SrLssWsFf</td><td>193</td><td>RsEWeLadsCmd</td> </tr> <tr> <td>14</td><td>VdsFdbk</td><td>50</td><td>VbusFdbk2</td><td>86</td><td>SlipGainEst</td><td>122</td><td>TestMark7A</td><td>158</td><td>SrLssWsEst</td><td>194</td><td>REWeLadsCmdP</td> </tr> <tr> <td>15</td><td>VuvFdbk</td><td>51</td><td>VdsFdbk2</td><td>87</td><td>SlipGainFf</td><td>123</td><td>TestMark7B</td><td>159</td><td>SrLssWsCmd</td><td>195</td><td>RsEWeLaqsCmd</td> </tr> <tr> <td>16</td><td>VvwFdbk</td><td>52</td><td>VqsFdbk2</td><td>88</td><td>Ws2</td><td>124</td><td>TestMark7C</td><td>160</td><td>SrLssVdsErr</td><td>196</td><td>RsEstIdsRat</td> </tr> <tr> <td>17</td><td>VqsFdbk</td><td>53</td><td>VdsSpdVltFit</td><td>89</td><td>SlipGain</td><td>125</td><td>TestMark7D</td><td>161</td><td>SLVdsErrComp</td><td>197</td><td>RsEstIqsRat</td> </tr> <tr> <td>18</td><td>IdsCmd</td><td>54</td><td>WrEst1</td><td>90</td><td>SlipGainFiltr</td><td>126</td><td>TestMark7E</td><td>162</td><td>SrLssStrtTmr</td><td>198</td><td>FldWklnitTim</td> </tr> <tr> <td>19</td><td>IqsRatio</td><td>55</td><td>MuTestFrqRef</td><td>91</td><td>SlipVdsCmd</td><td>127</td><td>TestMark7F</td><td>163</td><td>SrLssStrtTmr</td><td>199</td><td>MotorVolts</td> </tr> <tr> <td>20</td><td>MulqsRef</td><td>56</td><td>TestFrqRef</td><td>92</td><td>SlpVdsCmdFilt</td><td>128</td><td>RWVuOut</td><td>164</td><td>SrLssWeAve</td><td>200</td><td>BusUtilizatn</td> </tr> <tr> <td>21</td><td>IqsCmd</td><td>57</td><td>FluxFiltrN_1</td><td>93</td><td>VdsLastError</td><td>129</td><td>RWVvOut</td><td>165</td><td>SrLssWeEst</td><td>201</td><td>MulqsRef2</td> </tr> <tr> <td>22</td><td>We2</td><td>58</td><td>PrchgDlayCtr</td><td>94</td><td>VdsPrportnal</td><td>130</td><td>RWVwOut</td><td>166</td><td>SrLssKpMonit</td><td>202</td><td>BusDropVolts</td> </tr> <tr> <td>23</td><td>VuTd</td><td>59</td><td>PrchTimOutCr</td><td>95</td><td>VdsPrportnal</td><td>131</td><td>RWVuOut1</td><td>167</td><td>SrLssKiMonit</td><td>203</td><td>BusDropVolts</td> </tr> <tr> <td>24</td><td>VvTd</td><td>60</td><td>PrchPilotCtr</td><td>96</td><td>IqsLimit</td><td>132</td><td>RWVvOut1</td><td>168</td><td>SLWeKScale</td><td>204</td><td>DbDuty</td> </tr> <tr> <td>25</td><td>VwTd</td><td>61</td><td>TrqEnableCtr</td><td>97</td><td>VqsCmdMotor</td><td>133</td><td>RWVwOut1</td><td>169</td><td>SrLssWrAve</td><td>205</td><td>EstThetaByMV</td> </tr> <tr> <td>26</td><td>VuCmd2</td><td>62</td><td>MuTscan1</td><td>98</td><td>We2FieldWeak</td><td>134</td><td>RWVuScaleOut</td><td>170</td><td>SrLssWrCmd</td><td>206</td><td>ETVdsFbkA</td> </tr> <tr> <td>27</td><td>VvCmd2</td><td>63</td><td>ErStatFromCp</td><td>99</td><td>We2FieldWeak</td><td>135</td><td>RWVvScaleOut</td><td>171</td><td>SLWeKC2Mon</td><td>207</td><td>ETVdsFbkA</td> </tr> <tr> <td>28</td><td>VwCmd2</td><td>64</td><td>FlxCurRteOut</td><td>100</td><td>VqsldsCmd</td><td>136</td><td>RWVwScaleOut</td><td>172</td><td>SLWrKA2Mon</td><td>208</td><td>ETVdsFbkS</td> </tr> <tr> <td>29</td><td>Kpwm</td><td>65</td><td>ThetaE</td><td>101</td><td>VqsMaxMotor</td><td>137</td><td>RWVuOut2</td><td>173</td><td>SrLssVdsCmd</td><td>209</td><td>ETVqsFbkS</td> </tr> <tr> <td>30</td><td>Vds_cemf</td><td>66</td><td>SinThetaE1</td><td>102</td><td>VqsMaxVbus</td><td>138</td><td>RWVuOut2</td><td>174</td><td>SrLssVdsCmd</td><td>210</td><td>ETAtanVqVd</td> </tr> <tr> <td>31</td><td>Vqs_cemf</td><td>67</td><td>SinThetaE2</td><td>103</td><td>CalcPUMtrFlx</td><td>139</td><td>RWVuOut2</td><td>175</td><td>SLQAWeCal</td><td>211</td><td>ETAtanVqVd</td> </tr> <tr> <td>32</td><td>VdsCmd2</td><td>68</td><td>SinThetaE3</td><td>104</td><td>FldWklnitTim</td><td>140</td><td>RWPosState</td><td>176</td><td>SLQADelay</td><td>212</td><td>VelRef2</td> </tr> <tr> <td>33</td><td>VqsCmd2</td><td>69</td><td>SinThetaE4</td><td>105</td><td>FluxldsFfFilt</td><td>141</td><td>RWNegState</td><td>177</td><td>SLQAWeEstAve</td><td>213</td><td>VelOutput</td> </tr> <tr> <td>34</td><td>IdsIntegral</td><td>70</td><td>SinThetaE5</td><td>106</td><td>FlxVqsCmdFilt</td><td>142</td><td>VdsFdbkFiltr</td><td>178</td><td>SLWeEstErr</td><td>214</td><td>TorqEst</td> </tr> <tr> <td>35</td><td>IqsIntegral</td><td>71</td><td>SinThetaE6</td><td>107</td><td>FlxVqsCmdFilt</td><td>143</td><td>VqsFdbkFiltr</td><td>179</td><td>SrLssIntMon</td><td>215</td><td>TorqEstFiltr</td> </tr> </table>	0	MulqsRef2	36	DcBus	72	ThetaEcor	108	VqsFluxPl	144	VbusFdbkFiltr	180	SrLssIntMon	1	SlipRatio	37	AGnd	73	SinThtaEcor1	109	VqsIntegral	145	VbusMemory	181	SLWeNegLmt	2	Ws	38	Wr2	74	SinThtaEcor2	110	VqsPrportl1	146	VpEnc0VelFbk	182	SLWrScale	3	WrEst2	39	FluxRatio1	75	SinThtaEcor3	111	VqsPrportnl2	147	VpEnc1VelFbk	183	SLErrNoCoher	4	We	40	VbusFdbk	76	SinThtaEcor4	112	TestMark70	148	VPOpt0VelFbk	184	SLIntLmtPosM	5	VdsCmd	41	FluxRatio2	77	DeltaCounts	113	TestMark71	149	VPOpt1VelFbk	185	SLIntLmtNegM	6	VqsCmd	42	FluxRatio3	78	MulRef2B	114	TestMark72	150	BitSelect1	186	RsEst	7	VuCmd1	43	FluxRatio4	79	SpdCount	115	TestMark73	151	BitSelect2	187	RsEstCosPhi	8	VvCmd1	44	MuFlxRtioRef	80	SpdError	116	TestMark74	152	SrLssWeEst2	188	RsEstCosPhi	9	VwCmd1	45	RcpFlxRatio1	81	SpdFdbk	117	TestMark75	153	SrLssPrportl	189	RsEstIqsCmdP	10	IuFdbk	46	MulfluxRef	82	SpdIntegral	118	TestMark76	154	SrLssPI	190	RsEstPhi	11	IwFdbk	47	MultestRef	83	SpdPrportnal	119	TestMark76	155	SrLssQAWeEst	191	RsEstSinPhi	12	IdsFdbk	48	MotVntc	84	SpdPI	120	TestMark78	156	SrLssQAWeEst	192	RsEstVqsFbkP	13	IqsFdbk	49	BaseSlip	85	SpdRef	121	TestMark79	157	SrLssWsFf	193	RsEWeLadsCmd	14	VdsFdbk	50	VbusFdbk2	86	SlipGainEst	122	TestMark7A	158	SrLssWsEst	194	REWeLadsCmdP	15	VuvFdbk	51	VdsFdbk2	87	SlipGainFf	123	TestMark7B	159	SrLssWsCmd	195	RsEWeLaqsCmd	16	VvwFdbk	52	VqsFdbk2	88	Ws2	124	TestMark7C	160	SrLssVdsErr	196	RsEstIdsRat	17	VqsFdbk	53	VdsSpdVltFit	89	SlipGain	125	TestMark7D	161	SLVdsErrComp	197	RsEstIqsRat	18	IdsCmd	54	WrEst1	90	SlipGainFiltr	126	TestMark7E	162	SrLssStrtTmr	198	FldWklnitTim	19	IqsRatio	55	MuTestFrqRef	91	SlipVdsCmd	127	TestMark7F	163	SrLssStrtTmr	199	MotorVolts	20	MulqsRef	56	TestFrqRef	92	SlpVdsCmdFilt	128	RWVuOut	164	SrLssWeAve	200	BusUtilizatn	21	IqsCmd	57	FluxFiltrN_1	93	VdsLastError	129	RWVvOut	165	SrLssWeEst	201	MulqsRef2	22	We2	58	PrchgDlayCtr	94	VdsPrportnal	130	RWVwOut	166	SrLssKpMonit	202	BusDropVolts	23	VuTd	59	PrchTimOutCr	95	VdsPrportnal	131	RWVuOut1	167	SrLssKiMonit	203	BusDropVolts	24	VvTd	60	PrchPilotCtr	96	IqsLimit	132	RWVvOut1	168	SLWeKScale	204	DbDuty	25	VwTd	61	TrqEnableCtr	97	VqsCmdMotor	133	RWVwOut1	169	SrLssWrAve	205	EstThetaByMV	26	VuCmd2	62	MuTscan1	98	We2FieldWeak	134	RWVuScaleOut	170	SrLssWrCmd	206	ETVdsFbkA	27	VvCmd2	63	ErStatFromCp	99	We2FieldWeak	135	RWVvScaleOut	171	SLWeKC2Mon	207	ETVdsFbkA	28	VwCmd2	64	FlxCurRteOut	100	VqsldsCmd	136	RWVwScaleOut	172	SLWrKA2Mon	208	ETVdsFbkS	29	Kpwm	65	ThetaE	101	VqsMaxMotor	137	RWVuOut2	173	SrLssVdsCmd	209	ETVqsFbkS	30	Vds_cemf	66	SinThetaE1	102	VqsMaxVbus	138	RWVuOut2	174	SrLssVdsCmd	210	ETAtanVqVd	31	Vqs_cemf	67	SinThetaE2	103	CalcPUMtrFlx	139	RWVuOut2	175	SLQAWeCal	211	ETAtanVqVd	32	VdsCmd2	68	SinThetaE3	104	FldWklnitTim	140	RWPosState	176	SLQADelay	212	VelRef2	33	VqsCmd2	69	SinThetaE4	105	FluxldsFfFilt	141	RWNegState	177	SLQAWeEstAve	213	VelOutput	34	IdsIntegral	70	SinThetaE5	106	FlxVqsCmdFilt	142	VdsFdbkFiltr	178	SLWeEstErr	214	TorqEst	35	IqsIntegral	71	SinThetaE6	107	FlxVqsCmdFilt	143	VqsFdbkFiltr	179	SrLssIntMon	215	TorqEstFiltr	Default: 0 MulqsRef2			
0	MulqsRef2	36	DcBus	72	ThetaEcor	108	VqsFluxPl	144	VbusFdbkFiltr	180	SrLssIntMon																																																																																																																																																																																																																																																																																																																																																																																																																																										
1	SlipRatio	37	AGnd	73	SinThtaEcor1	109	VqsIntegral	145	VbusMemory	181	SLWeNegLmt																																																																																																																																																																																																																																																																																																																																																																																																																																										
2	Ws	38	Wr2	74	SinThtaEcor2	110	VqsPrportl1	146	VpEnc0VelFbk	182	SLWrScale																																																																																																																																																																																																																																																																																																																																																																																																																																										
3	WrEst2	39	FluxRatio1	75	SinThtaEcor3	111	VqsPrportnl2	147	VpEnc1VelFbk	183	SLErrNoCoher																																																																																																																																																																																																																																																																																																																																																																																																																																										
4	We	40	VbusFdbk	76	SinThtaEcor4	112	TestMark70	148	VPOpt0VelFbk	184	SLIntLmtPosM																																																																																																																																																																																																																																																																																																																																																																																																																																										
5	VdsCmd	41	FluxRatio2	77	DeltaCounts	113	TestMark71	149	VPOpt1VelFbk	185	SLIntLmtNegM																																																																																																																																																																																																																																																																																																																																																																																																																																										
6	VqsCmd	42	FluxRatio3	78	MulRef2B	114	TestMark72	150	BitSelect1	186	RsEst																																																																																																																																																																																																																																																																																																																																																																																																																																										
7	VuCmd1	43	FluxRatio4	79	SpdCount	115	TestMark73	151	BitSelect2	187	RsEstCosPhi																																																																																																																																																																																																																																																																																																																																																																																																																																										
8	VvCmd1	44	MuFlxRtioRef	80	SpdError	116	TestMark74	152	SrLssWeEst2	188	RsEstCosPhi																																																																																																																																																																																																																																																																																																																																																																																																																																										
9	VwCmd1	45	RcpFlxRatio1	81	SpdFdbk	117	TestMark75	153	SrLssPrportl	189	RsEstIqsCmdP																																																																																																																																																																																																																																																																																																																																																																																																																																										
10	IuFdbk	46	MulfluxRef	82	SpdIntegral	118	TestMark76	154	SrLssPI	190	RsEstPhi																																																																																																																																																																																																																																																																																																																																																																																																																																										
11	IwFdbk	47	MultestRef	83	SpdPrportnal	119	TestMark76	155	SrLssQAWeEst	191	RsEstSinPhi																																																																																																																																																																																																																																																																																																																																																																																																																																										
12	IdsFdbk	48	MotVntc	84	SpdPI	120	TestMark78	156	SrLssQAWeEst	192	RsEstVqsFbkP																																																																																																																																																																																																																																																																																																																																																																																																																																										
13	IqsFdbk	49	BaseSlip	85	SpdRef	121	TestMark79	157	SrLssWsFf	193	RsEWeLadsCmd																																																																																																																																																																																																																																																																																																																																																																																																																																										
14	VdsFdbk	50	VbusFdbk2	86	SlipGainEst	122	TestMark7A	158	SrLssWsEst	194	REWeLadsCmdP																																																																																																																																																																																																																																																																																																																																																																																																																																										
15	VuvFdbk	51	VdsFdbk2	87	SlipGainFf	123	TestMark7B	159	SrLssWsCmd	195	RsEWeLaqsCmd																																																																																																																																																																																																																																																																																																																																																																																																																																										
16	VvwFdbk	52	VqsFdbk2	88	Ws2	124	TestMark7C	160	SrLssVdsErr	196	RsEstIdsRat																																																																																																																																																																																																																																																																																																																																																																																																																																										
17	VqsFdbk	53	VdsSpdVltFit	89	SlipGain	125	TestMark7D	161	SLVdsErrComp	197	RsEstIqsRat																																																																																																																																																																																																																																																																																																																																																																																																																																										
18	IdsCmd	54	WrEst1	90	SlipGainFiltr	126	TestMark7E	162	SrLssStrtTmr	198	FldWklnitTim																																																																																																																																																																																																																																																																																																																																																																																																																																										
19	IqsRatio	55	MuTestFrqRef	91	SlipVdsCmd	127	TestMark7F	163	SrLssStrtTmr	199	MotorVolts																																																																																																																																																																																																																																																																																																																																																																																																																																										
20	MulqsRef	56	TestFrqRef	92	SlpVdsCmdFilt	128	RWVuOut	164	SrLssWeAve	200	BusUtilizatn																																																																																																																																																																																																																																																																																																																																																																																																																																										
21	IqsCmd	57	FluxFiltrN_1	93	VdsLastError	129	RWVvOut	165	SrLssWeEst	201	MulqsRef2																																																																																																																																																																																																																																																																																																																																																																																																																																										
22	We2	58	PrchgDlayCtr	94	VdsPrportnal	130	RWVwOut	166	SrLssKpMonit	202	BusDropVolts																																																																																																																																																																																																																																																																																																																																																																																																																																										
23	VuTd	59	PrchTimOutCr	95	VdsPrportnal	131	RWVuOut1	167	SrLssKiMonit	203	BusDropVolts																																																																																																																																																																																																																																																																																																																																																																																																																																										
24	VvTd	60	PrchPilotCtr	96	IqsLimit	132	RWVvOut1	168	SLWeKScale	204	DbDuty																																																																																																																																																																																																																																																																																																																																																																																																																																										
25	VwTd	61	TrqEnableCtr	97	VqsCmdMotor	133	RWVwOut1	169	SrLssWrAve	205	EstThetaByMV																																																																																																																																																																																																																																																																																																																																																																																																																																										
26	VuCmd2	62	MuTscan1	98	We2FieldWeak	134	RWVuScaleOut	170	SrLssWrCmd	206	ETVdsFbkA																																																																																																																																																																																																																																																																																																																																																																																																																																										
27	VvCmd2	63	ErStatFromCp	99	We2FieldWeak	135	RWVvScaleOut	171	SLWeKC2Mon	207	ETVdsFbkA																																																																																																																																																																																																																																																																																																																																																																																																																																										
28	VwCmd2	64	FlxCurRteOut	100	VqsldsCmd	136	RWVwScaleOut	172	SLWrKA2Mon	208	ETVdsFbkS																																																																																																																																																																																																																																																																																																																																																																																																																																										
29	Kpwm	65	ThetaE	101	VqsMaxMotor	137	RWVuOut2	173	SrLssVdsCmd	209	ETVqsFbkS																																																																																																																																																																																																																																																																																																																																																																																																																																										
30	Vds_cemf	66	SinThetaE1	102	VqsMaxVbus	138	RWVuOut2	174	SrLssVdsCmd	210	ETAtanVqVd																																																																																																																																																																																																																																																																																																																																																																																																																																										
31	Vqs_cemf	67	SinThetaE2	103	CalcPUMtrFlx	139	RWVuOut2	175	SLQAWeCal	211	ETAtanVqVd																																																																																																																																																																																																																																																																																																																																																																																																																																										
32	VdsCmd2	68	SinThetaE3	104	FldWklnitTim	140	RWPosState	176	SLQADelay	212	VelRef2																																																																																																																																																																																																																																																																																																																																																																																																																																										
33	VqsCmd2	69	SinThetaE4	105	FluxldsFfFilt	141	RWNegState	177	SLQAWeEstAve	213	VelOutput																																																																																																																																																																																																																																																																																																																																																																																																																																										
34	IdsIntegral	70	SinThetaE5	106	FlxVqsCmdFilt	142	VdsFdbkFiltr	178	SLWeEstErr	214	TorqEst																																																																																																																																																																																																																																																																																																																																																																																																																																										
35	IqsIntegral	71	SinThetaE6	107	FlxVqsCmdFilt	143	VqsFdbkFiltr	179	SrLssIntMon	215	TorqEstFiltr																																																																																																																																																																																																																																																																																																																																																																																																																																										
545	<p><b>MC TP Value</b> Displays the data selected by Par 544 [MC TP Sel]. This display should only be used if the selected value is integer data. Par 545 [MC TP Value] is a diagnostic tool you can use to view internal drive parameters.</p>	Default: 0 Min/Max: -/+2147483648			32-bit Integer																																																																																																																																																																																																																																																																																																																																																																																																																																																
546	<p><b>MC TP Bit</b> Displays the data selected by Par 544 [MC TP Sel]. This display should only be used if the selected value is bit-enumerated data. Par 546 [MC TP Bit] is a diagnostic tool you can use to view internal drive parameters.</p>	Default: 00000000000000000000000000000000 Min: 00000000000000000000000000000000 Max: 11111111111111111111111111111111			32-bit Boolean																																																																																																																																																																																																																																																																																																																																																																																																																																																
548	<p><b>Est Speed Fdbk</b> Displays estimated motor speed, calculated when the selected feedback is sensorless or when encoderless ridethrough is enabled. A value of 4096 indicates a motor speed equal to the value in Par 4 Motor NP RPM.</p>	Default: 0 Min/Max: -/+32767			16-bit Integer																																																																																																																																																																																																																																																																																																																																																																																																																																																


No.	Name Description	Values	Linkable	Read-Write	Data Type	
550	<b>MC Diag Status</b> Indicates the status of the MC diagnostic test.					
		Options	Reserved Reserved Reserved Reserved Reserved Reserved Reserved PwrDiagFltP EncOffset Rot Dir Chk CommCrtEnds Comm Count CommParamCal CommLmEncLes Comm Lm Meas Comm SigmaLs Comm Rs Meas PDgTrWP-VNOn PDgTrWP-UNOn PDgTrVP-WNOn PDgVP-UNOn PDgUP-WNOn PDgTrUP-VNOn PDgTrUNWNOn PDgTrUPWPOn Pdiag TrWNOn Pdiag TrVNOn Pdiag TrUNOn Pdiag TrWNOn Pdiag TrVPOn Pdiag TrUPOn Pdg VbusSens			
		Default	0 0			
		Bit	31 30 29 28 27 26 25 24 23 22 21 20 19 18 17 16 15 14 13 12 11 10 9 8 7 6 5 4 3 2 1 0			0 = False 1 = True
551	<b>MC Diag Done</b> Indicates which MC diagnostic tests are complete.					
		Options	Reserved Reserved Reserved Reserved Reserved Reserved Reserved PwrDiagFltP PM EncOffset Rot Dir Chk CommCrtEnds Comm Count CommParamCal CommLmEncLes Comm Lm Meas Comm SigmaLs Comm Rs Meas PDgTrWP-VNOn PDgTrWP-UNOn PDgTrVP-WNOn PDgVP-UNOn UP-WNOn-U PDgTrUP-VNOn Ground Fault Ground Fault Pdiag TrWNOn Pdiag TrVNOn Pdiag TrUNOn Pdiag TrWNOn Pdiag TrVPOn Pdiag TrUPOn Pdg VbusSens			
		Default	0 0			
		Bit	31 30 29 28 27 26 25 24 23 22 21 20 19 18 17 16 15 14 13 12 11 10 9 8 7 6 5 4 3 2 1 0			0 = False 1 = True
552	<b>MC Diag Error 1</b> Displays the first diagnostic error encountered by the Motor Control (MC). Errors appear in this parameter in the order in which they occurred.					
		Options	Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Neg Paramet Not Rotating Not Rotating Reserved Reserved W,WP-VNOn-Wcur WP-UNOn-U VP-WNOn-Wcur W,VP-UNOn-Ucur PDgUP-WNOn UP-VNOn-Ucur PDgTrUNWNOn PDgTrUPWPOn UP,VPdevShrt UP,WPdevShrt VP,WPdevShrt UN,VNdevShrt UN,WNdevShrt VN,WNdevShrt Vbus Range			
		Default	0 0			
		Bit	31 30 29 28 27 26 25 24 23 22 21 20 19 18 17 16 15 14 13 12 11 10 9 8 7 6 5 4 3 2 1 0			0 = False 1 = True
553	<b>MC Diag Error 2</b> Displays the second diagnostic error encountered by the Motor Control (MC). Errors appear in this parameter in the order in which they occurred.					
		Options	Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Negative Wr Reserved Reserved WP-VNOn-Vvw WPUN-Vuv,Vvw VP-WNOn-Vvw VP-UNOn-Vuv UP-WN-Vuv,Vvw UP-VNOn-Vuv Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved SensOstRange			
		Default	0 0			
		Bit	31 30 29 28 27 26 25 24 23 22 21 20 19 18 17 16 15 14 13 12 11 10 9 8 7 6 5 4 3 2 1 0			0 = False 1 = True
554	<b>MC Diag Error 3</b> Displays the third diagnostic error encountered by the Motor Control (MC). Errors appear in this parameter in the order in which they occurred.					
		Options	Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved HP Fault HP Fault Reserved Reserved Reserved Reserved Reserved Vvw Volt Flt Vuv Volt Flt W Currnt Flt U Currnt Flt Reserved Ground Fault WNdeviceShrt VNdeviceShrt UNdeviceShrt WPdeviceShrt VPdeviceShrt UPdeviceShrt UPdeviceShrt Vbus Range			
		Default	0 0			
		Bit	31 30 29 28 27 26 25 24 23 22 21 20 19 18 17 16 15 14 13 12 11 10 9 8 7 6 5 4 3 2 1 0			0 = False 1 = True
555	<b>MC Status</b> Indicates status of the Motor Control (MC) Processor and related functions.					
		Options	Min Vqs MaxDCBus Vqs MaxMotor Vqs Max Vds Min Vds SrLssWsLimit Slip Limit Regen Iqs Limit FldWeakening Reserved Reserved Reserved Reserved Reserved FluxRatioRef Command Lim DC Bus Low MC Test Mode PreChrg Req PWM En PreChrg Done Flux En Torque En Change Dir MC CommisFlt MC CommisRun MC Fault MC Ready BaseBlockReq TorqueRunReq Flux Run Req MC En Req			
		Default	0 0			
		Bit	31 30 29 28 27 26 25 24 23 22 21 20 19 18 17 16 15 14 13 12 11 10 9 8 7 6 5 4 3 2 1 0			0 = False 1 = True
600	<b>Integer In00</b> Displays input word 00 of the controller communication format in integer format. Paired with Par 601 [Real In00], which displays the same data in floating point format.	Default:	0			
		Min/Max:	Min/Max: -/+2147483648		32-bit Integer	

No.	Name Description	Values	Linkable	Read-Write	Data Type
601	<b>Real In00</b> Displays input word 00 of the controller communication format in floating point format. Paired with Par 600 [Integer In00], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
602	<b>Integer In01</b> Displays input word 01 of the controller communication format in integer format. Paired with Par 603 [Real In01], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648			32-bit Integer
603	<b>Real In01</b> Displays input word 01 of the controller communication format in floating point format. Paired with Par 602 [Integer In01], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
604	<b>Integer In02</b> Displays input word 02 of the controller communication format in integer format. Paired with Par 605 [Real In02], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648			32-bit Integer
605	<b>Real In02</b> Displays input word 02 of the controller communication format in floating point format. Paired with Par 604 [Integer In02], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
606	<b>Integer In03</b> Displays input word 03 of the controller communication format in integer format. Paired with Par 607 [Real In03], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648			32-bit Integer
607	<b>Real In03</b> Displays input word 03 of the controller communication format in floating point format. Paired with Par 606 [Integer In03], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
608	<b>Integer In04</b> Displays input word 04 of the controller communication format in integer format. Paired with Par 609 [Real In04], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648			32-bit Integer
609	<b>Real In04</b> Displays input word 04 of the controller communication format in floating point format. Paired with Par 608 [Integer In04], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
610	<b>Integer In05</b> Displays input word 05 of the controller communication format in integer format. Paired with Par 611 [Real In05], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648			32-bit Integer
611	<b>Real In05</b> Displays input word 05 of the controller communication format in floating point format. Paired with Par 610 [Integer In05], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
612	<b>Integer In06</b> Displays input word 06 of the controller communication format in integer format. Paired with Par 613 [Real In06], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648			32-bit Integer
613	<b>Real In06</b> Displays input word 06 of the controller communication format in floating point format. Paired with Par 612 [Integer In06], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000 Comm Scale: x 1			Real
614	<b>Integer In07</b> Displays input word 07 of the controller communication format in integer format. Paired with Par 615 [Real In07], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648 Comm Scale: x 1			32-bit Integer
615	<b>Real In07</b> Displays input word 07 of the controller communication format in floating point format. Paired with Par 614 [Integer In07], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
616	<b>Integer In08</b> Displays input word 08 of the controller communication format in integer format. Paired with Par 617 [Real In08], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648			32-bit Integer
617	<b>Real In08</b> Displays input word 08 of the controller communication format in floating point format. Paired with Par 616 [Integer In08], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
618	<b>Integer In09</b> Displays input word 09 of the controller communication format in integer format. Paired with Par 619 [Real In09], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648			32-bit Integer
619	<b>Real In09</b> Displays input word 09 of the controller communication format in floating point format. Paired with Par 618 [Integer In09], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
620	<b>Integer In10</b> Displays input word 10 of the controller communication format in integer format. Paired with Par 621 [Real In10], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648			32-bit Integer
621	<b>Real In10</b> Displays input word 10 of the controller communication format in floating point format. Paired with Par 620 [Integer In10], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
622	<b>Integer In11</b> Displays input word 11 of the controller communication format in integer format. Paired with Par 623 [Real In11], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648			32-bit Integer

No.	Name Description	Values	Linkable	Read-Write	Data Type
623	<b>Real In11</b> Displays input word 11 of the controller communication format in floating point format. Paired with Par 622 [Integer In11], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
624	<b>Integer In12</b> Displays input word 12 of the controller communication format in integer format. Paired with Par 625 [Real In12], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648			32-bit Integer
625	<b>Real In12</b> Displays input word 12 of the controller communication format in floating point format. Paired with Par 624 [Integer In12], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
626	<b>Integer In13</b> Displays input word 13 of the controller communication format in integer format. Paired with Par 627 [Real In13], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648			32-bit Integer
627	<b>Real In13</b> Displays input word 13 of the controller communication format in floating point format. Paired with Par 626 [Integer In13], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
628	<b>Integer In14</b> Displays input word 14 of the controller communication format in integer format. Paired with Par 629 [Real In14], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648			32-bit Integer
629	<b>Real In14</b> Displays input word 14 of the controller communication format in floating point format. Paired with Par 628 [Integer In14], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
630	<b>Integer In15</b> Displays input word 15 of the controller communication format in integer format. Paired with Par 631 [Real In15], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648			32-bit Integer
631	<b>Real In15</b> Displays input word 15 of the controller communication format in floating point format. Paired with Par 630 [Integer In15], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
632	 <b>Integer Out00</b> Displays output word 00 of the controller communication format in integer format. Paired with Par 633 [Real Out00], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
633	 <b>Real Out00</b> Displays output word 00 of the controller communication format in floating point format. Paired with Par 632 [Integer Out00], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
634	 <b>Integer Out01</b> Displays output word 01 of the controller communication format in integer format. Paired with Par 635 [Real Out01], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
635	 <b>Real Out01</b> Displays output word 01 of the controller communication format in floating point format. Paired with Par 634 [Integer Out01], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
636	 <b>Integer Out02</b> Displays output word 02 of the controller communication format in integer format. Paired with Par 637 [Real Out02], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
637	 <b>Real Out02</b> Displays output word 02 of the controller communication format in floating point format. Paired with Par 636 [Integer Out02], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
638	 <b>Integer Out03</b> Displays output word 03 of the controller communication format in integer format. Paired with Par 639 [Real Out03], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
639	 <b>Real Out03</b> Displays output word 03 of the controller communication format in floating point format. Paired with Par 638 [Integer Out03], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
640	 <b>Integer Out04</b> Displays output word 04 of the controller communication format in integer format. Paired with Par 641 [Real Out04], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
641	 <b>Real Out04</b> Displays output word 04 of the controller communication format in floating point format. Paired with Par 640 [Integer Out04], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
642	 <b>Integer Out05</b> Displays output word 05 of the controller communication format in integer format. Paired with Par 643 [Real Out05], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
643	 <b>Real Out05</b> Displays output word 05 of the controller communication format in floating point format. Paired with Par 642 [Integer Out05], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
644	 <b>Integer Out06</b> Displays output word 06 of the controller communication format in integer format. Paired with Par 645 [Real Out06], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer




No.	Name Description	Values	Linkable	Read-Write	Data Type
645	<b>Real Out06</b> Displays output word 06 of the controller communication format in floating point format. Paired with Par 644 [Integer Out06], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
646	<b>Integer Out07</b> Displays output word 07 of the controller communication format in integer format. Paired with Par 647 [Real Out07], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
647	<b>Real Out07</b> Displays output word 07 of the controller communication format in floating point format. Paired with Par 646 [Integer Out07], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
648	<b>Integer Out08</b> Displays output word 08 of the controller communication format in integer format. Paired with Par 649 [Real Out08], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
649	<b>Real Out08</b> Displays output word 08 of the controller communication format in floating point format. Paired with Par 648 [Integer Out08], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
650	<b>Integer Out09</b> Displays output word 09 of the controller communication format in integer format. Paired with Par 651 [Real Out09], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
651	<b>Real Out09</b> Displays output word 09 of the controller communication format in floating point format. Paired with Par 650 [Integer Out09], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
652	<b>Integer Out10</b> Displays output word 10 of the controller communication format in integer format. Paired with Par 653 [Real Out10], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
653	<b>Real Out10</b> Displays output word 10 of the controller communication format in floating point format. Paired with Par 652 [Integer Out10], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
654	<b>Integer Out11</b> Displays output word 11 of the controller communication format in integer format. Paired with Par 655 [Real Out11], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648 Comm Scale: x16	✓	✓	32-bit Integer
655	<b>Real Out11</b> Displays output word 11 of the controller communication format in floating point format. Paired with Par 654 [Integer Out11], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
656	<b>Integer Out12</b> Displays output word 12 of the controller communication format in integer format. Paired with Par 657 [Real Out12], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
657	<b>Real Out12</b> Displays output word 12 of the controller communication format in floating point format. Paired with Par 656 [Integer Out12], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
658	<b>Integer Out13</b> Displays output word 13 of the controller communication format in integer format. Paired with Par 659 [Real Out13], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
659	<b>Real Out13</b> Displays output word 13 of the controller communication format in floating point format. Paired with Par 658 [Integer Out13], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
660	<b>Integer Out14</b> Displays output word 14 of the controller communication format in integer format. Paired with Par 661 [Real Out14], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
661	<b>Real Out14</b> Displays output word 14 of the controller communication format in floating point format. Paired with Par 660 [Integer Out14], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
662	<b>Integer Out15</b> Displays output word 15 of the controller communication format in integer format. Paired with Par 663 [Real Out15], which displays the same data in floating point format.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
663	<b>Real Out15</b> Displays output word 15 of the controller communication format in floating point format. Paired with Par 662 [Integer Out15], which displays the same data in integer format.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
664	<b>Lgx Comm Format</b> Indicates the Controller to Drive communication format. 16-Velocity Control, 0-Custom Format, 16-Position Control	Default: 0 "Not Used" Options: 0 "Not Used" 18 "UserDefin 1" 16 "Speed Ctrl" 19 "Motion" 17 "PositionCtrl" 32 UserDefin 2			

No.	Name Description	Values	Linkable	Read-Write	Data Type
670	<b>Pwr Strct Mode</b> Options Not Used Not Used Not Used Not Used Not Used Not Used Not Used Not Used Not Used Not Used Not Used Not Used Not Used Star Coupler Hi Pwr Strct Lo Pwr Strct Default 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 Bit 15 14 13 12 11 10 9 8 7 6 5 4 3 2 1 0 0 = False 1 = True	Bit 0: PowerFlex 700S Bit 1: Vacon HiHP			
671	<b>HiHP Drive Fault</b> Options Not Used Not Used Not Used Not Used Not Used EE Incompati HW Incompati Prchrg cnct uPrC Wtchdg Drive OvrLd FAN Alarm VBus Wtchdg VBus CRC Err VBus Lnk Lst VBus Com Dly AC Inpt Lss Default 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 Bit 15 14 13 12 11 10 9 8 7 6 5 4 3 2 1 0 0 = False 1 = True				
672	<b>HiHP GF Current</b> Determines the current level for the ground fault detection.	Units: Amps Default: 13.0500 Min/Max: 10.0000/200.0000		<input checked="" type="checkbox"/>	
673	<b>HiHP GF TimDelay</b> Determines the time delay for the ground fault detection.	Units: mSec Default: 200 Min/Max: 20/400		<input checked="" type="checkbox"/>	
691	 <b>DPI Ref Select</b> Selects which DPI port can provide a reference to the drive.	Default: 1 "Local HIM" Options: 1 "Local HIM" 4 "Reserved" 2 "Ext DPI Conn" 5 "Int DPI Comm" 3 "Aux DPI Conn"			
692	<b>DPI Baud Rate</b> Sets the baud rate for attached drive peripherals. Reset the drive for the change to take effect.	Default: Val 0 500K Options: Val 0 500K			
693	<b>Logic Mask</b> Determines which adapters can control the drive. Options Undefined Undefined Undefined Undefined Undefined Undefined Undefined Undefined DriveLogix Reserved Int DPI Conn Reserved Aux DPI Conn Ext DPI Conn Local HIM Terminal Blk Default 0 0 0 0 0 0 0 0 1 1 1 1 1 1 1 1 Bit 15 14 13 12 11 10 9 8 7 6 5 4 3 2 1 0 0 = False 1 = True				
694	<b>Start Mask</b> Controls which adapters can issue start commands. Options Undefined Undefined Undefined Undefined Undefined Undefined Undefined Undefined DriveLogix Reserved Int DPI Conn Reserved Aux DPI Conn Ext DPI Conn Local HIM Terminal Blk Default 0 0 0 0 0 0 0 0 1 1 1 1 1 1 1 1 Bit 15 14 13 12 11 10 9 8 7 6 5 4 3 2 1 0 0 = False 1 = True				
695	<b>Jog Mask</b> Controls which adapters can issue jog commands. Options Undefined Undefined Undefined Undefined Undefined Undefined Undefined Undefined DriveLogix Reserved Int DPI Conn Reserved Aux DPI Conn Ext DPI Conn Local HIM Terminal Blk Default 0 0 0 0 0 0 0 0 1 1 1 1 1 1 1 1 Bit 15 14 13 12 11 10 9 8 7 6 5 4 3 2 1 0 0 = False 1 = True				

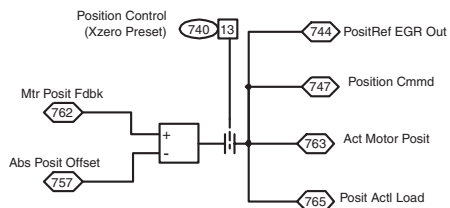
No.	Name Description	Values	Linkable	Read-Write	Data Type
696	<b>Direction Mask</b> Controls which adapters can issue forward/reverse direction commands.				
	Options	Undefined Undefined Undefined Undefined Undefined Undefined Undefined Undefined DriveLogix Reserved Int DPI Conn Reserved Aux DPI Conn Ext DPI Conn Local HIM Terminal Blk			
	Default	0 0 0 0 0 0 0 0 1 1 1 1 1 1 1 1			
	Bit	15 14 13 12 11 10 9 8 7 6 5 4 3 2 1 0			0 = False 1 = True
697	<b>Fault Clr Mask</b> Controls which adapters can clear a fault.				
	Options	Undefined Undefined Undefined Undefined Undefined Undefined Undefined Undefined DriveLogix Reserved Int DPI Conn Reserved Aux DPI Conn Ext DPI Conn Local HIM Terminal Blk			
	Default	0 0 0 0 0 0 0 0 1 1 1 1 1 1 1 1			
	Bit	15 14 13 12 11 10 9 8 7 6 5 4 3 2 1 0			0 = False 1 = True
700	<b>Stop Owner</b> Indicates which adapters that are presently issuing a valid stop command.				
	Options	Undefined Undefined Undefined Undefined Undefined Undefined Undefined Undefined DriveLogix Reserved Int DPI Conn Reserved Aux DPI Conn Ext DPI Conn Local HIM Terminal Blk			
	Default	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0			
	Bit	15 14 13 12 11 10 9 8 7 6 5 4 3 2 1 0			0 = False 1 = True
701	<b>Start Owner</b> Indicates which adapters that are presently issuing a valid start command.				
	Options	Undefined Undefined Undefined Undefined Undefined Undefined Undefined Undefined DriveLogix Reserved Int DPI Conn Reserved Aux DPI Conn Ext DPI Conn Local HIM Terminal Blk			
	Default	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0			
	Bit	15 14 13 12 11 10 9 8 7 6 5 4 3 2 1 0			0 = False 1 = True
702	<b>Jog Owner</b> Indicates which adapters that are presently issuing a valid jog command.				
	Options	Undefined Undefined Undefined Undefined Undefined Undefined Undefined Undefined DriveLogix Reserved Int DPI Conn Reserved Aux DPI Conn Ext DPI Conn Local HIM Terminal Blk			
	Default	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0			
	Bit	15 14 13 12 11 10 9 8 7 6 5 4 3 2 1 0			0 = False 1 = True
703	<b>Direction Owner</b> Indicates which adapter is currently has exclusive control of direction changes.				
	Options	Undefined Undefined Undefined Undefined Undefined Undefined Undefined Undefined DriveLogix Reserved Int DPI Conn Reserved Aux DPI Conn Ext DPI Conn Local HIM Terminal Blk			
	Default	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0			
	Bit	15 14 13 12 11 10 9 8 7 6 5 4 3 2 1 0			0 = False 1 = True

No.	Name Description	Values	Linkable	Read-Write	Data Type																																																		
704	<b>Fault Clr Owner</b> Indicates which adapter is currently clearing a fault.  Options <table border="1" style="margin-left: 20px;"> <tr> <td></td> <td>Undefined</td> <td>Undefined</td> <td>Undefined</td> <td>Undefined</td> <td>Undefined</td> <td>Undefined</td> <td>Undefined</td> <td>Undefined</td> <td>DriveLogix</td> <td>Reserved</td> <td>Int DPI Conn</td> <td>Reserved</td> <td>Aux DPI Conn</td> <td>Ext DPI Conn</td> <td>Local HIM</td> <td>Terminal Blk</td> </tr> <tr> <td>Default</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> </tr> <tr> <td>Bit</td> <td>15</td> <td>14</td> <td>13</td> <td>12</td> <td>11</td> <td>10</td> <td>9</td> <td>8</td> <td>7</td> <td>6</td> <td>5</td> <td>4</td> <td>3</td> <td>2</td> <td>1</td> <td>0</td> </tr> </table> <p style="margin-left: 20px;">0 = False 1 = True</p>		Undefined	Undefined	Undefined	Undefined	Undefined	Undefined	Undefined	Undefined	DriveLogix	Reserved	Int DPI Conn	Reserved	Aux DPI Conn	Ext DPI Conn	Local HIM	Terminal Blk	Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0			
	Undefined	Undefined	Undefined	Undefined	Undefined	Undefined	Undefined	Undefined	DriveLogix	Reserved	Int DPI Conn	Reserved	Aux DPI Conn	Ext DPI Conn	Local HIM	Terminal Blk																																							
Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0																																							
Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0																																							
707	<b>Data In A1 Int</b> Link A Word 1 (Integer) - Parameter number whose value will be written from a communications device data table. Parameters that can only be changed while the drive is stopped, cannot be used as Datalink inputs. Entering a parameter of this type will "Disable" the link. Refer to the manual that came with your communications option for datalink information.	Default: 0 Min/Max: -/+2147483648			32-bit Integer																																																		
708	<b>Data In A1 Real</b> Link A Word 1 (Real or Floating Point) - Parameters that can only be changed while the drive is stopped, cannot be used as Datalink inputs. Entering a parameter of this type will "Disable" the link. Refer to the manual that came with your communications option for datalink information.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real																																																		
709	<b>Data In A2 Int</b> Link A Word 2 (Integer) - Parameter number whose value will be written from a communications device data table. Parameters that can only be changed while the drive is stopped, cannot be used as Datalink inputs. Entering a parameter of this type will "Disable" the link. Refer to the manual that came with your communications option for datalink information.	Default: 0 Min/Max: -/+2147483648			32-bit Integer																																																		
710	<b>Data In A2 Real</b> Link A Word 2 (Real or Floating Point) - Parameters that can only be changed while the drive is stopped, cannot be used as Datalink inputs. Entering a parameter of this type will "Disable" the link. Refer to the manual that came with your communications option for datalink information.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real																																																		
711	<b>Data In B1 Int</b> Link B Word 1 (Integer) - Parameter number whose value will be written from a communications device data table. Parameters that can only be changed while the drive is stopped, cannot be used as Datalink inputs. Entering a parameter of this type will "Disable" the link. Refer to the manual that came with your communications option for datalink information.	Default: 0 Min/Max: -/+2147483648			32-bit Integer																																																		
712	<b>Data In B1 Real</b> Link B Word 1 (Real or Floating Point) - Parameters that can only be changed while the drive is stopped, cannot be used as Datalink inputs. Entering a parameter of this type will "Disable" the link. Refer to the manual that came with your communications option for datalink information.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real																																																		
713	<b>Data In B2 Int</b> Link B Word 2 (Integer) - Parameter number whose value will be written from a communications device data table. Parameters that can only be changed while the drive is stopped, cannot be used as Datalink inputs. Entering a parameter of this type will "Disable" the link. Refer to the manual that came with your communications option for datalink information.	Default: 0 Min/Max: -/+2147483648			32-bit Integer																																																		
714	<b>Data In B2 Real</b> Link B Word 2 (Real or Floating Point) - Parameters that can only be changed while the drive is stopped, cannot be used as Datalink inputs. Entering a parameter of this type will "Disable" the link. Refer to the manual that came with your communications option for datalink information.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real																																																		
715	<b>Data In C1 Int</b> Link C Word 1 (Integer) - Parameter number whose value will be written from a communications device data table. Parameters that can only be changed while the drive is stopped, cannot be used as Datalink inputs. Entering a parameter of this type will "Disable" the link. Refer to the manual that came with your communications option for datalink information.	Default: 0 Min/Max: -/+2147483648			32-bit Integer																																																		
716	<b>Data In C1 Real</b> Link C Word 1 (Real or Floating Point) - Parameters that can only be changed while the drive is stopped, cannot be used as Datalink inputs. Entering a parameter of this type will "Disable" the link. Refer to the manual that came with your communications option for datalink information.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real																																																		

No.	Name Description	Values	Linkable	Read-Write	Data Type																																																		
717	<b>Data In C2 Int</b> Link C Word 2 (Integer) - Parameter number whose value will be written from a communications device data table. Parameters that can only be changed while the drive is stopped, cannot be used as Datalink inputs. Entering a parameter of this type will "Disable" the link. Refer to the manual that came with your communications option for datalink information.	Default: 0 Min/Max: -/+2147483648			32-bit Integer																																																		
718	<b>Data In C2 Real</b> Link C Word 2 (Real or Floating Point) - Parameters that can only be changed while the drive is stopped, cannot be used as Datalink inputs. Entering a parameter of this type will "Disable" the link. Refer to the manual that came with your communications option for datalink information.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real																																																		
719	<b>Data In D1 Int</b> Link D Word 1 (Integer) - Parameter number whose value will be written from a communications device data table. Parameters that can only be changed while the drive is stopped, cannot be used as Datalink inputs. Entering a parameter of this type will "Disable" the link. Refer to the manual that came with your communications option for datalink information.	Default: 0 Min/Max: -/+2147483648			32-bit Integer																																																		
720	<b>Data In D1 Real</b> Link D Word 1 (Real or Floating Point) - Parameters that can only be changed while the drive is stopped, cannot be used as Datalink inputs. Entering a parameter of this type will "Disable" the link. Refer to the manual that came with your communications option for datalink information.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real																																																		
721	<b>Data In D2 Int</b> Link D Word 2 (Integer) - Parameter number whose value will be written from a communications device data table. Parameters that can only be changed while the drive is stopped, cannot be used as Datalink inputs. Entering a parameter of this type will "Disable" the link. Refer to the manual that came with your communications option for datalink information.	Default: 0 Min/Max: -/+2147483648			32-bit Integer																																																		
722	<b>Data In D2 Real</b> Link D Word 2 (Real or Floating Point) - Parameters that can only be changed while the drive is stopped, cannot be used as Datalink inputs. Entering a parameter of this type will "Disable" the link. Refer to the manual that came with your communications option for datalink information.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real																																																		
723	<b>DLink OutDataTyp</b> Set bits to configure each Datalink output word for real (floating point) data transfer. Reset bits to configure each Datalink output word for integer data transfer.																																																						
	 <table border="1" style="margin-left: 20px;"> <thead> <tr> <th>Options</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>D2 Out Real</th> <th>D1 Out Real</th> <th>C2 Out Real</th> <th>C1 Out Real</th> <th>B2 Out Real</th> <th>B1 Out Real</th> <th>A2 Out Real</th> <th>A1 Out Real</th> </tr> </thead> <tbody> <tr> <td>Default</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> </tr> <tr> <td>Bit</td> <td>15</td> <td>14</td> <td>13</td> <td>12</td> <td>11</td> <td>10</td> <td>9</td> <td>8</td> <td>7</td> <td>6</td> <td>5</td> <td>4</td> <td>3</td> <td>2</td> <td>1</td> <td>0</td> </tr> </tbody> </table> <p style="margin-left: 20px;">0 = False 1 = True</p>	Options	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	D2 Out Real	D1 Out Real	C2 Out Real	C1 Out Real	B2 Out Real	B1 Out Real	A2 Out Real	A1 Out Real	Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0			
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724	<b>Data Out A1 Int</b> Link A Word 1 (Integer) - Parameter number whose value will be written to a communications device data table..	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer																																																		
725	<b>Data Out A1 Real</b> Link A Word 1 (Real or Floating Point) - Parameter number whose value will be written to a communications device data table..	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real																																																		
726	<b>Data Out A2 Int</b> Link A Word 2 (Integer) - Parameter number whose value will be written to a communications device data table.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer																																																		
727	<b>Data Out A2 Real</b> Link A Word 2 (Real or Floating Point) - Parameter number whose value will be written to a communications device data table.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real																																																		
728	<b>Data Out B1 Int</b> Link B Word 1 (Integer) - Parameter number whose value will be written to a communications device data table.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer																																																		
729	<b>Data Out B1 Real</b> Link B Word 1 (Real or Floating Point) - Parameter number whose value will be written to a communications device data table.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real																																																		
730	<b>Data Out B2 Int</b> Link B Word 2 (Integer) - Parameter number whose value will be written to a communications device data table.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer																																																		
731	<b>Data Out B2 Real</b> Link B Word 2 (Real or Floating Point) - Parameter number whose value will be written to a communications device data table.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real																																																		
732	<b>Data Out C1 Int</b> Link C Word 1 (Integer) - Parameter number whose value will be written to a communications device data table.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer																																																		

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733	<b>Data Out C1 Real</b> Link C Word 1 (Real or Floating Point) - Parameter number whose value will be written to a communications device data table.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real																																																																																																			
734	<b>Data Out C2 Int</b> Link C Word 2 (Integer) - Parameter number whose value will be written to a communications device data table.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer																																																																																																			
735	<b>Data Out C2 Real</b> Link C Word 2 (Real or Floating Point) - Parameter number whose value will be written to a communications device data table.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real																																																																																																			
736	<b>Data Out D1 Int</b> Link D Word 1 (Integer) - Parameter number whose value will be written to a communications device data table.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer																																																																																																			
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738	<b>Data Out D2 Int</b> Link D Word 2 (Integer) - Parameter number whose value will be written to a communications device data table.	Default: 0 Min/Max: -/+2147483648 Comm Scale: x 1	✓	✓	32-bit Integer																																																																																																			
739	<b>Data Out D2 Real</b> Link D Word 2 (Real or Floating Point) - Parameter number whose value will be written to a communications device data table.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real																																																																																																			
740	<p><b>Position Control</b> Set bits to enable various position control functions.</p> <ul style="list-style-type: none"> <li>Setting bit 1 [Speed Out En] enables position regulator output at Par 318 [Posit Spd Output].</li> <li>Setting bit 2 [Integ En] enables integrator operation. Resetting it resets the integrator.</li> <li>Setting bit 3 [Integ Hold] holds integrator in present state.</li> <li>Setting bit 4 [X Offset Pol] reverses polarity of offset parameters.</li> <li>Setting bit 5 [X Offset Ref] permits changing the value of position offsets without changing actual position. Resetting it makes the position offset relative to the re-referenced value or the latched value upon enable if re-reference was not performed.</li> <li>Bit 6 [ActPosit Rst] is only operational when Bit 8 [Xzero Preset] is off. When bit 6 [ActPosit Rst] is set, Pars 744 [PositRef EGR Out], 747 [Position Cmmnd], 763 [Act Motor Posit] and 765 [Posit Actl Load] will be set to the value of Par 762 [Mtr Posit Fdbk] upon drive enable. When bit 6 [ActPosit Rst] is cleared, the above four parameters are set to a value of position reference that is selected by Par 742 [Aux Posit Ref].</li> <li>Setting bit 7 [AbsoluteMode] puts the position regulator in Absolute mode.</li> <li>Setting bit 8 [Xzero Preset] presets Pars 744 [PositRef EGR Out], 47 [Position Cmmnd], 763 [Act Motor Posit] and 765 [Posit Actl Load] with the value in Par 762 [Mtr Posit Fdbk] minus Par 757 [Abs Posit Offset] upon drive enable.</li> <li>Setting bit 10 [Pt-Pt ReRef] enables setting or changing Par 758 [Pt-Pt Posit Ref] without changing actual position.</li> <li>Setting bit 13 [Interp Rev] reverses direction of interpolated position and speed. Setting bit 16 [X Watch1 En] enables position Watch 1. Resetting it clears Par 741 [Position Status] bit 8 [Posit Watch1].</li> <li>Setting bit 17 [X Watch1 Dir] causes Position Watch 1 output to be set when Par 763 [Act Motor Posit] is greater than Par 780 [PositDct1 Stpt]. Re-setting bit 17 [X Watch1 Dir] causes Position Watch 1 output to be set when Par 763 [Act Motor Posit] is less than Par 780 [PositDct1 Stpt].</li> <li>Setting bit 18 [X Watch2 En] enables position Watch 2. Resetting it clears Par 741 [Position Status] bit 9 [Posit Watch2].</li> <li>Setting bit 19 [X Watch2 Dir] causes Position Watch 2 output to be set when Par 763 [Act Motor Posit] is greater than Par 781 [PositDct2 Stpt]. Re-setting bit 19 [X Watch2 Dir] causes Position Watch 2 output to be set when Par 763 [Act Motor Posit] is less than Par 781 [PositDct2 Stpt].</li> </ul> <p>Options</p> <table border="1"> <thead> <tr> <th></th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>X Watch2 Dir</th> <th>X Watch2 En</th> <th>X Watch1 Dir</th> <th>X Watch1 En</th> <th>Reserved</th> <th>Reserved</th> <th>Interp Rev</th> <th>Reserved</th> <th>Reserved</th> <th>Pt-Pt ReRef</th> <th>Reserved</th> <th>Xzero Preset</th> <th>AbsoluteMode</th> <th>ActPosit Rst</th> <th>X Offset Ref</th> <th>X Offset Pol</th> <th>integ Hold</th> <th>integ En</th> <th>Speed Out En</th> <th>Reserved</th> </tr> </thead> <tbody> <tr> <td>Default</td> <td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>1</td><td>0</td><td>1</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>1</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>1</td><td>0</td> </tr> <tr> <td>Bit</td> <td>31</td><td>30</td><td>29</td><td>28</td><td>27</td><td>26</td><td>25</td><td>24</td><td>23</td><td>22</td><td>21</td><td>20</td><td>19</td><td>18</td><td>17</td><td>16</td><td>15</td><td>14</td><td>13</td><td>12</td><td>11</td><td>10</td><td>9</td><td>8</td><td>7</td><td>6</td><td>5</td><td>4</td><td>3</td><td>2</td><td>1</td><td>0</td> </tr> </tbody> </table> <p>0 = False 1 = True</p>						Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	X Watch2 Dir	X Watch2 En	X Watch1 Dir	X Watch1 En	Reserved	Reserved	Interp Rev	Reserved	Reserved	Pt-Pt ReRef	Reserved	Xzero Preset	AbsoluteMode	ActPosit Rst	X Offset Ref	X Offset Pol	integ Hold	integ En	Speed Out En	Reserved	Default	0	0	0	0	0	0	0	0	0	0	0	0	1	0	1	0	0	0	0	0	0	0	0	1	0	0	0	0	0	0	1	0	Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	X Watch2 Dir	X Watch2 En	X Watch1 Dir	X Watch1 En	Reserved	Reserved	Interp Rev	Reserved	Reserved	Pt-Pt ReRef	Reserved	Xzero Preset	AbsoluteMode	ActPosit Rst	X Offset Ref	X Offset Pol	integ Hold	integ En	Speed Out En	Reserved																																																																								
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Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0																																																																								
741	<p><b>Position Status</b> Indicates status of position control algorithms.</p> <ul style="list-style-type: none"> <li>Bit 0 [X IGain LLim] indicates the position integrator is at the lower limit.</li> <li>Bit 1 [X IGain HLim] indicates the position integrator is at the high limit.</li> <li>Bit 2 [X Spd LLim] indicates the position regulator output at the low limit.</li> <li>Bit 3 [X Spd HLim] indicates the position regulator output is at the high limit.</li> <li>Bit 4 [PtPtRRef Act] tbd</li> <li>Bit 5 [XOffRRef Act] tbd</li> <li>Bit 7 [Regulator On] indicates position regulator is active.</li> <li>Bit 8 [Posit Watch1] indicates Position Watch 1 has detected motor position equal to its setpoint, from the proper direction.</li> <li>Bit 9 [Posit Watch2] indicates Position Watch 2 has detected motor position equal to its setpoint, from the proper direction.</li> <li>Bit 10 [In Position] indicates Par 769 [Position Error] is within the position deadband specified by parameter 782 [In Posit BW].</li> </ul> <p>Options</p> <table border="1"> <thead> <tr> <th></th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>In Position</th> <th>Posit Watch2</th> <th>Posit Watch1</th> <th>Regulator On</th> <th>Reserved</th> <th>XOffRRef Act</th> <th>PtPtRRef Act</th> <th>X Spd HLim</th> <th>X Spd LLim</th> <th>X IGain HLim</th> <th>X IGain LLim</th> </tr> </thead> <tbody> <tr> <td>Default</td> <td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>1</td><td>0</td><td>1</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>1</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>1</td><td>0</td> </tr> <tr> <td>Bit</td> <td>31</td><td>30</td><td>29</td><td>28</td><td>27</td><td>26</td><td>25</td><td>24</td><td>23</td><td>22</td><td>21</td><td>20</td><td>19</td><td>18</td><td>17</td><td>16</td><td>15</td><td>14</td><td>13</td><td>12</td><td>11</td><td>10</td><td>9</td><td>8</td><td>7</td><td>6</td><td>5</td><td>4</td><td>3</td><td>2</td><td>1</td><td>0</td> </tr> </tbody> </table> <p>0 = False 1 = True</p>						Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	In Position	Posit Watch2	Posit Watch1	Regulator On	Reserved	XOffRRef Act	PtPtRRef Act	X Spd HLim	X Spd LLim	X IGain HLim	X IGain LLim	Default	0	0	0	0	0	0	0	0	0	0	0	0	0	1	0	1	0	0	0	0	0	0	1	0	0	0	0	0	0	1	0	Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0		
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No.	Name Description	Values	Linkable	Read-Write	Data Type
742	<b>Posit Ref Sel</b> Enter a value to select the position mode and corresponding reference.	Default: 1 "AuxPosit Ref" Options: 0 "Interpolate" 2 "Pt to Pt" 1 "AuxPosit Ref"			
743	<b>Aux Posit Ref</b> Supplies position reference to the position regulator when selected by Par 742 [Posit Ref Sel]. This input is designed to be linked to a position count accumulator such as a virtual encoder or hardware accumulator.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
744	<b>PositRef EGR Out</b> Accumuated output of the position reference Electronic Gear Ratio. When the position regulator is not enabled, this parameter is initialized to Par 762 [Mtr Posit Fdbk] or to the selected position reference as determined by Par 740 [Position Control] bit 6.	Default: 0 Min/Max: -/+2147483648			32-bit Integer
745	<b>PositRef EGR Mul</b> An integer value in the numerator of the Electronic Gear Ratio function that is precision multiplied by the selected position reference. A negative value will effect a change in polarity	Default: 1 Min/Max: -/+2000000	✓	✓	32-bit Integer
746	<b>PositRef EGR Div</b> An integer value in the denominator of the Electronic Gear Ratio function that divides into the product of the numerator and the selected position reference. Remainders are accumulated and not lost.	Default: 1 Min/Max: 1/2000000			32-bit Integer
747	<b>Position Cmmd</b> Final accumulated command to the position regulator. When the position regulator is not enabled, this parameter is initialized to Par 762 [Mtr Posit Fdbk] or to the selected position reference as determined by Par 740 [Position Control] bit 6. Thereafter, its value will reflect the result of reference and offset changes.	Default: 0 Min/Max: -/+2147483648			32-bit Integer
748	<b>CoarsePosit Trgt</b> Input to the interpolator. This is a course position target reference.	Default: 0 Min/Max: -/+2147483648	✓		DWord
749	<b>Interp Position</b> Input to the interpolator. This is a course position target reference.	Default: 0 Min/Max: -/+2147483648			DWord
750	<b>Course Spd Trgt</b> Input to the interpolator. This is a course speed target reference.	Default: 0 Min/Max: -/+2200000000.0000		✓	Real
751	<b>Interp Speed</b> Output from the interpolator. This is a fine speed target reference. Interpolated value of Par 750 [Course Spd Trgt] if available, or the first derivative of Par 784 [CoursePosit Trgt] if not available.	Default: 0 Min/Max: -/+8.0000			Real
752	<b>Interp AccelRate</b> Output from interpolator. This is a fine acceleration rate. First derivative of Par 750 [Course Spd Trgt] if available, or zero (0) if not available.	Default: 0 Min/Max: -/+8.0000			Real
753	<b>Posit Offset 1</b> Suplies a position reference offset, which is summed after the Electronic Gear Ratio and used to phase trim position reference. A step in the offset position will be internally rate limited and added to the selected reference position. The rate of correction is set by Par 755 [Posit Offset Spd]. The initial value of this parameter is latched upon position enable without causing a change in reference. Subsequent changes to the value will be relative to the latched value. See Par 740 [Position Control] bit 5 for re-referencing the offsets.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
754	<b>Posit Offset 2</b> Supplies another position reference offset, which is summed directly with Par 753 [Positi Offset 1]. Used to trim the phase of the selected position reference. Position offset will be internally rate limited to a velocity set by Par 755 [Posit Offset Spd].	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
755	<b>Posit Offset Spd</b> Sets the speed of position offset. A position offset command will not exceed this speed. The actual speed of offset is limited to a maximum value of 1/(inertia * pos gain) so as not to cause a torque pulse greater than 1 per unit. The speed will change exponentially.	Units: RPM Default: 176.4000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0	✓	✓	Real
756	<b>X Offst SpdFilt</b> Displays the output of a first order filter whose time response is shaped specifically to provide an output that represents the actual speed of offset correction. It may be used as feed forward into speed reference to secure minimal position error during changes to offset.	Units: RPM Default: 0.0000 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0			Real
757	<b>Abs Posit Offset</b> Provides an offset to absolute position. Setting Par 740 [Position Control] / bit 8 [Xzero Preset] presets Pars 744 [PositRef EGR Out], 747 [Position Cmmd], 763 [Act Motor Posit] and 765 [Posit Actl Load] with the value in Par 762 [Mtr Posit Fdbk] minus Par 757 [Abs Posit Offset] upon drive enable.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer



No.	Name Description	Values	Linkable	Read-Write	Data Type
758	<b>Pt-Pt Posit Ref</b> Provides position reference to the point to point position regulator, when the value in Par 742 [Posit Ref Sel] equals 2 [Pt to Pt]. The initial value is latched upon position enable without causing movement. Subsequent changes to reference are relative to the latched position unless the position is re-referenced by Par 740 [Position Control] / bit 10 [Pt-Pt ReRef]. Position moves may be made within the limits of plus or minus 31 bits. Point to point reference may be changed, and even reversed, during a move.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
759	<b>Pt-Pt Accel Time</b> Acceleration time (sec) to base speed, active only in point to point mode. Acceleration to a relatively low speed may be exponential	Units: Sec Default: 10.0000 Min/Max: 0.1000/6553.5000	✓	✓	Real
760	<b>Pt-Pt Decel Time</b> Deceleration time (sec) from base speed to zero, active only in point to point mode. Some tailing can be expected at the end of a move as the drive comes into command position. It is left to the user to select a time that does not place the drive in current or torque limit. Deceleration from relatively low speed may be exponential.	Units: Sec Default: 10.0000 Min/Max: 0.1000/6553.5000	✓	✓	Real
761	<b>Pt-Pt Filt BW</b> Sets the bandwidth of a low pass filter which affects smoothness at the start of deceleration in the point to point mode. A high filter bandwidth will produce a more square deceleration torque, one with a higher level of jerk. Typical values range from 5 to 100 (rad/sec). A zero value will bypass the filter. Tail-out is influenced mainly by Par 768 Posit Reg P Gain].	Units: R/S Default: 25.0000 Min/Max: 0.0000/500.0000	✓	✓	Real
762	<b>Mtr Posit Fdbk</b> Displays the accumulated pulse count of the primary feedback device as a 32 bit integer. The primary feedback device is selected by Par 222 [Motor Fdbk Sel].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
763	<b>Act Motor Posit</b> Displays the accumulated motor position as a 32 bit integer. It tracks Par 762 [Mtr Posit Fdbk]. When the position regulator is not enabled, this parameter is initialized to Par 762 [Mtr Posit Fdbk] or to the selected position reference as determined by Par 740 [Position Control] bit 6.	Default: 0 Min/Max: -/+2147483648			32-bit Integer
764	<b>Posit Load Fdbk</b> Tracks the load position, as a 32 bit integer. When a gear box connects the load to the motor, Par 766 [Posit FB EGR Mul] and Par 767 [Posit FB EGR Div] must be set to account for the gear ratio. Set Par 766 [Posit FB EGR Mul] equal to Par 767 [Posit FB EGR Div] if the load is directly connected to the motor.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
765	<b>Posit Actl Load</b> Holds the accumulated output of the Load Gear Ratio as a 32 bit integer and forms the primary feedback for the position regulator integral channel. It is very important that the load gear ratio be precisely set such that the delta pulse count of one motor revolution equals the delta pulse count of this parameter. When the position regulator is not enabled, this parameter is initialized to Par 762 [Mtr Posit Fdbk] or to the selected position reference as determined by Par 740 [Position Control] bit 6.	Default: 0 Min/Max: -/+2147483648			32-bit Integer
766	<b>Posit FB EGR Mul</b> A 32 bit integer in the numerator of the load Electronic Gear Ratio function. It is multiplied by Par 764 [Posit Load Fdbk] and divided by Par 767 [Posit FB EGR Div] to reflect the load pulse count to the motor (effectively removing the gear box ratio). The accumulated position values Par 763 [Act Motor Posit] and Par 764 [Posit Actl Load] will be equal if the ratio is set properly. There may be some difference due to lost motion in the gear train, but there should not be an accumulated difference. It is often necessary to count gear teeth as gear box manufacturers often approximate exact ratios with decimal numbers. Enter a negative value in the numerator to account for reversed motor rotation.	Default: 1 Min/Max: -/+1000000	✓	✓	32-bit Integer
767	<b>Posit FB EGR Div</b> This is a 32 bit integer that forms the denominator of the load Electronic Gear Ratio function.	Default: 1 Min/Max: 1/2000000			32-bit Integer
768	<b>PositReg P Gain</b> Sets position regulator gain as measured from position error to speed reference. The gain number is identically equal to position regulator bandwidth in rad/sec. For example: A gain of 10 means that a per unit position error of 0.1 sec. will effect a 1.0 pu speed change (1 per unit position error is the distance traveled in 1 sec. at base motor speed). The maximum value of this parameter is typically 1/3 of the speed bandwidth (rad/sec) but may be set considerably higher with careful tuning of the speed regulator output lead/lag filter.	Units: R/S Default: 4.0000 Min/Max: 0.0000/200.0000	v	✓	Real
769	<b>Position Error</b> Actual position error in motor pulse counts. When the position regulator is not enabled, this 32 bit integer register is initialized to zero. When the position regulator is enabled, this parameter contains the running value of position error, often referred to as "following error".	Default: 0 Min/Max: -/+2147483648			32-bit Integer
770	<b>PositReg Integ</b> Sets position regulator integral gain as measured from position error to velocity reference. It has gain units of (per unit velocity/sec) / (per unit position) and is unit compatible with Par 768 [PositReg P Gain]. An integral gain of 25 means that a per unit position error of 0.1 sec will effect a 2.5 pu speed change per sec. A typical maximum value is $\frac{1}{2}$ [PositReg P Gain] <sup>2</sup> . Note: 1 per unit position is the distance traveled in 1 sec. at base motor speed.	Units: /S2 Default: 4.0000 Min/Max: 0.0000/1000.0000 Comm Scale: x 1	✓	✓	Real



No.	Name Description	Values	Linkable	Read-Write	Data Type
771	<b>PositReg Droop</b> Position Droop limits the low frequency gain of the position regulators integral channel to a value of (1/droop). It provides a means to fine tune the stability for load mounted feedback devices where lost motion may cause a problem. Typically, position droop will have a value that is less than (1/position gain), perhaps even zero for tightly coupled loads. Position droop has a gain value of (per unit position) / (per unit speed). Note: 1 per unit position is the distance traveled in 1 sec. at base motor speed.	Default: 0.0000 Min/Max: 0.0000/0.2500	✓	✓	Real
772	<b>XReg Integ LoLim</b> The negative limit of the position integrator.	Units: RPM Default: -176.4000 Min/Max: -14112.0000/0.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0	✓	✓	Real
773	<b>XReg Integ HiLim</b> The positive limit of the position integrator.	Units: RPM Default: 176.4000 Min/Max: 0.0000/14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0	✓	✓	Real
774	<b>XReg Integ Out</b> The output of the position regulator integral channel after application of the limits. This output is set to zero if the integral gain is set to zero or the integrator is not enabled.	Units: RPM Default: 0 Min/Max: -/+14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0			Real
775	<b>XReg Spd LoLim</b> The negative limit of total position regulator output. Point to point mode uses this parameter to set the reverse speed reference.	Units: RPM Default: -176.4000 Min/Max: -14112.0000/0.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0	✓	✓	Real
776	<b>XReg Spd HiLim</b> The positive limit of total position regulator output. Point to point mode uses this parameter to set the forward speed reference.	Units: RPM Default: 176.4000 Min/Max: 0.0000/14112.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0	✓	✓	Real
777	<b>Posit TP Select</b> Enter or write a value to select position regulator data displayed in Par 778 [Posit TP Data Int] and Par 779 [Posit TP DataReal].	Default: 0 "Zero" Options: 0 "Zero" 9 "Limiter Out" 1 "del Xos Vout" 10 "Ref EGR In" 2 "del Xcmd" 11 "OffsetSpdLim" 3 "del Act Load" 12 "PtoP SpdLim" 4 "del Act Mtr" 13 "Sec per Edge" 5 "Integ Error" 14 "Edge per Sec" 6 "Xprop Out" 15 "Ratio Guess" 7 "Reserved" 16 "Sync Count" 8 "PreLim Xvout"			
778	<b>PositTP Data Int</b> Displays the data selected by Par [Posit TP Sel]. This display should only be used if the selected value is integer data.	Default: 0 Min/Max: -/+2147483648			32-bit Integer
779	<b>PositTP DataReal</b> Displays the data selected by Par [Posit TP Sel] in RPM. This display should only be used if the selected value is floating point data.	Units: RPM Default: 0.0000 Min/Max: -/+3.8880799961088.0000 Comm Scale: Par 4 [Motor NP RPM] = 1.0			Real
780	<b>PositDetct1 Stpt</b> Provides the setpoint for Position Watch 1. Position Watch 1 is enabled and configured with Par 740 [Position Control] bits 16 & 17. Position Watch 1 compares this value with Par 784 [Posit Dect1 In] and sets bit 8 of Par 741 [Position Status] when the appropriate condition is satisfied.	Default: 0 Min/Max: -/+2147483648			32-bit Integer
781	<b>PositDetct2 Stpt</b> Provides the setpoint for Position Watch 2. Position Watch 2 is enabled and configured with Par 740 [Position Control] bits 18 & 19. Position Watch 2 compares this value with Par 785 [Posit Dect2 In] and sets bit 9 of Par 741 [Position Status] when the appropriate condition is satisfied.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
782	<b>In Posit BW</b> Sets overall bandwidth of the In Position detector. The detector sets bit 10 [In Position] of Par 741 [Position Status], when Par 769 [Position Error] is within this bandwidth for a sufficient time, specified by Par 783 [In Posit Dwell]. A modest hysteresis count is added to the position bandwidth after the position error is within specified limits.	Default: 200 Min/Max: 0/1000000	✓	✓	32-bit Integer
783	<b>In Posit Dwell</b> Position error must be within the value specified by Par 782 [In Posit BW] for this amount of time before the In Position detector sets bit 10 [In Position] of Par 741 [Position Status]. A momentary out of position indication will reset the internal timer and clear the In Position status bit.	Units: Sec Default: 0.0040 Min/Max: 0.0000/10.0000	✓	✓	Real
784	<b>Posit Dect1 In</b> Provides the input variable for Position Watch 1. Position Watch 1 is enabled and configured with Par 740 [Position Control] bits 16 & 17. Position Watch 1 compares this value with Par 780 [PositDetct1 Stpt] and sets bit 8 of Par 741 [Position Status] when the appropriate condition is satisfied. A default link connects this parameter to Par 763 [Act Motor Posit].	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer



No.	Name Description	Values	Linkable	Read-Write	Data Type
800	<b>Anlg In1 Data</b> Displays the value of Analog Input 1. This is the final value (after conversion, offsetting, scaling and filtering).	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
801	<b>Anlg In1 Volts</b> Displays sum of the Par 803 [Anlg In1 Offset] and the analog to digital conversion of Analog Input 1. The display range is +/-10V. If switch SW1-1 is closed (set for +/-1.0V) the value is scaled and displayed as +/-10V.	Units: Volt Default: 0.0000 Min/Max: -/+10.0000			Real
802	<b>Anlg In1 Scale</b> Scales the range of Analog Input 1 to the range of Par 800 [Anlg In1 Data]. Par 801 [Anlg In1 Volts] is multiplied by this number to produce the input to the lead lag filter function. Par 802 = 1, Par 800 = 10 when 10V is applied.	Units: /1v Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
803	<b>Anlg In1 Offset</b> Applies an offset to Analog Input 1. The output of the analog to digital conversion is summed with this number to produce Par 801 [Anlg In1 Volts]. This is used to zero out the analog input.	Units: Volt Default: 0.0000 Min/Max: -/+20.0000	✓	✓	Real
804	<b>AI 1 Filt Gain</b> Provides the lead term for the Analog Input 1 filter. Values greater than 1 will result in a lead function and value less than 1 will result in a lag function.	Default: 1.0000 Min/Max: -/+5.0000	✓	✓	Real
805	<b>Anlg In1 Filt BW</b> Sets the frequency for the Analog Input 1 filter.	Units: R/S Default: 0.0000 Min/Max: 0.0000/3760.0000	✓	✓	Real
806	<b>Anlg In2 Data</b> Displays the value of Analog Input 2. This is the final value (after conversion, offsetting, scaling and filtering).	Units: Volt Default: 0.0000 Min/Max: -/+2200000000.0000 Comm Scale: x 1			Real
807	<b>Anlg In2 Volts</b> Displays sum of the Par 809 [Anlg In2 Offset] and the analog to digital conversion of Analog Input 1. The display range is +/-10V. If switch SW1-1 is closed (set for +/-1.0V) the value is scaled and displayed as +/-10V.	Units: Volt Default: 0.0000 Min/Max: -/+10.0000			Real
808	<b>Anlg In2 Scale</b> Scales the range of Analog Input 1 to the range of Par 806 [Anlg In2 Data]. Par 807 [Anlg In2 Volts] is multiplied by this number to produce the input to the lead lag filter function.	Units: /1v Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
809	<b>Anlg In2 Offset</b> Applies an offset to Analog Input 1. The output of the analog to digital conversion is summed with this number to produce Par 807 [Anlg In2 Volts].	Units: Volt Default: 0.0000 Min/Max: -/+20.0000	✓	✓	Real
810	<b>AI 2 Filt Gain</b> Provides the lead term for the Analog Input 1 filter. Values greater than 1 will result in a lead function and value less than 1 will result in a lag function.	Default: 1.0000 Min/Max: -/+5.0000	✓	✓	Real
811	<b>Anlg In2 Filt BW</b> Sets the frequency for the Analog Input 1 filter.	Units: R/S Default: 0.0000 Min/Max: 0.0000/3760.0000	✓	✓	Real
812	<b>Anlg Out1 Offset</b> Provides an offset for analog output one, before the scaling and limit blocks in the Analog Output One function. Is summed with either Par 814 [AnlgOut1 Integer] or 815 [Anlg Out1 Real] at the beginning of the function.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
813	<b>Anlg Out2 Offset</b> Provides an offset for analog output one, before the scaling and limit blocks in the Analog Output Two function. Is summed with either Par 819 [AnlgOut2 Integer] or 820 [Anlg Out2 Real] at the beginning of the function.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
814	<b>AnlgOut1 Integer</b> Link this parameter to an integer source parameter and that source will control Analog Output 1.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
815	<b>Anlg Out1 Real</b> Link this parameter to a real (floating point) source parameter and that source will control Analog Output 1.	Default: 0.0000 Min/Max: -/+2200000000.0000.0000	✓	✓	Real
816	<b>Anlg Out1 Volts</b> Displays the voltage reference for Analog Output 1, before the digital to analog conversion.	Units: Volt Default: 0.0000 Min/Max: -/+10.0000			Real
817	<b>Anlg Out1 Scale</b> Scales the range of the source parameter to the range of Analog Output 1. Par 814 [AnlgOut1 Integer] or Par 815 [Anlg Out1 Real] is multiplied by this number after the limit function.	Units: /1v Default: 0.0000 Min/Max: -/+2200000000.0000	v	✓	Real
818	<b>Anlg Out1 Zero</b> Applies an offset to the scaled value. This parameter is summed with the output of the scaling block. This sum produces Par 816 [Anlg Out1 Volts]. Typically this value corresponds to 0V for Analog Output One.	Units: Volt Default: 0.0000 Min/Max: -/+20.0000	✓	✓	Real
819	<b>AnlgOut2 Integer</b> Link this parameter to an integer source parameter and that source will control Analog Output 2.	Default: 0 Min/Max: -/+2147483648	✓	✓	Real

No.	Name Description	Values	Linkable	Read-Write	Data Type																																																																																																					
820	<b>Anlg Out2 Real</b> Link this parameter to a real (floating point) source parameter and that source will control Analog Output 2.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real																																																																																																					
821	<b>Anlg Out2 Volts</b> Displays the voltage reference for Analog Output 2, before the digital to analog conversion.	Units: Volt Default: 0.0000 Min/Max: -/+10.0000			Real																																																																																																					
822	<b>Anlg Out2 Scale</b> Scales the range of the source parameter to the range of Analog Output 2. Par 819 [AnlgOut2 Integer] or Par 820 [Anlg Out2 Real] is multiplied by this number after the limit function.	Units: /1v Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real																																																																																																					
823	<b>Anlg Out2 Zero</b> Applies an offset to the scaled value. This parameter is summed with the output of the scaling block. This sum produces Par 821 [Anlg Out2 Volts]. Typically this value corresponds to 0V for Analog Output Two.	Units: Volt Default: 0.0000 Min/Max: -/+20.0000	✓	✓	Real																																																																																																					
824	<b>Local I/O Status</b> Displays the status of the local I/O.	<table border="1"> <thead> <tr> <th>Options</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>VPL Gate Ena</th> <th>Watch Dog</th> <th>VP TP2 Out</th> <th>VP TP1 Out</th> <th>Aux Out 2</th> <th>Aux Out 1</th> <th>Output Relay</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>LogixPresent</th> <th>Dign 3</th> <th>Dign 2</th> <th>Dign 1</th> <th>Enable In</th> </tr> </thead> <tbody> <tr> <td>Default</td> <td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td> </tr> <tr> <td>Bit</td> <td>31</td><td>30</td><td>29</td><td>28</td><td>27</td><td>26</td><td>25</td><td>24</td><td>23</td><td>22</td><td>21</td><td>20</td><td>19</td><td>18</td><td>17</td><td>16</td><td>15</td><td>14</td><td>13</td><td>12</td><td>11</td><td>10</td><td>9</td><td>8</td><td>7</td><td>6</td><td>5</td><td>4</td><td>3</td><td>2</td><td>1</td><td>0</td> </tr> </tbody> </table> <p>0 = False 1 = True</p>	Options	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	VPL Gate Ena	Watch Dog	VP TP2 Out	VP TP1 Out	Aux Out 2	Aux Out 1	Output Relay	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	LogixPresent	Dign 3	Dign 2	Dign 1	Enable In	Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0			
Options	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	VPL Gate Ena	Watch Dog	VP TP2 Out	VP TP1 Out	Aux Out 2	Aux Out 1	Output Relay	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	LogixPresent	Dign 3	Dign 2	Dign 1	Enable In																																																																									
Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0																																																																									
Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0																																																																										
825	<b>En In Debounce</b> Sets the value of the debounce filter for the Enable input. The filter requires the input signal to be stable for the specified time period. Input transitions within the filter time setting will be ignored.	Units: mSec Default: 8.0000/0.0000 Min/Max: 15.5000	✓	✓	Real																																																																																																					
826	<b>Dign1 Data</b> Sets the value of Par 828 [Dign1 Src Data], except for the bit controlled by bit 1 [Dign1] of Par 824 [Local I/O Status].	Default: 00000000000000000000000000000000 Min: 00000000000000000000000000000000 Max: 111111111111111111111111111111111111	✓	✓	32-bit Boolean																																																																																																					
827	<b>Dign1 Bit</b> Selects the bit, in Par 828 [Dign1 Src Data], which is controlled by bit controlled by bit 1 [Dign1] of Par 824 [Local I/O Status].	Default: 0 Min/Max: -32/31	✓	✓	16-bit Integer																																																																																																					
828	<b>Dign1 User Data</b> Provides a source of data controlled by bit 1 [Dign1] of Par 824 [Local I/O Status].  Link to a Read-Write parameter and enter a value of 13 in Par 838 [Dign1 Sel] to activate this function.	Default: 00000000000000000000000000000000 Min: 00000000000000000000000000000000 Max: 1111111111111111111111111111111111			32-bit Boolean																																																																																																					
829	<b>Dign1 Debounce</b> Sets the value of the debounce filter for Digital Input 1. The filter requires the input signal to be stable for the specified time period. Input transitions within the filter time setting will be ignored.	Units: mSec Default: 8.0000 Min/Max: 0.0000/15.5000	✓	✓	Real																																																																																																					
830	<b>Dign2 Data</b> Sets the value of Par 832 [Dign2 Src Data], except for the bit controlled by bit 2 [Dign2] of Par 824 [Local I/O Status].	Default: 00000000000000000000000000000000 Min: 00000000000000000000000000000000 Max: 1111111111111111111111111111111111	✓	✓	32-bit Boolean																																																																																																					
831	<b>Dign2 Bit</b> Selects the bit, in Par 832 [Dign2 Src Data], which is controlled by bit controlled by bit 2 [Dign2] of Par 824 [Local I/O Status].	Default: 0 Min/Max: -32/31	✓	✓	16-bit Integer																																																																																																					
832	<b>Dign2 User Data</b> Provides a source of data controlled by bit 2 [Dign2] of Par 824 [Local I/O Status].  Link to a Read-Write parameter and enter a value of 13 in Par 839 [Dign2 Sel] to activate this function.	Default: 00000000000000000000000000000000 Min: 00000000000000000000000000000000 Max: 1111111111111111111111111111111111 Comm Scale: Inputs & Outputs Digital Inputs			32-bit Boolean																																																																																																					
833	<b>Dign2 Debounce</b> Sets the value of the debounce filter for Digital Input 2. The filter requires the input signal to be stable for the specified time period. Input transitions within the filter time setting will be ignored.	Units: mSec Default: 8.0000 Min/Max: 0.0000/15.5000	✓	✓	Real																																																																																																					
834	<b>Dign3 Data</b> Sets the value of Par 836 [Dign3 Src Data], except for the bit controlled by bit 3 [Dign3] of Par 824 [Local I/O Status].	Default: 00000000000000000000000000000000 Min: 00000000000000000000000000000000 Max: 1111111111111111111111111111111111	✓	✓	32-bit Boolean																																																																																																					
835	<b>Dign3 Bit</b> Selects the bit, in Par 836 [Dign3 Src Data], which is controlled by bit controlled by bit 3 [Dign3] of Par 824 [Local I/O Status].	Default: 0 Min/Max: -32/31	✓	✓	16-bit Integer																																																																																																					
836	<b>Dign3 User Data</b> Provides a source of data controlled by bit 3 [Dign3] of Par 824 [Local I/O Status].  Link to a Read-Write parameter and enter a value of 13 in Par 840 [Dign3 Sel] to activate this function.	Default: 00000000000000000000000000000000 Min: 00000000000000000000000000000000 Max: 1111111111111111111111111111111111			32-bit Boolean																																																																																																					

No.	Name Description	Values	Linkable	Read-Write	Data Type
837	<b>DigIn3 Debounce</b> Sets the value of the debounce filter for Digital Input 3. The filter requires the input signal to be stable for the specified time period. Input transitions within the filter time setting will be ignored.	Units: mSec Default: 8.0000 Min/Max: 0.0000/15.5000	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>	Real
838	<b>DigIn 1 Sel</b> Enter or write a value to select the function of digital input 1.	Default: 0 "Not Used" Options: 0 "Not Used" 8 "Fwd/Reverse" 1 "Normal Stop" 9 "CurLim Stop" 2 "Start" 10 "Coast Stop" 3 "Run" 11 "Aux Fault" 4 "Clear Faults" 12 "AuxFault Inv" 5 "Stop - CF" 13 "User Select" 6 "Jog 1" 14 "PreChrg/Disc" 7 "Jog 2"			
839	<b>DigIn 2 Sel</b> Enter or write a value to select the function of digital input 2.	Default: 4 "Norm Stop-CF" Options: 0 "Not Used" 14 "Normal Stop" 1 "Enable" 15 "Spd Ref Sel1" 2 "Clear Faults" 16 "Spd Ref Sel2" 3 "Ext Fault" 17 "Spd Ref Sel3" 4 "Norm Stop-CF" 18 "CurLim Stop" 5 "Start" 19 "Coast Stop" 6 "Reverse" 21 "BscIndx Step" 7 "Run" 22 "BscIndxStpRv" 8 "Fwd/Reverse" 26 "PI Trim En" 9 "CurLim Stop" 29 "Trend Trig" 10 "Jog 1" 30 "PreCharge En" 11 "Aux Fault" 31 "Regis 1 Ltch" 12 "AuxFault Inv" 32 "+Hrd OvrTrvl" 13 "Jog 2" 33 "-Hrd OvrTrvl"			
840	<b>DigIn 3 Sel</b> Enter or write a value to select the function of digital input 3.	Default: 0 "Not Used" Options: 0 "Not Used" 13 "User Select" 1 "Normal Stop" 14 "Reserved" 2 "Start" 15 "Reserved" 3 "Run" 16 "Reserved" 4 "Clear Faults" 17 "Reserved" 5 "Stop-CF" 18 "Reserved" 6 "Jog 1" 19 "Reserved" 7 "Jog 2" 21 "Reserved" 8 "Fwd/Reverse" 22 "Reserved" 9 "CurLim Stop" 23 "Logix Motion" 10 "Coast Stop" 24 "+Hrd OvrTrvl" 11 "Aux Fault" 25 "-Hrd OvrTrvl" 12 "AuxFault Inv"			
841	<b>Relay Out Data</b> Link a word to this parameter that will control the Relay Output. The bit within the selected word that will control the Relay Output is set by Par 842 [Relay Out Bit].	Default: 00000000000000000000000000000000 Min: 00000000000000000000000000000000 Max: 11111111111111111111111111111111	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>	32-bit Boolean
842	<b>Relay Out Bit</b> Selects the bit, from the word linked to Par 841 that will change the status of the Relay Output (e.g., when Par 842 [Relay Out Bit] equals 0, bit 0 of Par 841 [Relay Out 1 Data] will control the Relay Output).	Default: 0 Min/Max: -32/31	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>	16-bit Integer
843	<b>DigOut 1 Data</b> Link a word to this parameter that will control Digital Output 1. The bit within the selected word that will control Digital Output 1 is set by Par 844 [Dig Out 1 Bit].	Default: 00000000000000000000000000000000 Min: 00000000000000000000000000000000 Max: 11111111111111111111111111111111	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>	32-bit Boolean
844	<b>DigOut 1 Bit</b> Selects the bit, from the word linked to Par 843, that will change the status of Digital Output 1 (e.g., when Par 844 [Dig Out 1 Bit] equals 0, bit 0 of Par 843 [Dig Out 1 Data] will control Digital Output 1).	Default: 0 Min/Max: -32/31	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>	16-bit Integer
845	<b>DigOut 2 Data</b> Link a word to this parameter that will control Digital Output 2. The bit within the selected word that will control Digital Output 2 is set by Par 846 [Dig Out 2 Bit].	Default: 00000000000000000000000000000000 Min: 00000000000000000000000000000000 Max: 11111111111111111111111111111111	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>	32-bit Boolean
846	<b>DigOut 2 Bit</b> Selects the bit, from the word linked to Par 845, that will change the status of Digital Output 2 (e.g., when Par 846 [Dig Out 2 Bit] equals 0, bit 0 of Par 845 [Dig Out 2 Data] will control Digital Output 2).	Default: 0 Min/Max: -32/31	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>	16-bit Integer
850	<b>ParamAccessLevel</b> The value of this parameter establishes the level of parameter access for the Human Interface Module (HIM). • Value 0 - Basic grants access to the minimum number of parameters • Value 1 - Advance grants access to a larger group of parameters • Value 2 - Engineering grants access to all the parameters	Default: 0 "Basic" Options: 0 "Basic" 1 "Advanced" 2 "Engineering"			
901	<b>MotnUpdatePeriod</b> Servo update period for the servo axis (drive).	Units: uSec Default: 2000 Min/Max: 1/999999			DWord



No.	Name Description	Values	Linkable	Read-Write	Data Type																																																																																																																																	
909	<b>Motn EventCtrl</b> Shows configuration state of Motion Event functions.																																																																																																																																					
	Options																																																																																																																																					
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	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Home	Home Arm	Regis2 Posit	Regis2 X Arm	Regis1 Posit	Regis1 X Arm	Watch Posit	Watch X Arm																																																																																																																						
Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0																																																																																																																						
Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0																																																																																																																						
		0 = False 1 = True																																																																																																																																				
911	<b>Motn Mx Pos Trvl</b> Positive soft overtravel threshold for the Motion Servo Axis.	Default: 0 Min/Max: -/+2147483648			DWord																																																																																																																																	
912	<b>Motn Mx Neg Trvl</b> Negative soft overtravel threshold for the Motion Servo Axis.	Default: 0 Min/Max: -/+2147483648			DWord																																																																																																																																	
913	<b>Motn PositErrTol</b> Position error tolerance for the Motion Servo Axis.	Default: 4096 Min/Max: 0/2147483648			DWord																																																																																																																																	
914	<b>Motn Positlock Tol</b> Position lock tolerance for the Motion Servo Axis.	Default: 0 Min/Max: 0/2147483648			DWord																																																																																																																																	
917	<b>Motn Posit Cmmd</b> Position command input from the Motion Planner. This is linked as the course to the interpolator's "CoursePosit Trgt."	Default: 0 Min/Max: -/+2147483648			DWord																																																																																																																																	
918	<b>Motn Speed Cmmd</b> Speed command input from the Motion Planner. This is linked as the source to the interpolator's "Coarse Spd Trgt."	Units: P.U. Default: 0.0000 Min/Max: -/+8.0000			Real																																																																																																																																	
919	<b>Motn Posit Sync</b> Synchronization input signal from the Motion Planner. Pulse received once per coarse update period. This is linked as the course to "Interp SynchInput."																																																																																																																																					
	Options																																																																																																																																					
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	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Sync Unstbl	Sync Loss	InterpSynch	SyncDataActv	Sync Pulse																																																																																																	
Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0																																																																																										
Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0																																																																																																						
		0 = False 1 = True																																																																																																																																				
920	<b>FdbkAxis FdbkSel</b> Selection for the Motion Feedback Only Axis feedback source. Note: Selections 5 and 6 are only available when compatible feedback option card is installed.	1 "Encoder 1"																																																																																																																																				
		0 "Encoder 0" 6 "FB Opt Port1"																																																																																																																																				
		1 "Encoder 1" 7 "SL DirIntRx0"																																																																																																																																				
		2 "Reserved" 8 "SL DirIntRx1"																																																																																																																																				
		3 "Reserved" 9 "SL DirIntRx2"																																																																																																																																				
		4 "Reserved" 10 "SL DirIntRx3"																																																																																																																																				
5 "FB Opt Port0"																																																																																																																																						
921	<b>FdbkAxis FdbkVal</b> Present value of the selected feedback for the Motion Feedback Only Axis.	Default: 0 Min/Max: -/+2147483648			DWord																																																																																																																																	
922	<b>Motn TP Select</b> Selector for diagnostic testpoint relating to Motion functionality.	0 "ServoAxisCnfg"																																																																																																																																				
		0 "ServoAxisCnfg" 16 ""CST Upper"																																																																																																																																				
		1 "ServoAxisUnwd" 17 "Reserved"																																																																																																																																				
		2 "Marker Dist" 18 "Reserved"																																																																																																																																				
		3 "HomeEvent X" 19 "I/O Rx Seq#"																																																																																																																																				
		4 "Watch Posit" 20 "I/O Rx Msg#"																																																																																																																																				
		5 "Home Posit" 21 "I/O Tx Msg#"																																																																																																																																				
		6 "SrvoMRP Ofst" 22 "Syn Rx Seq#"																																																																																																																																				
		7 "SrvoAct Ofst" 23 "Syn RxMsg#"																																																																																																																																				
		8 "PositRegis 1" 24 "Syn Tx Msg#"																																																																																																																																				
		9 "PositRegis 2" 25 "EvtRx Seq#"																																																																																																																																				
		10 "FdbkAxisCnfg" 26 "EvtRx Msg#"																																																																																																																																				
		11 "FdbkAxisUnwd" 27 "EvtRx Tx Msg#"																																																																																																																																				
		12 "FdbkMRP Ofst" 28 "Asy Rx Seq#"																																																																																																																																				
		13 "FdbkAct Ofst" 29 "Asy Rx Msg#"																																																																																																																																				
		14 "TimeEvt Stat" 30 "Asy Tx Msg#"																																																																																																																																				
15 "CST Lower" 31 "Reset Msg#"																																																																																																																																						
923	<b>Motn TP Value</b> Data for diagnostic testpoint relating to Motion functionality.	Default: 0 Min/Max: -/+2147483648			DWord																																																																																																																																	
924	<b>Motn RotaryCmmd</b> Position command input from the Motion Planner to the ServoAxis when configured in rotary mode.	Default: 0 Min/Max: -/+2147483648			DWord																																																																																																																																	
925	<b>MotnUnwdTurnCmmd</b> Position unwind turns command input from the Motion Planner to the Servo Axis when configured in rotary mode.	Default: 0 Min/Max: -/+32768			Word																																																																																																																																	

No.	Name Description	Values	Linkable	Read-Write	Data Type																																																						
926	<b>SrvoAxis RotFdbk</b> Position feedback output to the Motion Planner for the Servo Axis when configured in rotary mode.	Default: 0 Min/Max: -/+2147483648			DWord																																																						
927	<b>SrvoAxisUnwdFdbk</b> Position unwind feedback output to the Motion Planner for the Servo Axis when configured in rotary mode.	Default: 0 Min/Max: -/+32768			Word																																																						
928	<b>FdbkAxis RotFdbk</b> Position feedback output to the Motion Planner for the Feedback Only Axis when configured in rotary mode.	Default: 0 Min/Max: -/+2147483648			DWord																																																						
929	<b>FdbkAxisUnwdFdbk</b> Position unwind feedback output to the Motion Planner for the Feedback Only Axis when configured in rotary mode.	Default: 0 Min/Max: -/+32768			Word																																																						
930	<b>MotnCnfgErrParam</b> Indicates a parameter that is not configured properly for a motion connection to be accepted. Parameter could either have a wrong value or an incorrect link. When the "Config OK" bit of "Motn Cnct Status" is set, then this parameter contains the parameter number of an incorrectly configured parameter. If more than one parameter is incorrectly configured, they are displayed after others are fixed. If there are not configuration problems relating to Motion, then this parameter contains the value of zero and the "Config OK" bit is cleared.	Default: 0 Min/Max: 0/65535			Word																																																						
940 941	<b>+Sft OvrTrvlCnfg</b> -Sft OvrTrvlCnfg Synchronization input to the Interpolator has been lost or has become excessively irregular. <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FltCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> <li>Value 3 - Flt RampStop configures the drive to perform a ramp stop and set the appropriate fault bit, in response this event.</li> <li>Value 4 - FltCurLimStp configures the drive to perform a current-limit stop and set the appropriate fault bit, in response this event.</li> </ul>	Default: 1 "Alarm" Options: 0 "Ignore" 1 "Alarm" 2 "FltCoastStop" 3 "Flt RampStop" 4 "FltCurLimStp"																																																									
942 943	<b>+Hrd OvrTrvlCnfg</b> -Hrd OvrTrvlCnfg Active signal from a digital input that is configured as a positive hard overtravel input. <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FltCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> <li>Value 3 - Flt RampStop configures the drive to perform a ramp stop and set the appropriate fault bit, in response this event.</li> <li>Value 4 - FltCurLimStp configures the drive to perform a current-limit stop and set the appropriate fault bit, in response this event.</li> </ul>	Default: 1 "Alarm" Options: 0 "Ignore" 1 "Alarm" 2 "FltCoastStop" 3 "Flt RampStop" 4 "FltCurLimStp"																																																									
944	<b>Position ErrCnfg</b> Position error for a Motion Servo Axis has exceeded the configured limit. <ul style="list-style-type: none"> <li>Value 0 - Ignore configures the drive to continue running, as normal, when this event occurs</li> <li>Value 1 - Alarm configures the drive to continue running and set the appropriate alarm bit when this event occurs</li> <li>Value 2 - FltCoastStop configures the drive to perform a coast stop and set the appropriate fault bit, in response this event.</li> <li>Value 3 - Flt RampStop configures the drive to perform a ramp stop and set the appropriate fault bit, in response this event.</li> <li>Value 4 - FltCurLimStp configures the drive to perform a current-limit stop and set the appropriate fault bit, in response this event.</li> </ul>	Default: 1 "Alarm" Options: 0 "Ignore" 1 "Alarm" 2 "FltCoastStop" 3 "Flt RampStop" 4 "FltCurLimStp"																																																									
1000	<b>SL Node Cnfg</b> Set bits to configure the SynchLink node. <ul style="list-style-type: none"> <li>Setting bit 0 configures the local node as the Time Master.</li> <li>Setting bit 2 configures the node to synchronize with the Time Master immediately (1-2S per node) on power-up or recovery. If you do not set bit 2, the node will stay in the fast mode, taking up to 36S per node to synchronize on power-up or recovery.</li> </ul>																																																										
<table border="1"> <thead> <tr> <th>Options</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Sync Now</th> <th>Reserved</th> <th>Time Keeper</th> </tr> </thead> <tbody> <tr> <td>Default</td> <td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td> </tr> <tr> <td>Bit</td> <td>15</td><td>14</td><td>13</td><td>12</td><td>11</td><td>10</td><td>9</td><td>8</td><td>7</td><td>6</td><td>5</td><td>4</td><td>3</td><td>2</td><td>1</td><td>0</td><td></td> </tr> </tbody> </table>						Options	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Sync Now	Reserved	Time Keeper	Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0	
Options	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Sync Now	Reserved	Time Keeper																																										
Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0																																										
Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0																																											
<p>0 = False 1 = True</p>																																																											





No.	Name Description	Values	Linkable	Read-Write	Data Type
1021	<b>SL Tx DirectSel0</b> Determines the source type for the data transmitted by direct transmit word 0. The source type selections are: no data, event, feedback and drive parameter. If drive parameter is selected, a parameter of the appropriate data format (integer or real) must be linked to Parameter 1141 [SL Dir Int Tx0] or Parameter 1142 [SL Dir Real Tx0]. Configure the selection by using the Peer Communication window.	Default: 0 "No Data" Options: 0 "No Data" 14 "Reserved" 1 "SL Multiply" 15 "Reserved" 2 "Event P0" 16 "Reserved" 3 "Event P1" 17 "Reserved" 4 "Event D0" 18 "Reserved" 5 "Event D1" 19 "Reserved" 6 "Event D2" 20 "Reserved" 7 "Event D3" 21 "Dir Tx Data" 8 "Event Opt0" 22 "Dir Rx Data" 9 "Event Opt1" 23 "E0 Accum" 10 "Event Status" 24 "E1 Accum" 11 "Reserved" 25 "Opt0 Accum" 12 "Reserved" 26 "Opt1 Accum" 13 "Reserved"			
1022	<b>SL Tx DirectSel1</b> Determines the source type for the data transmitted by direct transmit word 1. The source type selections are: no data, event, feedback and drive parameter. If drive parameter is selected, a parameter of the appropriate data format (integer or real) must be linked to Par 1143 [SL Dir Int Tx1] or Par 1144 [SL Dir Real Tx1]. Configure the selection by using the Peer Communication window.	Default: 0 "No Data" Options: 0 "No Data" 14 "Reserved" 1 "SL Multiply" 15 "Reserved" 2 "Event P0" 16 "Reserved" 3 "Event P1" 17 "Reserved" 4 "Event D0" 18 "Reserved" 5 "Event D1" 19 "Reserved" 6 "Event D2" 20 "Reserved" 7 "Event D3" 21 "Dir Tx Data" 8 "Event Opt0" 22 "Dir Rx Data" 9 "Event Opt1" 23 "E0 Accum" 10 "Event Status" 24 "E1 Accum" 11 "Reserved" 25 "Opt0 Accum" 12 "Reserved" 26 "Opt1 Accum" 13 "Reserved"			
1023	<b>SL Tx DirectSel2</b> Determines the source type for the data transmitted by direct transmit word 2. The source type selections are: no data, event, feedback and drive parameter. If drive parameter is selected, a parameter of the appropriate data format (integer or real) must be linked to Parameter 1145 [SL Dir Int Tx2] or Parameter 1146 [SL Dir Real Tx2]. Configure the selection by using the Peer Communication window.	Default: 0 "No Data" Options: 0 "No Data" 14 "Reserved" 1 "SL Multiply" 15 "Reserved" 2 "Event P0" 16 "Reserved" 3 "Event P1" 17 "Reserved" 4 "Event D0" 18 "Reserved" 5 "Event D1" 19 "Reserved" 6 "Event D2" 20 "Reserved" 7 "Event D3" 21 "Dir Tx Data" 8 "Event Opt0" 22 "Dir Rx Data" 9 "Event Opt1" 23 "E0 Accum" 10 "Event Status" 24 "E1 Accum" 11 "Reserved" 25 "Opt0 Accum" 12 "Reserved" 26 "Opt1 Accum" 13 "Reserved"			
1024	<b>SL Tx DirectSel3</b> Determines the source type for the data transmitted by direct transmit word 3. The source type selections are: no data, event, feedback and drive parameter. If drive parameter is selected, a parameter of the appropriate data format (integer or real) must be linked to Par 1147 [SL Dir Int Tx3] or Par 1148 [SL Dir Real Tx3]. Configure the selection by using the Peer Communication window.	Default: 0 "No Data" Options: 0 "No Data" 14 "Reserved" 1 "SL Multiply" 15 "Reserved" 2 "Event P0" 16 "Reserved" 3 "Event P1" 17 "Reserved" 4 "Event D0" 18 "Reserved" 5 "Event D1" 19 "Reserved" 6 "Event D2" 20 "Reserved" 7 "Event D3" 21 "Dir Tx Data" 8 "Event Opt0" 22 "Dir Rx Data" 9 "Event Opt1" 23 "E0 Accum" 10 "Event Status" 24 "E1 Accum" 11 "Reserved" 25 "Opt0 Accum" 12 "Reserved" 26 "Opt1 Accum" 13 "Reserved"			
1030	<b>SL Mult A In</b> Displays the A Multiplier Input, as a floating point (real) value. This value is divided by the Par 1032 [SL Mult Base]. The source of the A Multiplier is determined by the "Rx Direct Data Selector" (Pars 1011-1014). The possible sources are: zero, Par 1054 [Dir Int Rx0], Par 1056 [Dir Int Rx1], Par 1058 [Dir Int Rx2], or Par 1060 [Dir Int Rx3]. The SynchLink Multiply function takes this input before it is converted to floating point.	Default: 0.0000 Min/Max: 0.0000/65535.0000			Real
1031	<b>SL Mult B In</b> The B Multiplier Input. This must be a floating point (real) value. The SynchLink Multiply function takes this input after it is converted to integer.	Default: 1.0000 Min/Max: 0.25000/2.0000	✓	✓	Real



No.	Name Description	Values	Linkable	Read-Write	Data Type
1056	<b>SL Dir Int Rx1</b> Displays the integer value of the Direct Received Data for word 1. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1057 [SL Dir Real Rx1].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1057	<b>SL Dir Real Rx1</b> Displays the floating point (real) value of the Direct Received Data for word 1. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1056 [SL Dir Int Rx1].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1058	<b>SL Dir Int Rx2</b> Displays the integer value of the Direct Received Data for word 2. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1059 [SL Dir Real Rx2].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1059	<b>SL Dir Real Rx2</b> Displays the floating point (real) value of the Direct Received Data for word 2. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1058 [SL Dir Int Rx2].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1060	<b>SL Dir Int Rx3</b> Displays the integer value of the Direct Received Data for word 3. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1061 [SL Dir Real Rx3].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1061	<b>SL Dir Real Rx3</b> Displays the floating point (real) value of the Direct Received Data for word 3. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1060 [SL Dir Int Rx3].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1073	<b>SL Buf Int Rx00</b> Displays the integer value of the Buffered Received Data for word 0. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1074 [SL Buf Real Rx00].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1074	<b>SL Buf Real Rx00</b> Displays the floating point (real) value of the Buffered Received Data for word 0. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1073 [SL Buf Int Rx00].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1075	<b>SL Buf Int Rx01</b> Displays the integer value of the Buffered Received Data for word 1. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1076 [SL Buf Real Rx01].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1076	<b>SL Buf Real Rx01</b> Displays the floating point (real) value of the Buffered Received Data for word 1. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1075 [SL Buf Int Rx01].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1077	<b>SL Buf Int Rx02</b> Displays the integer value of the Buffered Received Data for word 2. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1078 [SL Buf Real Rx02].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1078	<b>SL Buf Real Rx02</b> Displays the floating point (real) value of the Buffered Received Data for word 2. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1077 [SL Buf Int Rx02].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1079	<b>SL Buf Int Rx03</b> Displays the integer value of the Buffered Received Data for word 3. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1080 [SL Buf Real Rx03].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1080	<b>SL Buf Real Rx03</b> Displays the floating point (real) value of the Buffered Received Data for word 3. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1079 [SL Buf Int Rx03].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1081	<b>SL Buf Int Rx04</b> Displays the integer value of the Buffered Received Data for word 4. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1082 [SL Buf Real Rx04].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1082	<b>SL Buf Real Rx04</b> Displays the floating point (real) value of the Buffered Received Data for word 4. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1081 [SL Buf Int Rx04].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1083	<b>SL Buf Int Rx05</b> Displays the integer value of the Buffered Received Data for word 5. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1084 [SL Buf Real Rx05].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1084	<b>SL Buf Real Rx05</b> Displays the floating point (real) value of the Buffered Received Data for word 5. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1083 [SL Buf Int Rx05].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real

No.	Name Description	Values	Linkable	Read-Write	Data Type
1085	<b>SL Buf Int Rx06</b> Displays the integer value of the Buffered Received Data for word 6. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1086 [SL Buf Real Rx06].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1086	<b>SL Buf Real Rx06</b> Displays the floating point (real) value of the Buffered Received Data for word 6. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1085 [SL Buf Int Rx06].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1087	<b>SL Buf Int Rx07</b> Displays the integer value of the Buffered Received Data for word 7. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1088 [SL Buf Real Rx07].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1088	<b>SL Buf Real Rx07</b> Displays the floating point (real) value of the Buffered Received Data for word 7. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1087 [SL Buf Int Rx07].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1089	<b>SL Buf Int Rx08</b> Displays the integer value of the Buffered Received Data for word 8. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1090 [SL Buf Real Rx08].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1090	<b>SL Buf Real Rx08</b> Displays the floating point (real) value of the Buffered Received Data for word 8. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1089 [SL Buf Int Rx08].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1091	<b>SL Buf Int Rx09</b> Displays the integer value of the Buffered Received Data for word 9. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1092 [SL Buf Real Rx09].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1092	<b>SL Buf Real Rx09</b> Displays the floating point (real) value of the Buffered Received Data for word 9. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1091 [SL Buf Int Rx09].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1093	<b>SL Buf Int Rx10</b> Displays the integer value of the Buffered Received Data for word 10. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1094 [SL Buf Real Rx10].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1094	<b>SL Buf Real Rx10</b> Displays the floating point (real) value of the Buffered Received Data for word 10. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1093 [SL Buf Int Rx10].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1095	<b>SL Buf Int Rx11</b> Displays the integer value of the Buffered Received Data for word 11. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1096 [SL Buf Real Rx11].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1096	<b>SL Buf Real Rx11</b> Displays the floating point (real) value of the Buffered Received Data for word 11. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1095 [SL Buf Int Rx11].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1097	<b>SL Buf Int Rx12</b> Displays the integer value of the Buffered Received Data for word 12. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1098 [SL Buf Real R12].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1098	<b>SL Buf Real Rx12</b> Displays the floating point (real) value of the Buffered Received Data for word 12. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1097 [SL Buf Int R12].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1099	<b>SL Buf Int Rx13</b> Displays the integer value of the Buffered Received Data for word 13. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1100 [SL Buf Real Rx13].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1100	<b>SL Buf Real Rx13</b> Displays the floating point (real) value of the Buffered Received Data for word 13. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1099 [SL Buf Int R13].	Default: 0.0000 Min/Max: -/+2200000000.0000.0000			Real
1101	<b>SL Buf Int Rx14</b> Displays the integer value of the Buffered Received Data for word 14. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1102 [SL Buf Real R14].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1102	<b>SL Buf Real Rx14</b> Displays the floating point (real) value of the Buffered Received Data for word 14. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1101 [SL Buf Int R14].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real

No.	Name Description	Values	Linkable	Read-Write	Data Type
1103	<b>SL Buf Int Rx15</b> Displays the integer value of the Buffered Received Data for word 15. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1104 [SL Buf Real Rx15].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1104	<b>SL Buf Real Rx15</b> Displays the floating point (real) value of the Buffered Received Data for word 15. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1103 [SL Buf Int Rx15].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1105	<b>SL Buf Int Rx16</b> Displays the integer value of the Buffered Received Data for word 16. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1106 [SL Buf Real Rx16].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1106	<b>SL Buf Real Rx16</b> Displays the floating point (real) value of the Buffered Received Data for word 16. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1105 [SL Buf Int Rx16].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1107	<b>SL Buf Int Rx17</b> Displays the integer value of the Buffered Received Data for word 17. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1108 [SL Buf Real Rx17].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1108	<b>SL Buf Real Rx17</b> Displays the floating point (real) value of the Buffered Received Data for word 17. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1107 [SL Buf Int Rx17].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1109	<b>SL Buf Int Rx18</b> Displays the integer value of the Buffered Received Data for word 18. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1110 [SL Buf Real Rx18].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1110	<b>SL Buf Real Rx18</b> Displays the floating point (real) value of the Buffered Received Data for word 18. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1109 [SL Buf Int Rx18].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1111	<b>SL Buf Int Rx19</b> Displays the integer value of the Buffered Received Data for word 19. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1112 [SL Buf Real Rx19].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1112	<b>SL Buf Real Rx19</b> Displays the floating point (real) value of the Buffered Received Data for word 19. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1111 [SL Buf Int Rx19].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1113	<b>SL Buf Int Rx20</b> Displays the integer value of the Buffered Received Data for word 20. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1114 [SL Buf Real Rx20].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1114	<b>SL Buf Real Rx20</b> Displays the floating point (real) value of the Buffered Received Data for word 20. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1113 [SL Buf Int Rx20].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1115	<b>SL Buf Int Rx21</b> Displays the integer value of the Buffered Received Data for word 21. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1116 [SL Buf Real Rx21].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1116	<b>SL Buf Real Rx21</b> Displays the floating point (real) value of the Buffered Received Data for word 21. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1115 [SL Buf Int Rx21].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1117	<b>SL Buf Int Rx22</b> Displays the integer value of the Buffered Received Data for word 22. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1118 [SL Buf Real Rx22].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1118	<b>SL Buf Real Rx22</b> Displays the floating point (real) value of the Buffered Received Data for word 22. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1117 [SL Buf Int Rx22].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1119	<b>SL Buf Int Rx23</b> Displays the integer value of the Buffered Received Data for word 23. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1120 [SL Buf Real Rx23].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1120	<b>SL Buf Real Rx23</b> Displays the floating point (real) value of the Buffered Received Data for word 23. Data transmitted from one node to another must be the same data type. This parameter is paired with Par 1119 [SL Buf Int Rx23].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real



No.	Name Description	Value	Linkable	Read-Write	Data Type																													
1144	<b>SL Dir Real Tx1</b> Provides floating point (real) data for Direct Transmit word 1, if the data type for word 1 (indicated in Par 1140 [Tx Dir Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real																													
1145	<b>SL Dir Int Tx2</b> Provides integer data for Direct Transmit word 2, if the data type for word 2 (indicated in Par 1140 [Tx Dir Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer																													
1146	<b>SL Dir Real Tx2</b> Provides floating point (real) data for Direct Transmit word 2, if the data type for word 2 (indicated in Par 1140 [Tx Dir Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real																													
1147	<b>SL Dir Int Tx3</b> Provides integer data for Direct Transmit word 3, if the data type for word 3 (indicated in Par 1140 [Tx Dir Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer																													
1148	<b>SL Dir Real Tx3</b> Provides floating point (real) data for Direct Transmit word 3, if the data type for word 3 (indicated in Par 1140 [Tx Dir Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real																													
1160	<b>Tx Buf Data Type</b> Indicates the data type of each Buffered Transmit word. If the word's bit is set the data type is floating point (real). If the bit is not set the data type is integer. Use the Peer Communication window to configure this selection.																																	
	Options																																	
	Reserved	Reserved	Reserved	Real Tx28	Real Tx27	Real Tx26	Real Tx25	Real Tx24	Real Tx23	Real Tx22	Real Tx21	Real Tx20	Real Tx19	Real Tx18	Real Tx17	Real Tx16	Real Tx15	Real Tx14	Real Tx13	Real Tx12	Real Tx11	Real Tx10	Real Tx9	Real Tx8	Real Tx7	Real Tx6	Real Tx5	Real Tx4	Real Tx3	Real Tx2	Real Tx1	Real Tx0		
	Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	
	Bit	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0	0 = False 1 = True
1161	<b>SL Buf Int Tx00</b> Provides integer data for Direct Transmit word 0, if the data type for word 0 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer																													
1162	<b>SL Buf Real Tx00</b> Provides floating point (real) data for Direct Transmit word 0, if the data type for word 0 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real																													
1163	<b>SL Buf Int Tx01</b> Provides integer data for Direct Transmit word 1, if the data type for word 1 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer																													
1164	<b>SL Buf Real Tx01</b> Provides floating point (real) data for Direct Transmit word 1, if the data type for word 1 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real																													
1165	<b>SL Buf Int Tx02</b> Provides integer data for Direct Transmit word 2, if the data type for word 2 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer																													
1166	<b>SL Buf Real Tx02</b> Provides floating point (real) data for Direct Transmit word 2, if the data type for word 2 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real																													
1167	<b>SL Buf Int Tx03</b> Provides integer data for Direct Transmit word 3, if the data type for word 3 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer																													
1168	<b>SL Buf Real Tx03</b> Provides floating point (real) data for Direct Transmit word 3, if the data type for word 3 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real																													
1169	<b>SL Buf Int Tx04</b> Provides integer data for Direct Transmit word 4, if the data type for word 4 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer																													
1170	<b>SL Buf Real Tx04</b> Provides floating point (real) data for Direct Transmit word 4, if the data type for word 4 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real																													
1171	<b>SL Buf Int Tx05</b> Provides integer data for Direct Transmit word 5, if the data type for word 5 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer																													
1172	<b>SL Buf Real Tx05</b> Provides floating point (real) data for Direct Transmit word 5, if the data type for word 5 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real																													
1173	<b>SL Buf Int Tx06</b> Provides integer data for Direct Transmit word 6, if the data type for word 6 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer																													
1174	<b>SL Buf Real Tx06</b> Provides floating point (real) data for Direct Transmit word 6, if the data type for word 6 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real																													
1175	<b>SL Buf Int Tx07</b> Provides integer data for Direct Transmit word 7, if the data type for word 7 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer																													

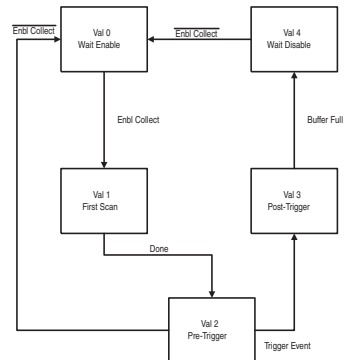


No.	Name Description	Value	Linkable	Read-Write	Data Type
1176	<b>SL Buf Real Tx07</b> Provides floating point (real) data for Direct Transmit word 7, if the data type for word 7 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1177	<b>SL Buf Int Tx08</b> Provides integer data for Direct Transmit word 8, if the data type for word 8 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1178	<b>SL Buf Real Tx08</b> Provides floating point (real) data for Direct Transmit word 8, if the data type for word 8 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1179	<b>SL Buf Int Tx09</b> Provides integer data for Direct Transmit word 9, if the data type for word 9 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1180	<b>SL Buf Real Tx09</b> Provides floating point (real) data for Direct Transmit word 9, if the data type for word 9 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1181	<b>SL Buf Int Tx10</b> Provides integer data for Direct Transmit word 10, if the data type for word 10 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1182	<b>SL Buf Real Tx10</b> Provides floating point (real) data for Direct Transmit word 10, if the data type for word 10 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1183	<b>SL Buf Int Tx11</b> Provides integer data for Direct Transmit word 11, if the data type for word 11 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1184	<b>SL Buf Real Tx11</b> Provides floating point (real) data for Direct Transmit word 11, if the data type for word 11 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1185	<b>SL Buf Int Tx12</b> Provides integer data for Direct Transmit word 12, if the data type for word 12 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1186	<b>SL Buf Real Tx12</b> Provides floating point (real) data for Direct Transmit word 12, if the data type for word 12 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1187	<b>SL Buf Int Tx13</b> Provides integer data for Direct Transmit word 13, if the data type for word 13 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1188	<b>SL Buf Real Tx13</b> Provides floating point (real) data for Direct Transmit word 13, if the data type for word 13 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1189	<b>SL Buf Int Tx14</b> Provides integer data for Direct Transmit word 14, if the data type for word 14 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1190	<b>SL Buf Real Tx14</b> Provides floating point (real) data for Direct Transmit word 14, if the data type for word 14 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1191	<b>SL Buf Int Tx15</b> Provides integer data for Direct Transmit word 15, if the data type for word 15 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1192	<b>SL Buf Real Tx15</b> Provides floating point (real) data for Direct Transmit word 15, if the data type for word 15 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1193	<b>SL Buf Int Tx16</b> Provides integer data for Direct Transmit word 16, if the data type for word 16 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	v	32-bit Integer
1194	<b>SL Buf Real Tx16</b> Provides floating point (real) data for Direct Transmit word 16, if the data type for word 16 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1195	<b>SL Buf Int Tx17</b> Provides integer data for Direct Transmit word 17, if the data type for word 17 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1196	<b>SL Buf Real Tx17</b> Provides floating point (real) data for Direct Transmit word 17, if the data type for word 17 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1197	<b>SL Buf Int Tx18</b> Provides integer data for Direct Transmit word 18, if the data type for word 18 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1198	<b>SL Buf Real Tx18</b> Provides floating point (real) data for Direct Transmit word 18, if the data type for word 18 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real

No.	Name Description	Value	Linkable	Read-Write	Data Type
1199	<b>SL Buf Int Tx19</b> Provides integer data for Direct Transmit word 19, if the data type for word 19 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1200	<b>SL Buf Real Tx19</b> Provides floating point (real) data for Direct Transmit word 19, if the data type for word 19 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1201	<b>SL Buf Int Tx20</b> Provides integer data for Direct Transmit word 20, if the data type for word 20 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1202	<b>SL Buf Real Tx20</b> Provides floating point (real) data for Direct Transmit word 20, if the data type for word 20 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	v	Real
1203	<b>SL Buf Int Tx21</b> Provides integer data for Direct Transmit word 21, if the data type for word 21 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1204	<b>SL Buf Real Tx21</b> Provides floating point (real) data for Direct Transmit word 21, if the data type for word 21 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1205	<b>SL Buf Int Tx22</b> Provides integer data for Direct Transmit word 22, if the data type for word 22 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1206	<b>SL Buf Real Tx22</b> Provides floating point (real) data for Direct Transmit word 22, if the data type for word 22 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1207	<b>SL Buf Int Tx23</b> Provides integer data for Direct Transmit word 23, if the data type for word 23 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1208	<b>SL Buf Real Tx23</b> Provides floating point (real) data for Direct Transmit word 23, if the data type for word 23 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1209	<b>SL Buf Int Tx24</b> Provides integer data for Direct Transmit word 24, if the data type for word 24 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1210	<b>SL Buf Real Tx24</b> Provides floating point (real) data for Direct Transmit word 24, if the data type for word 24 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1211	<b>SL Buf Int Tx25</b> Provides integer data for Direct Transmit word 25, if the data type for word 25 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1212	<b>SL Buf Real Tx25</b> Provides floating point (real) data for Direct Transmit word 25, if the data type for word 25 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000 Comm Scale: x 1	✓	✓	Real
1213	<b>SL Buf Int Tx26</b> Provides integer data for Direct Transmit word 26, if the data type for word 26 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1214	<b>SL Buf Real Tx26</b> Provides floating point (real) data for Direct Transmit word 26, if the data type for word 26 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	real
1215	<b>SL Buf Int Tx27</b> Provides integer data for Direct Transmit word 27, if the data type for word 27 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1216	<b>SL Buf Real Tx27</b> Provides floating point (real) data for Direct Transmit word 27, if the data type for word 27 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1217	<b>SL Buf Int Tx28</b> Provides integer data for Direct Transmit word 28, if the data type for word 28 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1218	<b>SL Buf Real Tx28</b> Provides floating point (real) data for Direct Transmit word 28, if the data type for word 28 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1219	<b>SL Buf Int Tx29</b> Provides integer data for Direct Transmit word 29, if the data type for word 29 (indicated in Par 1160 [Tx Buf Data Type]) is integer.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1220	<b>SL Buf Real Tx29</b> Provides floating point (real) data for Direct Transmit word 29, if the data type for word 29 (indicated in Par 1160 [Tx Buf Data Type]) is real.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real

No.	Name Description	Value	Linkable	Read-Write	Data Type																																																		
1226	<b>SL Comm TP Sel</b> Enter or write a value to select SynchLink data displayed by Par 1227 [SL Comm TP Data].	Default: 0 "Zero" Options: 0 "Zero" 13 "BufSeqErrTim" 1 "SL MultA Src" 14 "Rx Sys Rev" 2 "SL Mult A In" 15 "Tx Axis Size" 3 "SL Mult B In" 16 "Tx Dir Size" 4 "SL Mult Out" 17 "Tx Buf Size" 5 "Rx Axis Size" 18 "Tx Pkg Size" 6 "Rx Dir Size" 19 "Tx Seq Cnt" 7 "Rx Buf Size" 20 "Tx Index 0" 8 "Rx Pkg Size" 21 "Tx Index 1" 9 "Rx Seq Cnt" 22 "Tx Index 2" 10 "Rx Index 0" 23 "Rx Vendor ID" 11 "Rx Index 1" 24 "Rx ModuleTyp" 12 "Rx Index 2" 25 "Rx Serial #"																																																					
1227	<b>SL Comm TP Data</b> Displays data selected by Par 1226 [SL Comm TP Sel].	Default: 0 Min/Max: -/+2147483648			32-bit Integer																																																		
1228	<b>SL Error History</b> Displays SynchLink faults which have occurred since the last fault clear operation or power cycle. <ul style="list-style-type: none"> <li>• Bit 0 [Sync Loss] indicates SynchLink communication has failed, after it had been established</li> <li>• Bit 1 [Rx Loss] indicates the receive port is not receiving data, and the receive port configuration is set to receive data</li> <li>• Bit 2 [Many BOF Err] indicates the number of Beginning Of Frame (BOF) errors exceeds limit set by Par 1235 [SL BOF Err Limit]</li> <li>• Bit 3 [Many CRC Err] indicates the number of Cyclic Redundancy Check (CRC) errors exceeds limit set by Par 1234 [SL CRC Err Limit]</li> <li>• Bit 4 [Pkg Msg Err] indicates the received package sequence number has not matched for 1.0S</li> <li>• Bit 5 [CommForm Err] indicates the format of received data does not match the configuration of the receive port</li> <li>• Bit 6 [Sys Rev Err] indicates the system revision in the received data does not match the value of Par 1001 [SynchLink Rev]</li> <li>• Bit 7 [Mult TKeeper] indicates more than one node on the SynchLink system is configured as a time keeper</li> </ul> <p>Options</p> <table border="1"> <thead> <tr> <th></th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Mult TKeeper</th> <th>Sys Rev Err</th> <th>CommForm Err</th> <th>Pkg Msg Err</th> <th>Many CRC Err</th> <th>Many BOF Err</th> <th>Rx Loss</th> <th>Sync Loss</th> </tr> </thead> <tbody> <tr> <td>Default</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> </tr> <tr> <td>Bit</td> <td>15</td> <td>14</td> <td>13</td> <td>12</td> <td>11</td> <td>10</td> <td>9</td> <td>8</td> <td>7</td> <td>6</td> <td>5</td> <td>4</td> <td>3</td> <td>2</td> <td>1</td> <td>0</td> </tr> </tbody> </table> <p>0 = True 1 = False</p>		Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Mult TKeeper	Sys Rev Err	CommForm Err	Pkg Msg Err	Many CRC Err	Many BOF Err	Rx Loss	Sync Loss	Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0			
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Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0																																							
1229	<b>SL Error Status</b> Indicates presence of SynchLink faults. This data is visible on the SynchLink diagnostics tab of the Peer Communication window. <ul style="list-style-type: none"> <li>• Bit 0 [Sync Loss] indicates SynchLink communication has failed, after it had been established</li> <li>• Bit 1 [Rx Loss] indicates the receive port is not receiving data, and the receive port configuration is set to receive data</li> <li>• Bit 2 [Many BOF Err] indicates the number of Beginning Of Frame (BOF) errors exceeds limit set by Par 1235 [SL BOF Err Limit]</li> <li>• Bit 3 [Many CRC Err] indicates the number of Cyclic Redundancy Check (CRC) errors exceeds limit set by Par 1234 [SL CRC Err Limit]</li> <li>• Bit 4 [Pkg Msg Err] indicates the received package sequence number has not matched for 1.0S</li> <li>• Bit 5 [CommForm Err] indicates the format of received data does not match the configuration of the receive port</li> <li>• Bit 6 [Sys Rev Err] indicates the system revision in the received data does not match the value of Par 1001 [SynchLink Rev]</li> <li>• Bit 7 [Mult TKeeper] indicates more than one node on the SynchLink system is configured as a time keeper</li> </ul> <p>Options</p> <table border="1"> <thead> <tr> <th></th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Mult TKeeper</th> <th>Sys Rev Err</th> <th>CommForm Err</th> <th>Pkg Msg Err</th> <th>Many CRC Err</th> <th>Many BOF Err</th> <th>Rx Loss</th> <th>Sync Loss</th> </tr> </thead> <tbody> <tr> <td>Default</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> </tr> <tr> <td>Bit</td> <td>15</td> <td>14</td> <td>13</td> <td>12</td> <td>11</td> <td>10</td> <td>9</td> <td>8</td> <td>7</td> <td>6</td> <td>5</td> <td>4</td> <td>3</td> <td>2</td> <td>1</td> <td>0</td> </tr> </tbody> </table> <p>0 = False 1 = True</p>		Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Mult TKeeper	Sys Rev Err	CommForm Err	Pkg Msg Err	Many CRC Err	Many BOF Err	Rx Loss	Sync Loss	Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0			
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Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0																																							
1230	<b>SL CRC Err Accum</b> Displays the total accumulated number of CRC errors. Clearing a fault resets this accumulator. This data is visible on the SynchLink diagnostics tab of the Peer Communication window.	Default: 0 Min/Max: 0/4294967296			32-bit Integer																																																		
1231	<b>SL CRC Error</b> Displays the number of CRC errors that occurred during the last test (last 8 mS). This data is visible on the SynchLink diagnostics tab of the Peer Communication window.	Default: 0 Min/Max: 0/4294967296			32-bit Integer																																																		
1232	<b>SL BOF Err Accum</b> Displays the total accumulated number of BOF errors. Clearing a fault resets this accumulator. This data is visible on the SynchLink diagnostics tab of the Peer Communication window.	Default: 0 Min/Max: 0/4294967296			32-bit Integer																																																		
1233	<b>SL BOF Error</b> Displays the number of BOF errors that occurred during the last test (last 8 mS). This data is visible on the SynchLink diagnostics tab of the Peer Communication window.	Default: 0 Min/Max: 0/4294967296			32-bit Integer																																																		
1234	<b>SL CRC Err Limit</b> The number of CRC errors per test (per 8 mS) allowed before the drive declares a SynchLink CRC Error exception event. Set this limit on the SynchLink diagnostics tab of the Peer Communication window.	Default: 2 Min/Max: 0/256			32-bit Integer																																																		

No.	Name Description	Value	Linkable	Read-Write	Data Type																																																		
1235	<b>SL BOF Err Limit</b> The number of BOF errors per test (per 8 mS) allowed before the drive declares a SynchLink BOF Error exception event. Set this limit on the SynchLink diagnostics tab of the Peer Communication window.	Default: 2 Min/Max: 0/256			32-bit Integer																																																		
1250	<b>Trend Control</b> Set bits to configure the Data Trend function: <ul style="list-style-type: none"> <li>Bit 0 [Enbl Collect] - Trend data collection begins on the rising edge of this bit and continues until either this bit is set low or the trend data has been completely collected. This bit should be cleared following either the 'Triggered' status or 'Complete' status in order to complete the trend sequence. This bit can also be cleared at any time to force the trend data sampling to stop and set the 'Complete' status bit.</li> <li>Setting bit 1 [In1 Real] - specifies the Real data type for Trend Input 1. The source for Real data is Par 1265 [Trend In1 Real]. Clearing the bit specifies the Integer data type. The source for Integer data is Par 1264 [Trend In1 Int].</li> <li>Setting bit 2 [In2 Real] - specifies the Real data type for Trend Input 2. The source for Real data is Par 1267 [Trend In2 Real]. Clearing the bit specifies the Integer data type. The source for Integer data is Par 1266 [Trend In2 Int].</li> <li>Setting bit 3 [In3 Real] - specifies the Real data type for Trend Input 3. The source for Real data is Par 1269 [Trend In3 Real]. Clearing the bit specifies the Integer data type. The source for Integer data is Par 1268 [Trend In3 Int].</li> <li>Setting bit 4 [In4 Real] - specifies the Real data type for Trend Input 4. The source for Real data is Par 1271 [Trend In4 Real]. Clearing the bit specifies the Integer data type. The source for Integer data is Par 1270 [Trend In4 Int].</li> <li>Setting bit 15 [Auto Output] causes the trend output parameters to automatically cycle through the entire trend buffer at the rate specified in Par 1253 [Trend Rate]. Typically, you link the output to an analog output for display on an oscilloscope.</li> <li>Auto output is accomplished by writing to Par 1283 [TrendBuffPointer]. Clearing this bit requires manual selection of Par 1283 [TrendBuffPointer] to view the trend buffer contents.</li> </ul> Options <table border="1"> <thead> <tr> <th></th> <th>Auto Output</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>In 4 Real</th> <th>In 3 Real</th> <th>In 2 Real</th> <th>In 1 Real</th> <th>Enbl Collect</th> </tr> </thead> <tbody> <tr> <td>Default</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> </tr> <tr> <td>Bit</td> <td>15</td> <td>14</td> <td>13</td> <td>12</td> <td>11</td> <td>10</td> <td>9</td> <td>8</td> <td>7</td> <td>6</td> <td>5</td> <td>4</td> <td>3</td> <td>2</td> <td>1</td> <td>0</td> </tr> </tbody> </table> 0 = False 1 = True		Auto Output	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	In 4 Real	In 3 Real	In 2 Real	In 1 Real	Enbl Collect	Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0			
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Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0																																							
1251	<b>Trend Status</b> Bits indicate the status of the Data Trend function: <ul style="list-style-type: none"> <li>Bit 1 [Triggered] indicates a Trend Trigger event has been detected. This bit will clear in response to the rise of Par 1250 [Trend Control] / bit 0 [Enbl Collect].</li> <li>Bit 2 [Complete] indicates all the post trigger data samples have been gathered and the trend buffers are full. It will also be set if the Par 1250 [Trend Control] / bit 0 [Enbl Collect] is cleared before the trigger occurs. The trend data outputs will be updated from the contents of the trend buffer data when this bit is set. Par 1250 [Trend Control] / bit 0 [Enbl Collect] can be cleared after this bit is set without affecting the trend data buffer contents. This bit will clear in response to the rise of Par 1250 [Trend Control] / bit 0 [Enbl Collect]. The trend outputs will be forced to zero while this bit is clear.</li> </ul> Options <table border="1"> <thead> <tr> <th></th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Reserved</th> <th>Complete</th> <th>Triggered</th> <th>Reserved</th> </tr> </thead> <tbody> <tr> <td>Default</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> <td>0</td> </tr> <tr> <td>Bit</td> <td>15</td> <td>14</td> <td>13</td> <td>12</td> <td>11</td> <td>10</td> <td>9</td> <td>8</td> <td>7</td> <td>6</td> <td>5</td> <td>4</td> <td>3</td> <td>2</td> <td>1</td> <td>0</td> </tr> </tbody> </table> 0 = False 1 = True		Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Complete	Triggered	Reserved	Default	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0			
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Bit	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0																																							
1252	<b>Trend State</b> Value indicates the state of the Data Trend function. <ul style="list-style-type: none"> <li>Value 0 - Wait Enable indicates the trend function is ready and waiting to begin data collection. Setting bit 0 [Enbl Collect] of Par 1250 [Trend Control] will cause data collection to begin. In this state, Par 1283 [TrendBuffPointer] and the Trend Output parameters are active.</li> <li>Value 1 - First Scan indicates the Trend function is executing the first pass through the trend sample buffer. This takes 512 ms. (0.5 ms x 1024 samples). When it enters this state, the Trend function clears bit 1 [Triggered] and 2 [Complete] bits of Par 1251 [Trend Status]. While in this state, the Trend function refreshes the data. Also while in this state, the function forces the Trend Output parameters to zero. When done, it enters the Pre-trigger state.</li> <li>Value 2 - Pre-trigger indicates the Trend function is sampling the trend inputs and storing them in memory, at a rate determined by parameter 1253 [Trend Rate]. Sampling continues until either the trend trigger event occurs or bit 0 [Enbl Collect] of Par 1250 [Trend Control] is cleared. While in this state, the Trend function forces the Trend Output parameters to zero. If the trigger event occurs, the function sets bit 1 [Triggered] of Par 1251 [Trend Status] and enters the Post-trigger state. If bit 0 [Enbl Collect] of Par 1250 [Trend Control] is cleared, the function sets bit 2 [Complete] of Par 1251 [Trend Status] and returns to the Wait Enable state.</li> <li>Value 3 - Post-trigger indicates the Trend function is continuing to sample and save the trend inputs until the buffer is full. While in this state, the function forces the Trend Output parameters to zero value. When the buffer is full, the function sets bit 2 [Complete] of Par 1251 [Status bit] and enters the Wait Disable state.</li> <li>Value 4 - Wait Disable indicates the Trend function is complete and waiting for bit 0 [Enbl Collect] of Par 1250 [Trend Control] to be cleared. When this is done, the trend function returns to the Wait Enable state. While in the Wait Disable state, Par 1283 [TrendBuffPointer] and the Trend Output Parameters are active.</li> </ul> Default: 0 "Wait Enable" Options: 0 "Wait Enable" 1 "First Scan" 2 "Pre-trigger" 3 "Post-trigger" 4 "Wait Disable"																																																						
1253	<b>Trend Rate</b> Sets the sample time for both trend input and output updates.	Units: mSec Default: 0.5000 Min/Max: 0.5000/1000.0000	✓	✓	Real																																																		



No.	Name Description	Value	Linkable	Read-Write	Data Type
1254	<b>Trend TrigA Int</b> Provides the integer input for the A trigger function. This integer is converted to a real number and summed with Par 1255 [Trend TrigA Real]. The result is compared with the Trigger B sum. If the A sum exceeds the B sum, then a trend trigger will occur.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1255	<b>Trend TrigA Real</b> Provides the real input for the A trigger function. This real number is summed with Par 1254 [Trend TrigA Int]. The result is compared with the Trigger B sum. If the A sum exceeds the B sum, then a trend trigger will occur.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1256	<b>Trend TrigB Int</b> Provides the integer input for the B trigger function. This integer is converted to a real number and summed with Par 1257 [Trend TrigB Real]. The result is compared with the Trigger A sum. If the A sum exceeds the B sum, then a trend trigger will occur.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1257	<b>Trend TrigB Real</b> Provides the real input for the B trigger function. This real number is summed with Par 1257 [Trend TrigB Real]. The result is compared with the Trigger A sum. If the A sum exceeds the B sum, then a trend trigger will occur.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1258	<b>Trend Trig Data</b> This is the logic input for the Trend Trigger Function. A trigger will occur on the rise of the specified bit in this word. The bit will be specified by Par 1259 [Trend Trib Bit].	Default: 00000000000000000000000000000000 Min: 00000000000000000000000000000000 Max: 111111111111111111111111111111111111	✓	✓	32-bit Boolean
1259	<b>Trend Trig Bit</b> Specifies the bit in Par 1258 [Trend Trig Data] that will cause a Trend Trigger to occur. Positive numbers specify rising edges and negative numbers specify falling edges.	Default: 0 Min/Max: -32/31	✓	✓	16-bit Integer
1260	<b>Trend PreSamples</b> Specifies the number pre-trigger samples in the trend buffer. Pre-trigger samples are the samples that occur before the trigger and remain in the buffer. The remainder of the trend buffer will contain post-trigger samples.	Default: 511 Min/Max: 0/1022 j	✓	✓	16-bit Integer
1264	<b>Trend In1 Int</b> Provides integer input to the Trend 1. The Trending function samples this parameter for Trend Buffer 1, if bit 1 [In 1 Real] is cleared.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1265	<b>Trend In1 Real</b> Provides real input to the Trend 1. The Trending function samples this parameter for Trend Buffer 1, if bit 1 [In 1 Real] is set.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1266	<b>Trend In2 Int</b> Provides integer input to the Trend 2. The Trending function samples this parameter for Trend Buffer 2, if bit 2 [In 2 Real] is cleared.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1267	<b>Trend In2 Real</b> Provides real input to the Trend 2. The Trending function samples this parameter for Trend Buffer 2, if bit 2 [In 2 Real] is set.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1268	<b>Trend In3 Int</b> Provides integer input to the Trend 3. The Trending function samples this parameter for Trend Buffer 3, if bit 3 [In 3 Real] is cleared.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1269	<b>Trend In3 Real</b> Provides real input to the Trend 3. The Trending function samples this parameter for Trend Buffer 3, if bit 3 [In 3 Real] is set.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1270	<b>Trend In4 Int</b> Provides integer input to the Trend 4. The Trending function samples this parameter for Trend Buffer 4, if bit 4 [In 4 Real] is cleared.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1271	<b>Trend In4 Real</b> Provides real input to the Trend 4. The Trending function samples this parameter for Trend Buffer 4, if bit 4 [In 4 Real] is set.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1280	<b>Trend Marker Int</b> Marks the start of data for trend buffers that are using integer data. The Trend Marker can be used to provide a scope trigger signal for the Auto Output function.	Default: 0 Min/Max: -/+2147483648	✓	✓	32-bit Integer
1281	<b>Trend Marker Real</b> Marks the start of data for trend buffers that are using real data. The Trend Marker can be used to provide a scope trigger signal for the Auto Output function.	Default: 0.0000 Min/Max: -/+2200000000.0000	✓	✓	Real
1283	<b>TrendBuffPointer</b> Selects the trend buffer element to be displayed in the Trend Output Parameters when the trend function is inactive (not collecting data samples). A zero value points to the element that corresponds to the trigger event. Negative values point to pre-trigger data. Positive values point to post-trigger data. When the Auto Output function is running, this parameter will automatically sequence through it's full range, at a rate set by Par 1253 [Trend Rate].	Default: 0 Min/Max: -/+1023	✓	✓	16-bit Integer
1284	<b>Trend Out1 Int</b> Displays the output for Trend Buffer 1, if the buffer is using integer data. This will equal the value of the element, in Trend Buffer 1, specified by Par 1283 [TrendBuffPointer].	Default: 0 Min/Max: -/+2147483648			32-bit Integer
1285	<b>Trend Out1 Real</b> Displays the output for Trend Buffer 1, if the buffer is using real data. This will equal the value of the element, in Trend Buffer 1, specified by Par 1283 [TrendBuffPointer].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real



No.	Name Description	Value	Linkable	Read-Write	Data Type
1375	<b>SW Real 1 NC</b> The real switch moves the value of this parameter into Par 1376 [SW Real 1 Output] when bit 0 [SW Int 1 On] is reset.	Default: 0.0000 Min/Max: -/+2200000000.0000			Real
1376	<b>SW Real 1 Output</b> Displays the output of the real switch. It will reflect the value of either Parameter 1374 [SW Real 1 NO] or 1375 [SW Real 1 NC].	Default: 0.0000 Min/Max: -/+2200000000.0000			Real

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Anlg In2 Offset	809
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Spd Fdbk TP Sel	77
Spd Gain TP Data	99
Spd Gain TP Sel	98
Spd Obs Trq Gain	227
Spd Observer BW	220
Spd Ref Bypass	37
Spd Ref TP Data	52
Spd Ref TP RPM	51
Spd Ref TP Sel	50
Spd Ref1 Divide	11
Spd Ref2 Multi	13
Spd Reg BW	90
Spd Reg Damping	91
Spd Reg Droop	86
Spd Reg I Gain	82
Spd Reg Neg Lim	103
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Spd Reg PI Out	302
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Spd Reg TP Data	109
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Spd Trim1 SpdRef	47
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SpdRef Filt BW	36
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SpdReg AntiBckup	84
SpdReg Integ Out	101
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SpdTrim 3 Scale	24
SpdTrim2 Filt BW	26
Speed Comp	55
Speed Error	100
Speed Ref 1	10
Speed Ref 2	12
Speed Ref 4	14
Speed Ref 5	15
Speed Ref DPI	20
Speed Ref Scale	38
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Speed Reg Ctrl	80
Speed Trim 1	21
Speed Trim 2	22
Speed Trim 3	23
SReg FB Filt BW	94
SReg Out Filt BW	96
SReg Torq Preset	87
SRegFB Filt Gain	93
SRegOut FiltGain	95
Start Mask	694
Start Owner	701
Stator Frequency	534
StatorInduc Gain	469
StatorInductance	490
StatorResistance	491
Stop Dwell Time	154
Stop Oper TP Sel	163
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STrim2 Filt Gain	25
SW Int 1 NC	1372
SW Int 1 NO	1371
SW Int 1 Output	1373
SW Real 1 NC	1375
SW Real 1 NO	1374
SW Real 1 Output	1376
Switch Control	1370
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SynchLink Status	316
Test Current Ref	431
Test Freq Rate	433
Test Freq Ref	432
Test Mode Config	514
Test Status	165
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Time Axis Rate	200
Torq NegLim Actl	124
Torq PosLim Actl	123
Torq Ref TP Data	131
Torq Ref TP Sel	130
Torq Ref1 Div	112
Torq Ref2 Mult	114
Torque En Dly	501
Torque Neg Limit	126
Torque Pos Limit	125
Torque Ref 1	111
Torque Ref 2	113
Torque Step	116
Torque Trim	115
Total Inertia	9
Trend Control	1250
Trend In1 Int	1264
Trend In1 Real	1265
Trend In2 Int	1266
Trend In2 Real	1267
Trend In3 Int	1268
Trend In3 Real	1269
Trend In4 Int	1270
Trend In4 Real	1271
Trend Mark Real	1281
Trend Marker Int	1280
Trend Out1 Int	1284
Trend Out1 Real	1285
Trend Out2 Int	1286
Trend Out2 Real	1287
Trend Out3 Int	1288
Trend Out3 Real	1289
Trend Out4 Int	1290
Trend Out4 Real	1291
Trend PreSamples	1260
Trend Rate	1253
Trend State	1252
Trend Status	1251
Trend Trig Bit	1259
Trend Trig Data	1258
Trend TrigA Int	1254
Trend TrigA Real	1255
Trend TrigB Int	1256
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Tx Buf Data Type	1160

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Tx Dir Data Type	1140
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User Data Int 02	397
User Data Int 03	398
User Data Int 04	399
User Data Int 05	1300
User Data Int 06	1301
UserData Real 01	1315
UserData Real 02	1316
UserData Real 03	1317
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UserData Real 05	1319
UserData Real 06	1320
Vds Command	542
Vds Fdbk Filt	441
Vds Max	438
Vds Min	440
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Voltage Class	403
VoltFdbkLossCnfg	394
VPL Build Number	315
VPL Firmware Rev	314
Vqs Command	541
Vqs Fdbk Filt	442
Vqs Max	437
Vqs Min	439
X Offst SpdFilt	756
XReg Integ HiLim	773
XReg Integ LoLim	772
XReg Integ Out	774
XReg Spd HiLim	776
XReg Spd LoLim	775
Xsync Gen Period	787
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## Troubleshooting

### Chapter Objectives

This chapter provides information to guide you in troubleshooting the PowerFlex 700S. A list and description of drive faults (with possible solutions, when applicable) and alarms is included.

For Information on...	See page...
<a href="#">Faults and Alarms</a>	<a href="#">4-1</a>
<a href="#">Drive Status</a>	<a href="#">4-1</a>
<a href="#">Manually Clearing Faults</a>	<a href="#">4-4</a>
<a href="#">Fault Descriptions</a>	<a href="#">4-4</a>

### Faults and Alarms

A fault is a condition that stops the drive. There are two fault types.

Type	Fault Description
①	<p>Non-Resettable</p> <p>This type of fault normally requires drive or motor repair. The cause of the fault must be corrected before the fault can be cleared. The fault will be reset on power up after repair</p>
②	<p>User Configurable</p> <p>Programming and commissioning personnel can configure the drive's response to these exception events. Responses include:</p> <ul style="list-style-type: none"> <li>• Ignore</li> <li>• Alarm</li> <li>• Fault Coast Stop</li> <li>• Fault Ramp Stop</li> <li>• Fault Current Limit Stop</li> </ul>

### Drive Status

The condition or state of your drive is constantly monitored. Any changes will be indicated through the front panel LEDs and/or the HIM (if present).

## LED Indications

Figure 4.1 Drive Status Indicators



Table 4.A Drive Status Indicators

#	Name	Color	State	Description	Action		
1	PWR (Power)	Green	Steady	Illuminates when power is applied to the drive.	No action - no faults present		
		2	STS (Status)	Green	Flashing	Drive ready, but not running & no faults are present.	No action - no faults present
				Green	Steady	Drive running, no faults are present.	No action - no faults present
		Yellow	Flashing	A type 2 (non-configurable) alarm condition exists, drive continues to run.	A run inhibit exists. Refer to <a href="#">Table 4.B</a>		
			Steady	A type 1 (user configurable) alarm condition exists, but drive continues to run.			
		Red	Flashing	A fault has occurred.	Refer to Table for faults.		
			Steady	A non-resettable fault has occurred.			
Red / Yellow	Flashing Alternately	The drive is in flash recovery mode. The only operation permitted is flash upgrade.	Complete Flash Upgrade				
3	PORT	Refer to the <i>Communication Adapter User Manual</i>	Status of DPI port internal communications (if present).				
	MOD		Status of communications module (when installed).				
	NET A		Status of network (if connected).				
	NET B		Status of secondary network (if connected).				
4	SYNCHLINK	Green	Steady	<ul style="list-style-type: none"> <li>The module is configured as the time keeper or</li> <li>The module is configured as a follower and synchronization is complete.</li> </ul>			
		Green	Flashing	The follower(s) are not configured with the time keeper.			
		Red	Flashing	<ul style="list-style-type: none"> <li>The module is configured as a time master on SynchLink and has received time information from another time master on SynchLink.</li> </ul>			
	ENABLE	Green	On	The drive's enable input is high.			

### Precharge Board LED Indications

Precharge Board LED indicators are found on Frame 5 & 6 drives. The LEDs are located above the “Line Type” jumper shown in [Figure 1.2](#).

Name	Color	State	Description
Power	Green	Steady	Indicates when precharge board power supply is operational
Alarm	Yellow	Flashing	Number in “[ ]” indicates flashes and associated alarm <sup>(1)</sup> :
		[1]	Low line voltage (<90%).
		[2]	Very low line voltage (<50%).
		[3]	Low phase (one phase <80% of line voltage).
		[4]	Frequency out of range or asymmetry (line sync failed).
		[5]	Low DC bus voltage (triggers ride-through operation).
		[6]	Input frequency momentarily out of range (40-65 Hz).
Fault	Red	Flashing	Number in “[ ]” indicates flashes and associated fault <sup>(2)</sup> :
		[2]	DC bus short (Udc <2% after 20 ms).
		[4]	Line sync failed or low line (Uac <50% Unom).
		[7]	DC bus short circuit detection active.

(1) An alarm condition automatically resets when the condition no longer exists

(2) A fault indicates a malfunction that must be corrected and can only be reset after cycling power.

**Table 4.B Common Causes of a Pre-Start Alarm**

Examine Parameter 156 [Run Inhibit Status]			
Bit	Description	Action	
1	No power is present at the Enable Terminal TB1- T7	Apply the enable	
2, 3, 4	A stop command is being issued	Close all stop inputs	
5	Power loss event is in progress, indicating a loss of the AC input voltage	Restore AC power	
6	Data supplied by the power structure EEPROM is invalid or corrupt	Cycle the power. If problem persists, replace the power structure.	
7	Flash Update in Progress	Complete Flash Procedures	
8	Drive is expecting a Start Edge and is receiving a continuous signal.	Open all start buttons and remove all start commands	
9	Drive is expecting a Jog Edge and is receiving a continuous signal.	Open all jog buttons and remove all jog commands	
10	A conflict exists between the Encoder PPR programming (Parameter 232 or 242) and the encoder configuration for edge counts (Parameter 233 or 243, bits 4 & 5).	Verify encoder data and reprogram	
11	The drive cannot precharge because a precharge input is programmed and no signal is present.	Reprogram the input or close the precharge control contact.	
12	Digital Configuration	Start input configured but stop not configured	Program <i>Par 838-840</i> to include a stop button, rewire the drive
		Run input configured but control options do not match	Program <i>Par 153</i> , Bit 8 to “0” (2 wire control)
		Start input configured but control options do not match	Program <i>Par 153</i> , Bit 8 to “1” (3 wire control)
		Multiple inputs configured as Start or Run	Reprogram <i>Par 838-840</i> so multiple starts, multiple runs or any combination do not exist
		Multiple inputs configured as Jog1	Reprogram <i>Par 838-840</i> so only (1) is set to Jog1
		Multiple inputs configured as Jog2	Reprogram <i>Par 838-840</i> so only (1) is set to Jog2
14	Invalid Feedback Device for Permanent Magnet Motor Control	Multiple inputs configured as Fwd/Rev	Reprogram <i>Par 838-840</i> so only (1) is set to Fwd/Rev
			Set <i>Par 222</i> to Value 5 (FB Opt Port0)

### HIM Indication

The HIM also provides visual notification of a fault.

Condition	Display
<p><b>Drive is indicating a fault.</b></p> <p>The LCD HIM immediately reports the fault condition by displaying the following:</p> <ul style="list-style-type: none"> <li>• “Faulted” appears in the status line</li> <li>• Fault number</li> <li>• Fault name</li> <li>• Time that has passed since fault occurred</li> </ul> <p>Press Esc to regain HIM control.</p>	

### Manually Clearing Faults

This section will contain a table that illustrates the HIM keystrokes necessary to clear faults.

Step	Key(s)
1. Press Esc to acknowledge the fault. The fault information will be removed so that you can use the HIM.	
2. Address the condition that caused the fault. The cause must be corrected before the fault can be cleared.	
3. After corrective action has been taken, clear the fault by one of these methods. <ul style="list-style-type: none"> <li>• Press Stop</li> <li>• Cycle drive power</li> <li>• Select “Clear Faults” from Diagnostic - Faults menu</li> </ul>	

### Fault Descriptions

#### Fault Descriptions and Configuration Parameters

Fault	No.	Type	Description	Action
+/- 12volt Power	33		The 12V dc control voltage is outside the tolerance range. The positive voltage power must be within the band from +15.25 to +11.4V dc. The negative voltage power must be within the band from -16.6 to -10V dc.	Replace switch mode power supply. For smaller frames, replace drive.
Abs Ovespd Det	1		Motor speed has exceeded the limits set by parameter 30 [Rev Speed Limit] minus parameter 335 [Abs OverSpd Lim] or parameter 31 [Fwd Speed Limit] plus parameter 335 [Abs OverSpd Lim]	<ol style="list-style-type: none"> <li>1. Verify the encoder feedback is correct polarity</li> <li>2. Verify drive is not in torque mode, <i>Par 110</i> [Spd/Torq ModeSel], value 2, Torque Ref -If in torque mode, verify load is present.</li> <li>3. Verify min/max settings <i>Par 30</i> [Rev Speed Lim] and <i>Par 31</i> [Fwd Speed Lim].</li> <li>4. Verify the load is not overhauling. -If the load is overhauling, turn bus regulator off, <i>Par 414</i> [Bus/Reg Cnfg], bit 2 (BusRef High).</li> </ol>
Brake OL Trip	38		<p>The calculated temperature of the dynamic braking resistor is too high. The temperature is calculated by a thermal model.</p> <ul style="list-style-type: none"> <li>• If the resistor is internal, the model uses resistor characteristic stored in the power structure EEPROM memory.</li> <li>• If the resistor is external, the model uses values of parameters 416 [Brake PulseWatts] and 417 [Brake Watts].</li> </ul>	<ol style="list-style-type: none"> <li>1. Verify actual temperature of brake -If hot, wait for brake to cool -If cold, cycle power to the drive</li> <li>2. If cold, verify <i>Par 416</i> [Brake PulseWatts] and <i>Par 417</i> [Brake Watts] are correct.</li> </ol>
Ctrl EE Checksum	35		The checksum read from the EEPROM does not match the checksum calculated	<ol style="list-style-type: none"> <li>1. Cycle power</li> <li>2. Replace MCB</li> </ol>



Fault	No.	Type	Description	Action
DC Bus Overvolt	24		Bus voltage has exceeded 815V dc in 400volt class drives or 405V dc for 200 volt class drives.	<ol style="list-style-type: none"> <li>1. Verify the AC Line.</li> <li>2. Verify that either <i>Par 414</i> [Brake/Bus Cnfg], the brake or bus regulator is enabled.</li> <li>3. Verify that <i>Par 128</i> [Regen Power Lim] is set properly.</li> <li>4. If <i>Par 414</i> bit 0 (Set Brake Enable) is set, verify braking resistor is properly sized.</li> </ol>
DC Bus Undervolt	42		Bus voltage has fallen below the level configured by parameter 409 [Line Undervolts].	<ol style="list-style-type: none"> <li>1. Verify the AC Line.</li> <li>2. In frames 1-4, verify the precharge resistor is present. (With power off, there should be a resistance between DC+ and BR+). In frames 5 &amp; 6, check the precharge board for errors. See the precharge board LED for fault sequency.</li> </ol>
DPI Loss Port 1	49		DPI Port 1 has stopped communicating.  A SCAN port device is connected to a drive operating DPI devices at 500k Baud	Verify DPI device is present in port 1.
DPI Loss Port 2	50		DPI Port 2 has stopped communicating.  A SCAN port device is connected to a drive operating DPI devices at 500k Baud	Verify DPI device is present in port 2.
DPI Loss Port 3	51		DPI Port 3 has stopped communicating.  A SCAN port device is connected to a drive operating DPI devices at 500k Baud	Verify DPI device is present in port 3.
DPI Loss Port 4	52		DPI Port 4 has stopped communicating.  A SCAN port device is connected to a drive operating DPI devices at 500k Baud	Verify DPI device is present in port 4.
DPI Loss Port 5	53		DPI Port 5 has stopped communicating.  A SCAN port device is connected to a drive operating DPI devices at 500k Baud	Verify AC line power
DPI Loss Port 6	54		DPI Port 6 has stopped communicating.  A SCAN port device is connected to a drive operating DPI devices at 500k Baud	
Drive Power Loss	10		DC Bus voltage has fallen below the minimum value <ul style="list-style-type: none"> <li>• Parameter 306 [DC Bus Voltage] displays bus voltage</li> <li>• Parameter 330 [Fault TP Data] displays the minimum value when parameter 329 [Fault TP Sel] is set to five</li> </ul> The drive must first complete precharge before this check is made	
DSP Device Error	20		A DSP (VPL) interrupt task has not been completed in the allotted time.	
DSP Memory Error	19		Flash memory does not match the SRAM memory	
Encoder 0 Loss	3		One of the following has occurred on encoder 0: <ul style="list-style-type: none"> <li>• missing encoder (broken wire)</li> <li>• quadrature error</li> <li>• phase loss</li> </ul>	SynchLink report the event status to the VPL which acts according to the configuration of parameter 365 [Encdr0 Loss Cnfg]. Reconnect encoder or replace encoder.
Encoder 1 Loss	4		One of the following has occurred on encoder10: <ul style="list-style-type: none"> <li>• missing encoder (broken wire)</li> <li>• quadrature error</li> <li>• phase loss</li> </ul>	SynchLink report the event status to the VPL which acts according to the configuration of parameter 366 [Encdr1 Loss Cnfg]. Reconnect encoder or replace encoder.
Err Inertia Test	21		Not Used	

Fault	No.	Type	Description	Action
Ext Fault Input	18		<p>A digital input has detected an external fault.</p> <p>Enter a value of 11 [Aux Fault] or 12 [AuxFault Inv] in one of the following parameters to configure an input to detect an external fault:</p> <ul style="list-style-type: none"> <li>• 838 [Digin 1 Sel]</li> <li>• 839 [Digin 2 Sel]</li> <li>• 840 [Digin 3 Sel]</li> </ul>	
Faults Cleared	65		Fault que marker only, place after faults have been cleared	
Ground Fault	26		A current to earth exceeds 35% of the peak drive rating	Check the motor and external wiring to the drive output terminals for a grounded condition.
HiHp Bus Com Dly	66		(High HP ONLY) Communication time delay on High HP comm bus has occurred.	
HiHp Bus CRC Er	68		(High HP ONLY) Too many CRC errors on the High HP comm bus.	
HiHp Drv OvrLoad	71		(High HP ONLY) High HP power circuit detects drive overload.	
HiHp Bus Link Ls	67		(High HP ONLY) High HP communication link is lost.	
HiHp Bus WtchDog	69		(High HP ONLY) The High HP comm bus watchdog cannot detect communication.	
HiHp Fan Fdbk Ls	70		(High HP ONLY) Fan feedback is lost, and the loss is detected by the High HP Power Circuit.	
HiHp In PhaseLs	65		(High HP ONLY) AC input phase is lost. The fault is detected by High HP power circuit.	
HiHp PrChrg Cntc	73		(High HP ONLY) Precharge contactor feedback is lost. this fault is detected by the High HP power circuit.	
HiHp PwrBdOTemp	75		(High HP ONLY) Power Board on High HP drive exceeds 85 degrees C.	
HiHp PwrBd PrcEr	72		(High HP ONLY) UProcessor on the High HP power circuit detects comm error.	
HiHp PwrEE Error	74		(High HP ONLY) Mismatch on the power rating data in PowerEE occurs.	
Inst Overcurrent	27		Instantaneous motor current exceeds 214% of rating	
Inv OLoad Pend	16		<p>The drive's operating point is approaching the intermittent current rating limitation. If output current remains at or above present levels, an Inverter Overload condition will occur.</p> <p>Operation of the Inverter Overload function is configured with the following parameters:</p> <ul style="list-style-type: none"> <li>• 336 [Service Factor]</li> <li>• 337 [Mtr I2T Curr Min]</li> <li>• 338 Mtr [I2T Spd Min]</li> <li>• 339 Mtr [I2T Calibrat]</li> </ul>	Reduce the load on the drive
Inv OLoad Trip	17		<p>The drive's operating point has exceeded the intermittent current rating and a foldback to the continuous rating in parameter 400 [Rated Amps] has occurred.</p> <p>Operation of the Inverter Overload function is configured with the following parameters:</p> <ul style="list-style-type: none"> <li>• 336 [Service Factor]</li> <li>• 337 [Mtr I2T Curr Min]</li> <li>• 338 Mtr [I2T Spd Min]</li> <li>• 339 Mtr [I2T Calibrat]</li> </ul>	Reduce mechanical load
Inv Otemp Pend	14		<p>Parameter 313 [Heatsink Temp] is within 10° C of maximum.</p> <p>View the maximum heat sink temperature in parameter 348 [Drive OL TP Data] when parameter 347 [Drive OL TP Se] is set to 30 [fMaxHsDegc].</p>	

Fault	No.	Type	Description	Action
Inv Otemp Trip	15		Parameter 313 [Heatsink Temp] is above the maximum limit or temperature sensor has failed (shorted or open).  See parameter 346 [Drive OL Status] / bit 0 [NTC Shorted] and bit 1 [NTC Open].	
Interp Out Synch	46		Interpolator is out of synch on motion control mode.	
Logix Closed	63		The DriveLogix controller has closed the Controller to Drive connection.	Verify drive is present in I/O
Logix Link Chng	64		A required link in the Controller to Drive Communication Format has been modified.	Clear fault
Logix Out of Run	61		The DriveLogix controller is in a Non-Run mode. Non-Run modes include program, remote-program and faulted modes.	Clear fault
Logix Timeout	62		The communication connection to the DriveLogix controller has timed out.	
MC Commissn Fail	23		The drive has failed to complete either the Motor Autotuning procedure or the Power Circuits Diagnostics test. Parameters 552 [MC Diag Error 1], 553 [MC Diag Error 2], and 554 [MC Diag Error 3] display Motor Autotuning and Power Circuit Diagnostic faults.	
MC Diag Error 3			Drive current, inductance, voltage and speed are not within Motor Nameplate specifications. This fault occur most frequently on low HP motors.	<ol style="list-style-type: none"> <li>1. Verify that motor nameplate data is entered correctly into the drive.</li> <li>2. Verify the motor is wired for the correction voltage entering into the drive.</li> <li>3. Verify the encoder (if used) and velocity feedback is correct.</li> <li>4. Change tuning mode to Parameter 515 [NoRotate Tune], bit 9.</li> </ol>
MC Firmware	30		One of the following Motor Control (MC) firmware errors has occurred: <ul style="list-style-type: none"> <li>• MC Task Over Run</li> <li>• Illegal Interrupt</li> <li>• Self Diagnostic Fault</li> <li>• Data Error</li> </ul>	
Motor Oload Pend	12		A motor overload is pending.  Parameter 308 [Output Current] is squared, scaled and integrated over time. When this integrated value exceeds 0.5, this Exception Event occurs.  The integrator's output can be viewed in Parameter 330 [Fault TP Data] when parameter 329 [Fault TP Sel] is set to 123 [Mtr OL Outpt]. The overload integration rate is affected by parameters 336 [Service Factor], 337 [Mtr I2T Curr Min], 3387[Mtr I2T Spd Miin] and 339 [Mtr I2T Calibrat].	Reduce mechanical load
Motor Oload Trip	11		A motor overload trip has occurred.  Parameter 308 [Output Current] is squared, scaled and integrated over time. When this integrated value exceeds 1.0, this Exception Event occurs.  The integrator's output can be viewed in Parameter 330 [Fault TP Data] when parameter 329 [Fault TP Sel] is set to 123 [Mtr OL Outpt]. The overload integration rate is affected by parameters 336 [Service Factor], 337 [Mtr I2T Curr Min], 3387[Mtr I2T Spd Miin] and 339 [Mtr I2T Calibrat].	Reduce mechanical load
Motor Overload			A motor overload is pending	Enter correct motor nameplate full load amps. Parameter 2 [Motor NP FLA] or reduce excess load.
Motor Poles Fault			The poles of the motor do not match its rating.	Enter correct motor nameplate RPM. Parameter 4 [Motor NP RPM].

Fault	No.	Type	Description	Action
Motor Stalled	13		The motor has stalled. These three conditions have occurred at the same time for the amount of time specified in parameter 373 [Motor Stall Time]: <ul style="list-style-type: none"> <li>• Drive is not stopped (parameter 150 [Logic State Mach] not equal to zero)</li> <li>• Drive is on limit (parameter 304 [Limit Status] not equal to zero)</li> <li>• Drive is at zero speed (parameter 155 [Logic Status] / bit 13 [At Zero Spd] is set).</li> </ul>	<ol style="list-style-type: none"> <li>1. Increase torque limit</li> <li>2. Reduce mechanical load</li> </ol>
Net Loss DPI P1	55		A communications fault has occurred on the communication adapter at DPI port 1.	
Net Loss DPI P2	56		A communications fault has occurred on the communication adapter at DPI port 2.	
Net Loss DPI P3	57		A communications fault has occurred on the communication adapter at DPI port 3.	
Net Loss DPI P4	58		A communications fault has occurred on the communication adapter at DPI port 4.	
Net Loss DPI P5	59		A communications fault has occurred on the communication adapter at DPI port 5.	
Net Loss DPI P6	60		A communications fault has occurred on the communication adapter at DPI port 6.	
No Ctrl Device	48		The controlling device (HIM or controller) has been disconnected while the drive was running.	
Over Frequency Fault	22		Encoderless algorithm fails to converge on correct speed. Two possible causes: Velocity regulator is attempting to run below motor's slip speed Frequency regulator "pulls out" and commanded motor frequency slows to to maximum frequency limit.	
Opt Port 0 Loss	5		A fault on port 0 of the Hi-Resolution Encoder Feedback Option Card, MDI Option Card, or Resolver Feedback Option Card has occurred.  Parameter 260 [Hi-Res0 Status] displays the fault status for port 0 of the Hi-Resolution Encoder Feedback Option Card.  Parameter 267 [Resolver0 Status] displays the fault status for port 0 of the Resolver Feedback Option Card.	
Opt Port 1 Loss	6		The Linear sensor portion of the MDI feedback option card has detected a fault condition.  Parameter 286 [Linear1 Status] displays the fault status for linear portion of the MDI feedback Option Card.	
Position Error	85		Position feedback exceeds the position error tolerance setting, Par 913 [Motn PositErrTol].	
PowerEE CRC fail	39		The Cycling Ring Checksum (CRC) of the data stored in the Power Board EEPROM does not match the stored CRC.	
Precharge Error	31		The precharge function has failed to complete within 30 seconds of the precharge request.  A precharge request is initiated when the DC Bus voltage is above the Undervoltage Trip level and the precharge input is high (the requirement for the precharge being high can be bypassed by setting parameter 838 [Digln 1 Sel] to a value other than 14 - PreChrg/Disc).	
PWM Asynch	32		The Motor Control Processor is not synchronized with SynchLink.	
PWM Signal short	29		This fault is detected when ever the actual IGBT gate are different than the commanded IGBT states. This fault is detected by the Motor Control processor.	
Ridethru Timeout	41		The drive has been in a bus loss ridethrough condition for more than two seconds.	

Fault	No.	Type	Description	Action
Runtime Data Rst	44		Runtime data (hours, energy) has been reset to zero due to a checksum error.	
Slink Comm Fail	9		A SynchLink communication fault has occurred.  Parameter 1229 [SL Error Status] displays SynchLink errors.	
Slink Mult Oflow	40		A SynchLink Multiplier Overflow has occurred. Parameter 1034 [SL Mult State] displays SynchLink multiplier overflow errors.	
VoltageFdbk Loss	43		Loss of Motor or DC Bus Voltage Feedback has occurred because of a communication failure between Motor Control and Voltage Feedback board.	
VPL/MC Comm Fail	28		A communication failure has occurred between the Velocity Position Loop (VPLP) processor and the Motor Control (MC) processor on the main control board. Possible causes are: <ul style="list-style-type: none"> <li>• MC has failed to complete or pass diagnostic tests This is Indicated when Fault Test Point 16 equals 1. This test point is viewed in parameter 330 [Fault TP Data] when parameter 329 [Fault TP Select] equals 16.</li> <li>• VPL has not detected MC handshake activity for over 32 ms. This is Indicated when Fault Test Point 16 equals 1. This test point is viewed in parameter 330 [Fault TP Data] when parameter 329 [Fault TP Select] equals 15.</li> <li>• MC has not detected VPL handshake activity for over 32 ms.</li> </ul>	
Vref Decel Fail	2		The value of parameter 301 [Motor Spd Ref] has failed to decrease during a ramp to zero speed stop. This could possibly be due to a speed trim from parameters 21 [Speed Trim 1], 22 [Speed Trim 2] or 23 [Speed Trim 3].	





## Supplemental Information

### Chapter Objectives

For Information on ...	See Page...
<a href="#">Specifications</a>	<a href="#">A-1</a>
<a href="#">DPI Communication Configurations</a>	<a href="#">A-3</a>
<a href="#">Output Devices</a>	<a href="#">A-5</a>
<a href="#">Drive, Fuse &amp; Circuit Breaker Ratings</a>	<a href="#">A-5</a>
<a href="#">List of Motors with Compatible Thermistor Ratings</a>	<a href="#">A-13</a>
<a href="#">Spare Connectors</a>	<a href="#">A-14</a>
<a href="#">Dimensions</a>	<a href="#">A-15</a>

### Specifications

Category	Specification						
<b>Protection</b>		<b>200-208V Drive</b>	<b>240V Drive</b>	<b>380/400V Drive</b>	<b>480V Drive</b>	<b>600V Drive</b>	<b>690V Drive</b>
	AC Input Overvoltage Trip:	247VAC	285VAC	475VAC	570VAC	690VAC	
	Bus Overvoltage Trip:	350VDC	405VDC	675VDC	810VDC	1013VDC	
	Bus Undervoltage Trip:	Adjustable					
	Nominal Bus Voltage:	281VDC	324VDC	540VDC	648VDC	810VDC	
	Heat Sink Thermistor:	Monitored by microprocessor overtemp trip					
	Drive Overcurrent Trip	Calculated value, 105% of motor rated to 200% of drive rated 105% of 3 sec. rating (158%-210%) 143% of 3 sec rating (215%-287%)					
	Software Current Limit:						
	Hardware Current Limit:						
	Instantaneous Current Limit:	143% of 3 sec rating (215%-287%)					
	Line Transients:	Up to 6000 volts peak per IEEE C62.41-1991					
	Control Logic Noise Immunity:	Showering arc transients up to 1500V peak					
	Power Ride-Thru:	15 milliseconds at full load					
	Logic Control Ride-Thru	0.25 sec., drive not running					
	Ground Fault Trip:	Phase-to-ground on drive output					
	Short Circuit Trip:	Phase-to-phase on drive output					
<b>Agency Certification</b>	The drive is designed to meet the following specifications: NFPA 70 – US National Electric Code NEMA ICS 3.1 – Safety Standards for Construction and Guide for Selection, Installation and Operation of Adjustable Speed Drive Systems. NEMA 250 – Enclosures for Electrical Equipment IEC 146 – International Electrical Code.						
		UL and cUL Listed to UL508C and CAN/CSA-C2.2 No. 14-M91					
		Marked for all applicable European Directives EMC Directive (89/336/EEC) Emissions EN 61800-3 Adjustable Speed electrical power drive systems Part 3 Immunity EN 61800-3 Second Environment, Restricted Distribution Low Voltage Directive (73/23/EEC) EN 50178 Electronic Equipment for use in Power Installations					

Category	Specification		
<b>Environment</b>	Altitude:	1000 m (3300 ft.) max. without derating	
	Surrounding Air Temperature without Derating:		
	Open Type:	0 to 50° C (32 to 122° F)	
	IP20:	0 to 50° C (32 to 122° F)	
	NEMA Type 1:	0 to 40° C (32 to 104° F)	
	IP56, NEMA Type 4X:	0 to 40° C (32 to 104° F)	
	Storage Temperature (all const.):	-40 to 70° C (-40 to 158° F)	
	Relative Humidity:	5 to 95% non-condensing	
<b>Electrical</b>	Shock:	10G peak for 11 ms duration (+/- 1.0 ms)	
	Vibration:	0.152 mm (0.006 in.) displacement, 1G peak, 5.5 Hz	
	AC Input		
	Voltage Tolerance:	See for Full Power and Operating Range	
	Frequency Tolerance:	47-63 Hz	
	Input Phases:	Three-phase input provides full rating for all drives. Single-phase operation provides 50% of rated current.	
	DC Input		
	Voltage Tolerance	+/- 10% of Nominal Bus Voltage (above)	
	Displacement Power Factor:	0.98 across speed range	
	Efficiency:	97.5% at rated amps, nominal line volts.	
<b>Control</b>	Max. Short Circuit Current Rating: Using Recommended Fuse or Circuit Breaker Type	Maximum short circuit current rating to match specified fuse/circuit breaker capability. ≤200,000 Amps	
	Maximum Drive to Motor Power Ratio	The drive to motor rating cannot exceed a 2:1 ratio	
<b>Control</b>	Method		
	Induction Motor:	Ratings apply to all drives (refer to the Derating Guidelines). The drive can be supplied as 6 pulse or 12 pulse in a configured package. Indirect Self-Organized, Field-Oriented Control Current-regulated, sine-coded PWM with programmable carrier frequency	
	Brushless Motor:		
	Carrier Frequency		
	Frames 0 - 4	Drive rating: 4 kHz, Settings: 2, 4, 8, 10 kHz	
	Output Voltage Range:	0 to rated motor voltage	
	Output Frequency Range:	0 – 300 Hz	
	Speed Control	Speed regulation - without feedback	0.1% of base speed across 120:1 speed range
		120:1 operating range	50 rad/sec bandwidth
	Speed Control	Speed regulation - with feedback	0.001% of base speed across 120:1 speed range
		1000:1 operating range	300 rad/sec bandwidth
	Torque Regulation	Torque Regulation - without feedback	+/-10%, 600 rad/sec bandwidth
		Torque Regulation - with feedback	+/-5%, 2500 rad/sec bandwidth
	Selectable Motor Control:	Field Oriented Control with and without a feedback device and permanent magnet motor control	
Stop Modes:	Multiple programmable stop modes including – Ramp, Coast and Current Limit		
Accel/Decel	Independently programmable accel and decel times adjustable from 0 to 6553.5 in 0.1 second increments.		
S-Curve Time	Adjustable from 0.5 to 4.0 seconds		
Intermittent Overload:	110% Overload capability for up to 1 minute 150% Overload capability for up to 3 seconds		
Current Limit Capability:	Independent Motoring and Regenerative Power Limits programmable to 800% of rated output current		
Electronic Motor Overload Protection	Class 10 protection with speed sensitive response. Investigated by U.L. to comply with N.E.C. Article 430 U.L. File E59272, volume 12.		



Category	Specification	
Feedback	Encoder Inputs (2):	Dual Channel Plus Marker, Isolated with differential transmitter Output (Line Drive) Incremental, Dual Channel Quadrature type
	Encoder Voltage Supply:	5V DC or 12 V DC (5 V DC requires an external power supply) 320 mA/channel
	Maximum Required Input Frequency:	500 kHz
	Hi-Resolution Stegmann Option:	Refer to specifications on <a href="#">page C-1</a>
Feedback	Encoder Voltage Supply:	11.5V DC @ 130 mA
	Hi-Resolution Feedback:	Sine/Cosine 1V P-P Offset 2.5
	Maximum Cable Length:	182 m (600 ft.)
	RS-485 Interface:	Hi-Resolution Feedback Option card obtains the following information via the Hiperface RS-485 interface shortly after power-up: Address, Command Number, Mode, Number of turns, Number of Sine/Cos cycles, Checksum
Feedback	Customer-I/O Plug (P1) - Hi Res:	Allen-Bradley PN: S94262912 Weidmuller PN: BL3.50/90/12BK
	Resolver Option:	
	Excitation Frequency:	9300 Hz Max
	Excitation Voltage:	4.25-26 Vrms
	Operating Frequency Range:	1 - 10 kHz
Feedback	Resolver Feedback Voltage:	2V ± 300 mV
	Maximum Cable Length:	152.4 meters (500 ft.)
	User Available MemoryBase:	256 kbytes
	With Memory Expansion Board:	768 kbytes
	Battery:	1756-BA1 (Allen-Bradley PN 94194801) 0.59g lithium
DriveLogix	Serial Cable:	1761-CBLPM02 to 1761-NET-AIC
		1761-CBLPA00 to 1761-NET-AIC
		1756-CP3 directly to controller
		1747-CP3 directly to controller
		category 3 (2)
DriveLogix	Flex I/O Connection:	Up to (8) modules
	FLEXBUS Current Output:	640 mA maximum @ 5.1V dc
	Cable:	4100-CCF3

## DPI Communication Configurations

## Typical Programmable Controller Configurations

**Important:** If programs are written that continuously write information to the drive, care must be taken to properly format the block transfer. If attribute 10 is selected for the block transfer, values will be written only to RAM and will not be saved by the drive. This is the preferred attribute for continuous transfers. If attribute 9 is selected, each program scan will complete a write to the drives non-volatile memory (EEPROM). Since the EEPROM has a fixed number of allowed writes, continuous block transfers will quickly damage the EEPROM. Do Not assign attribute 9 to continuous block transfers. Refer to the individual communications adapter User Manual for additional details.



## Logic Status Word

Logic Bits																Status	Description
15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0		
															x	Enabled	0 = Not Enabled 1 = Enabled
															x	Running	0 = Not Running 1 = Running
														x		Command Direction	0 = Reverse 1 = Forward
												x				Actual Direction	0 = Reverse 1 = Forward
											x					Accel	0 = Not Accelerating 1 = Accelerating
											x					Decel	0 = Not Decelerating 1 = Decelerating
											x					Jogging	0 = Not Jogging 1 = Jogging
											x					Fault	0 = No Fault 1 = Fault
											x					Alarm	0 = No Alarm 1 = Alarm
											x					Flash Mode	0 = Not in Flash Mode 1 = In Flash Mode
											x					Run Ready	0 = Not Ready to Run 1 = Ready to Run
											x					At Limit <sup>(1)</sup>	0 = Not At Limit 1 = At Limit
											x					Tach Loss Sw	0 = Not Tach Loss Sw 1 = Tach Loss Sw
											x					At Zero Spd	0 = Not At Zero Speed 1 = At Zero Speed
											x					At Setpt Spd	0 = Not At Setpoint Speed 1 = At Setpoint Speed
											x					Reserved	

(1) See Parameter 304 - [Limit Status] in the PowerFlex 700S drive for a description of the limit status conditions.

## Output Devices

Common mode cores are internal to the drive. For information on output devices such as output contactors, cable terminators and output reactors refer to the *PowerFlex Reference Manual, Vol. 2*.

## Drive, Fuse & Circuit Breaker Ratings

The tables on the following pages provide PowerFlex 700S drive ratings (including continuous, 1 minute, and 3 second) and recommended AC input line fuses and circuit breakers.

### Fuse Size

Fuse sizes are the recommended minimum size based on 40° C ambient, 75° C wiring and U.S. N.E.C. Other country, state or local codes may require different fuse/circuit breaker ratings.

## Fuse Type

The recommend fuse type is listed below. If available current ratings do not match the tables provided, the fuse rating that exceeds the drive continuous rating should be chosen.

- IEC

BS88 (British Standard) Parts 1 & 2 <sup>(1)</sup>, EN60269-1, Parts 1 & 2, type go or equivalent should be used for these drives.

- UL

UL requirements specify that UL Class CC, T or J fuses must be used for all drives in this section <sup>(2)</sup>.

<sup>(1)</sup> Typical designations include, but may not be limited to the following; Ora 1 & 2:AC, AD, BC, BD, CD, DD, ED, EFS, EF, FF, FG, GF, GG, GH

<sup>(2)</sup> Typical designations include; Type CC - KTK, FNQ-R  
Type J - JKS, LPJ  
Type T - JJS, JJN

**208 Volt AC Input Protection Devices (See page 11 for Notes)**

Drive Catalog Number	Frame	HP Rating		Input Ratings		Output Amps			Dual Element Time Delay Fuse		Non-Time Delay Fuse		Circuit Breaker <sup>(3)</sup>	Motor Circuit Protector <sup>(4)</sup>	140M Motor Starter with Adjustable Current Range <sup>(5)(6)</sup>				Power Dissipation	
		ND	HD	Amps	kVA	Cont.	1 Min.	3 Sec.	Min. <sup>(1)</sup>	Max. <sup>(2)</sup>	Min. <sup>(1)</sup>	Max. <sup>(2)</sup>			Max. <sup>(10)</sup>	Max. <sup>(10)</sup>	Available Catalog Numbers <sup>(7)</sup>			
<b>208 Volt AC Input</b>																				
20DB2P2	1	0.5	0.33	1.9	0.7	2.5	2.8	3.8	3	6	3	10	15	3	140M-C2E-B25	140M-D8E-B25	-	-	-	NA
20DB4P2	1	1	0.75	3.7	1.3	4.8	5.6	7.0	6	10	6	17.5	15	7	140M-C2E-B63	140M-D8E-B63	-	-	-	NA
20DB6P8	1	2	1.5	6.8	2.4	7.8	10.4	13.8	10	15	10	30	30	15	140M-C2E-C10	140M-D8E-C10	140M-F8E-C10	-	-	NA
20DB9P6	1	3	2	9.5	3.4	11	12.1	17	12	20	12	40	40	15	140M-C2E-C16	140M-D8E-C16	140M-F8E-C16	-	-	NA
20DB015	1	5	3	15.7	5.7	17.5	19.3	26.3	20	35	20	70	70	30	140M-C2E-C20	140M-D8E-C20	140M-F8E-C20	-	-	NA
20DB022	1	7.5	5	23.0	8.3	25.3	27.8	38	30	50	30	100	100	30	140M-C2E-C25	140M-D8E-C25	140M-F8E-C25	140M-CMN-2500	NA	
20DB028	2	10	7.5	29.6	10.7	32.2	38	50.6	40	70	40	125	125	50	-	-	140M-F8E-C32	140M-CMN-4000	NA	
20DB042	3	15	10	44.5	16.0	48.3	53.1	72.5	60	100	60	175	175	70	-	-	140M-F8E-C45	140M-CMN-6300	NA	
20DB052	3	20	15	51.5	17.1	56	64	86	80	125	80	200	200	100	-	-	-	140M-CMN-6300	NA	
20DB070	4	25	20	72	25.9	78.2	93	124	90	175	90	300	300	100	-	-	-	140M-CMN-9000	NA	
20DB080	4	30	25	84.7	30.5	92	117	156	110	200	110	350	350	150	-	-	-	140M-CMN-9000	NA	
20DB104	5	40	-	113	40.7	120	132	175	150	250	150	475	350	150	-	-	-	-	NA	
		-	30	84.7	30.5	92	138	175	125	200	125	350	300	150	-	-	-	140M-CMN-9000	NA	
20DB130	5	50	-	122	44.1	130	143	175	175	275	175	500	375	250	-	-	-	-	NA	
		-	40	98	35.3	104	156	175	125	225	125	400	300	150	-	-	-	-	NA	
20DB154	6	60	-	167	60.1	177	195	266	225	350	225	500	500	250	-	-	-	-	NA	
		-	50	141	50.9	150	225	300	200	300	200	500	450	250	-	-	-	-	NA	
20DB192	6	75	-	208	75.0	221	243	308	300	450	300	600	600	400	-	-	-	-	NA	
		-	60	167	60.1	177	266	308	225	350	225	500	500	250	-	-	-	-	NA	

**240 Volt AC Input Protection Devices (See page 11 for Notes)**

Drive Catalog Number	Frame	HP Rating		Input Ratings		Output Amps			Dual Element Time Delay Fuse		Non-Time Delay Fuse		Circuit Breaker <sup>(3)</sup>	Motor Circuit Protector <sup>(4)</sup>	140M Motor Starter with Adjustable Current Range <sup>(5)(6)</sup>				Power Dissipation	
		ND	HD	Amps	kVA	Cont.	1 Min.	3 Sec.	Min. <sup>(1)</sup>	Max. <sup>(2)</sup>	Min. <sup>(1)</sup>	Max. <sup>(2)</sup>			Max. <sup>(10)</sup>	Max. <sup>(10)</sup>	Available Catalog Numbers <sup>(7)</sup>			
<b>240 Volt AC Input</b>																				
20DB2P2	1	0.5	0.33	1.7	0.7	2.2	2.4	3.3	3	6	3	10	15	3	140M-C2E-B25	140M-D8E-B25	-	-	-	NA
20DB4P2	1	1	0.75	3.3	1.4	4.2	4.8	6.4	5	8	5	15	15	7	140M-C2E-B63	140M-D8E-B63	-	-	-	NA
20DB6P8	1	2	1.5	5.9	2.4	6.8	9	12	10	15	10	25	25	15	140M-C2E-C10	140M-D8E-C10	140M-F8E-C10	-	-	NA
20DB9P6	1	3	2	8.3	3.4	9.6	10.6	14.4	12	20	12	35	35	15	140M-C2E-C16	140M-D8E-C16	140M-F8E-C16	-	-	NA
20DB015	1	5	3	13.7	5.7	15.3	16.8	23	20	30	20	60	60	30	140M-C2E-C20	140M-D8E-C20	140M-F8E-C20	-	-	NA
20DB022	1	7.5	5	19.9	8.3	22	24.2	33	25	50	25	80	80	30	140M-C2E-C25	140M-D8E-C25	140M-F8E-C25	140M-CMN-2500	NA	
20DB028	2	10	7.5	25.7	10.7	28	33	44	35	60	35	100	100	50	-	-	140M-F8E-C32	140M-CMN-4000	NA	
20DB042	3	15	10	38.5	16.0	42	46.2	63	50	90	50	150	150	50	-	-	140M-F8E-C45	140M-CMN-6300	NA	
20DB052	3	20	15	47.7	19.8	52	63	80	60	100	60	200	200	100	-	-	-	140M-CMN-6300	NA	
20DB070	4	25	20	64.2	26.7	70	78	105	90	150	90	275	275	100	-	-	-	140M-CMN-9000	NA	
20DB080	4	30	25	73.2	30.5	80	105	140	100	180	100	300	300	100	-	-	-	140M-CMN-9000	NA	
20DB104	5	40	-	98	40.6	104	115	175	125	225	125	400	300	150	-	-	-	-	NA	
		-	30	73	30.5	80	120	160	100	175	100	300	300	100	-	-	-	140M-CMN-9000	NA	
20DB130	5	50	-	122	50.7	130	143	175	175	275	175	500	375	250	-	-	-	-	NA	
		-	40	98	40.6	104	156	175	125	225	125	400	300	150	-	-	-	-	NA	
20DB154	6	60	-	145	60.1	154	231	308	200	300	200	600	450	250	-	-	-	-	NA	
		-	50	122	50.7	130	195	260	175	275	175	500	375	250	-	-	-	-	NA	
20DB192	6	75	-	180	74.9	192	211	288	225	400	225	600	575	250	-	-	-	-	NA	
		-	60	145	60.1	154	231	308	200	300	200	600	450	250	-	-	-	-	NA	

400 Volt AC Input Protection Devices (See page 11 for Notes)

Drive Catalog Number	Frame	kW Rating		Input Ratings		Output Amps			Dual Element Time Delay Fuse		Non-Time Delay Fuse		Circuit Breaker <sup>(3)</sup>	Motor Circuit Protector <sup>(4)</sup>	140M Motor Starter with Adjustable Current Range <sup>(5)(6)</sup>				Power Dissipation	
		ND	HD	Amps	kVA	Cont.	1 Min.	3 Sec.	Min. <sup>(1)</sup>	Max. <sup>(2)</sup>	Min. <sup>(1)</sup>	Max. <sup>(2)</sup>			Max. <sup>(10)</sup>	Max. <sup>(10)</sup>	Available Catalog Numbers <sup>(7)</sup>			
<b>400 Volt AC Input</b>																				
20DC1P3	1	0.37	0.25	1.1	0.77	1.3	1.4	1.9	3	3	3	6	15	3	140M-C2E-B16	-	-	-	-	NA
20DC2P1	1	0.75	0.55	1.8	1.3	2.1	2.4	3.2	3	6	3	8	15	3	140M-C2E-B25	140M-D8E-B25	-	-	NA	
20DC3P5	1	1.5	0.75	3.2	2.2	3.5	4.5	6.0	6	7	6	12	15	7	140M-C2E-B40	140M-D8E-B40	-	-	NA	
20DC5P0	1	2.2	1.5	4.6	3.2	5.0	5.5	7.5	6	10	6	20	20	7	140M-C2E-B63	140M-D8E-B63	-	-	NA	
20DC8P7	1	4	2.2	7.9	5.5	8.7	9.9	13.2	15	17.5	15	30	30	15	140M-C2E-C10	140M-D8E-C10	140M-F8E-C10	-	NA	
20DC011	1	5.5	4	10.8	7.5	11.5	13	17.4	15	25	15	45	45	15	140M-C2E-C16	140M-D8E-C16	140M-F8E-C16	-	NA	
20DC015	1	7.5	5.5	14.4	10.0	15.4	17.2	23.1	20	30	20	60	60	20	140M-C2E-C20	140M-D8E-C20	140M-F8E-C20	-	NA	
20DC022	1	11	7.5	20.6	14.3	22	24.2	33	30	45	30	80	80	30	140M-C2E-C25	140M-D8E-C25	140M-F8E-C25	-	NA	
20DC030	2	15	11	28.4	19.7	30	33	45	35	60	35	120	120	50	-	-	140M-F8E-C32	-	NA	
20DC037	2	18.5	15	35.0	24.3	37	45	60	45	80	45	125	125	50	-	-	140M-F8E-C45	-	NA	
20DC043	3	22	18.5	40.7	28.2	43	56	74	60	90	60	150	150	60	-	-	-	-	NA	
20DC056	3	30	22	53	36.7	56	64	86	70	125	70	200	200	100	-	-	-	-	NA	
20DC072	3	37	30	68.9	47.8	72	84	112	90	150	90	250	250	100	-	-	-	-	NA	
20DC085 <sup>(6)</sup>	4	45	-	81.4	56.4	85	94	128	110	200	110	300	300	150	-	-	-	-	NA	
		-	37	68.9	47.8	72	108	144	90	175	90	275	300	100	-	-	-	-	NA	
20DC105	5	55	-	100.5	69.6	105	116	158	125	225	125	400	300	150	-	-	-	-	NA	
		-	45	81.4	56.4	85	128	170	110	175	110	300	300	150	-	-	-	-	NA	
20DC125	5	55	-	121.1	83.9	125	138	163	150	275	150	500	375	250	-	-	-	-	NA	
		-	45	91.9	63.7	96	144	168	125	200	125	375	375	150	-	-	-	-	NA	
20DC140	6	75	-	149	103	140	154	210	200	300	200	550	400	250	-	-	-	-	NA	
		-	55	111	76	105	158	210	150	225	150	400	300	150	-	-	-	-	NA	
20DC170	6	90	-	164	126	170	187	255	250	375	250	600	500	250	-	-	-	-	NA	
		-	75	136	103	140	210	280	200	300	200	550	400	250	-	-	-	-	NA	
20DC205 <sup>(9)</sup>	6	110	-	199	148	205	220	289	250	450	250	600	600	400	-	-	-	-	NA	
		-	90	164	126	170	255	313	250	375	250	600	500	250	-	-	-	-	NA	
20DC260	6	132	-	255	177	260	286	390	350	550	350	750	750	400	-	-	-	-	NA	
		-	110	199	138	205	308	410	250	450	250	600	600	400	-	-	-	-	NA	
20DC261	9	132	-	256	171	261	287	410	325	575	325	700	700	400	-	-	-	-	NA	
		-	110	201	139	205	308	410	250	450	250	550	600	400	-	-	-	-	NA	
20DC300	9	160	-	294	204	300	330	500	375	800	375	800	800	400	-	-	-	-	NA	
		-	132	240	166	245	368	490	325	650	325	650	700	400	-	-	-	-	NA	
20DC385	10	200	-	377	261	385	424	600	500	850	500	1000	800	600	-	-	-	-	NA	
		-	160	294	204	300	450	600	375	675	375	800	800	400	-	-	-	-	NA	
20DC460	10	250	-	451	312	460	506	770	575	1000	575	1200	1200	600	-	-	-	-	NA	
		-	200	377	261	385	578	770	500	850	500	1000	800	600	-	-	-	-	NA	
20DC500	10	250	-	490	339	500	550	750	625	1100	625	1400	1200	800	-	-	-	-	NA	
		-	200	411	285	420	630	840	525	900	525	1000	1200	600	-	-	-	-	NA	

480 Volt AC Input Protection Devices (See page 11 for Notes)

Drive Catalog Number	Frame	HP Rating		Input Ratings		Output Amps			Dual Element Time Delay Fuse		Non-Time Delay Fuse		Circuit Breaker <sup>(3)</sup>	Motor Circuit Protector <sup>(4)</sup>	140M Motor Starter with Adjustable Current Range <sup>(5)(6)</sup>			Power Dissipation	
		ND	HD	Amps	kVA	Cont.	1 Min.	3 Sec.	Min. <sup>(1)</sup>	Max. <sup>(2)</sup>	Min. <sup>(1)</sup>	Max. <sup>(2)</sup>	Max. <sup>(10)</sup>	Max. <sup>(10)</sup>	Available Catalog Numbers <sup>(7)</sup>			Watts	
<b>480 Volt AC Input</b>																			
20DD1P1	1	0.5	0.33	0.9	0.7	1.1	1.2	1.6	3	3	3	6	15	3	140M-C2E-B16	-	-	-	92
20DD2P1	1	1	0.75	1.6	1.4	2.1	2.4	3.2	3	6	3	8	15	3	140M-C2E-B25	-	-	-	103
20DD3P4	1	2	1.5	2.6	2.2	3.4	4.5	6.0	4	8	4	12	15	7	140M-C2E-B40	140M-D8E-B40	-	-	117
20DD5P0	1	3	2	3.9	3.2	5.0	5.5	7.5	6	10	6	20	20	7	140M-C2E-B63	140M-D8E-B63	-	-	135
20DD8P0	1	5	3	6.9	5.7	8.0	8.8	12	10	15	10	30	30	15	140M-C2E-C10	140M-D8E-C10	140M-F8E-C10	-	210
20DD011	1	7.5	5	9.5	7.9	11	12.1	16.5	15	20	15	40	40	15	140M-C2E-C16	140M-D8E-C16	140M-F8E-C16	-	243
20DD014	1	10	7.5	12.5	10.4	14	16.5	22	17.5	30	17.5	50	50	20	140M-C2E-C16	140M-D8E-C16	140M-F8E-C16	-	271
20DD022	1	15	10	19.9	16.6	22	24.2	33	25	50	25	80	80	30	140M-C2E-C25	140M-D8E-C25	140M-F8E-C25	140-CMN-2500	389
20DD027	2	20	15	24.8	20.6	27	33	44	35	60	35	100	100	50	-	-	140M-F8E-C32	140-CMN-4000	467
20DD034	2	25	20	31.2	25.9	34	40.5	54	40	70	40	125	125	50	-	-	140M-F8E-C45	140-CMN-4000	519
20DD040	3	30	25	36.7	30.5	40	51	68	50	90	50	150	150	50	-	-	140M-F8E-C45	140-CMN-4000	543
20DD052	3	40	30	47.7	39.7	52	60	80	60	110	60	200	200	70	-	-	-	140M-CMN-6300	708
20DD065	3	50	40	59.6	49.6	65	78	104	80	125	80	250	250	100	-	-	-	140M-CMN-9000	NA
20DD077	4	60	-	72.3	60.1	77	85	116	100	170	100	300	300	100	-	-	-	140M-CMN-9000	NA
		-	50	59.6	49.6	65	98	130	80	125	80	250	250	100	-	-	-	140M-CMN-9000	NA
20DD096	5	75	-	90.1	74.9	96	106	144	125	200	125	350	350	125	-	-	-	-	NA
		-	60	72.3	60.1	77	116	154	100	170	100	300	300	100	-	-	-	140M-CMN-9000	NA
20DD125	5	100	-	117	97.6	125	138	163	150	250	150	500	375	150	-	-	-	-	NA
		-	75	90.1	74.9	96	144	168	125	200	125	350	350	125	-	-	-	-	NA
20DD140	6	100	-	131	109	140	154	210	175	300	175	550	400	250	-	-	-	-	NA
		-	75	90	75	105	158	210	125	225	125	400	300	125	-	-	-	-	NA
20DD156	6	125	-	147	122	156	172	234	200	350	200	600	450	250	-	-	-	-	NA
		-	100	131	109	125	188	250	175	250	175	500	375	250	-	-	-	-	NA
20DD180	6	150	-	169	141	180	198	270	225	400	225	600	500	250	-	-	-	-	NA
		-	125	147	122	156	234	312	200	350	200	600	450	250	-	-	-	-	NA
20DD248	6	200	-	233	194	248	273	392	300	550	300	700	700	400	-	-	-	-	NA
		-	150	169	141	180	270	360	225	400	225	600	500	250	-	-	-	-	NA
20DD261	9	200	-	245	204	261	287	410	325	575	325	700	700	400	-	-	-	-	NA
		-	150	193	160	205	308	410	250	450	250	550	600	400	-	-	-	-	NA
20DD300	9	250	-	282	234	300	330	500	375	800	375	800	800	400	-	-	-	-	NA
		-	200	230	191	245	368	490	325	650	325	650	700	400	-	-	-	-	NA
20DD385	10	300	-	362	301	385	424	600	500	850	500	1000	800	600	-	-	-	-	NA
		-	250	282	234	300	450	600	375	675	375	800	800	400	-	-	-	-	NA
20DD460	10	350	-	432	359	460	506	770	575	1000	575	1200	1200	600	-	-	-	-	NA
		-	300	362	301	385	578	770	500	850	500	1000	800	600	-	-	-	-	NA
20DD500	10	450	-	469	390	500	550	750	625	1100	625	1400	1200	800	-	-	-	-	NA
		-	350	394	328	420	630	840	525	900	525	1000	1200	600	-	-	-	-	NA

600 Volt AC Input Protection Devices (See page 11 for Notes)

Drive Catalog Number	Frame	HP Rating		PWM Freq. kHz	Temp. °C	Input Ratings			Output Amps			Dual Element Time Delay Fuse		Non-Time Delay Fuse		Circuit Breaker <sup>(3)</sup>	Motor Circuit Protector <sup>(4)</sup>	140M Motor Starter with Adjustable Current Range <sup>(5)(6)</sup>				Power Dissipation Watts
		ND	HD			Amps	kVA	Cont.	1 Min.	3 Sec.	Min. <sup>(1)</sup>	Max. <sup>(2)</sup>	Min. <sup>(1)</sup>	Max. <sup>(2)</sup>	Max. <sup>(10)</sup>			Max. <sup>(10)</sup>	Available Catalog Numbers <sup>(7)</sup>			
<b>600 Volt AC Input</b>																						
20DE0P9	1	0.5	0.3	4	50	0.7	0.7	0.9	1.1	1.4	1	3	1	3	15	3	M-C2E-B10	-	-	-	NA	
20DE1P7	1	1	0.5	4	50	1.3	1.4	1.7	2	2.6	2	4	2	6	15	3	M-C2E-B16	-	-	-	NA	
20DE2P7	1	2	1	4	50	2.1	2.1	2.7	3.6	4.8	3	6	3	10	15	3	M-C2E-B25	-	-	-	NA	
20DE3P9	1	3	2	4	50	3.0	3.1	3.9	4.3	5.9	6	9	6	15	15	7	M-C2E-B40	M-D8E-B40	-	-	NA	
20DE6P1	1	5	3	4	50	5.3	5.5	6.1	6.7	9.2	9	12	9	20	20	15	M-C2E-B63	M-D8E-B63	-	-	NA	
20DE9P0	1	7.5	5	4	50	7.8	8.1	9	9.9	13.5	10	20	10	35	30	15	M-C2E-C10	M-D8E-C10	M-F8E-C10	-	NA	
20DE011	1	10	7.5	4	50	9.9	10.2	11	13.5	18	15	25	15	40	40	15	M-C2E-C10	M-D8E-C10	M-F8E-C10	-	NA	
20DE017	1	15	10	4	50	15.4	16.0	17	18.7	25.5	20	40	20	60	50	20	M-C2E-C16	M-D8E-C16	M-F8E-C16	-	NA	
20DE022	2	20	15	4	50	20.2	21.0	22	25.5	34	30	50	30	80	80	30	M-C2E-C25	M-D8E-C25	M-F8E-C25	-CMN-2500	NA	
20DE027	2	25	20	4	50	24.8	25.7	27	33	44	35	60	35	100	100	50	-	-	M-F8E-C25	-CMN-2500	NA	
20DE032	3	30	25	4	50	29.4	30.5	32	40.5	54	40	70	40	125	125	50	-	-	M-F8E-C32	-CMN-4000	NA	
20DE041	3	40	30	4	50	37.6	39.1	41	48	64	50	90	50	150	150	100	-	-	M-F8E-C45	-CMN-4000	NA	
20DE052	3	50	40	4	50	47.7	49.6	52	61.5	82	60	110	60	200	200	100	-	-	-	M-CMN-6300	NA	
20DE062	4	60	50	2	50	58.2	60.5	62	78	104	80	125	80	225	225	100	-	-	-	M-CMN-6300	NA	
20DE077	5	75	-	2	50	72.3	75.1	77	85	116	90	150	90	300	300	100	-	-	-	M-CMN-9000	NA	
		-	60	2	50	58.2	60.5	63	94	126	90	125	90	250	250	100	-	-	-	M-CMN-6300	NA	
20DE099	5	100	-	2	40	92.9	96.6	99	109	126	125	200	125	375	375	150	-	-	-	-	NA	
		-	75	2	40	72.3	75.1	77	116	138	100	175	100	300	300	100	-	-	-	-	M-CMN-9000	NA
20DE125	6	125	-	2	50	117	122	125	-	-	150	250	150	375	375	250	-	-	-	-	NA	
		-	100	2	50	92.9	96.6	99	-	-	125	200	125	375	375	150	-	-	-	-	NA	
20DE144	6	150	-	2		135	141	144	-	-	175	300	175	400	400	250	-	-	-	-	NA	
		-	125	2		117	122	125	-	-	150	275	150	375	375	250	-	-	-	-	NA	



**690 Volt AC Input Protection Devices (See Notes below)**

Drive Catalog Number	Frame	kW Rating		PWM Freq. kHz	Temp. °C	Input Ratings		Output Amps			Dual Element Time Delay Fuse		Non-Time Delay Fuse		Circuit Breaker <sup>(3)</sup>	Motor Circuit Protector <sup>(4)</sup>	Power Dissipation Watts
		ND	HD			Amps	kVA	Cont.	1 Min.	3 Sec.	Min. <sup>(1)</sup>	Max. <sup>(2)</sup>	Min. <sup>(1)</sup>	Max. <sup>(2)</sup>			
<b>690 Volt AC Input</b>																	
20DF052	5	45	–	4	50	46.9	56.1	52	57	78	60	110	60	175	175	–	NA
		–	37.5	4	50	40.1	48.0	46	69	92	50	90	50	150	150	–	NA
20DF060	5	55	–	4	50	57.7	68.9	60	66	90	80	125	80	225	225	–	NA
		–	45	4	50	46.9	56.1	52	78	104	60	110	60	175	175	–	NA
20DF082	5	75	–	2	50	79.0	94.4	82	90	123	100	200	100	375	375	–	NA
		–	55	2	50	57.7	68.9	60	90	120	80	125	80	225	225	–	NA
20DF098	5	90	–	2	40	94.7	113	98	108	127	125	200	125	375	375	–	NA
		–	75	2	40	79.0	94.4	82	123	140	100	200	100	375	375	–	NA
20DF119	6	110	–	2	50	115	137	119	131	179	150	250	150	400	–	–	NA
		–	90	2	50	94.7	113	98	147	196	125	200	125	375	–	–	NA
20DF142	6	132	–	2	50	138	165	142	156	213	175	300	175	450	–	–	NA
		–	110	2	50	115	137	119	179	238	150	250	150	400	–	–	NA

**Notes:**

- (1) Minimum protection device size is the lowest rated device that supplies maximum protection without nuisance tripping.
- (2) Maximum protection device size is the highest rated device that supplies drive protection. For US NEC, minimum size is 125% of motor FLA. Ratings shown are maximum.
- (3) Circuit Breaker - inverse time breaker. For US NEC, minimum size is 125% of motor FLA. Ratings shown are maximum.
- (4) Motor Circuit Protector - instantaneous trip circuit breaker. For US NEC minimum size is 125% of motor FLA. Ratings shown are maximum.
- (5) Bulletin 140M with adjustable current range should have the current trip set to the minimum range that the device will not trip.
- (6) Manual Self-Protected (Type E) Combination Motor Controller, UL listed for 208 Wye or Delta, 240 Wye or Delta, 480Y/277 or 600Y/ 347. Not UL listed for use on 480V or 600V Delta/Delta systems.
- (7) The AIC ratings of the Bulletin 140M Motor Protector may vary. See publication 140M-SG001.
- (8) 20BC085 current rating is limited to 45 degrees C ambient.
- (9) 20BC205 current rating is limited to 40 degrees C ambient.
- (10) Maximum allowable rating by US NEC. Exact size must be chosen for each installation.

**540 Volt DC Input Protection Devices (Footnotes found on page A-12)**

Drive Catalog Number	Frame	kW Rating		DC Input Ratings		Output Amps			Fuse	Non-Time Delay Fuse Bussmann Style or Equiv. ®
		ND	HD	Amps	kW	Cont.	1 Min.	3 Sec.		
<b>540 Volt DC Input</b>										
20DC1P3	1	0.37	0.25	1.3	0.7	1.3	1.4	1.9	3	JKS-3
20DC2P1	1	0.75	0.55	2.1	1.1	2.1	2.4	3.2	6	JKS-6
20DC3P5	1	1.5	0.75	3.7	2.0	3.5	4.5	6.0	8	JKS-8
20DC5P0	1	2.2	1.5	5.3	2.9	5.0	5.5	7.5	10	JKS-10
20DC8P7	1	4	3.0	9.3	5.0	8.7	9.9	13.2	20	JKS-20
20DC011	1	5.5	4	12.6	6.8	11.5	13	17.4	25	JKS-25
20DC015	1	7.5	5.5	16.8	9.1	15.4	17.2	23.1	30	JKS-30
20DC022	1	11	7.5	24	13	22	24.2	33	45	JKS-45
20DC030	2	15	11	33.2	17.9	30	33	45	60	JKS-60
20DC037	2	18.5	15	40.9	22.1	37	45	60	80	JKS-80
20DC043	3	22	18.5	47.5	25.7	43	56	74	90	JKS-90
20DC056	3	30	22	61.9	33.4	56	64	86	110	JKS-110
20DC072	3	37	30	80.5	43.5	72	84	112	150	JKS-150
20DC085	4	45	–	95.1	51.3	85	94	128	200	JKS-200
		–	37	80.5	43.5	72	108	144	150	JKS-150
20DH105 ●	5	55	–	117.4	63.4	105	116	158	200	JKS-200
		–	45	95.1	51.3	85	128	170	200	JKS-200
20DH125 ●	5	55	–	139.8	75.5	125	138	163	225	JKS-225
		–	45	91.9	63.7	96	144	168	150	Not Available at time of Print
20DH140 ●	6	75	–	158.4	85.6	140	154	210	300	JKS-300
		–	55	117.4	63.4	105	158	210	200	JKS-200
20DH170 ●	6	90	–	192.4	103.9	170	187	255	350	JKS-350
		–	75	158.4	85.6	140	210	280	300	JKS-300
20DH205 ●	6	110	–	232	125.3	205	220	289	400	JKS-400
		–	90	192.4	103.9	170	255	313	350	JKS-350
20DH261	9	132	–	312	161	261	287	410	500	170M6608
		–	110	245	127	205	308	410	500	170M6608
20DH300	9	160	–	359	186	300	330	500	630	170M6610
		–	132	293	152	245	368	490	630	170M6610

540 Volt DC Input Protection Devices, Cont'd

Drive Catalog Number	Frame	kW Rating		DC Input Ratings		Output Amps			Fuse	Non-Time Delay Fuse Bussman Style or Equiv. ⑥
		ND	HD	Amps	kW	Cont.	1 Min.	3 Sec.		
<b>540 Volt DC Input, Cont'd</b>										
20DH385	10	200	-	460	238	385	242	600	700	170M6611
		-	160	359	186	300	450	600	700	170M6611
20DH460	10	250	-	550	284	460	506	770	900	170M6613
		-	200	460	238	385	578	770	900	170M6613
20DH500	10	250	-	598	309	500	550	750	1000	170M6614
		-	200	502	260	420	630	840	1000	170M6614

650 Volt DC Input Protection Devices

Drive Catalog Number	Frame	HP Rating		DC Input Ratings		Output Amps			Fuse	Non-Time Delay Fuse Bussmann Style or Equiv. ⑥
		ND	HD	Amps	kW	Cont.	1 Min.	3 Sec.		
<b>650 Volt DC Input</b>										
20DD1P1	0	0.5	0.33	1.0	0.6	1.1	1.2	1.6	6	JKS-6
20DD2P1	0	1	0.75	1.9	1.2	2.1	2.4	3.2	6	JKS-6
20DD3P4	0	2	1.5	3.0	2.0	3.4	4.5	6.0	6	JKS-6
20DD5P0	0	3	2	4.5	2.9	5.0	5.5	7.5	10	JKS-10
20DD8P0	0	5	3	8.1	5.2	8.0	8.8	12	15	JKS-15
20DD011	0	7.5	5	11.1	7.2	11	12.1	16.5	20	JKS-20
20DD014	1	10	7.5	14.7	9.5	14	16.5	22	30	JKS-30
20DD022	1	15	10	23.3	15.1	22	24.2	33	45	JKS-45
20DD027	2	20	15	28.9	18.8	27	33	44	60	JKS-60
20DD034	2	25	20	36.4	23.6	34	40.5	54	70	JKS-70
20DD040	3	30	25	42.9	27.8	40	51	68	80	JKS-80
20DD052	3	40	30	55.7	36.1	52	60	80	100	JKS-100
20DD065	3	50	40	69.7	45.4	65	78	104	150	JKS-150
20DD077	4	60	-	84.5	54.7	77	85	116	150	JKS-150
		-	50	67.9	45.4	65	98	130	150	JKS-150
20DJ096 ⑥	5	75	-	105.3	68.3	96	106	144	200	JKS-200
		-	60	84.5	54.7	77	116	154	150	JKS-150
20DJ125 ⑥	5	100	-	137.1	88.9	125	138	163	250	JKS-250
		-	75	105.3	68.3	96	144	168	200	JKS-200
20DJ156 ⑥	6	125	-	171.2	110.9	156	172	234	300	JKS-300
		-	100	137.1	88.9	125	188	250	250	JKS-250
20DJ180 ⑥	6	150	-	204.1	132.2	180	198	270	400	JKS-400
		-	125	171.2	110.9	156	234	312	300	JKS-300
20DJ248	6	200	-	-	-	248	273	392	550	-
		-	150	-	-	-	180	270	360	400
20DJ261	9	200	-	299	186	261	287	410	500	170M6608
		-	150	235	146	205	308	410	500	170M6608
20DJ300	9	250	-	343	213	300	330	500	630	170M6610
		-	200	281	174	245	368	490	630	170M6610
20DJ385	10	300	-	441	274	385	242	600	700	170M6611
		-	250	343	213	300	450	600	700	170M6611
20DJ460	10	350	-	527	327	460	506	770	900	170M6613
		-	300	441	274	385	578	770	900	170M6613
20DJ500	10	450	-	572	356	500	550	750	1000	170M6614
		-	350	481	299	420	630	840	1000	170M6614

- ① Also applies to "P" voltage class.
- ② The power source to Common Bus inverters must be derived from AC Voltages 600V or less, as defined in NFPA70; Art 430-18 (NEC).  
 Battery supplies or MG sets are not included  
 The following devices were validated to break current of the derived power DC Bus:  
*Disconnects:* Allen-Bradley Bulletin No. 1321, 30 to 400 A; Bulletin No. 194, 30 to 400 A  
 ABB: OESA, 600 & 800 A; OESL, all sizes  
*Fuses:* Bussmann Type JKS, all sizes; Type 170M, Case Sizes 1, 2 and 3  
 Ferraz Shawmut Type HSJ, all sizes  
 For any other devices, please contact the factory.
- ⑥ Also applies to "R" voltage class.

## List of Motors with Compatible Thermistor Ratings

Motor Type	Motor (kW)	Type (Catalog No.) <sup>(1)</sup>	Poles	Base Speed (RPM)	Voltage (Vrms)	Rate Current (Arms)	Ex. Current (Arms)	GD2 (Kg/m <sup>2</sup> )
200 STD Motor	1.5	M-51027	4	1500	180	7.5	-	0.024
	2.2	M-51028	4	1500	180	11	-	0.045
	3.7	M-51001	4	1500	180	18	-	0.066
	3.7	M-51007-1	4	1500	180	18	-	0.066
	5.5	M-51002	4	1500	180	25	-	0.12
	5.5	M-51008-1	4	1500	180	25	-	0.12
	7.5	M-51003	4	1500	180	33	-	0.15
	7.5	M-51009-1	4	1500	180	33	-	0.15
	11	M-51004	4	1500	180	47	-	0.32
	11	M-51010-1	4	1500	180	47	-	0.32
	15	M-51005	4	1500	180	63	-	0.43
	15	M-51011-1	4	1500	180	63	-	0.43
	18.5	M-51012	4	1500	180	81	-	0.71
	18.5	M-51012-1	4	1500	180	81	-	0.71
	22	M-51013	4	1500	180	95	-	0.82
	22	M-51013-1	4	1500	180	95	-	0.82
	30	M-51050	4	1500	155	145	-	0.83
	37	M-51051	4	1500	155	183	-	1.1
	45	M-51052	4	1500	155	220	-	1.4
	55	M-51053	4	1500	155	265	-	2
75	M-51054	4	1500	155	346	-	2.7	
200 SVO Motor	0.75	M-51043	4	1500	140	5.3	-	0.0075
	1.5	M-51015	4	1500	140	11.4	-	0.0100
	2.2	M-51016	4	1500	140	15	-	0.0120
	3.7	M-51017	4	1500	140	24.5	-	0.0180
	5.5	M-51018	4	1500	140	34.8	-	0.0390
	7.5	M-51019	4	1500	140	44	-	0.0470
	11	M-51020	4	1500	140	67.1	-	0.0810
	15	M-51021	4	1500	140	80.7	-	0.1370
	22	M-51022	4	1500	140	120	-	0.2000
	30	M-51023	6	1000	155	176	-	0.5800
	37	M-51024	6	1000	155	210	-	0.7000
	55	M-51026	6	1000	135	334	-	1.1000
	55	M-51027	6	500	155	315	-	4.0000
400 STD Motor	1.5	MC-M2051	4	1500	320	4.7	2.045	-
	2.2	MC-M2052	4	1500	320	6.3	3.24	-
	3.7	MC-M2053	4	1500	320	10	5.25	-
	5.5	MC-M2054	4	1500	320	15.5	8.8	-
	7.5	MC-M2055	4	1500	320	20.5	11.25	-
	11	MC-M2056	4	1500	320	29	14.3	-
	15	MC-M2057	4	1500	320	37	16.4	-
	18.5	MC-M2058	4	1500	320	45	19.65	-
	22	MC-M2059	4	1500	320	53	23	-
	30	MC-M2060	4	1500	320	71	28.15	-
	37	MC-M2061	4	1500	320	85	29.7	-
	45	MC-M2062	4	1500	320	97	30.55	-
	55	MC-M2063	4	1500	320	121	-	-
	75	MC-M2064	4	1500	320	163	-	-
	90	MC-M2065	4	1500	320	188	-	-
	110	MC-M2066	4	1500	320	227	-	-
	132	MC-M2067	4	1500	320	280	-	-
160	MC-M2068	4	1500	320	335	-	-	
200	MC-M2069	4	1500	320	375	-	-	

Motor Type	Motor (kW)	Type (Catalog No.) <sup>(1)</sup>	Poles	Base Speed (RPM)	Voltage (Vrms)	Rate Current (Arms)	Ex. Current (Arms)	GD2 (Kg/m <sup>2</sup> )
400 SVO Motor	1.5	MC-M20	4	1500	280	5.4	-	-
	2.2	MC-M20	4	1500	280	7.3	-	-
	3.7	MC-M20	4	1500	280	12.3	-	-
	5.5	MC-M20	4	1500	280	17.3	-	-
	7.5	MC-M20	4	1500	280	22	-	-
	11	MC-M20	4	1500	280	34	-	-
	15	MC-M20	4	1500	280	42	-	-
	22	MC-M20	4	1500	280	58.5	-	-
	22	MC-M20	4	1500	280	58.5	-	-
	30	MC-M20	6	1000	280	88	-	-
37	MC-M20	6	1000	280	125	-	-	

(1) Manufacturer, Reliance Electric-Japan, catalog number for ordering.

## Spare Connectors

This section provides part numbers for “Customer-I/O” plugs (both Allen-Bradley numbers and connector manufacture numbers). This allows users to procure spare or replacement parts from Allen-Bradley or directly from the connector manufacturer.

### Main Control Board

Phoenix Contact manufactures all four “Customer-I/O” connectors for the Main Control Board, according to Allen-Bradley specifications. Allen-Bradley specifies custom markings on standard Phoenix Contact plugs.

Connector	Allen-Bradley Number	Phoenix Contact Standard Number
TB1 - Row T	305334-Q01	MCV 1,5/13-ST3, 81 27 21 1
TB1 - Row B	305334-Q02	MCV 1,5/13-ST3, 81 27 21 1
TB2 - Row T	305335-Q01	MCV 1,5/13-ST3, 81 18 03 68 8
TB2 - Row B	305335-Q02	MCV 1,5/13-ST3, 81 18 03 68 8

### High Resolution Encoder Interface Board

Weidmuller manufactures the “Customer-I/O” plug on the High Resolution Encoder Interface Board.

Connector	Allen-Bradley Number	Weidmuller Number
P1	S94262912	BL3.50/90/12BK

### Resolver Interface Board

Weidmuller manufactures the “Customer-I/O” plug on the Resolver Interface Board.

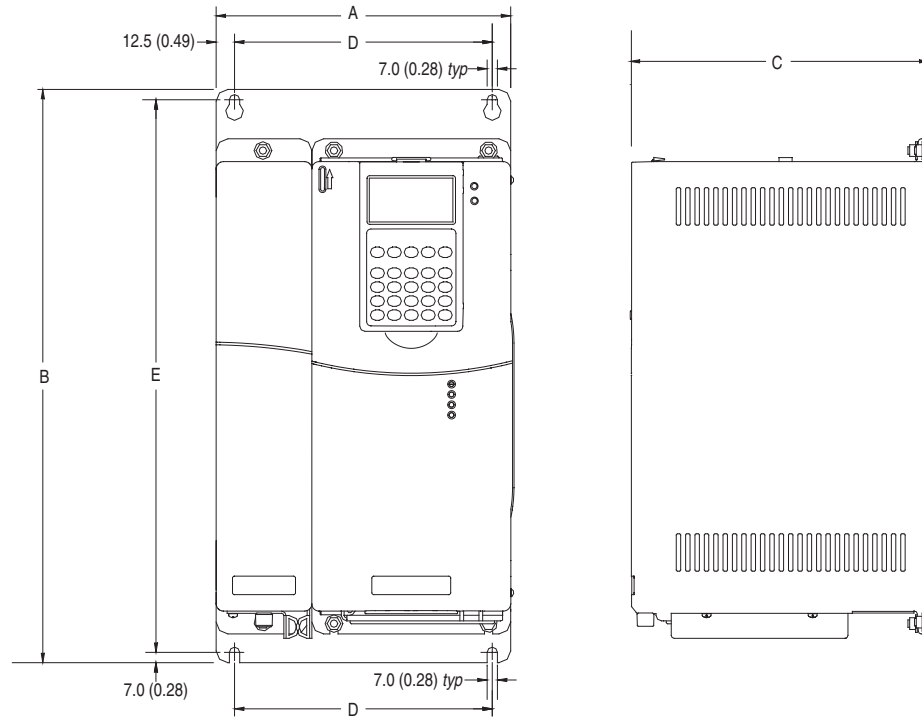
Connector	Allen-Bradley Number	Weidmuller Number
P1	S94262908	BL3.50/90/8BK

Dimensions

Table A.A PowerFlex 700S Frames

Frame	AC Input								DC Input			
	208/240		400V		480V		600V		540V		650V	
	ND HP	HD HP	ND kW	HD kW	ND HP	HD HP	ND HP	HD HP	ND HP	HD HP	ND HP	HD HP
1	2	1.5	7.5	5.5	10	7.5	10	7.5	7.5	5.5	10	7.5
	3	2	11	7.5	15	10	15	10	11	7.5	15	10
	5	3	-	-	-	-	-	-	-	-	-	-
	7.5	5	-	-	-	-	-	-	-	-	-	-
2	10	7.5	15	11	20	15	20	15	15	11	20	15
	-	-	18.5	15	25	20	25	20	18.5	15	25	20
3	15	10	22	18.5	30	25	30	25	22	18.5	30	25
	20	15	30	22	40	30	40	30	30	22	40	30
	-	-	37	30	50	40	50	40	37	30	50	40
4	25	20	45	37	60	50	60	50	45	37	60	50
	30	25	-	-	-	-	-	-	-	-	-	-
5	40	30	55	45	75	60	75	60	55	45	75	60
	50	40	-	-	100	75	100	75	-	-	100	75
6	60	50	75	55	125	100	-	-	75	55	125	100
	75	60	90	75	150	125	-	-	90	75	150	125
	-	-	110	90	-	-	-	-	110	90	-	-
	-	-	132	110	200	150	-	-	132	110	200	150
9	-	-	-	-	200	150	-	-	-	-	-	-
	-	-	-	-	250	200	-	-	-	-	-	-
10	-	-	-	-	300	250	-	-	-	-	-	-
	-	-	-	-	350	300	-	-	-	-	-	-
	-	-	-	-	450	350	-	-	-	-	-	-
	-	-	-	-	-	-	-	-	-	-	-	-

Figure A.1 PowerFlex 700S Frame 1-3 (Frame 1 Shown)

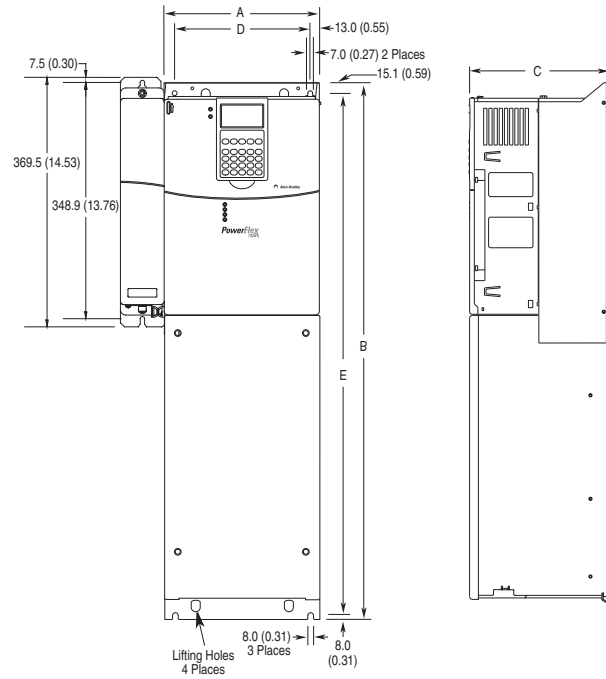


Dimensions are in millimeters and (inches)

Frame	A	B	C	D	E	Weight <sup>(1)</sup> kg (lbs.)
						Drive
1	200.0 (7.87)	389.0 (15.31)	202.8 (7.98)	175.0 (6.89)	375.0 (14.76)	11.3 (24.92)
2	285.0 (11.22)	389.0 (15.31)	202.7 (7.98)	250.0 (9.84)	375.0 (14.76)	18.4 (40.57)
3	285.0 (11.22)	564.0 (22.20)	202.7 (7.98)	250.0 (9.84)	550.0 (21.65)	26.6 (58.65)

(1) Weights include HIM, DriveLogix controller with ControlNet daughtercard, Hi-Resolution Encoder Option, and 20-COMM-C ControlNet adapter

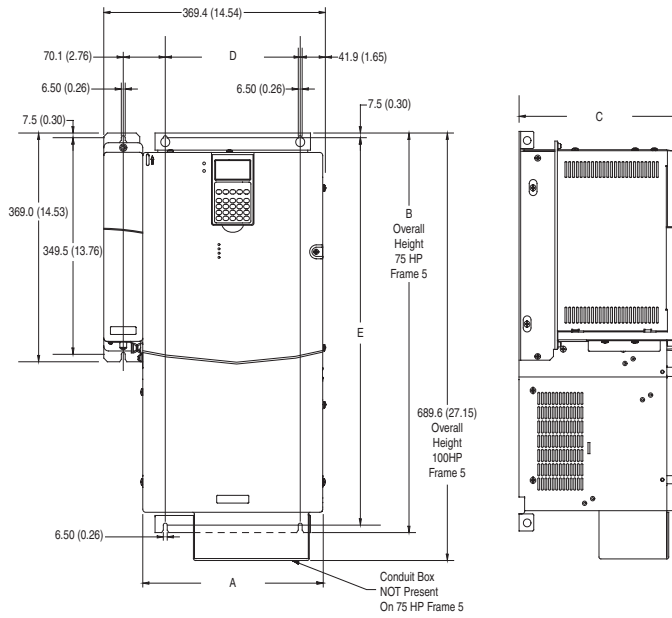
**Figure A.2 DPowerFlex 700S Frame 4**



Frame	A (Max.)	B	C (Max.)	D	E	Approx. Weight <sup>(1)</sup> kg (lbs.)	
						Drive	Drive & Packaging
4	220.8 (8.69)	758.8 (29.9)	201.8 (7.94)	192.0 (7.56)	741.7 (29.2)	28.4 (62.5)	29.03 (63.9)

(1) Weights include HIM and Standard I/O.

**Figure A.3 PowerFlex 700S Frame 5**



Dimensions are in millimeters and (inches)

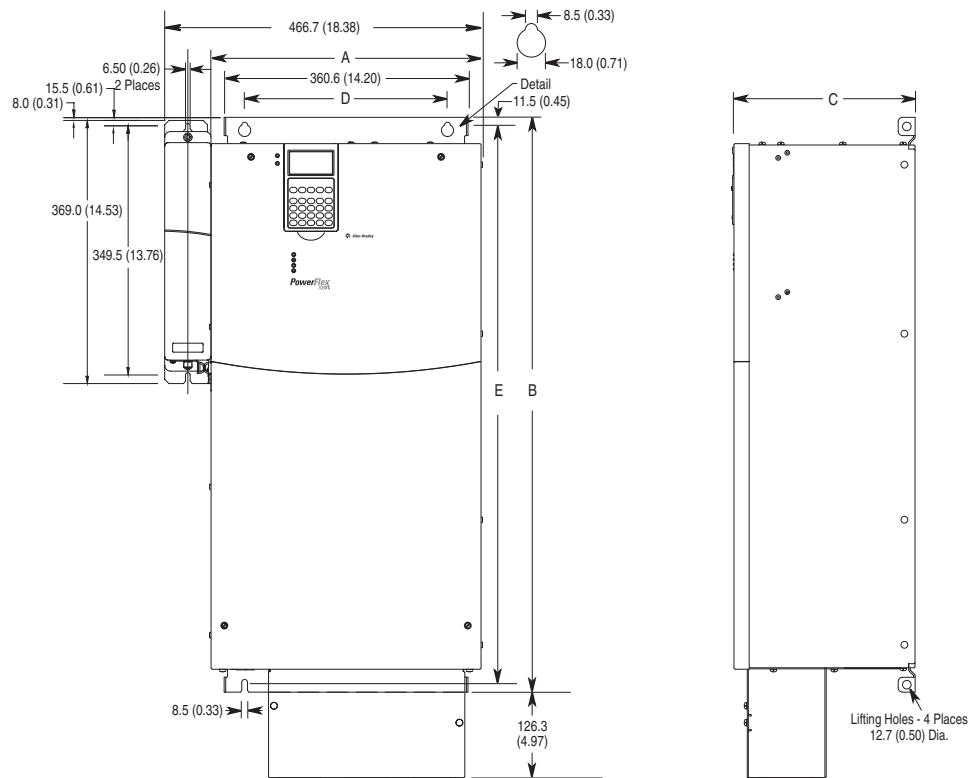
**Weight<sup>(1)</sup> kg (lbs.)**

**Drive**

**42.6 (93.93)**

(1) Weights include HIM, DriveLogix controller with ControlNet daughtercard, Hi-Resolution Encoder Option, and 20-COMM-C ControlNet adapter

Figure A.4 PowerFlex 700S Frame 6

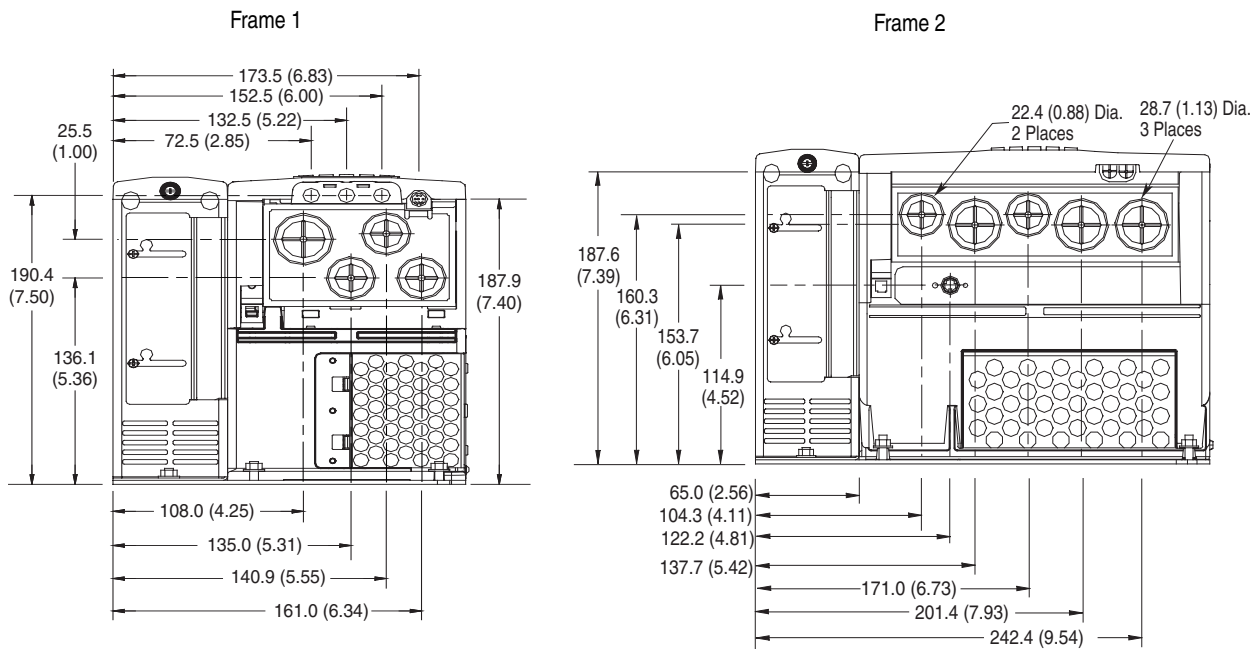


Dimensions are in millimeters and (inches)

Frame	A (Max.)	B	C (Max.)	D	E	Weight <sup>(1)</sup> kg (lbs.)	
						Drive	Drive and Packaging
6	403.80 (15.90)	850.00 (33.46)	275.50 (10.85)	300.00 (11.81)	825.0 (157.5)	70.31 (154.70)	89.09 (196.00)

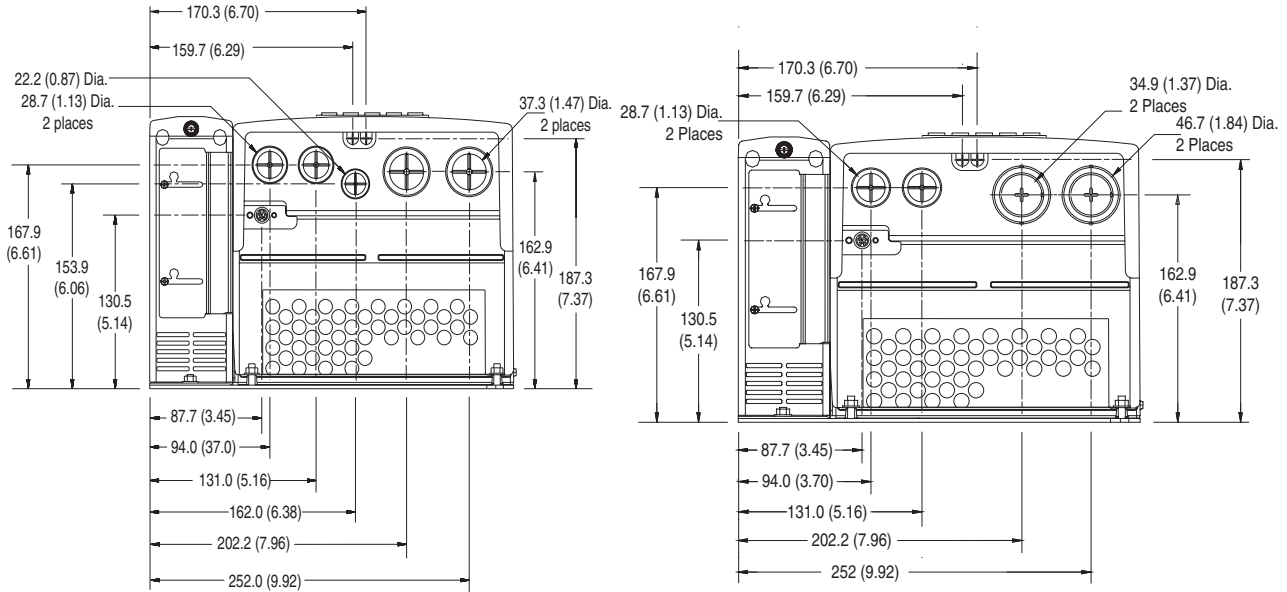
(1) Weights include HIM, DriveLogix controller with ControlNet daughtercard, Hi-Resolution Encoder Option, and 20-COMM-C ControlNet adapter

**Figure A.5 PowerFlex 700S Bottom View Dimensions**



**Frame 3 - All Drives except 50 HP, 480V (37 kW, 400V)**

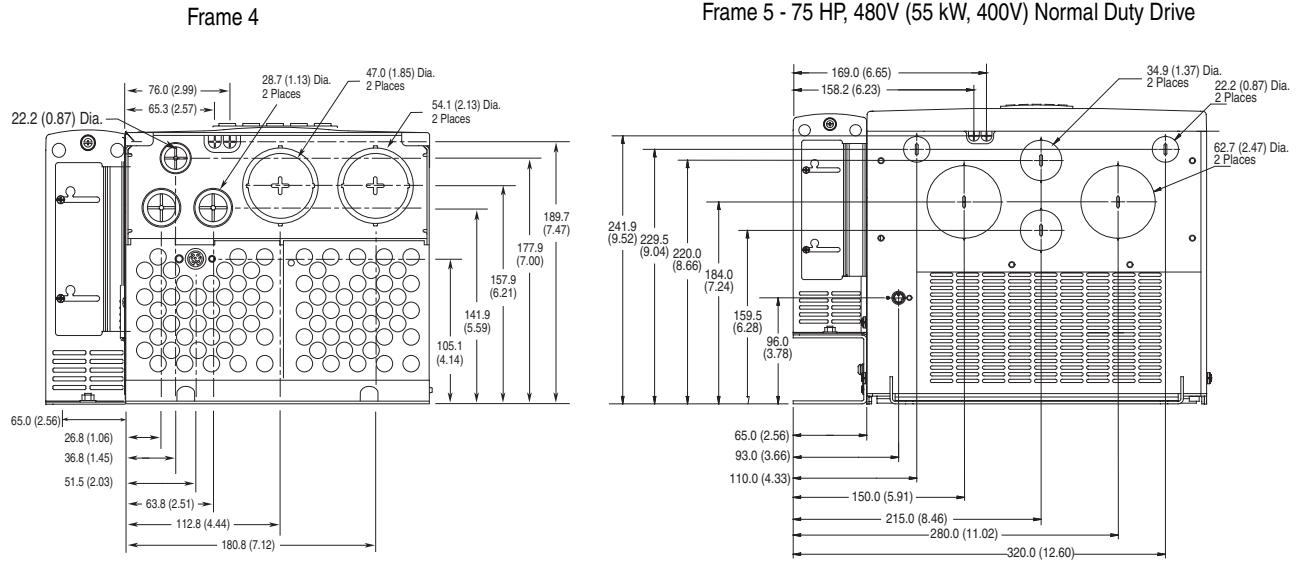
**Frame 3 - 50 HP, 480V (37 kW, 400V) Normal Duty Drive**



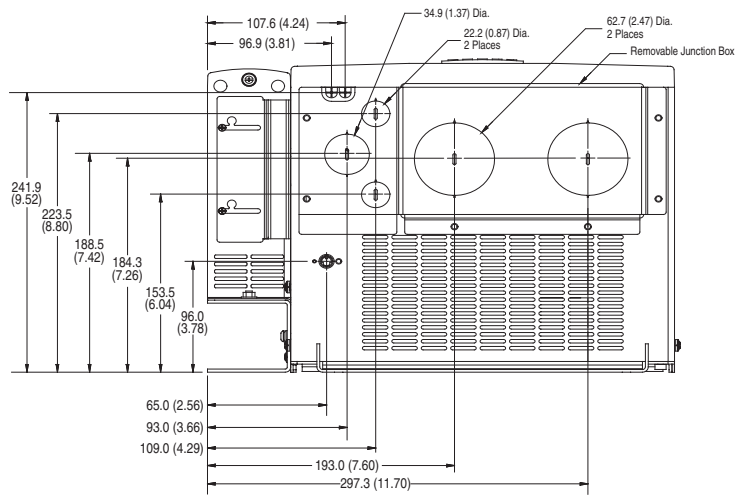
*Dimensions are in millimeters and (inches)*



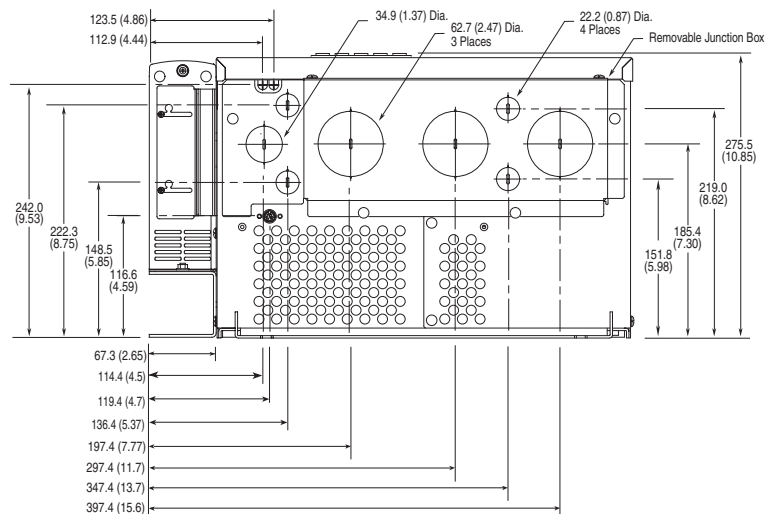
**Figure A.6 PowerFlex 700S Bottom View Dimensions (continued)**



**Frame 5 - 100 HP, 480V (55 kW, 400V) Normal Duty Drive**



**Frame 6**



Dimensions are in millimeters and (inches)



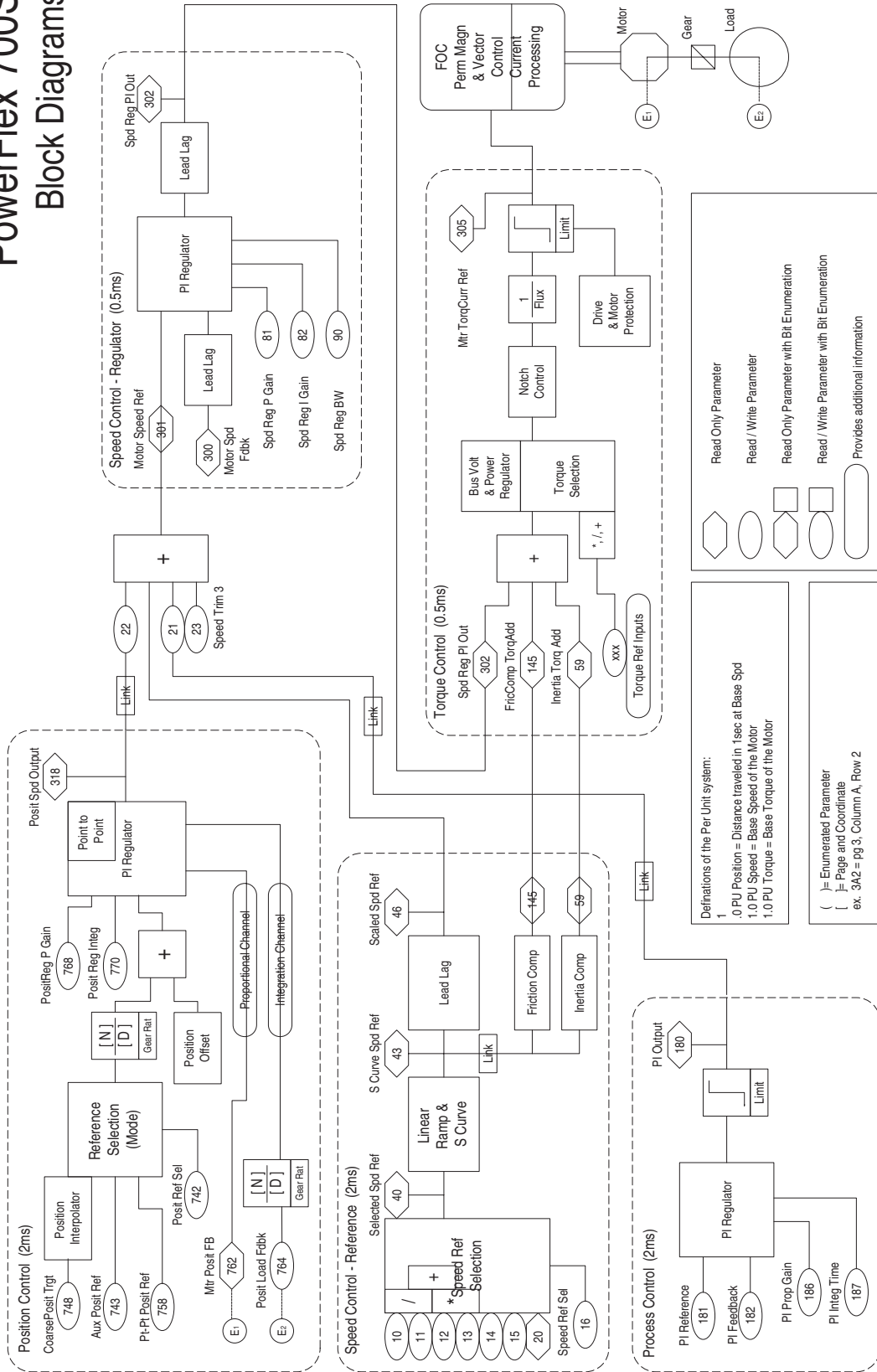
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## Control Block Diagrams

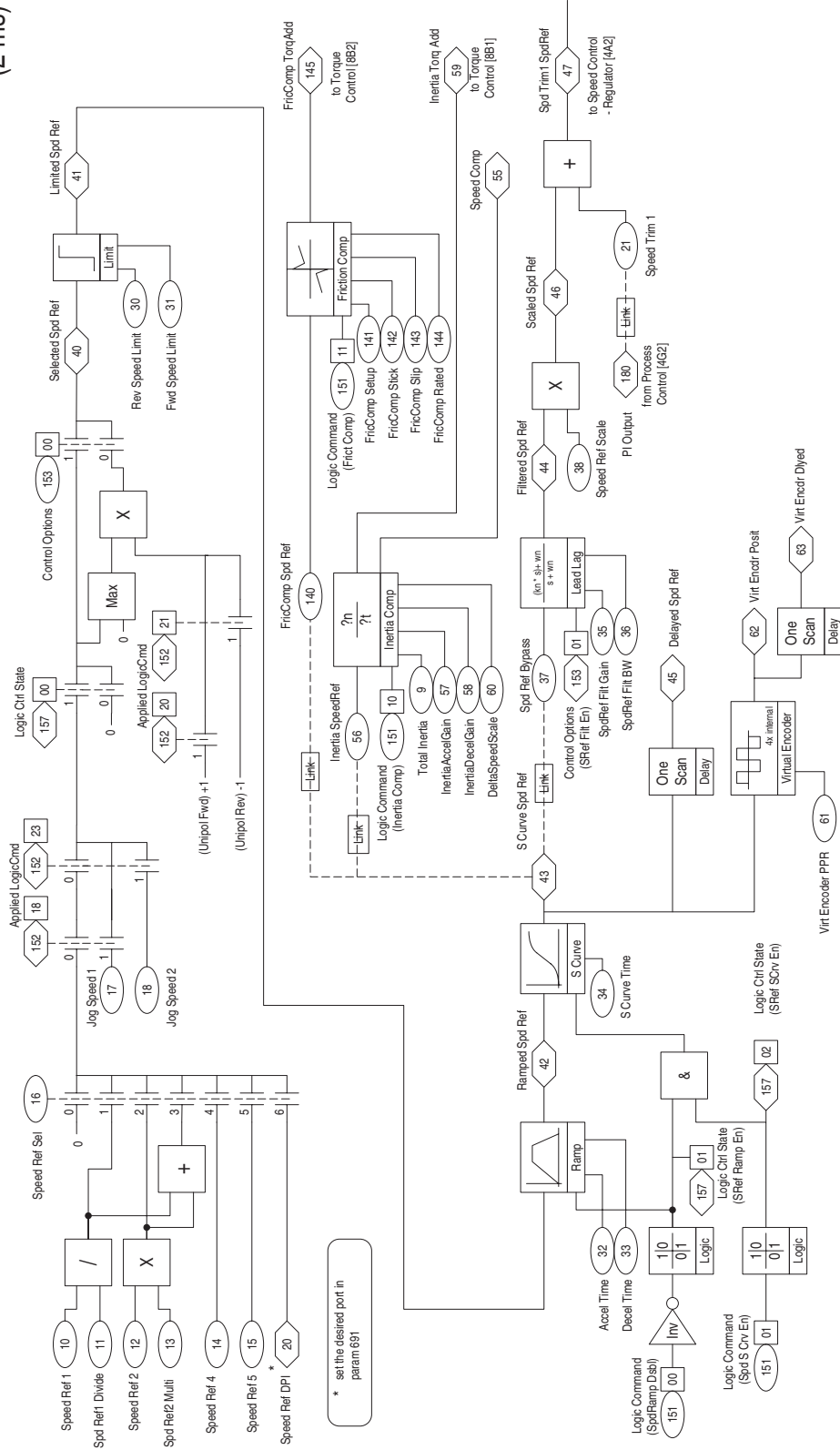
Flow diagrams on the following pages illustrate the drives' control algorithms.

<b>For Information on ...</b>	<b>See Page...</b>
Overview	<a href="#">B-2</a>
Speed Control - Reference	<a href="#">B-3</a>
Speed Control - Regulator	<a href="#">B-4</a>
Process Control	<a href="#">B-5</a>
Position Control - Interpolated/Direct	<a href="#">B-6</a>
Position Control - Point to Point	<a href="#">B-7</a>
Position Control - Auxiliary/Control	<a href="#">B-8</a>
Torque Control-Torque	<a href="#">B-9</a>
Torque Control-Current	<a href="#">B-10</a>
Speed/Position Feedback	<a href="#">B-11</a>
Inputs & Outputs - Discrete	<a href="#">B-12</a>
Inputs & Output - Analog	<a href="#">B-13</a>
Inverter Overload IT	<a href="#">B-14</a>
User Functions	<a href="#">B-15</a>
Control Logic	<a href="#">B-16</a>
Trend	<a href="#">B-17</a>

# PowerFlex 700S Block Diagrams



# Speed Control - Reference (2 ms)

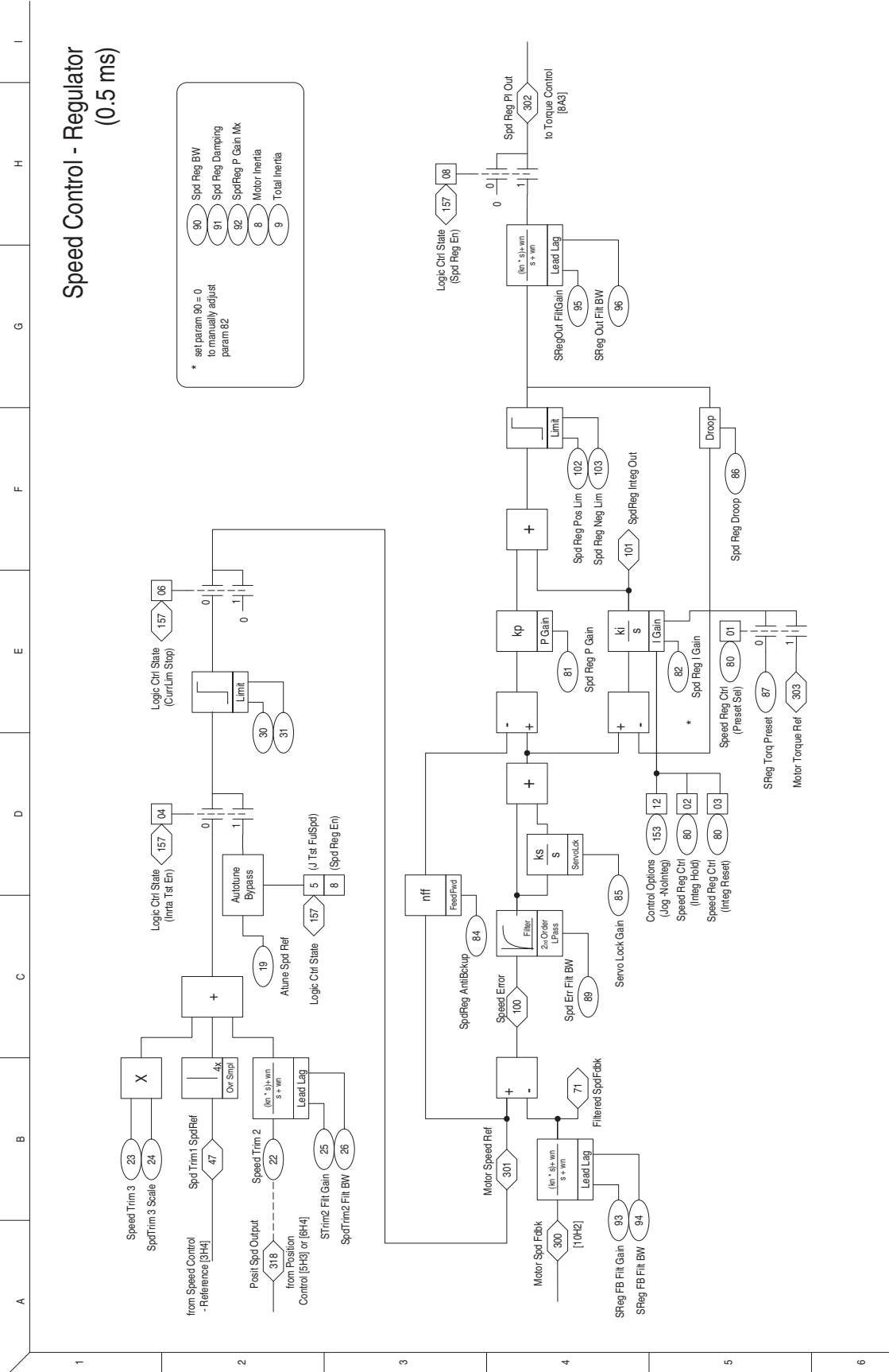


A	B	C	D	E	F	G	H	I
1	2	3	4	5	6			

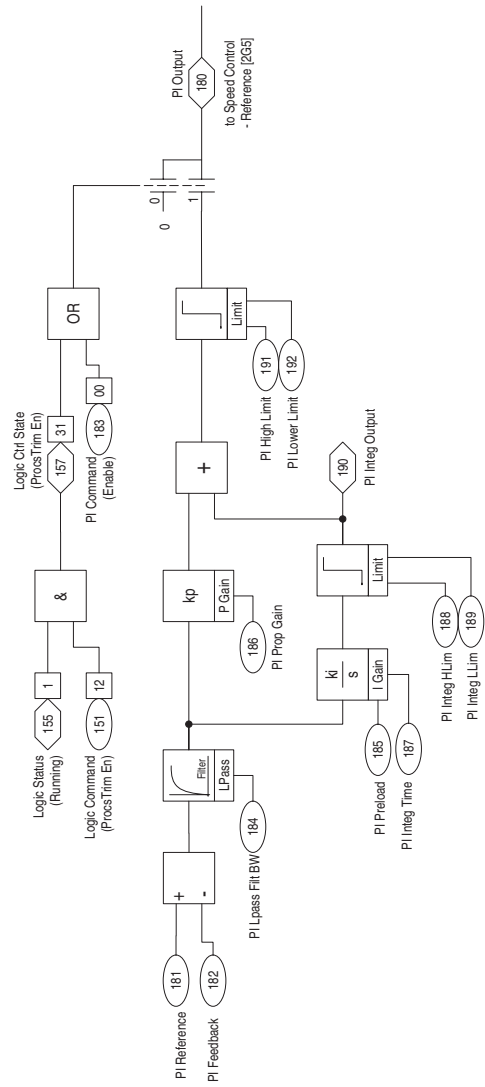
### Speed Control - Regulator (0.5 ms)

\* set param 90 = 0  
to manually adjust  
param 82

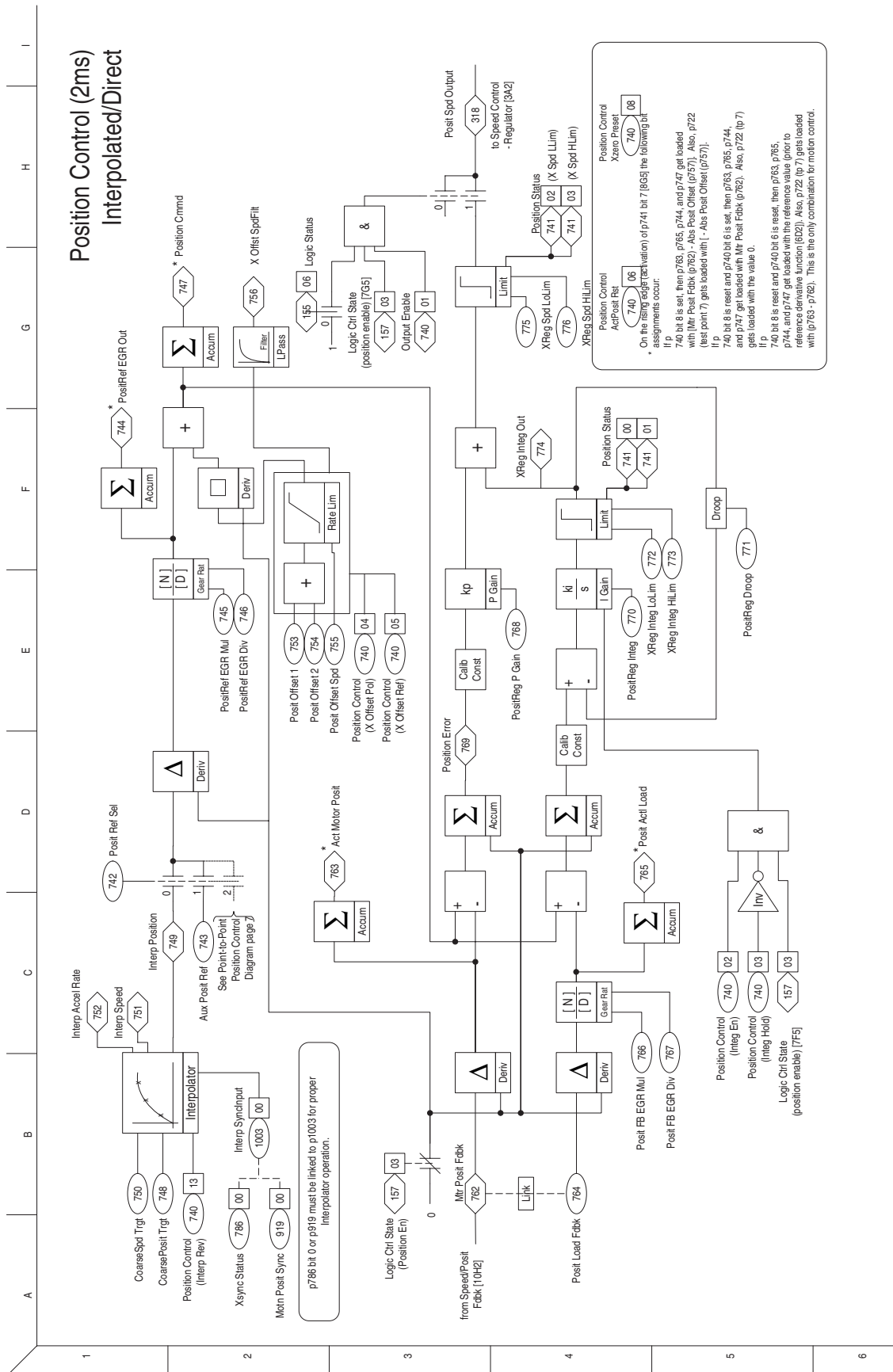
90 Spd Reg BW  
91 Spd Reg Damping  
92 SpdReg P Gain Mx  
8 Motor Inertia  
9 Total Inertia



## Process Control (2 ms)



### Position Control (2ms) Interpolated/Direct



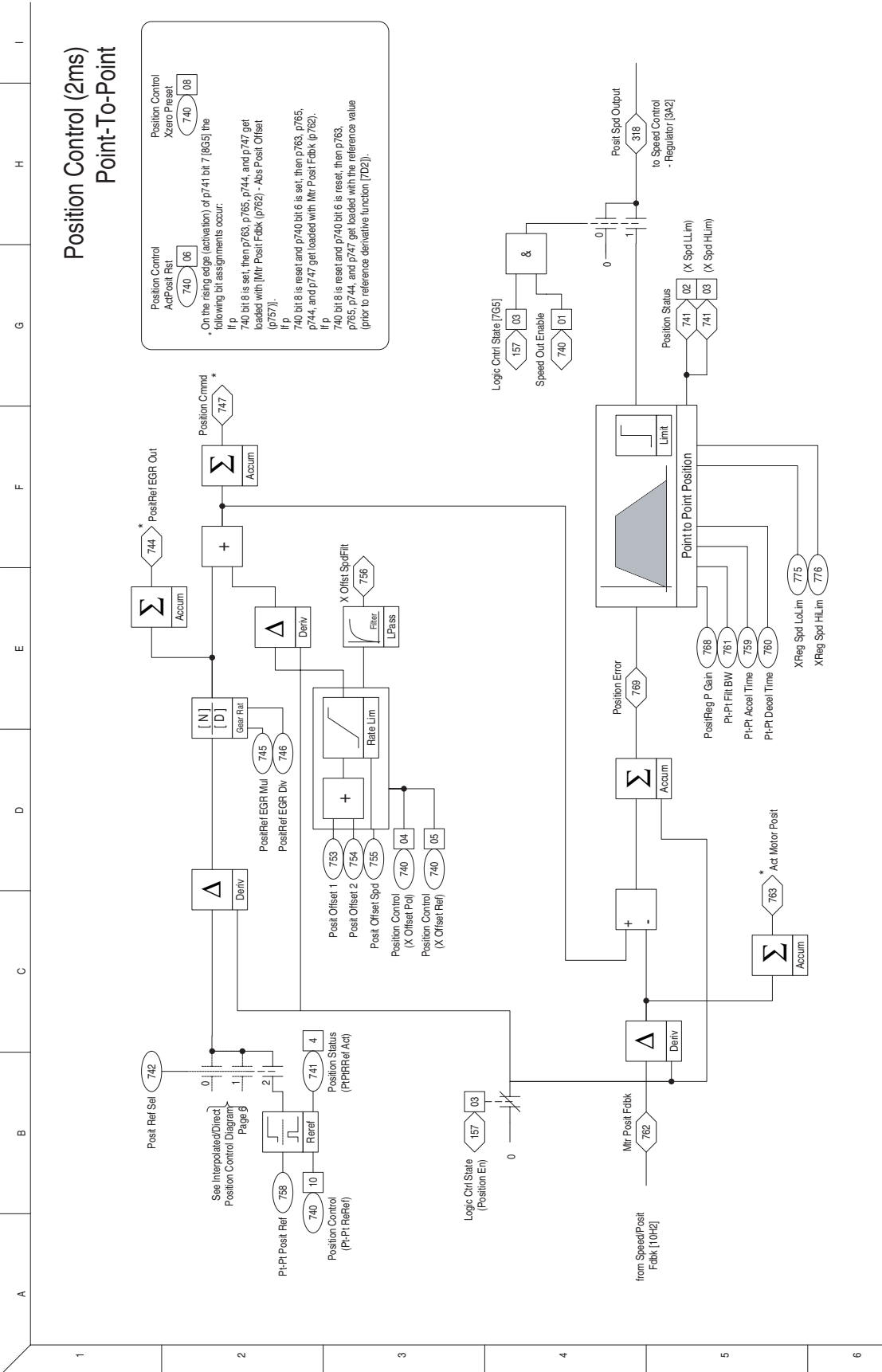


# Position Control (2ms) Point-To-Point

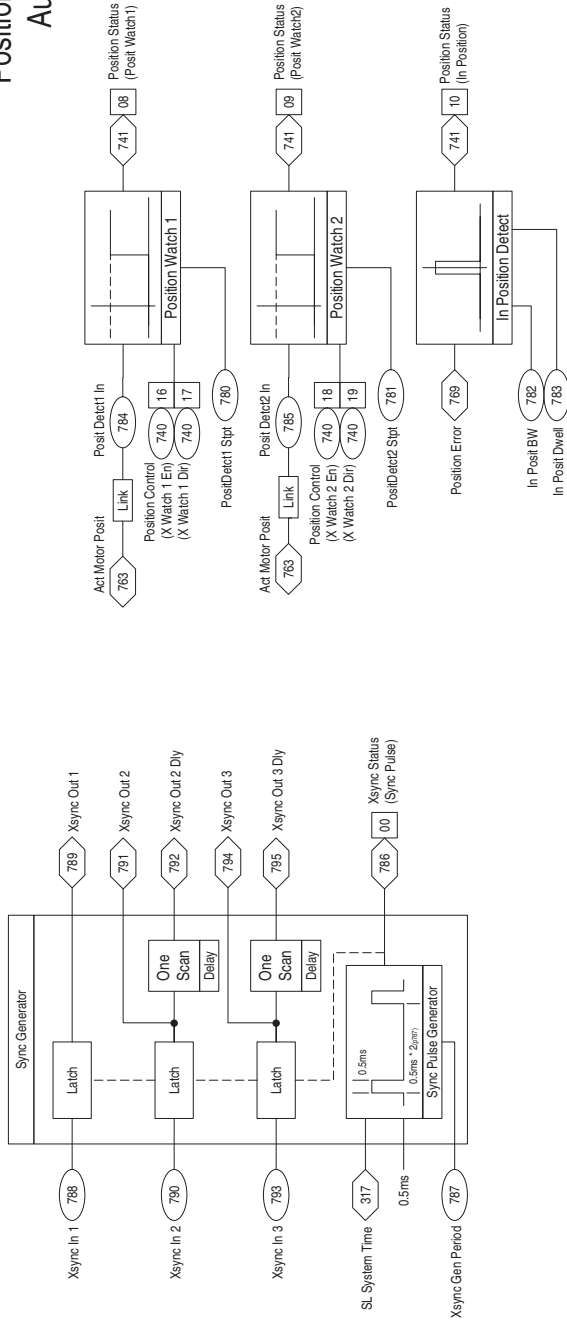
Position Control  
Act/Post Fdbk (740) 06  
Position Control  
Zero Preset (740) 08

On the rising edge (activation) of p741 bit 7 [865] the following bit assignments occur:

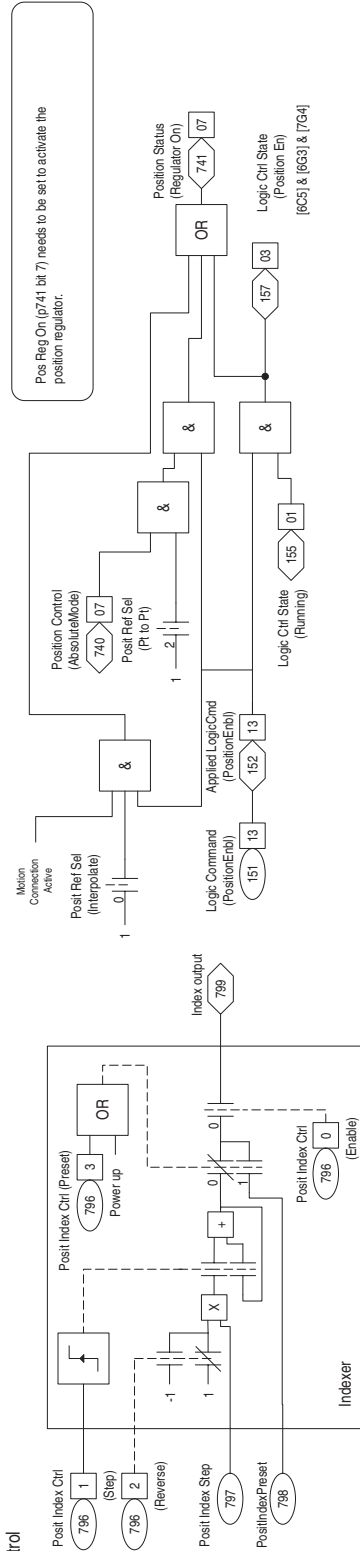
- If p740 bit 8 is set, then p763, p765, p744, and p747 get loaded with [Mtr Posit Fdbk (p762) - Abs Posit Offset (p757)].
- If p740 bit 6 is reset and p740 bit 6 is set, then p763, p765, p744, and p747 get loaded with [Mtr Posit Fdbk (p762) - Abs Posit Offset (p757)].
- If p740 bit 6 is reset and p740 bit 6 is set, then p763, p765, p744, and p747 get loaded with [Mtr Posit Fdbk (p762) - Abs Posit Offset (p757)].
- If p740 bit 6 is reset and p740 bit 6 is set, then p763, p765, p744, and p747 get loaded with the reference value (prior to reference derivative function [702]).



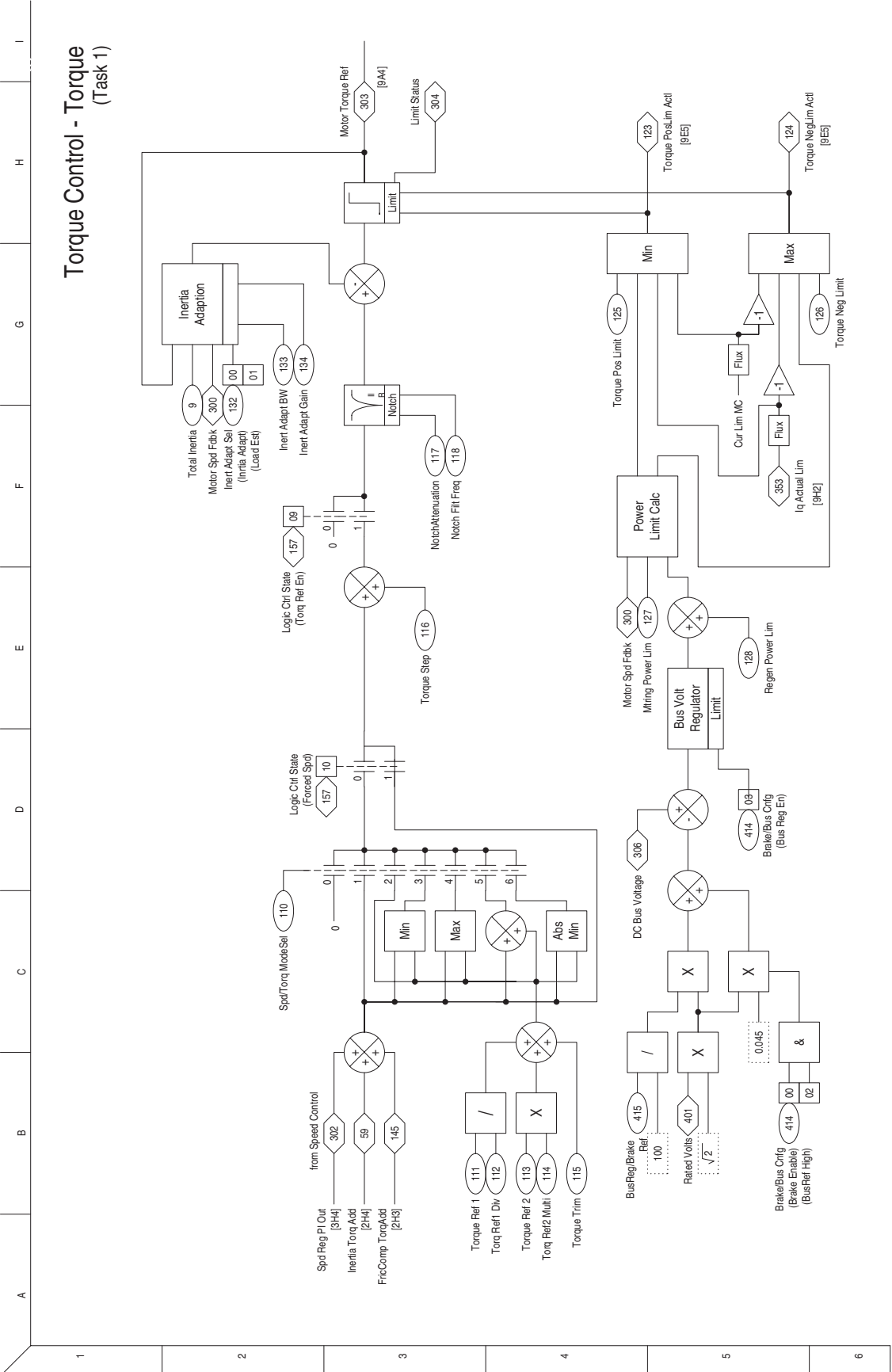
### Position Control (2ms) Auxiliary / Control



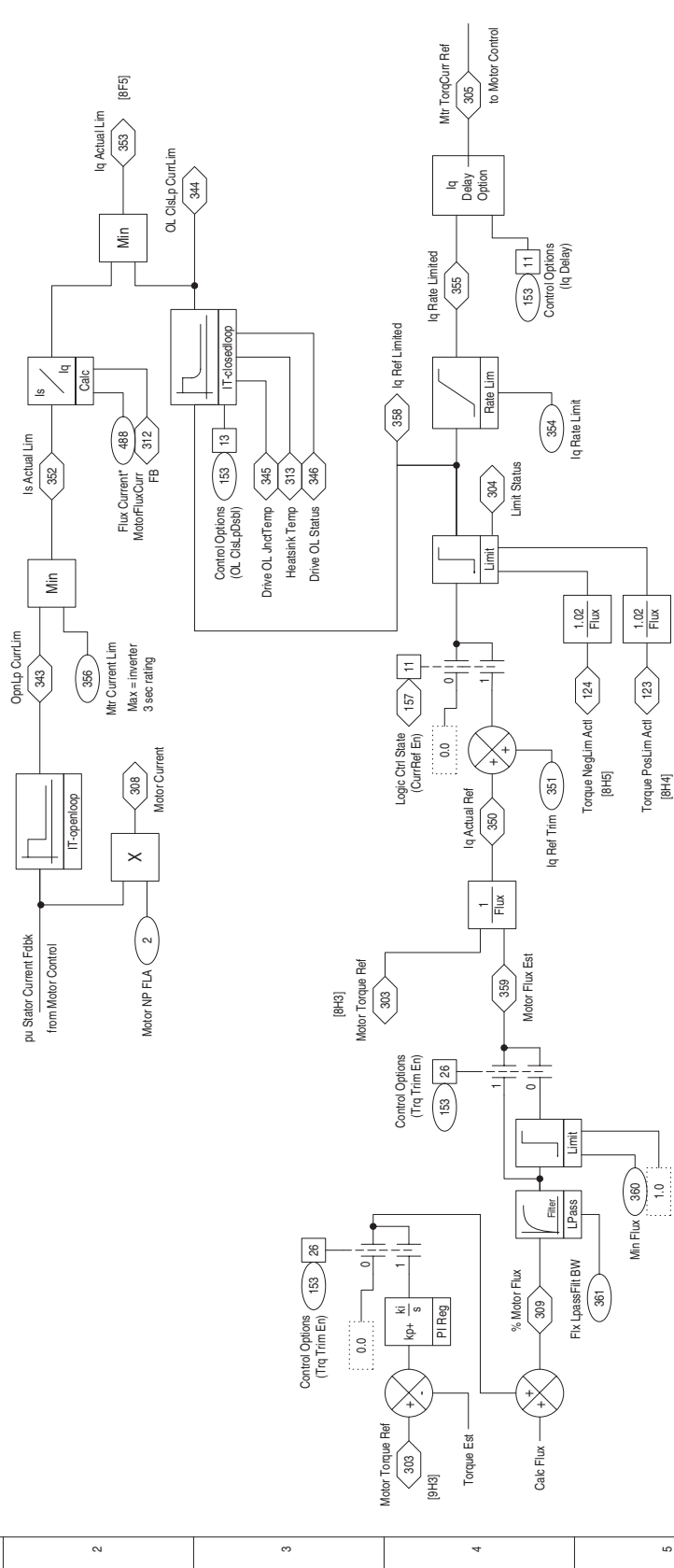
### Auxiliary Control



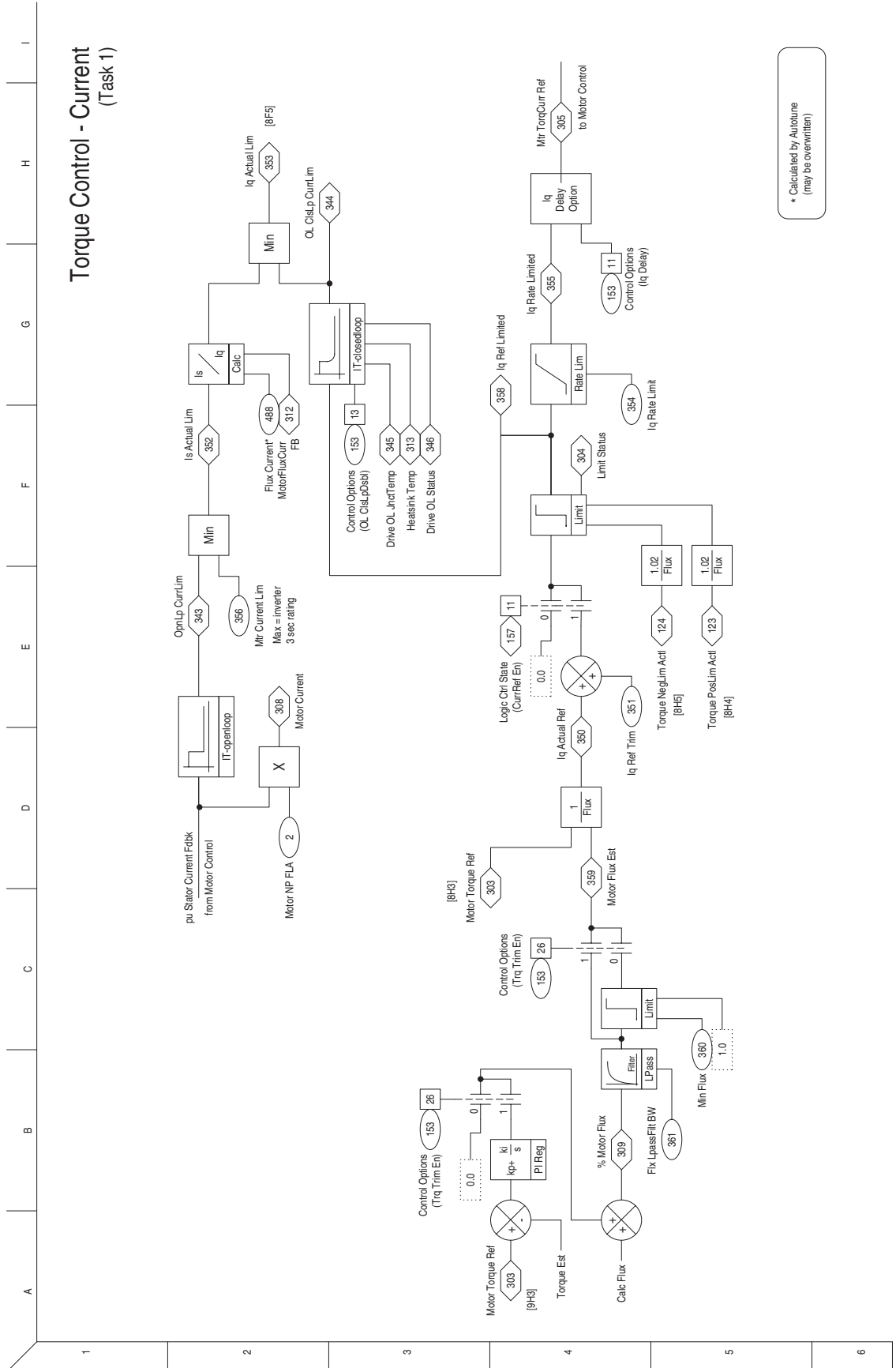
# Torque Control - Torque (Task 1)

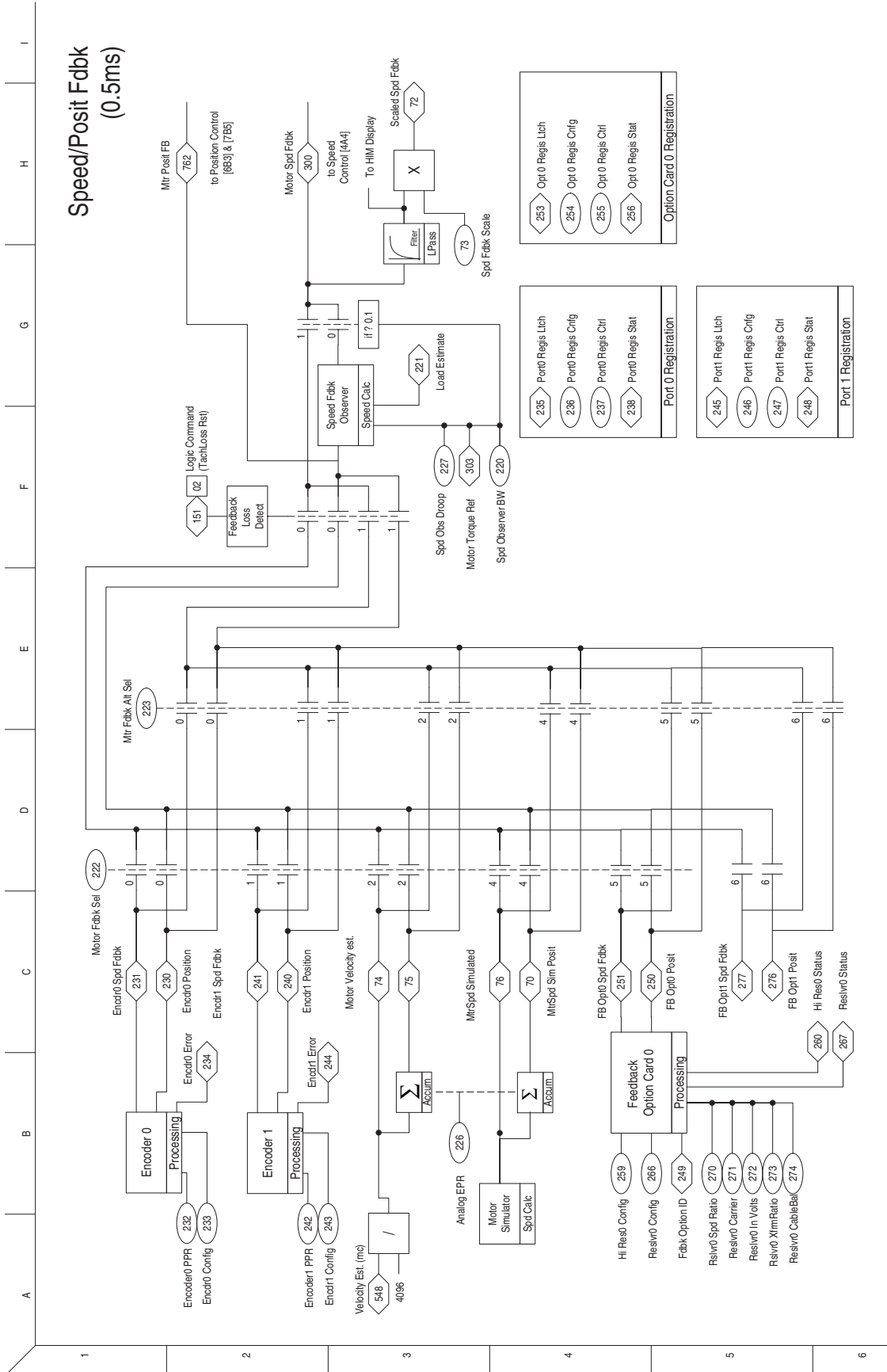


### Torque Control - Current (Task 1)

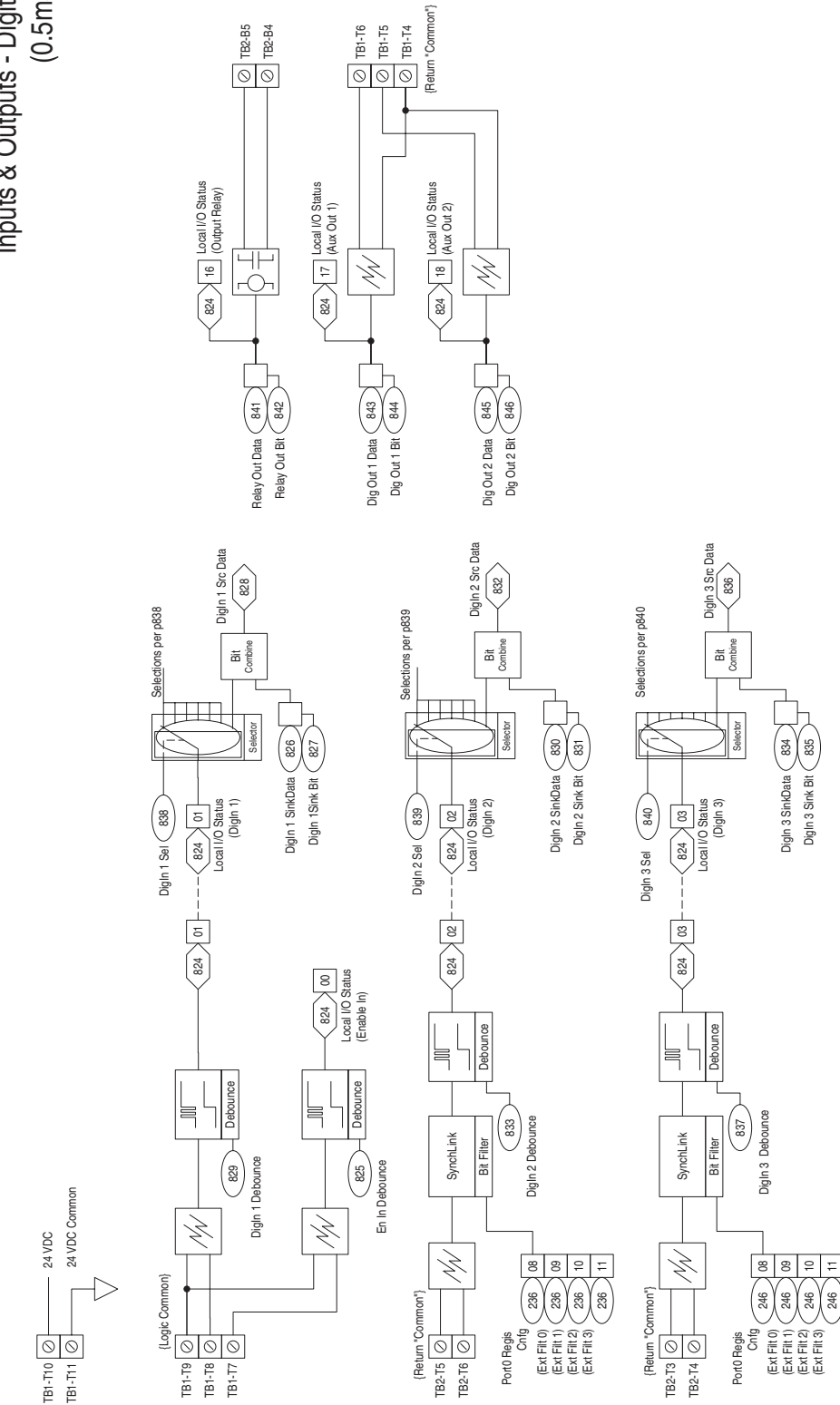


\* Calculated by Autotune (may be overwritten)





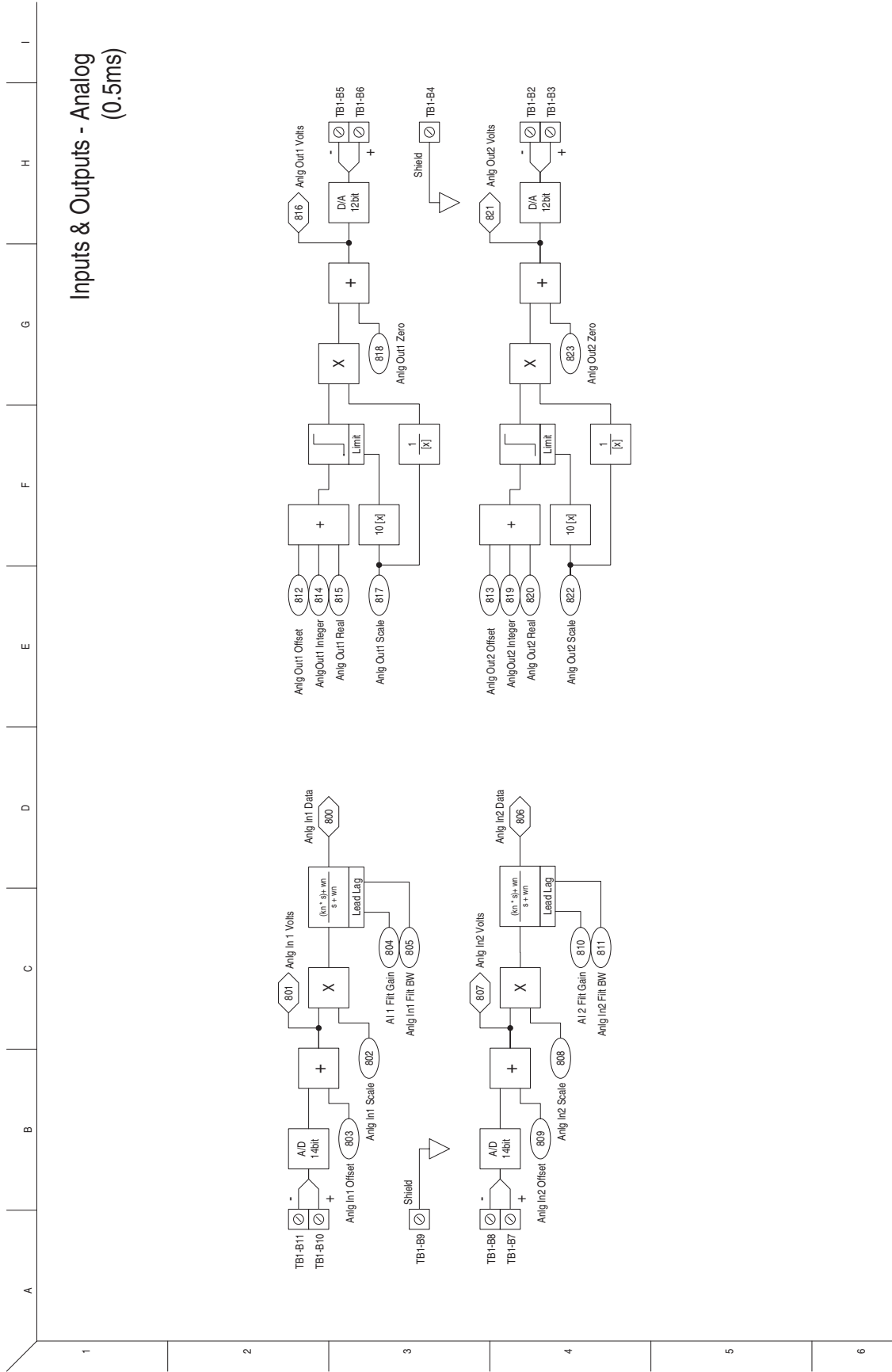
# Inputs & Outputs - Digital (0.5ms)



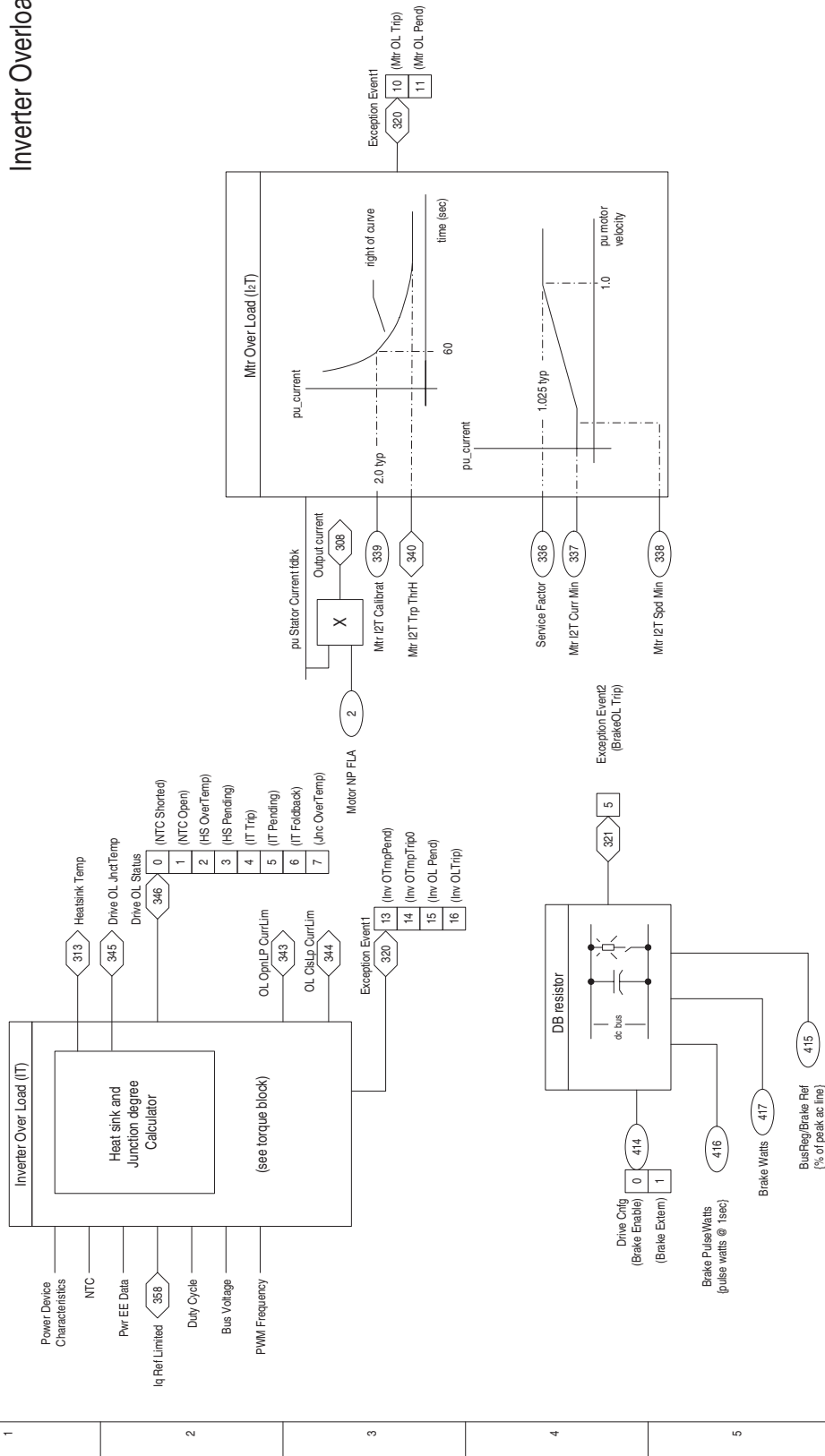
A B C D E F G H I

1 2 3 4 5 6

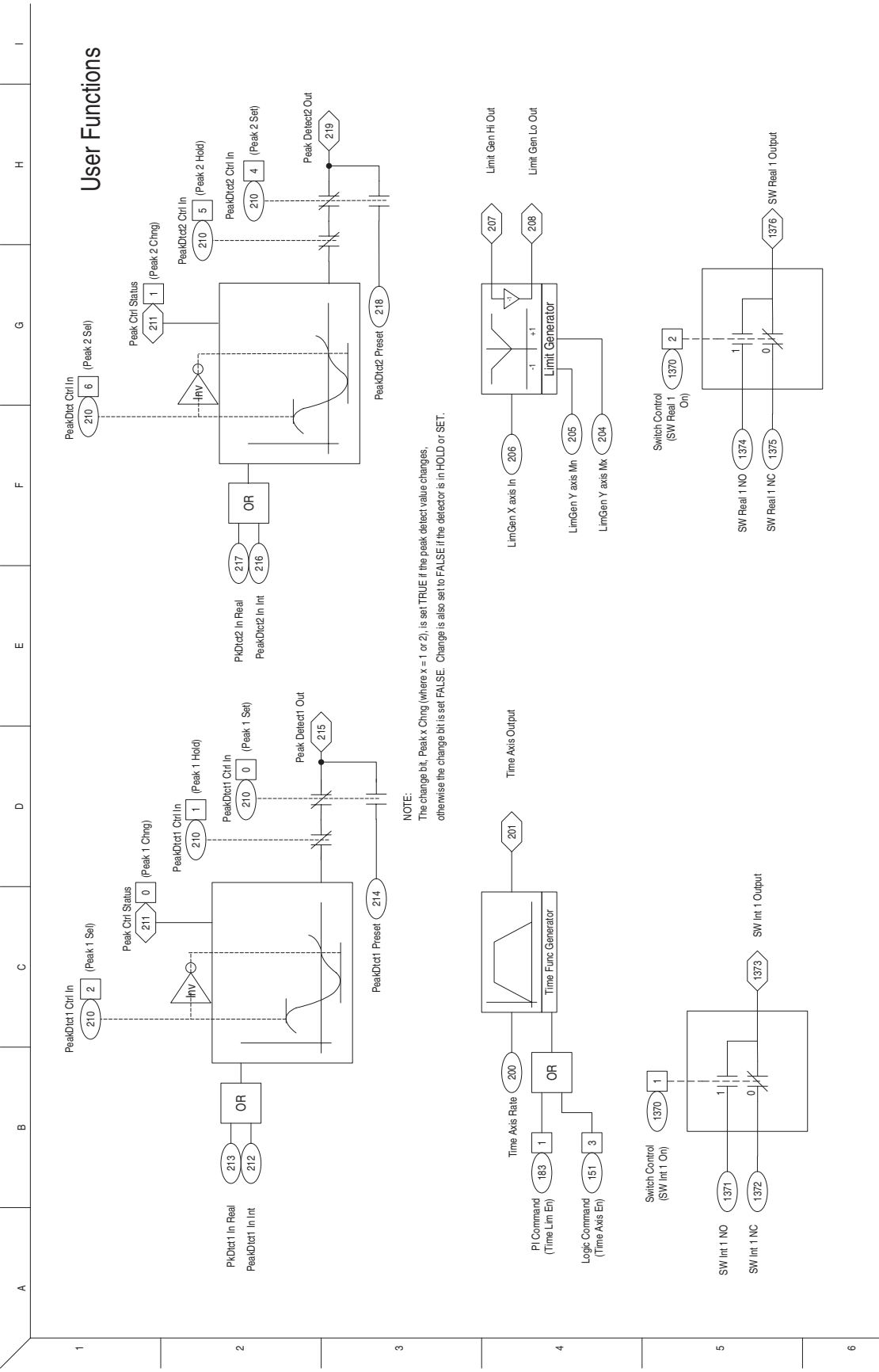
# Inputs & Outputs - Analog (0.5ms)



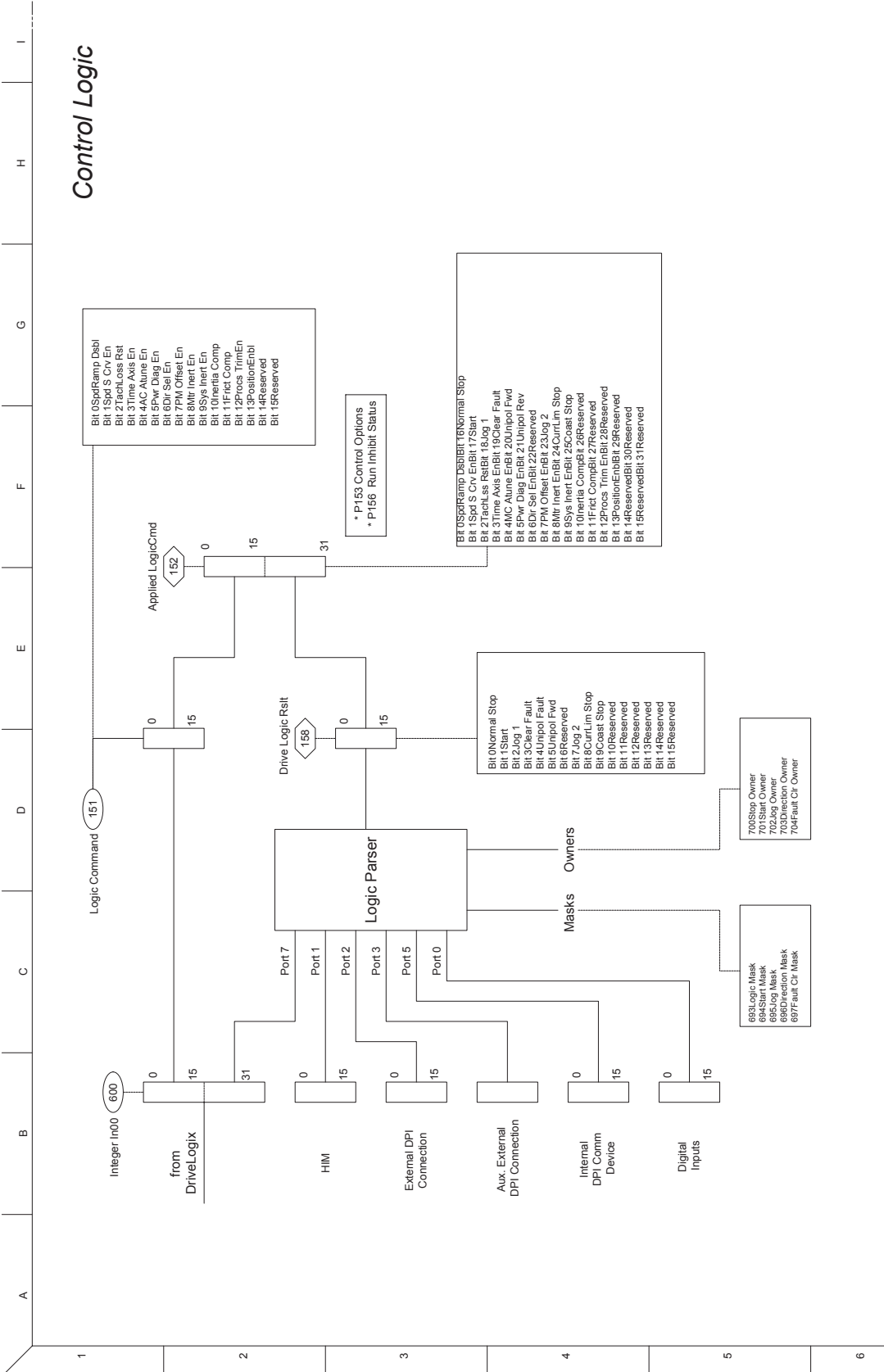
# Inverter Overload IT



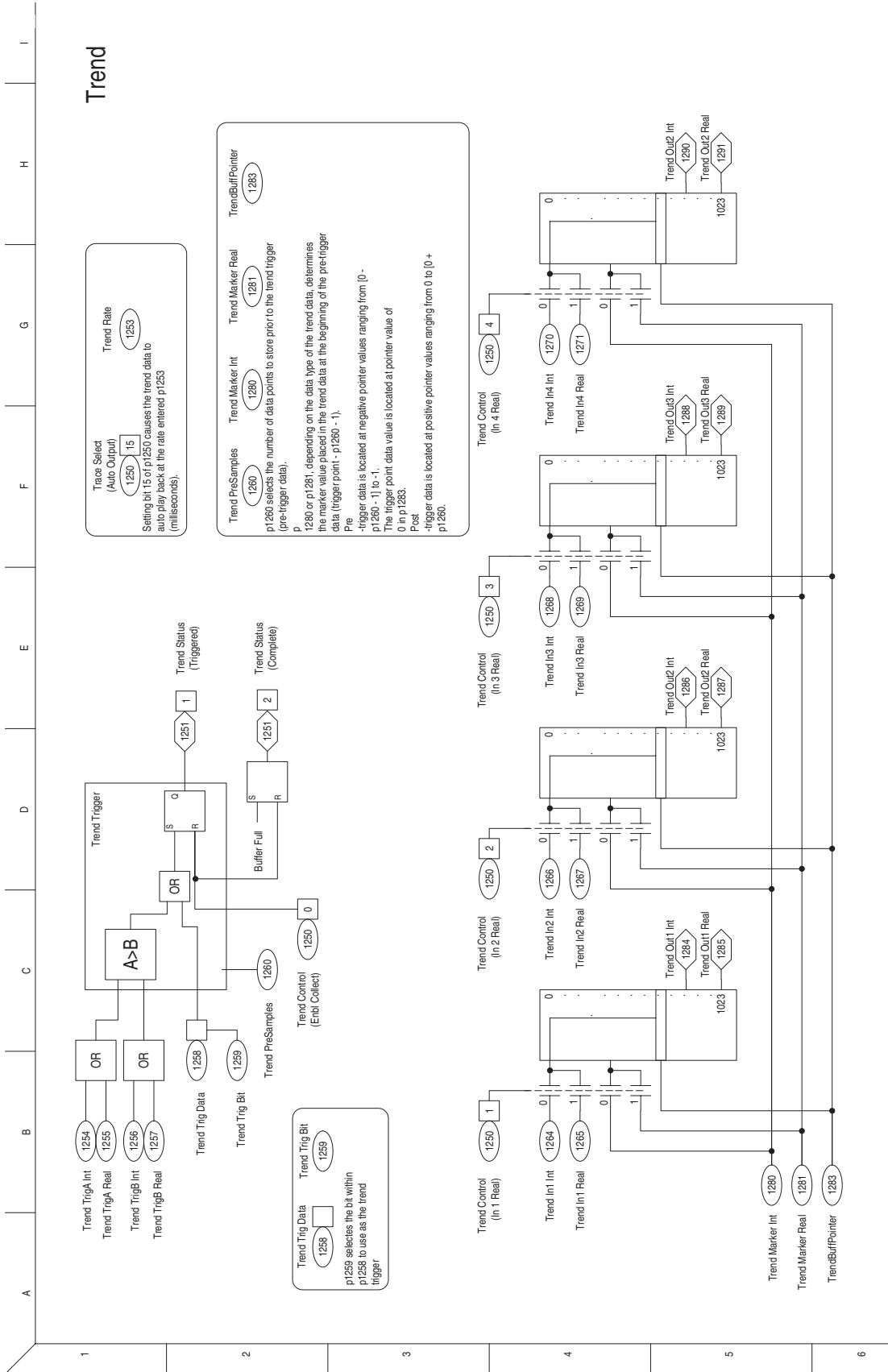




# Control Logic



# Trend





## PowerFlex 700S Stegmann Hi-Resolution Encoder Feedback Option

### Chapter Objectives

For Information on ...	See Page...
<a href="#">Specifications</a>	<a href="#">C-1</a>
<a href="#">Wiring the Stegmann Hi-Resolution Feedback Option Card to an Encoder</a>	<a href="#">C-2</a>

### Specifications

#### Stegmann Hi-Resolution Feedback Option Card Specifications

Consideration	Description
Encoder Voltage Supply	11.5V dc @ 130 mA
Hi-Resolution Feedback	Sine/Cosine 1V P-P Offset 2.5
Maximum Cable Length	90m (295 ft)
Maximum Frequency (Encoder Speed)	12.5 $\mu$ s/cycle (4687.5 RPM for encoders with 1024 sine cycles per revolution) (9375 RPM for encoders with 512 sine cycles per revolution)
RS-485 Interface	The Hi-Resolution Feedback Option card obtains the following information via the Hiperface RS-485 interface shortly after power-up: <ul style="list-style-type: none"> <li>• Address</li> <li>• Command Number</li> <li>• Mode</li> <li>• Number of turns</li> <li>• Number of Sine/Cos cycles</li> <li>• Checksum</li> </ul>
Customer-I/O plug (P1)	Allen-Bradley PN: S94262912 Weidmuller PN: BL3.50/90/12BK

### Supported Encoders

[Table C.A](#) specifies which encoders are supported by the 700S Hi-Resolution Stegmann Encoder Feedback Option module.

**Important:** Please note that encoders must be ordered as "Single Ended". This will ensure that the RS-485 channel has the proper termination network installed at the factory.

**Table C.A Supported Stegmann Encoders**

Model	Resolution	Comment
SINCOS® SCS-60, SCS-70, SCM-60, and SCM-70	512 sine cycles per revolution.	SCM-60 and SCM-70 have built-in mechanical turns counter.
SINCOS® SCS-KIT-101 and SCM-KIT-101	1024 sine cycles per revolution.	SCM-60 and SCM-70 have built-in mechanical turns counter.
SINCOS® SRS-50, SRS-60, SRM-50, and SRM-60	1024 sine cycles per revolution.	SRM-50 and SRM-60 have built-in mechanical turns counter.
SINCOS® SRS/M 25	1024 sine cycles per revolution	SRS25 and SRM25 have built-in mechanical turns counter. IP65 Protection Class. Size 25 square flange mounting.
SINCOS® SRS660	1024 sine cycles per revolution	Hollow-shaft up to 14 mm diameter
SINCOS® SHS-170	512 sine cycles per revolution.	While the software supports this encoder, the SHS-170 draws excessive current and should only be used with an external power supply.

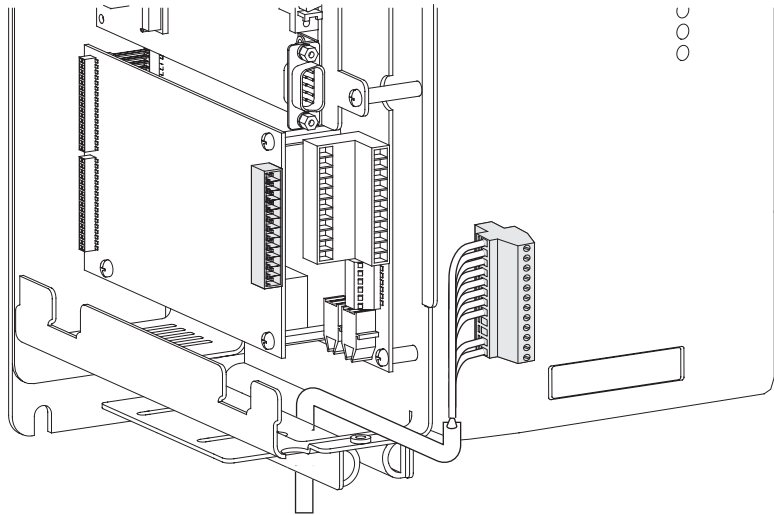
SINCOS®, SINCODER® and LINCODER® are registered trademarks of Stegmann Inc.

### Wiring the Stegmann Hi-Resolution Feedback Option Card to an Encoder

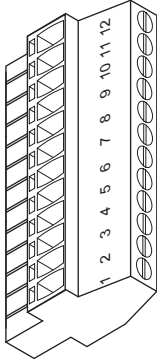
Terminal block P1 contains connection points for a Stegmann Hiperface® encoder. This terminal block resides on the Hi-Resolution Encoder Feedback Option card.

Hiperface® is a registered trademark of Stegmann Inc.

**Figure C.1 Control Assembly Sliding Access Panel**



▶ **TIP:** Remember to route wires through the sliding access panel at the bottom of the Control Assembly.



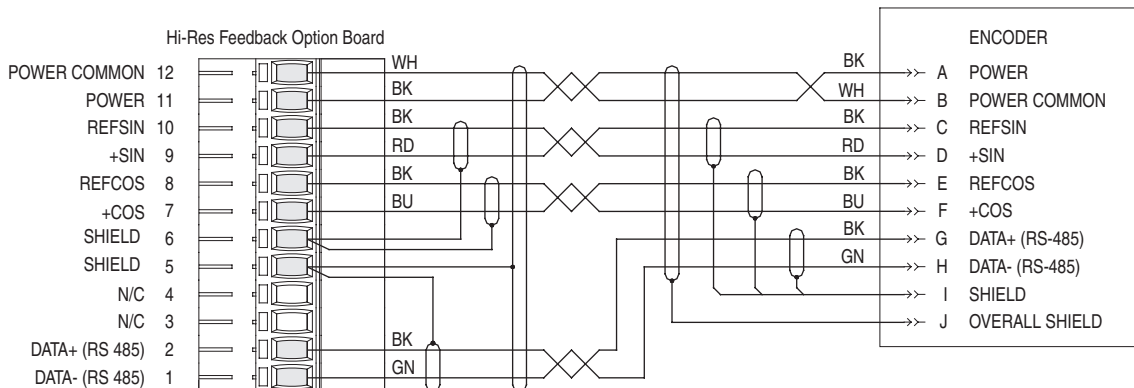
Terminal	Signal	Description
12	POWER COMMON	Power supply for encoder interface.
11	POWER	
10	REFSIN	Negative Sine signal.
9	+SIN	Positive Sine signal.
8	REFCOS	Negative Cosine signal.
7	+COS	Positive Cosine signal.
6	SHIELD	Connection point for encoder cable shield.
5	SHIELD	
4	N/C	Not connected.
3	N/C	
2	DATA+ (RS 485)	Positive DH485 terminal.
1	DATA- (RS 485)	Negative DH485 terminal.

### Recommended Cables

If you are using this motor and feedback device:	Use this cable:	See this wiring diagram:
Allen-Bradley 1326AB-BXXXX-21ML, and -21MKXL motors with embedded Stegmann rotary encoder	Allen-Bradley 1326-CECU-XXL-XXX	<a href="#">Figure C.2 on page C-3</a>
Allen-Bradley 1326AB-BXXXX-M2L, -M2KXL, -S2L, and -S2KXL motors with embedded Stegmann rotary encoder	Allen-Bradley 2090-CDNFDMP-SXX	<a href="#">Figure C.3 on page C-4</a>
Allen-Bradley MP-Series 460V motors with embedded Stegmann rotary encoder	Allen-Bradley 2090-CDNFDMP-SXX or 2090-XXNFMP-SXX	<a href="#">Figure C.3 on page C-4</a>
Allen-Bradley MP-Series 230V motors with embedded Stegmann rotary encoder	Allen-Bradley 2090-UXNFDMP-SXX or 2090-XXNFMP-SXX	<a href="#">Figure C.4 on page C-4</a>
Any other motor with external Stegmann SHS-170 rotary encoder	Stegmann shielded twisted-pair cable with 12-pin DIN style connector	<a href="#">Figure C.5 on page C-4</a>
Any other motor with external Stegmann SCS-60, SCS-70, SCM-60 or SCM-70, SRS-50, SRS-60, SRM-60, SRM-60, SRS-25 or SRM-252 rotary encoder	Stegmann shielded twisted-pair cable with 12-pin DIN style connector or 8-pin Berg style connector	<a href="#">Figure C.5 on page C-4</a> or <a href="#">Figure C.7 on page C-5</a>
Any other motor with external Stegmann SCS-Kit 101 or SCK-Kit 101 rotary encoder	Stegmann shielded twisted-pair cable with 8-pin Berg style connector	<a href="#">Figure C.7 on page C-5</a>
Any other motor with external Stegmann SRS660 rotary encoder	Is available only with pre-attached Stegmann shielded twisted-pair cable of various lengths	<a href="#">Figure C.8 on page C-5</a>

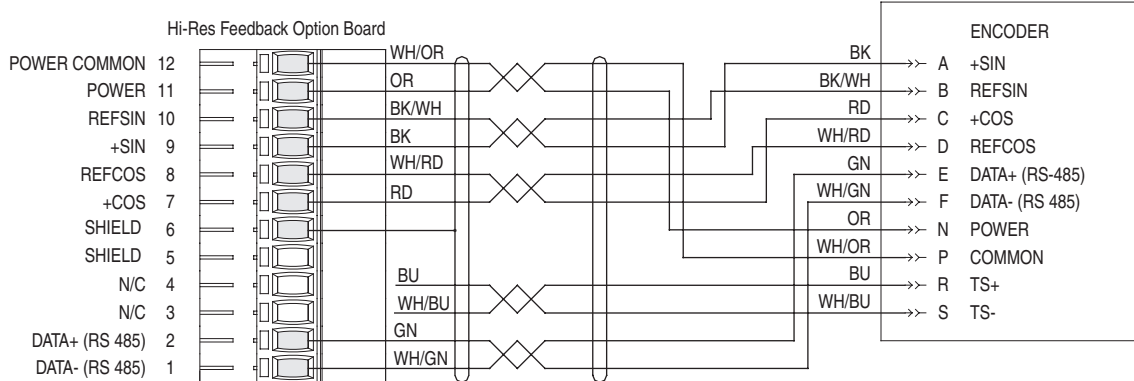
### Connection Examples

Figure C.2 1326-CECU-XXL-XXX cable

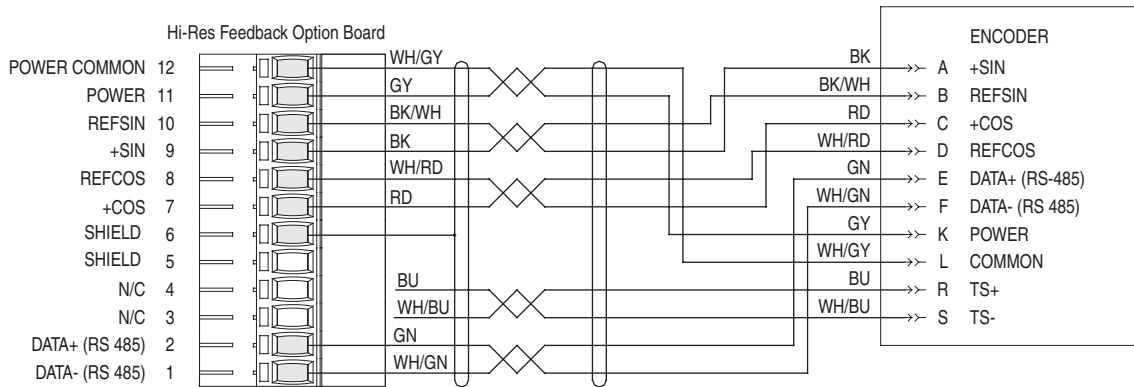


Connection Examples

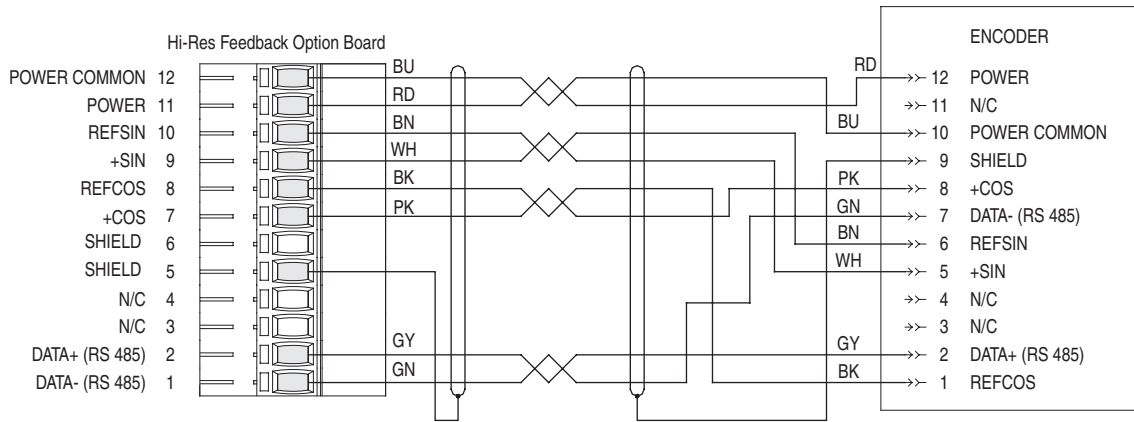
**Figure C.3 460V MP Series Motor with 2090-CDNFDMP-SXX or 2090-XXNFMP-SXX cable; or 1326AB-BXXXX-M2L, -M2KXL, -S2L, and -S2KXL motor with 2090-XXNFMP-SXX cable**



**Figure C.4 230V MP Series Motor with 2090-UXNFDMP-SXX or 2090-XXNFMP-SXX cable**



**Figure C.5 Stegmann shielded twisted-pair cable with 12-pin DIN style connector**





Connection Examples

Figure C.6 Stegmann shielded twisted-pair cable with 10-pin MS style connector

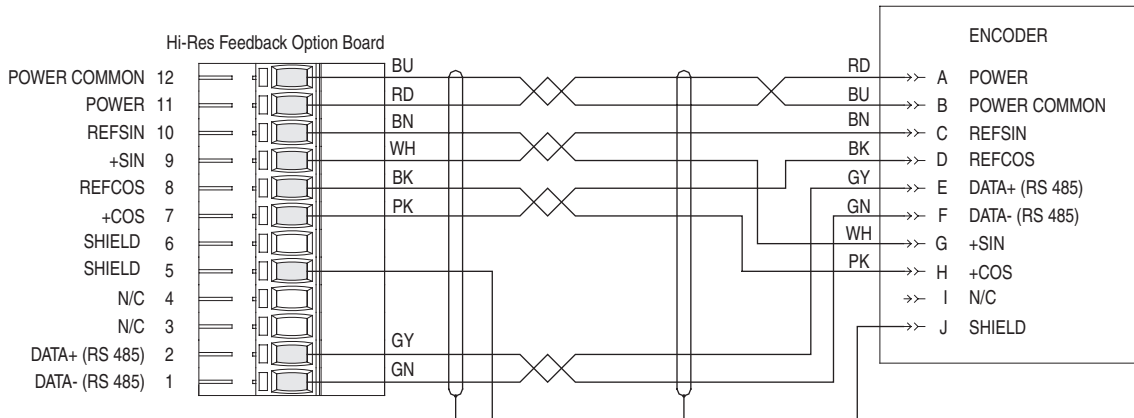


Figure C.7 Stegmann shielded twisted-pair cable with 8-pin Berg style connector

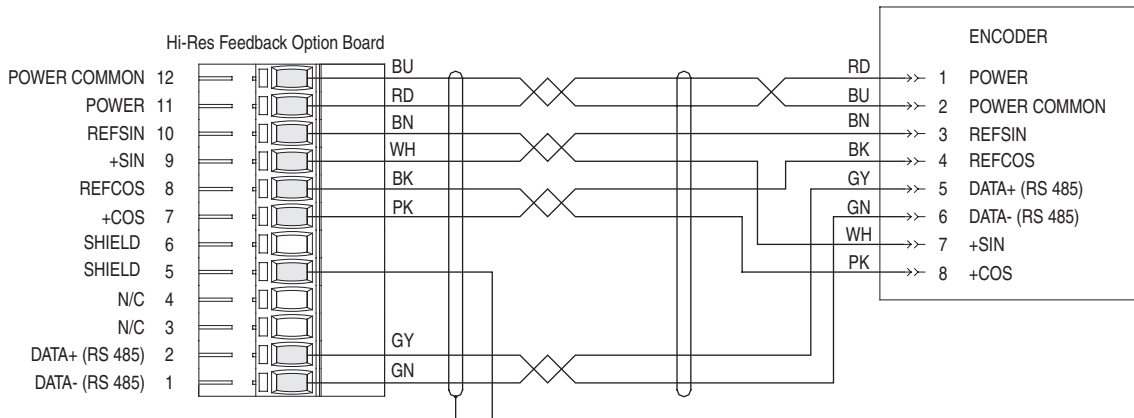
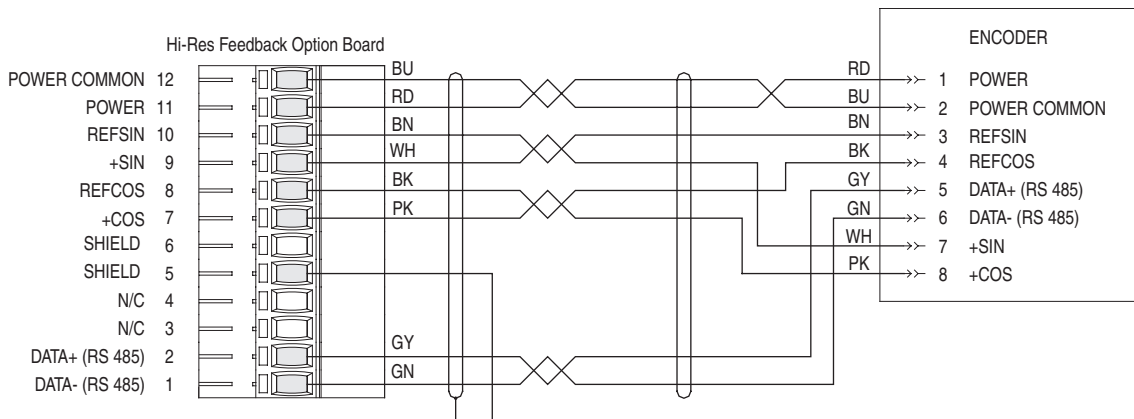


Figure C.8 Stegmann pre-attached shielded twisted-pair cable



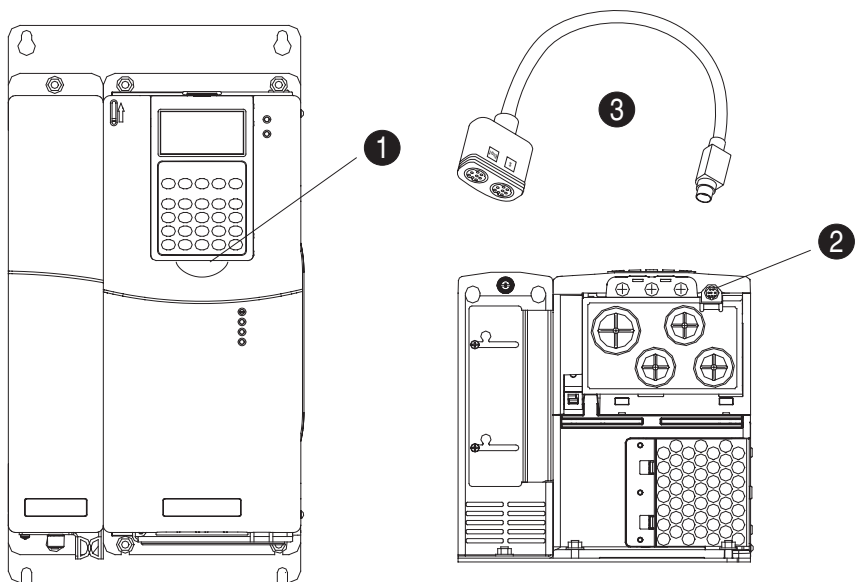


## HIM Overview

For Information on ...	See Page...
<a href="#">External and Internal Connections</a>	<a href="#">D-1</a>
<a href="#">LCD Display Elements</a>	<a href="#">D-2</a>
<a href="#">Removing/Installing the HIM</a>	<a href="#">D-3</a>

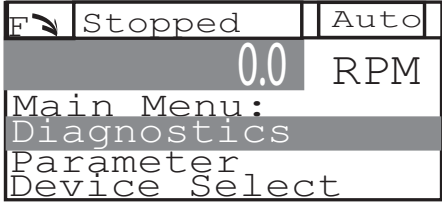
### External and Internal Connections

The PowerFlex 700S provides cable connection for a handheld HIM or Port Expander/Splitter (Frame 1 shown).



No.	Connector	Description
❶	DPI Port 1	HIM connection when installed in cover.
❷	DPI Port 2	Cable connection for handheld and remote options.
❸	DPI Port 3 or 2	Splitter cable connected to DPI Port 2 provides additional port.









## LCD Display Elements

Display	Description					
	<table border="1"> <tr> <td>Direction</td> <td>Drive Status</td> <td>Alarm</td> <td>Auto/Manual</td> <td>Information</td> </tr> </table> <p>Commanded or Output Frequency</p>	Direction	Drive Status	Alarm	Auto/Manual	Information
Direction	Drive Status	Alarm	Auto/Manual	Information		
	Programming / Monitoring / Troubleshooting					


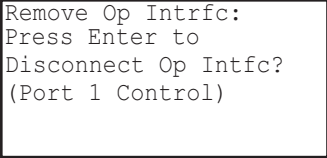
## ALT Functions

To use an ALT function, press the ALT key release it, then press the programming key associated with one of the following functions:

**Table D.A ALT Key Functions**

ALT Key and then...			
		S.M.A.R.T.	Function not available
		View	Allows the selection of how parameters will be viewed or detailed information about a parameter or component.
		Lang	Not Functional at this time
		Auto/Man	Function not available
		Remove	Allows HIM removal without causing a fault if the HIM is not the last controlling device and does not have Manual control of the drive.
		Exp	Allows the value to be entered as an exponent.
		Param #	Allows entry of a parameter number for viewing/editing.

**Removing/Installing the HIM** The HIM can be removed or installed while the drive is powered.

Step	Key(s)	Example Displays
<p>To remove the HIM...</p> <ol style="list-style-type: none"><li>1. Press ALT and then Enter (Remove). The Remove HIM configuration screen appears.</li><li>2. Press Enter to confirm that you want to remove the HIM.</li><li>3. Remove the HIM from the drive.</li></ol> <p>To install HIM...</p> <ol style="list-style-type: none"><li>1. Insert into drive or connect cable.</li></ol>	 The image shows the ALT key (a black circle with 'ALT' in yellow) followed by a plus sign and the Enter key (a blue circle with a white arrow pointing down and to the right).	 A terminal window with a black border containing the text: 'Remove Op Intrfc: Press Enter to Disconnect Op Intfc? (Port 1 Control)'. The text is displayed in a monospaced font.



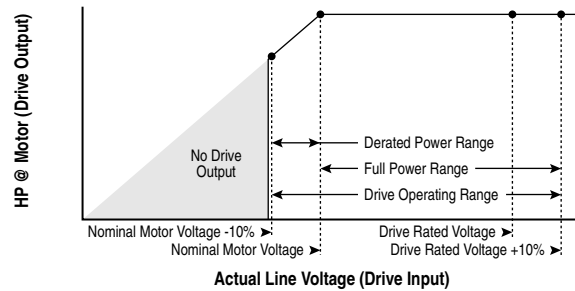
## Application Notes

For Information on ...	See Page...
<a href="#">Motor Overload</a>	<a href="#">E-3</a>
<a href="#">Stop Dwell Time</a>	<a href="#">E-6</a>
<a href="#">Setpt 1 Data</a>	<a href="#">E-7</a>
<a href="#">Setpt 2 Data</a>	<a href="#">E-8</a>
<a href="#">Input Voltage Range/Tolerance</a>	<a href="#">E-1</a>

### Input Voltage Range/ Tolerance

Drive Rating	Nominal Line Voltage	Nominal Motor Voltage	Drive Full Power Range	Drive Operating Range
200-240	200	200†	200-264	180-264
	208	208	208-264	
	240	230	230-264	
380-400	380	380†	380-528	342-528
	400	400	400-528	
	480	460	460-528	
500-600 (Frames 1-4 Only)	600	575†	575-660	432-660
500-690 (Frames 5 & 6 Only)	600	575†	575-660	475-759
	690	690	690-759	475-759

Drive Full Power Range =	Nominal Motor Voltage to Drive Rated Voltage + 10%. Rated current is available across the entire Drive Full Power Range
Drive Operating Range =	Lowest† Nominal Motor Voltage - 10% to Drive Rated Voltage + 10%. Drive Output is linearly derated when Actual Line Voltage is less than the Nominal Motor Voltage

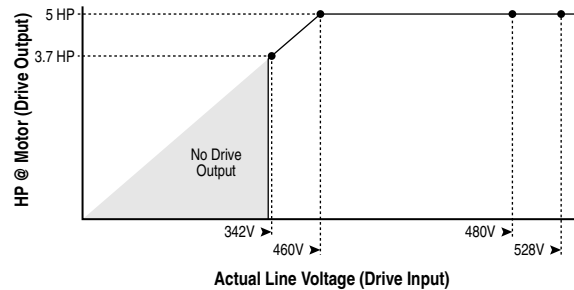


### Example:

Calculate the maximum power of a 5 HP, 460V motor connected to a 480V rated drive supplied with 342V Actual Line Voltage input.

- Actual Line Voltage / Nominal Motor Voltage = 74.3%
- $74.3\% \times 5 \text{ HP} = 3.7 \text{ HP}$
- $74.3\% \times 60 \text{ Hz} = 44.6 \text{ Hz}$

At 342V Actual Line Voltage, the maximum power the 5 HP, 460V motor can produce is 3.7 HP at 44.6 Hz.



## Motor Control Technology

Within the PowerFlex family there are several motor control technologies:

- Torque Producers
- Torque Controllers
- Speed Regulators

### Torque Producers

#### Volts/Hertz

This technology follows a specific pattern of voltage and frequency output to the motor, regardless of the motor being used. The shape of the V/Hz curve can be controlled a limited amount, but once the shape is determined, the drive output is fixed to those values. Given the fixed values, each motor will react based on its own speed/torque characteristics.

This technology is good for basic centrifugal fan/pump operation and for most multi-motor applications. Torque production is generally good.

#### Sensorless Vector

This technology combines the basic Volts/Hertz concept with known motor parameters such as Rated FLA, HP, Voltage, stator resistance and flux producing current. Knowledge of the individual motor attached to the drive allows the drive to adjust the output pattern to the motor and load conditions. By identifying motor parameters, the drive can maximize the torque produced in the motor and extend the speed range at which that torque can be produced.

This technology is excellent for applications that require a wider speed range and applications that need maximum possible torque for breakaway, acceleration or overload. Centrifuges, extruders, conveyors and others are candidates.



## Torque Controllers

### Vector

This technology differs from the two above, because it actually controls or regulates torque. Rather than allowing the motor and load to actually determine the amount of torque produced, Vector technology allows the drive to regulate the torque to a defined value. By independently identifying and controlling both flux and torque currents in the motor, true control of torque is achieved. High bandwidth current regulators remain active with or without encoder feedback to produce outstanding results.

This technology is excellent for those applications where torque control, rather than mere torque production, is key to the success of the process. These include web handling, demanding extruders and lifting applications such as hoists or material handling.

Vector Control can operate in one of two configurations:

#### 1. Encoderless

Not to be confused with Sensorless Vector above, Encoderless Vector based on Allen-Bradley's patented Field Oriented Control technology means that a feedback device is not required. Torque control can be achieved across a significant speed range without feedback.

#### 2. Closed Loop (with Encoder)



Vector Control with encoder feedback utilizes Allen-Bradley's Force Technology™. This industry leading technology allows the drive to control torque over the entire speed range, including zero speed. For those applications that require smooth torque regulation at very low speeds or full torque at zero speed, Closed Loop Vector Control is the answer.

## Speed Regulators

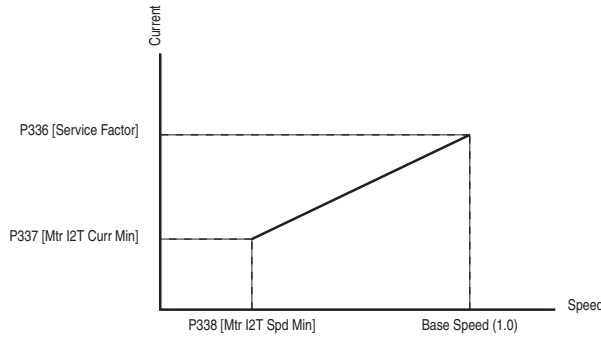
Any of the PowerFlex drives, regardless of their motor control technology (Volts/Hz, Sensorless Vector or Vector) can be set up to regulate speed. Speed regulation and torque regulation must be separated to understand drive operation.

## Motor Overload

### Mtr I2T Spd Min

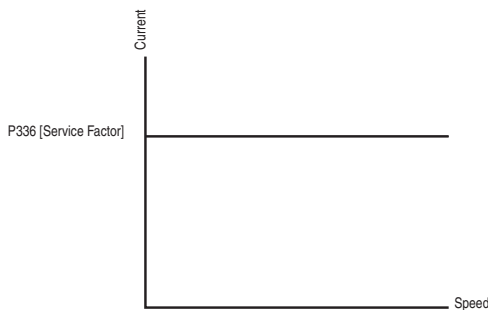
Sets the minimum speed for the motor overload ( $I^2T$ ) function. The value indicates minimum speed below the minimum current threshold [Mtr I2T Curr Min], and these are the first current/speed breakpoint. From this point the current threshold is linear to the value specified by the motor service factor [Service Factor].

**Figure E.1 Motor Overload Curve With Parameter 338 [Mtr I2T Spd Min] Is Less Than 1.0**



When motor current exceeds the value of the curve, Mtr OL Output integrates. A motor overload exception event occurs when the value in Mtr OL Output reaches 1.0. The value of Mtr OL Output is visible in parameter 330 [Fault TP Data] when the value of parameter 329 [Fault TP Sel] equals 13.

**Figure E.2 Motor Overload Curve With Parameter 338 [Mtr I2T Spd Min] Is Equal To 1.0**



When the value of parameter 338 [Mtr I2T Spd Min] equals 1.0, the curve is flat - at the value of rated motor current times the value of parameter 336 [Service Factor]. If motor current exceeds the value of the curve, the value of Mtr OL Output integrates. The value of Mtr OL Output is visible in parameter 330 [Fault TP Data] when the value of parameter 329 [Fault TP Sel] equals 13.

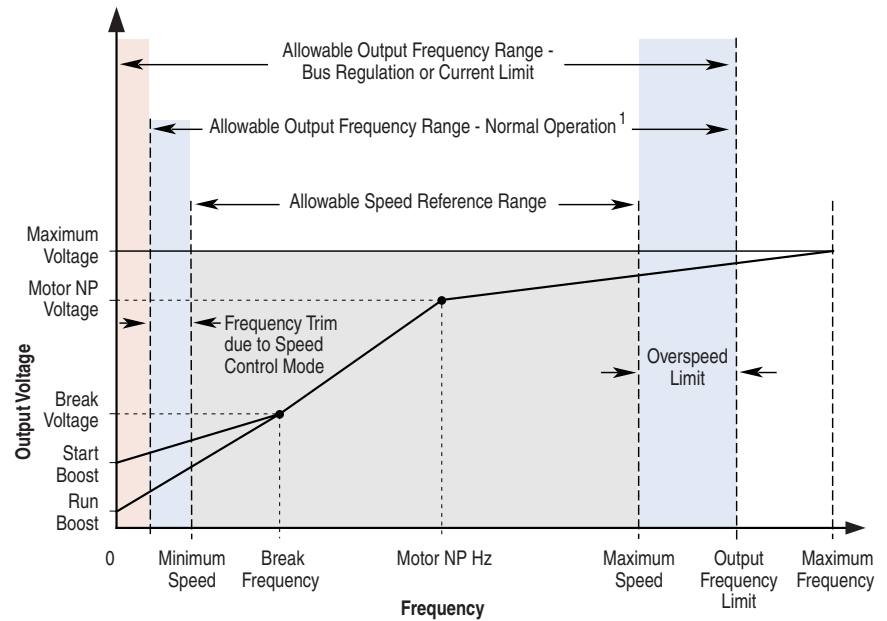
## Overspeed

Overspeed Limit is a user programmable value that allows operation at maximum speed, but also provides an “overspeed band” that will allow a speed regulator such as encoder feedback or slip compensation to increase the output frequency above maximum speed in order to maintain maximum motor speed.

The figure below illustrates a typical Custom V/Hz profile. Minimum Speed is entered in Hertz and determines the lower speed reference limit during normal operation. Maximum Speed is entered in Hertz and determines the upper speed reference limit. The two “Speed” parameters only limit the speed reference and not the output frequency.

The actual output frequency at maximum speed reference is the sum of the speed reference plus “speed adder” components from functions such as slip compensation.

The Overspeed Limit is entered in Hertz and added to Maximum Speed and the sum of the two (Speed Limit) limit the output frequency. This sum (Speed Limit) must be compared to Maximum Frequency and an alarm is initiated which prevents operation if the Speed Limit exceeds Maximum Frequency.



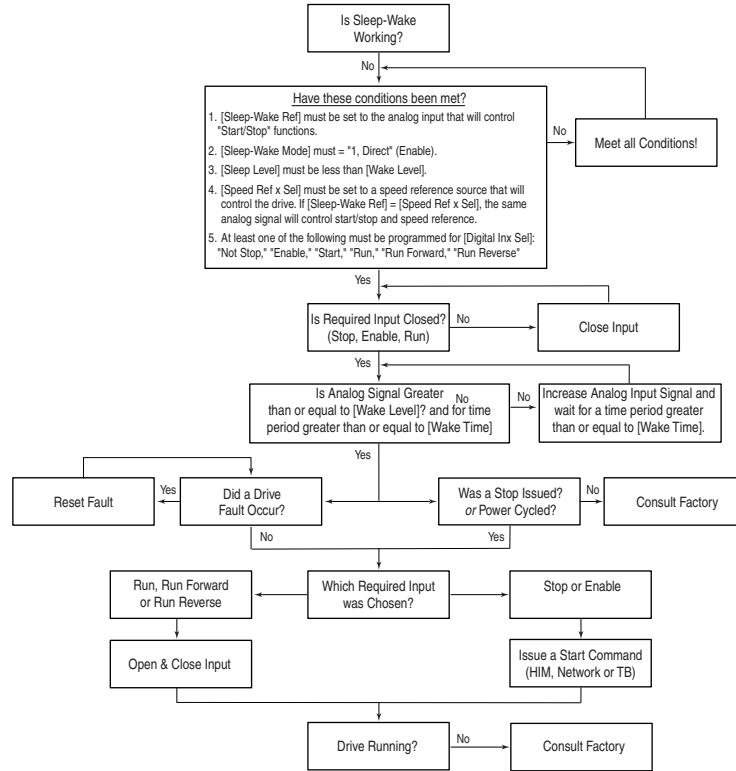
Note 1: The lower limit on this range can be 0 depending on the value of Speed Adder

## Sleep Wake Mode

This function stops (sleep) and starts (wake) the drive based on separately configurable analog input levels rather than discrete start and stop signals. The drive will start (wake) when an analog signal is greater than or equal to the user specified [Wake Level], and stop the drive when an analog signal is less than or equal to the user specified [Sleep Level].

### Definitions

- Wake - A start command generated when the analog input value remains above [Wake Level] for a time greater than [Wake Time].
- Sleep - A Stop command generated when the analog input value remains below [Sleep Level] for a time greater than [Sleep Time].
- Speed Reference – The active speed command to the drive as selected by drive logic and [Speed Ref x Sel].
- Start Command - A command generated by pressing the Start button on the HIM, closing a digital input programmed for Start, Run, Run Forward or Run Reverse.

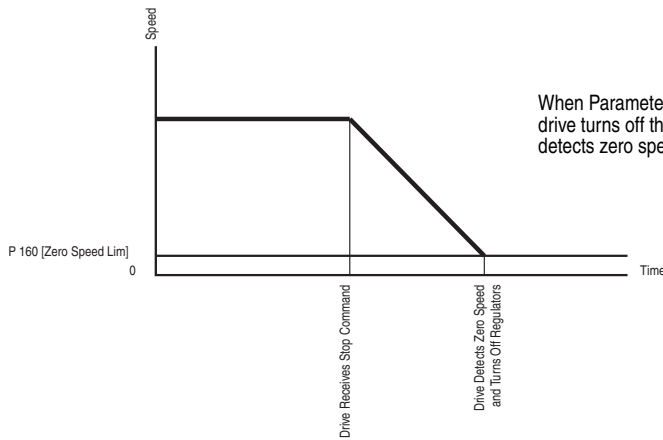


## Stop Dwell Time

Sets an adjustable delay time between detecting zero speed and disabling the speed and torque regulators, when responding to a stop command.

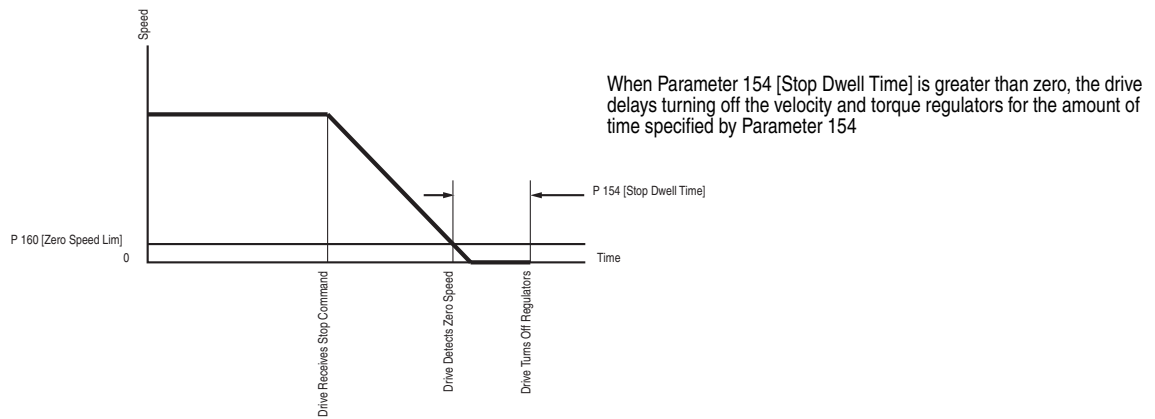
**Important:** Consult industry and local codes when setting the value of this parameter.

**Figure E.3 Drive Operation When Parameter 154 [Stop Dwell Time] Equals Zero**



When Parameter 154 [Stop Dwell Time] equals zero, the drive turns off the velocity and torque regulators when it detects zero speed.

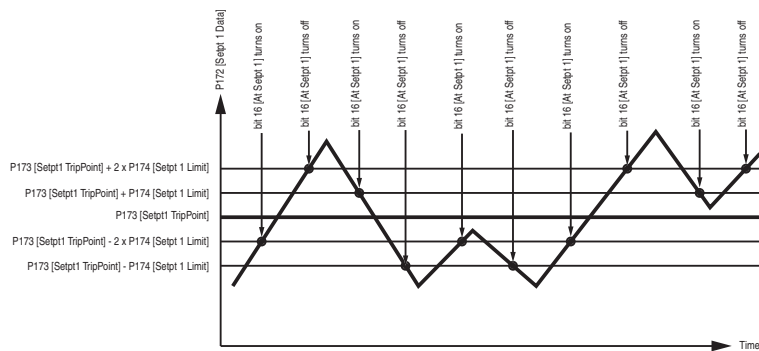
**Figure E.4 Drive Operation When Parameter 154 [Stop Dwell Time] Equals Zero**



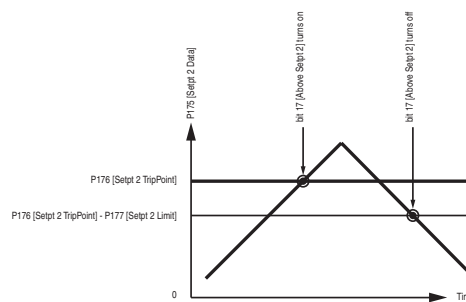
**Setpt 1 Data**

Provides data for comparison to Parameter 173 [Setpt1 TripPoint], driving bit 16 [At Setpt 1] of Parameter 155 [Logic Status].

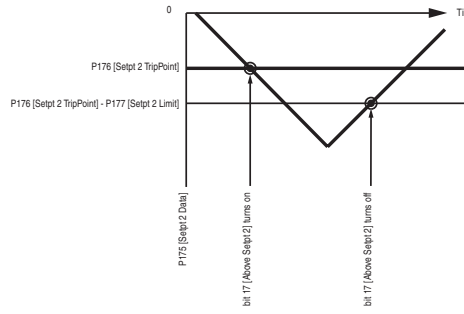
**Figure E.5 Detector 1 - Positive Set Mode (Bit 0 [Peak 1 Set] and 2 [Peak 1 Sel] On)**



**Figure E.6 Detector 2 - Positive Level Detection with Parameter 176 [Setpt 2 TripPoint] Greater Than Zero**



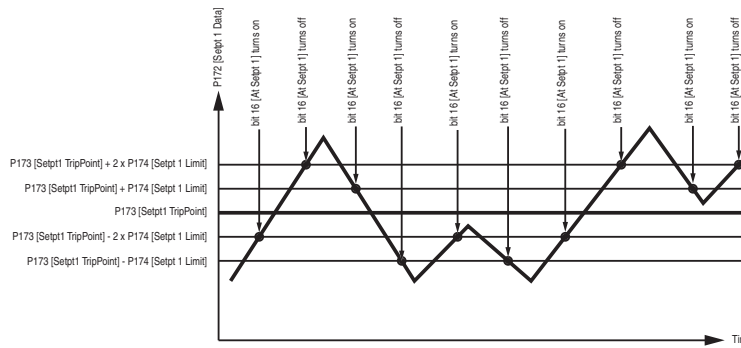
**Figure E.7 Detector 2 - Negative Level Detection with Parameter 176 [Setpt 2 TripPoint] Less Than Zero**



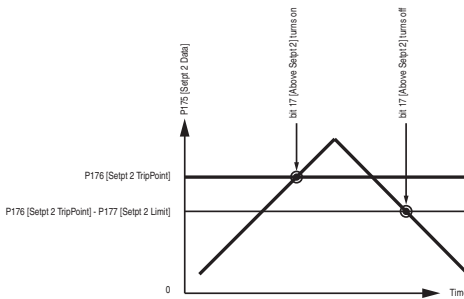
**Setpt 2 Data**

Provides data for comparison to Parameter 177 [Setpt2 TripPoint], driving bit 17 [Above Setpt 2] of Parameter 155 [Logic Status].

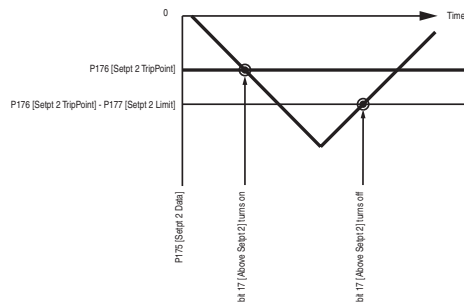
**Figure E.8 Detector 1 - Positive Set Mode (Bit 0 [Peak 1 Set] and 2 [Peak 1 Sel] On)**



**Figure E.9 Detector 2 - Positive Level Detection with Parameter 176 [Setpt 2 TripPoint] Greater Than Zero**



**Figure E.10 Detector 2 - Negative Level Detection with Parameter 176 [Setpt 2 TripPoint] Less Than Zero**









## PowerFlex 700S Resolver Feedback Option Card

### Chapter Objectives

For Information on ...	See Page...
<a href="#">Chapter Objectives</a>	<a href="#">F-1</a>
<a href="#">Specifications</a>	<a href="#">F-1</a>

### Specifications

#### Resolver Feedback Option Card Specifications

Consideration	Description
Excitation Frequency	2400 Hz
Excitation Voltage	26 Vrms
Resolver Feedback Voltage	2 Vrms +/- 300 mV
Customer-I/O plug (P1)	Allen-Bradley PN: S94262908 Weidmuller PN: BL3.50/90/8BK

### Compatible Resolvers

[Table G](#) specifies which resolvers are supported by the 700S Resolver Feedback Option module.

**Table G Compatible Resolvers.**

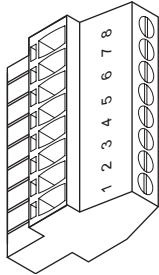
Manufacturer	Manufacturer Catalog Number	Notes
Tamagawa	TS-2014N181E32	x 1, flange-mounted enclosure
Tamagawa	TS-2014N182E32	x 2, flange-mounted enclosure
Tamagawa	TS-2014N185E32	x 5, flange-mounted enclosure
Tamagawa	TS-2087N12E9	x 2, HD foot-mounted enclosure, double shaft
Tamagawa	TS-2087N1E9	x 1, HD foot-mounted enclosure
Tamagawa	TS-2087N2E9	x 2, HD foot-mounted enclosure
Tamagawa	TS-2087N5E9	x 5, HD foot-mounted enclosure
Tamagawa	TS-2087N11E9	x 1, HD foot-mounted enclosure, double shaft
Advanced Micro Controls Inc. (AMCI)	R11X-C10/7	

Allen-Bradley servo motors may be ordered with factory installed resolvers. [Table H](#) specifies which factory installed resolvers are supported by the 700S Resolver Feedback Option module.

**Table H Compatibility with Resolvers on Allen-Bradley Motors**

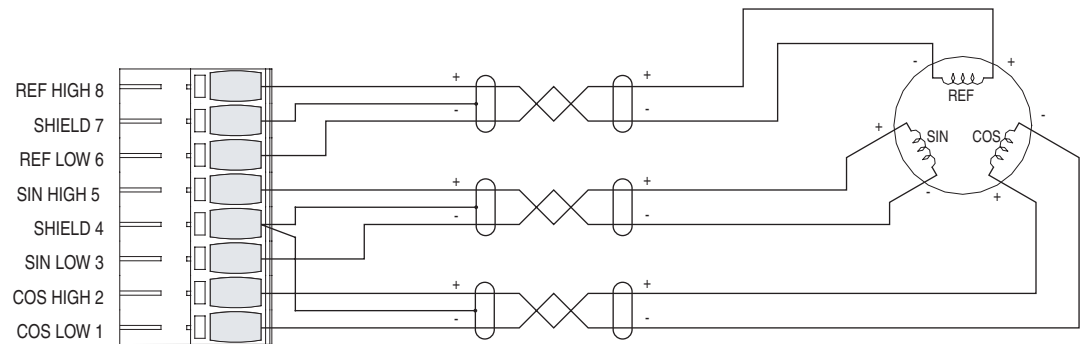
Motor / Resolver Type	Compatible	Notes
1326 AB 230V Primary Resolver	No	Receiver type - not supported
1326 AB 230V Secondary Resolver	Yes	Transmitter type - supported Secondary resolver is geared to motor - not intended for motor speed / position feedback
1326 AB 460V Primary Resolver	Yes	Transmitter type - supported
1326 AB 460V Secondary Resolver	Yes	Transmitter type - supported Secondary resolver is geared to motor - not intended for motor speed / position feedback
1326AD 230V Rare Earth	No	Receiver type - not supported
1326AH 460V Explosion Proof Motor Primary Resolver	Yes	Transmitter type - supported
1326AH 460V Explosion Proof Motor Secondary Resolver	Yes	Transmitter type - supported Secondary resolver is geared to motor - not intended for motor speed / position feedback
1326AS 460V Rare Earth	Yes	Transmitter type - supported
MPL 460V	Yes	Transmitter type - supported

**Wiring the Resolver Feedback Option Card to a Resolver**

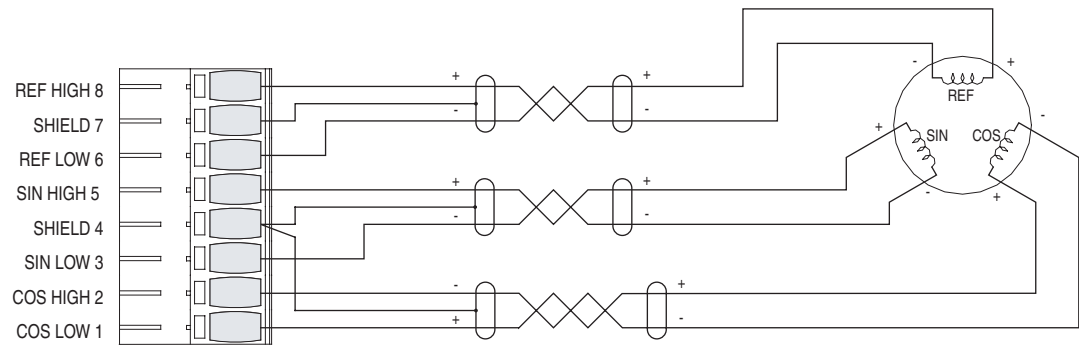
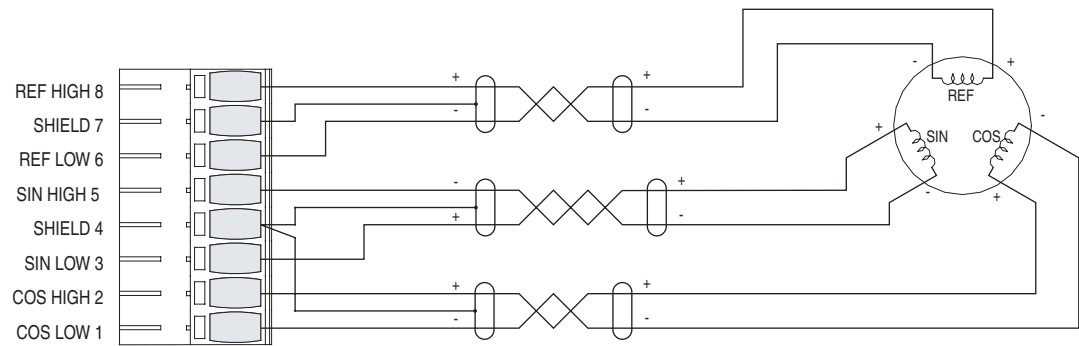
	Terminal	Signal	Description
	8	REF HIGH	Positive Reference signal
	7	SHIELD	Connection point for resolver cable shield
	6	REF LOW	Negative Reference signal
	5	SIN HIGH	Positive Sine signal
	4	SHIELD	Connection point for resolver cable shield
	3	SIN LOW	Negative Sine signal
	2	COS HIGH	Positive Cosine signal
	1	COS LOW	Negative Cosine signal

**Connection Examples**

Resolver Interface - Clockwise Rotation = Count Up



Resolver Interface - Clockwise Rotation = Count Down (Reverse Polarity of Sine or Cosine Signals)





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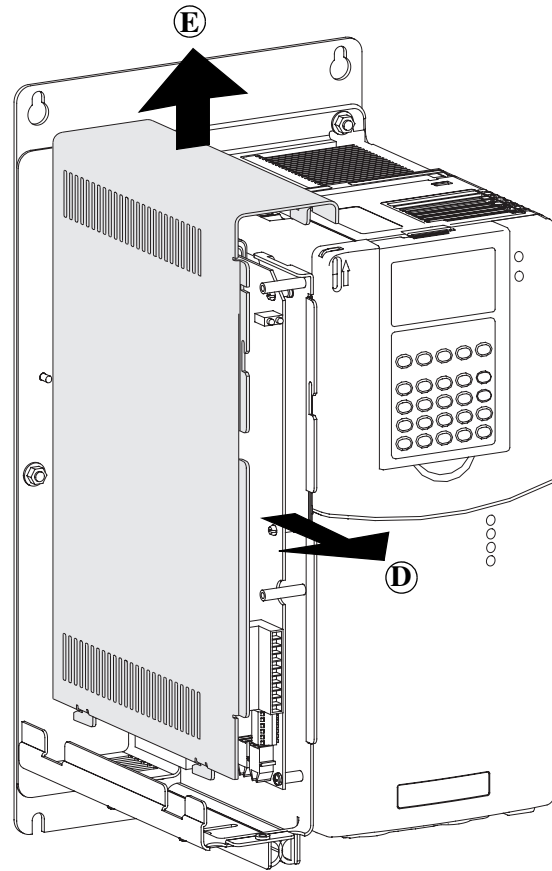
## Access Procedures

### Using this Appendix

For information about:	See page
<a href="#">Removing Cover(s)</a>	<a href="#">G-1</a>
<a href="#">Replacing Cover(s)</a>	<a href="#">G-3</a>

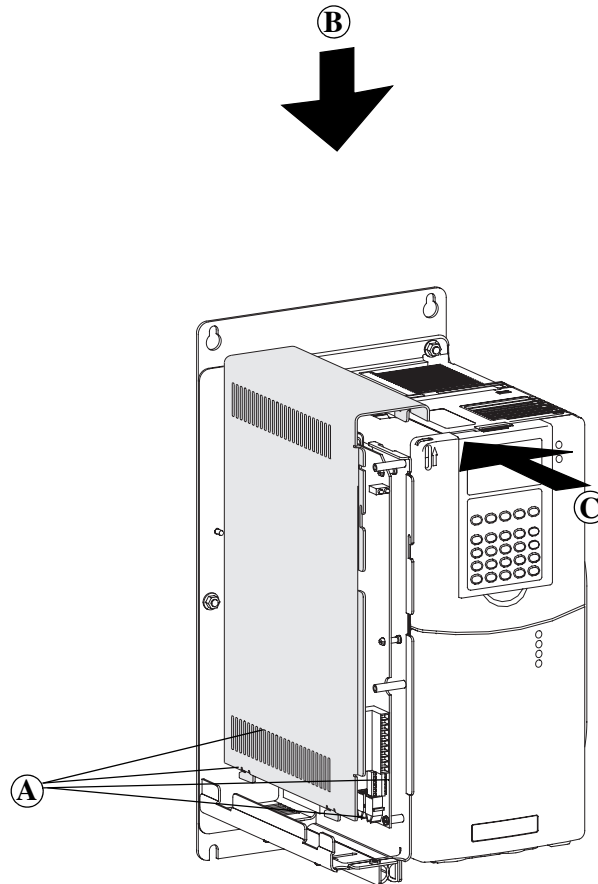
### Removing Cover(s)

Task	Description
Ⓐ	Loosen captive screw
Ⓑ	Push down on front cover
Ⓒ	Pull front cover away from assembly
Ⓓ	Pull side cover forward
Ⓔ	Lift side cover off of control assembly

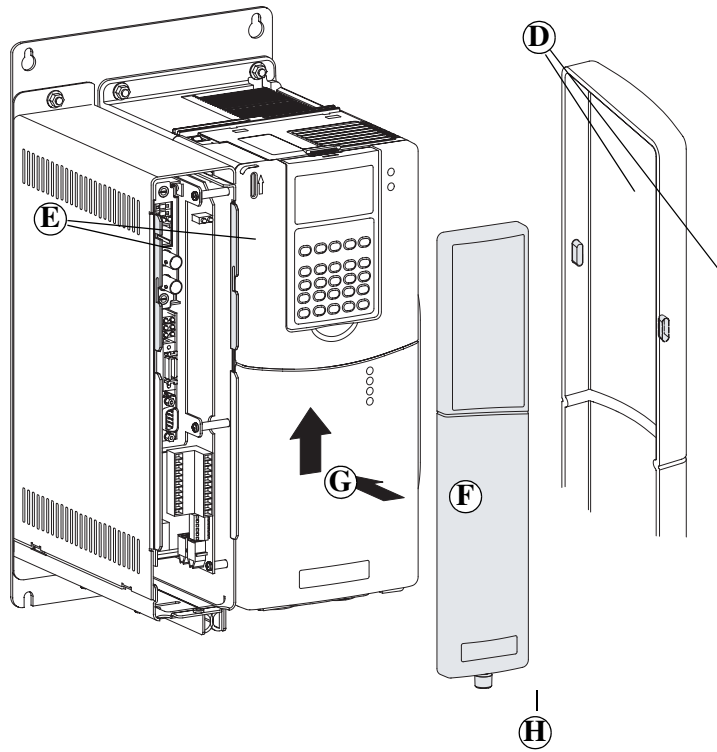


## Replacing Cover(s)

Task	Description
Ⓐ	Align tabs on side cover with slots on drive
Ⓑ	Push side cover down onto control assembly
Ⓒ	Push side cover back onto control assembly



Task	Description
Ⓓ	Locate tabs on inside of front cover
Ⓔ	Align tabs on front cover with slots on flanges
Ⓕ	Push front cover onto drive
Ⓖ	Push front cover up into slots
Ⓗ	Tighten captive screw





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[www.rockwellautomation.com](http://www.rockwellautomation.com)

**Corporate Headquarters**

Rockwell Automation, 777 East Wisconsin Avenue, Suite 1400, Milwaukee, WI, 53202-5302 USA, Tel: (1) 414.212.5200, Fax: (1) 414.212.5201

**Headquarters for Allen-Bradley Products, Rockwell Software Products and Global Manufacturing Solutions**

Americas: Rockwell Automation, 1201 South Second Street, Milwaukee, WI 53204-2496 USA, Tel: (1) 414.382.2000, Fax: (1) 414.382.4444  
Europe/Middle East/Africa: Rockwell Automation SA/NV, Vorstlaan/Boulevard du Souverain 36, 1170 Brussels, Belgium, Tel: (32) 2 663 0600, Fax: (32) 2 663 0640  
Asia Pacific: Rockwell Automation, 27/F Citicorp Centre, 18 Whitfield Road, Causeway Bay, Hong Kong, Tel: (852) 2887 4788, Fax: (852) 2508 1846

**Headquarters for Dodge and Reliance Electric Products**

Americas: Rockwell Automation, 6040 Ponders Court, Greenville, SC 29615-4617 USA, Tel: (1) 864.297.4800, Fax: (1) 864.281.2433  
Europe/Middle East/Africa: Rockwell Automation, Brühlstraße 22, D-74834 Eitztal-Dallau, Germany, Tel: (49) 6261 9410, Fax: (49) 6261 17741  
Asia Pacific: Rockwell Automation, 55 Newton Road, #11-01/02 Revenue House, Singapore 307987, Tel: (65) 6356-9077, Fax: (65) 6356-9011

**U.S. Allen-Bradley Drives Technical Support**

Tel: (1) 262.512.8176, Fax: (1) 262.512.2222, Email: [support@drives.ra.rockwell.com](mailto:support@drives.ra.rockwell.com), Online: [www.ab.com/support/abdrives](http://www.ab.com/support/abdrives)

Publication 20D-UM001E-EN-P – August, 2004  
Supersedes 20D-UM001D-EN-P - May, 2003