Firmware manual ACS880 spinning and traverse control program (option +N5500)





List of related manuals

Drive hardware manuals	Code (English)
ACS880-01 drives hardware manual	3AUA0000078093
ACS880-04 drive modules (200 to 560 kW, 300 to 700 hp)	3AUA0000128301
hardware manual	
ACS880-04XT drive module packages (500 to 1200 kW)	3AXD50000025169
hardware manual	
ACS880-04 single drive module packages hardware	3AUA0000138495
manual	57670000130430
	24114.0000105718
ACS880-07 drives (45 to 710 kW, 50 to 700 hp) hardware	3AUA0000105718
manual	
ACS880-07 drives (560 to 2800 kW) hardware manual	3AUA0000143261
ACS880-14 and -34 single drive module packages	3AXD50000022021
hardware manual	
ACS880-104 inverter modules hardware manual	3AUA0000104271
ACS880-107 inverter units hardware manual	3AUA0000102519
Drive firmware manuals and guides	
	24//4000085067
ACS880 primary control program firmware manual	3AUA0000085967
ACS880 drives with primary control program, quick start-up	3AUA0000098062
guide	
Adaptive programming application guide	3AXD50000028574
Drive (IEC 61131-3) application programming manual	3AUA0000127808

Option manuals and guides

ACX-AP-x assistant control panels user's manual	3AUA0000085685
	3AUA0000094606
manual	
Manuals and quick guides for I/O extension modules,	
fieldbus adapters, encoder interfaces, etc.	
Cybersecurity for ABB drives Technical guide	3AXD10000492137

You can find manuals and other product documents in PDF format on the Internet. See section *Document library on the Internet* on the inside of the back cover. For manuals not available in the Document library, contact your local ABB representative.

*A list of links to all manuals applicable to this product is available in the Document library:

Product	Code
ACS880-01 drives	9AKK105408A7004
ACS880-04 drive modules (200 to 710 kW, 300 to 700 hp)	9AKK105713A4819
ACS880-07 drives (45 to 710 kW, 50 to 700 hp)	9AKK105408A8149
ACS880-07 drives (560 to 2800 kW)	9AKK105713A6663

Firmware manual

ACS880 spinning and traverse control program (option +N5500)

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Introduction to the manual

Contents of this chapter

This chapter describes the contents of the manual. It also contains information on the applicability, safety and intended audience.

Applicability

This manual applies to the following control program versions:

Control program	Version
ACS880 spinning and traverse control program	application: 2.10.0.0 or later
	 loading package: 2.10.0.0 or later
ACS880 primary control program	2.6x or later

You can see firmware and loading package versions in parameters:

- 07.04 Firmware name
- 07.05 Firmware version
- 07.06 Loading package name
- 07.07 Loading package version

You can also see the firmware version on the drive control panel from **System info** in the main menu.

This spinning and traverse application program is based on IEC standard 61131-3.

Target audience

This manual is intended for people who design, commission, or operate the drive system.

Licensing

The Spinning control program (+N5500), version ASPLCx v2.10.0.0 or later comes with a license key on the ZMU-02 memory unit. The program activates only after recognizing the key and correspondingly registers itself with the spinning software.

Device	License key
ZMU-02 memory unit license key	N8023 MU Interlock key – Spinning
Spinning software (loading package)	N8024 Licensed appl Spinning

You can see the license information in the Drive Composer PC tool or in the ACS-APx control panel from **System info** \rightarrow **Licenses**.



After the program is downloaded to the memory unit with the license key, the program remains there unless you remove it. This makes it possible for you to upgrade the spinning application later on a separate spinning loading package.

If the program was loaded to the memory unit without the license key, then the drive indicates a fault 64A5 Licensing fault. See the auxiliary fault code in the Event logger to know the plus code of the missing license, in this case N8023. For further assistance, contact your local ABB representative.

Safety instructions

Obey all safety instructions delivered with the drive.

- Read the **complete safety instructions** before you install, commission, or use the drive. The complete safety instructions are delivered with the drive as either part of the *Hardware manual*, or, in the case of ACS880 multidrives, as a separate document.
- Read the **firmware function-specific warnings and notes** before changing parameter values. These warnings and notes are included in the parameter descriptions presented in chapter *Parameters*.

Contents of the manual

This manual contains the following chapters:

- *Quick start-up guide* contains the basic start-up sequence of the drive and additional alternative checklists for starting up the drive with the control program.
- Using the control panel provides basic instructions on using the control panel.
- Spinning and traverse program features describes the program features specific to the spinning and traverse application.
- *Standard program features* describes the control locations and operation modes, as well as the program features that are not specific to spinning application.
- Default control connections presents the default connection diagram.
- Parameters describes the parameters of the drive.
- Additional Parameter data contains further information on the parameters.
- *Fault tracing* lists the warning and fault messages with possible causes and remedies.
- *Fieldbus control through the embedded fieldbus interface (EFB)* describes the communication to and from a fieldbus network using the embedded fieldbus interface of the drive.
- *Fieldbus control through a fieldbus adapter* describes the communication to and from a fieldbus network using an optional fieldbus adapter module.
- Control chain diagrams shows the parameter structure within the drive.

Related documents

See the *List of related manuals* on the inside of the front cover.

Terms and abbreviations safety instructions

Term/abbreviation	Definition					
AC 800M	Type of programmable controller manufactured by ABB.					
ACS800	A product family of ABB drives					
ACS-AP-I	Turne of control namel used with ACC2000 drives					
ACS-AP-W	Type of control panel used with ACS880 drives					
AI	Analog input; interface for analog input signals					
AO	Analog output; interface for analog output signals					
BCU	Type of control unit used in ACS880 drives, primarily those with parallel- connected inverter or supply modules.					
D2D	Drive-to-drive; communication link between drives that is implemented by application programming. See Drive application programming manual (IEC 61131-3) (3AUA0000127808 [English])					
DC link	DC circuit between rectifier and inverter					
DDCS	Distributed drives communication system; a protocol used in communication between ABB drive equipment.					
DI	Digital input; interface for digital input signals					
DIO	Digital input/output; interface that can be used as a digital input or output					
DO	Digital output; interface for digital output signals					
Drive	Frequency converter for controlling AC motors. The drive consists of a rectifier and an inverter connected together by the DC link. In drives up to approximately 500 kW, these are integrated into a single module (drive module). Larger drives typically consist of separate supply and inverter units.					
DriveBus	A communication link used by, for example, ABB controllers. ACS880 drives can be connected to the DriveBus link of the controller. See page <i>71</i> .					
DTC	Direct torque control. See page 75.					
EFB	Embedded fieldbus interface. See page 589.					
FAIO	Optional analog I/O extension module					
EFB	Embedded fieldbus					
FBA	Fieldbus adapter					
FCAN-01	Optional CANopen adapter					
FCNA-01	Optional ControlNet adapter					
FDCO-0x	Optional DDCS communication module					
FDNA-01	Optional DeviceNet TM adapter					
FECA-01	Optional EtherCAT® adapter					
FEN-01	Optional TTL encoder interface module					
FEN-11	Optional absolute encoder interface module					
FEN-21	Optional resolver interface module					
FEN-31	Optional HTL encoder interface module					

Term/abbreviation	Definition
FENA-11	Optional Ethernet/IP, Modbus/TCP and PROFINET IO adapter
FENA-21	Optional dual-port Ethernet/IP, Modbus/TCP and PROFINET IO adapter
FEPL-02	Optional POWERLINK adapter
FIO-01	Optional digital I/O extension module
FIO-11	Optional analog I/O extension module
FPBA-01	Optional PROFIBUS DP adapter
FSCA-01	Optional Modbus/RTU adapter
FSO-xx	Optional safety functions module
HTL	High-threshold logic
ID run	Motor identification run. During the identification run, the drive will identify the characteristics of the motor for optimum motor control.
IGBT	Insulated gate bipolar transistor; a voltage-controlled semiconductor type widely used in inverters and IGBT supply units due to their easy controllability and high switching frequency
INU-LSU	Type of optical <i>DDCS</i> communication link between two converters, for example the <i>Supply unit</i> and the <i>Inverter unit</i> of a drive system.
Inverter unit	The part of the drive that converts DC to AC for the motor.
I/O	Input/Output
ISU	An IGBT supply unit; type of supply unit implemented using IGBT switching components, used in regenerative and low-harmonic drives.
Line-side converter	See Supply unit.
LSU	See Supply unit.
ModuleBus	A communication link used by, for example, ABB controllers. ACS880 drives can be connected to the optical ModuleBus link of the controller.
Motor-side converter	See Inverter unit.
Network control	 With fieldbus protocols based on the Common Industrial Protocol (CIPTM), such as DeviceNet and Ethernet/IP, denotes the control of the drive using the Net Ctrl and Net Ref objects of the ODVA AC/DC Drive Profile. For more information, see <u>www.odva.org</u>, and the following manuals: <i>FDNA-01 DeviceNet adapter module User's manual</i> (3AFE68573360
	 [English]), and <i>FENA-01/-11 Ethernet adapter module User's manual</i> (3AUA0000093568 [English]).
Parameter	User-adjustable operation instruction to the drive, or signal measured or calculated by the drive
PID controller	Proportional–integral–derivative controller. Drive speed control is based on PID algorithm.
PLC	Programmable logic controller
Power unit	Contains the power electronics and power connections of the drive (or inverter module). The drive control unit is connected to the power unit.

Term/abbreviation	Definition
PTC	Positive temperature coefficient
RDCO-0x	DDCS communication module
RFG	Ramp function generator.
RO	Relay output; interface for a digital output signal. Implemented with a relay.
SSI	Synchronous serial interface
STO	Safe torque off
Supply unit	The part of the drive that converts AC to DC. An IGBT supply unit (<i>ISU</i>) is also capable of feeding regenerative energy back into the supply network.
TTL	Transistor-transistor logic
UPS	Uninterruptible power supply; power supply equipment with battery to maintain output voltage during power failure
ZCU	Type of control unit used in ACS880 drives (primarily in drive modules, or inverter/supply units consisting of a single power module). Consists of a ZCON board built into a plastic housing.
	Depending on the type of hardware, the control unit may be integrated into or fitted onto the drive/inverter module, or installed separately.

Cybersecurity disclaimer

This product is designed to be connected to and to communicate information and data via a network interface. It is Customer's sole responsibility to provide and continuously ensure a secure connection between the product and Customer network or any other network (as the case may be). Customer shall establish and maintain any appropriate measures (such as but not limited to the installation of firewalls, application of authentication measures, encryption of data, installation of anti-virus programs, etc) to protect the product, the network, its system and the interface against any kind of security breaches, unauthorized access, interference, intrusion, leakage and/or theft of data or information. ABB and its affiliates are not liable for damages and/or losses related to such security breaches, any unauthorized access, interference, intrusion, leakage and/or theft of data or information.

See also section User lock (page 124).

Quick start-up guide

Contents of this chapter

This chapter contains the basic start-up sequence of the drive and additional alternative checklists for starting up the drive with the control program.

In this chapter, the drive is set up using the ACS-AP-I control panel. You can also do the start-up sequence using the Drive composer PC tool. For basic start-up sequence and control program start-up, see:



- Drive start-up on page 20
- Spinning control start-up on page 27
- Traverse control start-up on page 29

Before you start

Make sure that the drive has been mechanically and electrically installed as described in the appropriate *Quick installation guide* and/or *Hardware manual*.

Safety

WARNING! All electrical installation and maintenance work on the drive should be carried out by qualified electricians only.

Never work on the drive, the brake chopper circuit, the motor cable or the motor when power is applied to the drive. Always make sure by measuring that no voltage is actually present.

WARNING! Make sure that the machinery into which the drive with brake control function is integrated fulfills the personnel safety regulations. Note that the frequency converter (a Complete Drive Module or a Basic Drive Module, as defined in IEC 61800-2), is not considered as a safety device mentioned in the European Machinery Directive and related harmonized standards. Thus, the personnel safety of the complete machinery must not be based on a specific frequency converter feature (such as the brake control function), but it has to be implemented as defined in the application specific regulations.

Drive start-up

Safety										
WARNING! Obey all safety instructions for the drive. Only qualified electricians are allowed to start up the drive.										
Check the installation. See the installation checklist in the appropriate Hardware manual										
 Check that the starting of the motor does not cause any danger. De-couple the driven machine if there is a risk of damage in case of an incorrect direction of rotation, or a Normal ID run is required during the drive start-up, when the load torque is higher than 20% or the machinery is not able to withstand the nominal torque transient during the ID run. 										
1 – Power-up, date and time settings										
	Power up the drive. Note: It is normal that warning messages appear at various points along the start-up process. To hide a message and to resume the start-up process, press . Hide any warnings now to enter the Home view (shown on the right). The two commands at the bottom of the display (in this case, Options and Menu), show the functions of the two softkeys . and . located below the display. The commands assigned to the softkeys vary depending on the context.	Remote (► Motor speed used rpm Motor current A Motor torque % % Options 12:34	0.0 rpm 0.00 0.00 ► 0.0 Menu							

In the Home view, press 🔙 (Menu).	Remote 🔿	0.0 rpm
The main Menu (right) appears.	Menu —	
	C Parameters	
	🔀 Assistants	•
	Energy efficiency	►
	Event lea	
	Exit 12:34	Select
Highlight Settings on the menu using	Remote (*	0.0 rpm
and $[\bullet]$ and press \bigcirc (Select).	Settings	
	Language	►
	Date & time	►
	Edit texts	•
	Display settings	
	Back 12:34	Select
In the Settings menu, highlight Date & time	Remote 🔿	0.0 rpm
(if not already highlighted) and press () (Select).	Date & time	
	Date	01.01.1980
	Time	12:34:56
		.month.year
	Show time as	24-hour
	Daylight saving	EU
	Back 12:35	Edit
In the Date 9 times many highlight Date (1)		
In the Date & time menu, highlight Date (if not already highlighted) and press	Remote 🔿	0.0 rpm
(Select).	Date	
	Day Month Y	ear
	01.01.19	100
	Tuesday	
	Cancel 12:35	Save

 $\langle \hat{} \rangle$

	Set the correct date:	Remote 🔿	0.0 rpm
	 Use and b to move the cursor left and right. 	Motor speed used	
	 Use A and to change the value. 	rpm	0.00
	 Press (Save) to accept the new 	Motor current	000
	setting.	► A	0.00
	Check/adjust all the remaining settings in the Date & time menu.	Motor torque %	0.0
	The Show clock setting determines whether the time is shown at all times in the bottom	Options 12:35	Menu
	pane of the display.		
	After you have made the settings, press (Back or Exit) repeatedly until the Home view (right) reappears.		
	2 – Supply voltage and r	notor data settings	
	Switch to local control to ensure that external	Local (*	0.0 rpm
	control is disabled by pressing the Loc/Rem key. Local control is indicated by the text "Local" in the top pane.	Motor speed used rpm	0.00
>		 ▲ Motor current A 	0.00
		Motor torque %	0.0
		Options 12:36	Menu
	Open the main Menu by pressing Solution (Menu).	Local (*	0.0 rpm
		Menu —	
		O Parameters	►
		Assistants	•
		Energy efficiency	►
		Exit 12:36	Select

Highlight Parameters and press (Select).	Local (* Parameters Favorites By function Complete Modified	on	0.0 rpm ► ► ►
	Back	12:36	Select
Highlight Complete list using ▲ and ▼ and press	05 Diagno	values eferences lgs and faults lstics I and status words	0.0 rpm
 Highlight parameter group <i>95 HW</i> configuration and press (Select). Note that the list wraps around in either direction between groups 99 and 01. In this case, it is quicker to use ▲ to locate group 95 on the list. After selecting a group, a listing of parameters within the group is displayed. 	95.01 Supp 95.02 Adap 95.04 Contr	tive voltage limits ol board supply Inte	
Highlight parameter 95.01 Supply voltage (if	Back	12:36	Edit
(Edit). The available parameter settings are listed.	[0] Not g [1] 208.	240 V 415 V 480 V	0.0 rpm

	Highligh		corre (Save		ting o	n the	list a	ind	Local	~		0.0 rpm
			Jave	;).					95 HW	configu	ration ——	
									95.01 S	upply vo	ltage 38	30415 V
											voltage limits	Disable
										•	ard supply Inf	
									Back		12:36	Edit
	Press (99 Moto		•		• •			•	• .	os again	. Select paran	neter group
	Set para	amete	er <mark>99</mark> .	.04 Mc	otor c	ontrol	moa	le.				
	DTC = I	Direct	t torq	ue cor	ntrol;	Scala	r					
			•					mode i	s recomm	ended if		
	• the n	omina	al cur	rent of	f the r	motor	is le	ss thai	n 1/6 of the	e nomina	al current of th	ne drive,
					•	•			notor conr			
	• the d	rive c	ontro	ls mul	tiple r	motor	s and	d the n	umber of I	motors c	onnected is v	ariable.
Refe	er to the	moto	r nam	neplate	e for t	he fol	lowir	ng para	ameter set	tings. W	henever poss	ible, enter
the	values <u>e</u> z	xactly	<u>/</u> as s	hown	on th	e mot	or na	amepla	ite.			
	Example	e of a	a nam	eplate	e of ai	n indu	ctior	1	Example	of a nan	neplate of a p	ermanent
	(asynch	ironoi	us) m	otor:					magnet n	notor:		
	(b)		• •									
	Ψ		AB	BBM	oto	rs	CE	- ⊕-)	(+)	AB	B Motors	
	3 ~ moto	or		A 200 M					3 ~ motor	M2BJ 2	80SMB 10 B3	
			IEC	200 M/L N				~	S1 SPEC IN	ISUL.	No 3424522	
						F	IP 5		JK-21640-1		Ins.cl. F	IP 55
1			•	<u> </u>	113.01.							11 33
	V	Hz	kW	r/min	Α	cos g	PIA/IN	^t E/s	V Hz	kW r/	min A cos φ	IA/IN t _{E/s}
	V 690 Y 400 D	Hz 50 50	kW 30 30		1	cos g 0.83 0.83	PIA/IN	^t E/s			· · ·	
	690 Y 400 D 660 Y	50 50 50	30 30 30	r/min 1475 1475 1470	A 32.5 56 34	0.83 0.83 0.83	> IA/IN	tE/s	V Hz 400 D 50		min A cos φ 00 103 0.97	
	690 Y 400 D 660 Y 380 D	50 50 50 50	30 30 30 30	r/min 1475 1475 1470 1470	A 32.5 56 34 59	0.83 0.83 0.83 0.83	P IA/IN	^t E/s		55 6	· · ·	IA/IN t _{E/s}
	690 Y 400 D 660 Y 380 D 415 D 440 D	50 50 50 50 50 60	30 30 30 30 30 30 35	r/min 1475 1475 1470 1470 1475 1770	A 32.5 56 34 59 54 59	0.83 0.83 0.83	P IA/IN		400 D 50	55 6 2GBJ2	00 103 0.97	IA/IN t _{E/s}
	690 Y 400 D 660 Y 380 D 415 D	50 50 50 50 50 60	30 30 30 30 30 30 35	r/min 1475 1475 1470 1470 1475	A 32.5 56 34 59 54 59	0.83 0.83 0.83 0.83 0.83	> IA/IN	^t E/s	400 D 50 Prod. code	55 6 2GBJ2	00 103 0.97 85220-ADA40544	IA/IN t _{E/s}
	690 Y 400 D 660 Y 380 D 415 D 440 D	50 50 50 50 50 60 3G	30 30 30 30 30 30 35	r/min 1475 1475 1470 1470 1475 1770 2001 - A	A 32.5 56 34 59 54 59	0.83 0.83 0.83 0.83 0.83	> IA/IN	· · · · ·	400 D 50 Prod. code	55 6 2GBJ2	00 103 0.97 85220-ADA40544	IA/IN t _{E/s}
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Mak	Make the following parameter settings in the same manner.					
	99.07 Motor nominal voltage					
	The allowable range is $1/6 \times U_N \dots 2 \times U_N$ of the drive.					
	With permanent magnet motors, the nominal voltage is the BackEMF voltage at nominal speed. If the voltage is given in volt/rpm (eg. 60 V per 1000 rpm), the voltage at a nominal speed of 3000 rpm is 3×60 V = 180 V. Note that nominal voltage is not the same as equivalent DC motor voltage (EDCM) given by some manufacturers. The nominal voltage can be calculated by dividing the EDCM voltage by 1.7 (or square root of 3).					
	99.08 Motor nominal frequency					
	With permanent magnet motors, if the nominal frequency is not shown on the nameplate, it can be calculated using the following formula:					
	$f = n \times p / 60$ where $n =$ nominal motor speed, $p =$ number of	of noto nairo				
	· · ·					
	99.09 Motor nominal speed					
	99.10 Motor nominal power					
	99.11 Motor nominal cos Φ 99.12 Motor nominal torque					
	These values are not required, but can be ent known, leave at 0.	ered to improve control accuracy. If not				
	99.13 ID run requested					
	This parameter selects the mode of the identit	ication run (DTC motor control mode only).				
	Note: The drive must be in local control for the	e identification run.				
	WARNING! The identification run modes marked thus * will run the motor in the forward direction (see below for details). Make sure it is safe to run the motor before choosing any of these modes.					
	 *Normal mode should be selected whenever possible. This mode is recommended for hoist drives. The driven machinery must be de-coupled from the motor if the load torque is higher than 20%, or 					
	 the machinery is not able to withstand the nominal torque transient during the identification run. 					
	* <i>Reduced</i> mode should be selected if the mechanical losses are higher than 20%, ie. the load cannot be de-coupled, or full flux is required to keep the motor brake open (eg. with conical motors).					
	The <i>Standstill</i> mode should be selected if neither the * <i>Normal</i> or * <i>Reduced</i> mode can be used. This mode is recommended for trolley and long travel motions with which it is very difficult or impossible to disconnect the motor from the mechanical system. Notes :					
	 This mode cannot be used with a permaner than 20% of nominal. 	nt magnet motor if the load torque is higher				
	 Mechanical brake is not opened by the logic 	c for the identification run.				
	Ensure that the Safe torque off and emergence	y stop circuits (if present) are closed.				
	Start the identification run by pressing the (Start) button.A warning will indicate that the identification run is in progress.					

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Check that the motor runs in the correct direction (forward direction shown below). With a positive speed reference, the motor has to run to the direction of lifting a load.



The identification run has completed when the drive stops and the value of parameter *99.13* reverts to *None*.

If the motor ran in the wrong direction, correct the motor cabling or adjust parameter *99.16 Motor phase order*.



Spinning control start-up

This section describes how to set up the drive for spinning application.

Note: The spinning pattern runs only in remote mode. In Local mode drive uses keypad speed reference and spinning pattern will not run.

	Safety				
1	WARNING! Obey all safety instructions for the drive. Only qualified electricians are allowed to start up the drive.				
	Preliminary actions				
	Make sure that you have completed the basic start-up sequence of the drive. See <i>Drive start-up</i> on page <i>20</i> .				
	Power up the drive and wait for 10 seconds. This is to make sure that all the boards are powered and the application is running.				
	Switch to Remote control by pressing the Loc/Rem key, or alternatively, use the Drive composer PC tool.				
	Control signal settings with I/O				
	Set parameter 99.200 Application select = Spinning.				
	Set the speed limits. <i>30.11 Minimum speed</i> = 0 rpm (if the motor is to run only in one direction) <i>30.12 Maximum speed</i> = maximum running speed of the motor				
	Set the spinning pattern parameters in groups: 75 Pattern1 76 Pattern2 77 Pattern3 78 Pattern4				
	 The drive now follows the ramp times defined in parameter groups 7578. After the start command (or after power shutdown) the drive ramps up at acceleration time (parameters 23.201 Acceleration time 1 or 23.203 Acceleration time 2). When the drive is paused it stops at the deceleration ramp (parameters 23.202 Deceleration time 1 or 23.204 Deceleration time 2). 				
	Trial run				
	Drive is now ready to run the pattern selected with parameter 74.01 Pattern selection.				
	Reset the active pattern with parameter 74.04 Reset active pattern and reset production with parameter 74.11 Production calculation reset.				
	Test run in remote mode with the motors still de-coupled from the driven machinery.				
	After the test run is completed successfully, couple the motor with driven machine and start the drive.				

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Fieldbus adapters

The fieldbus communication is not normally used with spinning control as all the controls, actual values and calculated signals are in the control board of the drive.

If fieldbus communication is used, see appropriate Installation and Start-up Guide.

The fieldbus communication is set up with parameter group 51 FBA A settings.



Traverse control start-up

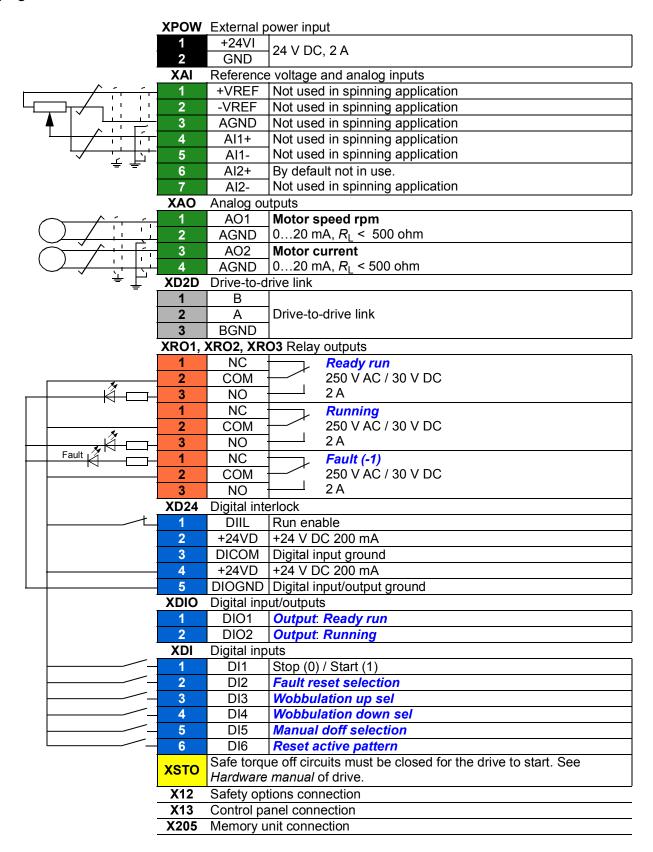
This section describes how to set up the drive for traverse application.

Note: The traverse control application runs in both local and remote control mode.

Safety					
WARNING! Obey all safety instructions for the drive. Only qualified electricians are allowed to start up the drive.					
Preliminary actions					
Make sure that you have completed the basic start-up sequence of the drive. See <i>Drive start-up</i> on page <i>20</i> .					
Power up the drive and wait for 10 seconds. This is to make sure that all the boards are powered and the application is running.					
Put the drive either in Local or Remote control by pressing the Loc/Rem key, or alternatively, use the Drive composer PC tool.					
In local control mode, use keypad reference as base speed of traverse.					
In remote control mode, use EXT1/EXT2 reference as base speed of traverse.					
Control signal settings with I/O					
Set parameter 99.200 Application select = Traverse					
Adjust the traverse control parameters in group 88 Traverse.					
Trial run					
Perform the test run with the motor still de-coupled from the drive machinery.					
Couple the motor and start the traverse after successful test run.					

Control connections

This figure shows the control connections for the spinning set-up described on page 27.



3

Using the control panel

Refer to *ACX-AP-x* assistant control panels user's manual (3AUA0000085685 [English]).

32 Using the control panel

4

Spinning and traverse program features

Contents of this chapter

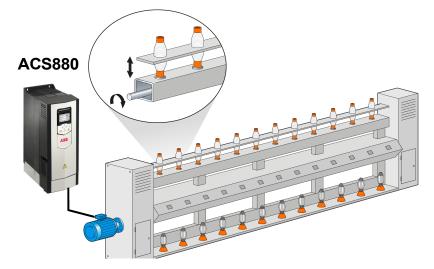
This chapter describes some of the important functions within the spinning and traverse control program, how to use them and how to program them to operate.

- See Overview of spinning control program features on page 35
- See Overview of traverse control program features on page 51.

WARNING! Make sure that the machinery into which the drive is integrated fulfills the personnel safety regulations. Note that the frequency converter (a Complete Drive Module or a Basic Drive Module, as defined in IEC 61800-2), is not considered as a safety device mentioned in the European Machinery Directive and related harmonized standards. Thus, the personnel safety of the complete machinery must not be based on a specific frequency converter feature, but it has to be implemented as defined in the application specific regulations.

Principle of Spinning and traverse control

The figure below shows the principle of Spinning and traverse control.



The Spinning and traverse control program is designed to run the spinning bobbins in ring frame textile machines. To achieve the best possible form for the doff, the spinning sequence should be ideal for a traverse of the yarn. This is done by giving pre-set values for speed based on the elapsed time or length.

Overview of spinning control program

The Spinning control program consists of 4 separate patterns. Each pattern consists of 16 steps which can be preset by parameters in groups 75...78. Any of these patterns can be selected to be the active pattern. The modes for each pattern are: Speed Time Patterns (STP), Speed Length Pattern [m] and Speed Length Pattern [%]. The used mode can be selected by a parameter in each pattern group. The speed values are defined in percentages, 100% equaling the nominal speed of the motor.

In addition to the base pattern function, there are three selectable functions:

- **Shift function** multiplies speed defined for the pattern. See description on page *40*.
- **Wobbulation** keeps the yarn tension below the breaking limit by wobbling the spinning speed. See description on page 47.
- **Manual Doff** makes the controlled end for doffing before the pattern is finished. See description on page 50.

The control program is designed in a way that the speed reference described in parameter 23.01 Speed ref ramp input in the motor control changes according to the parameters in groups 74 to 79.

Note: The spinning pattern runs only in remote mode. In Local mode, the drive uses keypad speed reference and spinning pattern does not run.

Activating Spinning function

The Spinning control function can be activated with parameter 99.200 Application select = Spinning.

Selecting the mode

The used modes Time or Length can be selected individually for each pattern using parameters 75.33 *Pattern1 mode*, 76.33 *Pattern2 mode*, 77.33 *Pattern3 mode*, and 78.33 *Pattern4 mode*.

Using the control panel

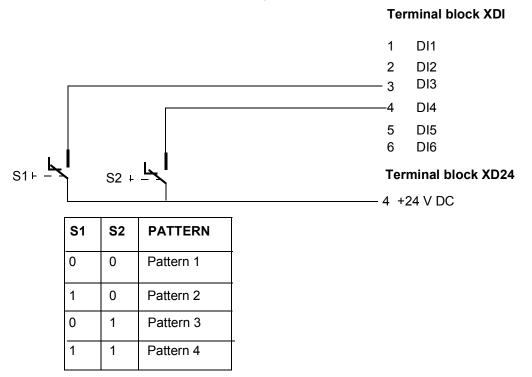
Spinning pattern runs only in Remote mode. In Local mode drive uses the keypad speed reference and so spinning pattern will not run.

The drive can be started from the control panel by selecting Local control from the panel. The display shows "Local" to indicate local mode. The drive can now be started using the Start push-button on the keypad. For description of settings, see chapter *Using the control panel* on page 31.

Selecting an active pattern

Active pattern

The pattern to be run can be selected with parameter 74.01 Pattern selection (PATTERN 1 PATTERN 2, PATTERN 3 or PATTERN 4) or by 2 binary coded digital inputs (DI3_4 and DI5_6). The pattern selection mode can be set by parameter 74.02 Pattern selection mode. If the parameter 74.02 Pattern selection mode = $DI3_4$, the function is as described as in the below figure.



The operation is same if digital inputs 5 and 6 are selected, that is parameter 74.02 *Pattern selection mode* = $DI5_6$.

If a pattern is changed while the drive is not running or the pattern is not paused, the pattern change is updated in parameter *09.05 Current pattern*.

Running section

The signal *09.08 Running section* indicates the currently running section from Section 1 to Section 16 of the active pattern.

Completed pattern time

The signal *09.11 Pattern completed time* indicates the elapsed time from the beginning of the active pattern.

Remaining pattern time

The signal *09.12 Remaining pattern time* indicates the remaining time to end of the active pattern.

Reset active pattern

The pattern can be reset, that is started from the beginning, only when the drive is not running. The pattern reset is separated from the fault reset to avoid resetting of pattern in case of certain fault conditions.

The source (digital input) to reset the active pattern can be selected with parameter 74.04 *Reset active pattern* if the following conditions are satisfied:

- Parameter 74.05 Pattern reset with interlock must be set as False.
- If parameter 74.05 Pattern reset with interlock is True or other DI is assigned, then DI status should be high and should meet below conditions:
 - If pattern is in Time mode, pattern elapsed time should be greater than value in parameter 74.08 Pattern reset time.
 - If pattern is in Length mode or in % Length mode, the delivered length should be greater than value in parameter 74.09 Pattern reset length.

Note: Make sure that the selected digital input is not used for other purposes.

Future pattern

If the pattern is changed while the pattern is running or paused, the pattern selected either by parameter 74.01 Pattern selection or DI3_4 or DI_5, based on the selection made in parameter 74.02 Pattern selection mode, is indicated in parameter 09.06 *Future pattern* immediately.

When the pattern is completed or reset, the value in parameter 09.06 Future pattern is moved to parameter 09.05 Current pattern.

If the pattern is changed while the pattern is not running or not paused, the changed pattern is updated in parameters *09.05 Current pattern* and *09.06 Future pattern*.

Start and pause commands

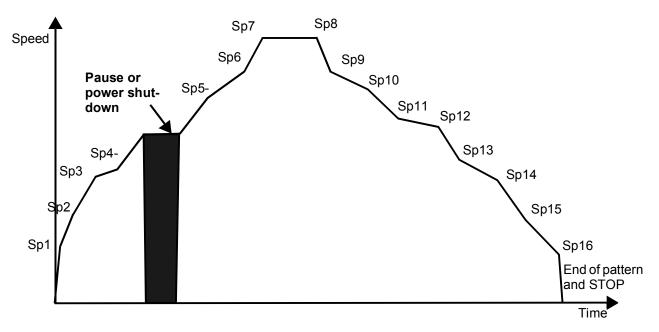
The start and pause of a pattern is controlled with parameters in group 20 *Start/stop/direction*. The running pattern can be paused at any time by drive stop command and restarted to continue at the speed it was paused.

Note: The direction change with group 20 *Start/stop/direction* parameters is disabled. You can reverse the spinning speed reference with parameter 74.07 *Reverse select*. See *Doff production* on page 49.

Spinning speed pattern modes

Time mode

If the Speed time pattern mode is selected, it may look like that depicted in the following figure where restarting after a pause command restarts the machine at the speed before the pause.



Length [m] mode

If the Speed length pattern mode [m] is selected all section values (x-axis) are set in meters. Parameters 75.36, 76.36, 77.36 and 78.36 show the total yarn delivery length.

Length [%] mode

If the Speed length pattern mode [%] is selected all section values (x-axis) are set in percentages of total yarn length. The total yarn delivery length set in parameters 75.37, 76.37, 77.37 and 78.37 is shared by these values programmatically.

If the sum of section percentages is not 100%, the warning *D200 Section sum not 100%* is displayed.

Spinning speed

Spinning Speed

The signal *09.35 Spinning speed* indicates the filtered speed of the bobbins according to parameters *79.01 Gear ratio* and *01.01 Motor speed used*.

Sliding average speed

The actual sliding average speed (parameter *09.38 Sliding average speed*) is based on the samples of program cycle speeds divided by the amount of cycles.

Average spindle speed calculation

Average spindle speed calculation is based on the pattern selected in groups 75 *Pattern1...78 Pattern4*. The average spindle speed constant is defined in parameter 79.01 *Gear ratio* and shift value is defined in parameter 79.07 *Pattern shift multiple*.

Formula for average spindle speed calculation:

$$N_{AVG} = N_{PATT} \times K_1 \times K_S$$

where,

N_{AVG} = average spindle speed (09.01...09.04)

N_{PATT} = average motor speed based on pattern parameters in groups 75 to 78

K₁= gear ratio between motor and spindle speeds

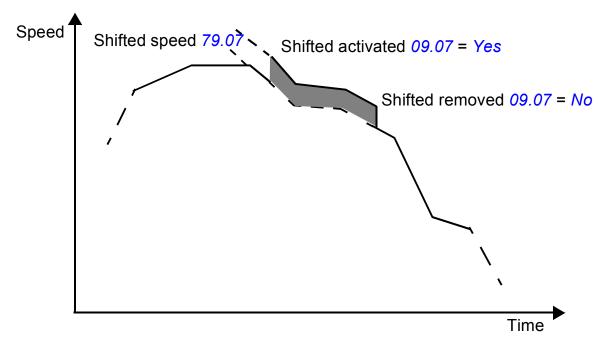
K_S = shift multiplier (79.07 *Pattern shift multiple*)

Parameters 09.01 (PATTERN1), 09.02 (PATTERN2), 09.03 (PATTERN3) and 09.04 (PATTERN4) show the calculated average spindle speed.

Shift function

The Shift function is normally used when thickness of spinning yarn is changed. The function operates as a multiplier for selected pattern speed (see figure below). The function can be selected with parameter 74.03 Shift function sel and indicated in signal 09.07 Shift selected as Yes.

The shift value is defined in parameter 79.07 *Pattern shift multiple* and is used as multiplier with speed reference. The function can be disabled by changing the selection from Yes to *No* in parameter 74.03 *Shift function sel*.



Production calculation

Production calculation is based on the average spindle speed, pattern time and TPI (twist per inch) constant value defined in parameter 75.34 Pattern1 TPI for pattern1. Similarly, TPI values for patterns 2, 3 and 4 are defined in parameters 76.34 Pattern2 TPI,77.34 Pattern3 TPI and 78.34 Pattern4 TPI respectively.

The completed production can be calculated either in hanks or kilograms.

Production in active pattern

Parameters 09.13 Pattern production Kg and 09.14 Pattern production hank indicate the completed production in kilograms and hanks during the active pattern.

Hank calculation

$$H_C = \frac{N_{AVG} \times T_C}{TPI \times 36 \times 840}$$

where,

 H_C = Completed hanks in the active pattern (09.13)

N_{AVG} = Average speed of the active PATTERN (09.01 Average spindle speed1... 09.04 Average spindle speed4) or (09.38 Sliding average speed)

 T_C = Elapsed pattern time in minutes (09.11)

T.P.I = Twist per inch

36 = Inches per yard

840 = Hank (840 yards delivered)

Kilogram calculation

Production [kg] =
$$\frac{n_{AVG} \times T_E \times N_S \times 0.4536[kg]}{TPI \times 36 \times 840 \times K_{CN}}$$

where,

n_{AVG} = average speed of the active pattern (09.01 Average spindle speed1... 09.04 Average spindle speed4) or (09.38 Sliding average speed)

T_E= current pattern elapsed time in minutes

 $N_{\rm S}$ = number of spindles

0.4536 = kgs per lbs

T.P.I = Twist per inch

36 = inches per yard

840 = hank (840 yards delivered)

K_{CN} = number of yarn count

The formula with signal and parameter numbers:

 $\frac{Par9.25 \times Par9.11 \times Par79.12 \times 0.4536}{TPI \times 36 \times 840 \times Countnumber}$

Production in current shift

Parameters 09.17 Current shift production Kg and 09.18 Current shift production Hank indicate the completed production in kilograms or hanks in the current shift.

When the active pattern elapses, the value of signals 09.13 Pattern production Kg and 09.14 Pattern production hank are transferred to 09.17 and 09.18 respectively by adding to their previous value.

The same procedure is repeated after every completed pattern. After work shift has elapsed, the value in the signals 09.17 and 09.18 are transferred to signals 83.01 *Shift1 production Kg* and 83.02 *Shift1 production Hank*. The signals 09.17 and 09.18 are reset.

Parameters 09.19...09.24 indicate following current shift production details.

- total run time of machine
- total stop time of machine
- KWH consumption
- KWH consumed to produce a kilogram
- Grams per active spindle (GPS), and
- Total number of completed patterns.

See Shift production parameter description from page 167.

Production in previous shifts

The parameter group *83 Shift Report* indicates the following production details for Shift1 to Shift5.

- Shift production in kilograms
- Shift production in Hanks
- Run time of machine
- Stop time of machine
- KWH consumption
- KWH consumed to produce a kilogram
- · Grams per active spindle (GPS), and
- Total number of completed patterns.

See description of shift report parameters from page 422.

Running time indication

The signals 09.19, 83.03, 83.11, 83.19, 83.27 and 83.35 indicate the total running time for which the drive was running during last five work shifts including the current shift. The work shift time can be specified in parameter 79.11 Work shift time.

Reset production calculation

Production values and shift run time values (parameters *09.13...09.24*) can be reset by setting parameter *74.11 Production calculation reset* = *Reset now*. After reset is done, change the value back to *No*. Reset makes it possible to synchronise the calculations according to work shifts.

Reverse function

In some spinning machines it is required to run in both directions. It is possible to change directions by switching On the DI selected in parameter 74.07 Reverse select, when the below conditions are satisfied:

- Pattern is finished or reset
- Drive is not running

Note: DI used for this function must not be used for any other purpose.

Length calculation

Delivery length

The formula for the actual delivery length calculation is:

$$L_D = \frac{n_{RAVG} \times t_{ED}}{TPI \times 39.37}$$

where,

 L_D = delivery length in meters (parameter 09.36)

 N_{RAVG} = actual "real" average spinning speed in rpm (parameter 09.38)

TPI = twist per inch (T.P.I * 39.37 = Twist per meter)

T_{ED} = elapsed pattern time

Remaining length

The formula for remaining length calculation is:

Total pattern length - Actual delivery length

$$L_R = L - L_D$$

where

 L_R = Remaining length in meters (parameter 09.37)

 L_D = Delivery length in meters (parameter 09.36)

L = Required length i.e. sum of pattern section lengths [m]

Front roller measurement

Twist per inch

The signal *09.35 Actual TPI* indicates the measured twist-per-inch value if measurement is selected with parameter *79.15 Front roller measurement* selection. If measurement is not in use the signal *09.35* shows the actual TPI value set for different patterns in parameters *75.34*, *76.34*, *77.34* and *78.34*.

Front roller speed

Parameter 09.40 Front roller speed indicates the front roller speed in rpm if measurement is selected by parameter 79.15 Front roller measurement selection.

Restart after power failure

Restart after power failure is a selectable function which starts the drive automatically after a power shutdown (provided that the drive was running before shutdown). The function can be enabled with parameter 20.02 Ext1 start trigger type = Level in Ext1 mode or 20.07 Ext2 start trigger type = Level in Ext2 mode.

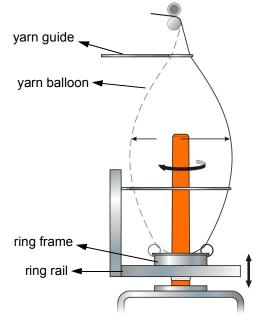
Note: Obey all safety aspects if this function is selected.

Preventing yarn breakage

In ring frame spinning machines, the yarn is led to the doff through a yarn guide and a spinning ring. The spinning ring makes the yarn circle around the bobbin, thus twisting the yarn. See figure below.

Balloon

The figure below shows the situation when the doff build up has just started.



The circular movement of the yarn forms a kind of balloon around the bobbin, causing the yarn to have centrifugal force. This force can break the yarn if the tension increases beyond the yarn strength. The yarn tension is described by the following formula:

$$F = M\omega^2 R$$

where,

- F = Force experienced by the yarn
- M = Mass of the yarn

 ω = Spinning speed

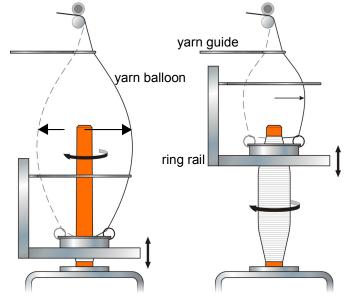
R = Radius of the balloon

Wobbulation function

Description

The probability of yarn breakage is highest at the start of a doff where the radius of the balloon is greatest. To obtain the desired form for the doff, the ring rail constantly moves up and down. At the same time it changes its position upwards until the doff is full. At the start of the build up the diameter of the doff gradually increases to the maximum value. As the diameter increases the speed is decreased to keep the yarn tension constant.

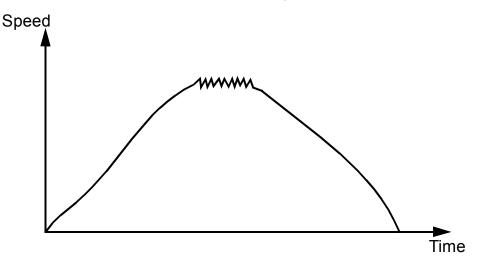
Wobbulation controls the size of the balloon to maintain the yarn tension below the breaking limit. This is done by increasing and decreasing the spinning speed according to the ring rail position and the doff build up stage (see below figure). The speed increment or decrement is done by using limit switches at both ends of the ring rail movement area.



a) Empty bobbin (high tension) b) Built up doff (low tension)

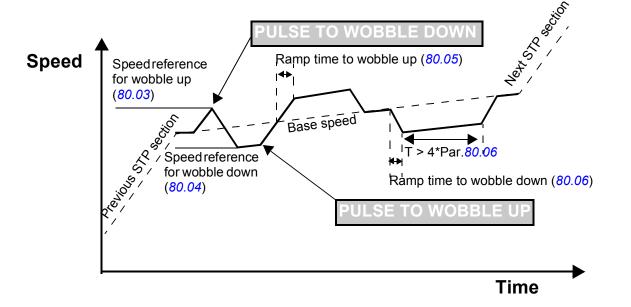
Wobbulation in the pattern

Wobbulation is used when speed is highest and doff build-up is thin.



Activating wobbulation

Wobbulation can be enabled with parameters *80.01* Wobbulation up sel and *80.02* Wobbulation down sel. The wobbulation speed parameters *80.03* Wobbulation up multiple and *80.04* Wobbulation down multiple are multipliers for the speed reference. The ramp times can be set with parameters *80.06* Wobbulation acc time and *80.06* Wobbulation dec time. The limit switches can be connected with parameters *80.01* Wobbulation up sel and *80.02* Wobbulation down sel.



- The rising edge of the DI selected in parameter 80.01 Wobbulation up sel activates the Wobbulation up, that is the speed accelerates to the value defined in parameter 80.03 Wobbulation up multiple.
- The rising edge of DI selected in *80.02 Wobbulation down sel* starts the Wobbulation down, that is the speed decelerates to the value defined in parameter *80.04 Wobbulation down multiple*.

The drive ramps to the base speed, when the drive is running at either upper or lower wobbulation speed and the wobbulation command is not received during the time T > 4*Par.80.06 (or Par. 80.05).

Doff production

The parameter group *84 Doff report* indicates the following production details for Doff1 to Doff10.

- Doff production in kilograms
- Doff production in Hanks
- Doff total run time
- Doff pattern stop time
- Doff KWh
- Doff KWh per kilogram

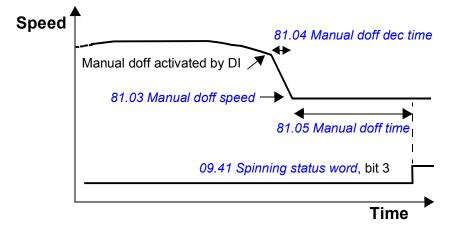
See description of doff report parameters from page 425.

Manual doff function

Manual doff function can be used to end doffing before an actual pattern is completed. There are two modes of activating the Manual doff function:

- Parameter 81.01 Manual doff selection mode = Par 81.02. In this mode, the source to activate manual doff is selected with parameter 81.02 Manual doff selection.
- Parameter 81.01 Manual doff selection mode = Automatic. In this mode manual doff is activated based on the percent value set in parameter 81.08 Manual doff activation percent.
 - In time mode, manual doff is activated when the percentage of completed pattern time is greater than manual doff activation percentage set in parameter *81.08*.
 - In length mode, manual doff is activated when the percentage of completed length is greater than manual doff activation percentage set in parameter *81.08*.

Parameters *81.04* and *81.05* define the Manual doff function as shown in the figure below. The drive stops modulating after manual doffing ends.



The parameter 09.41 Spinning status word, bit 3 can be connected to digital output, for example, to control the associated devices (see group 11 Standard DIO, FI, FO).

Doff-end alarm

When manual doff is activated, an alarm to indicate the finishing of a pattern can be given by directing parameter *09.41 Spinning status word*, bit 2 or bit 4 (with blink) to any digital output (Group *11 Standard DIO, FI, FO*).

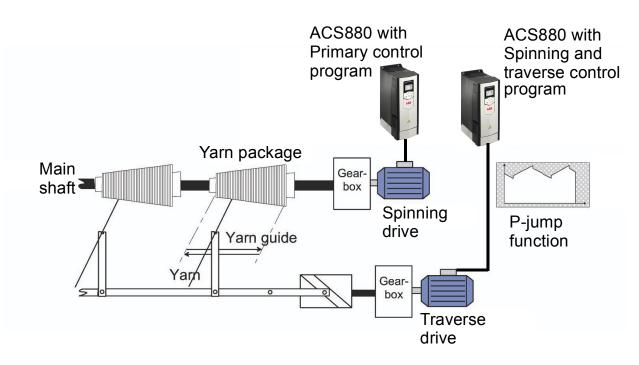
Time mode – time before the alarm can be defined with parameter *81.06 Doff end alarm time*.

Length or %length mode – length before the alarm can be defined with parameter *81.07 Doff End alarm length*.

Overview of traverse control program

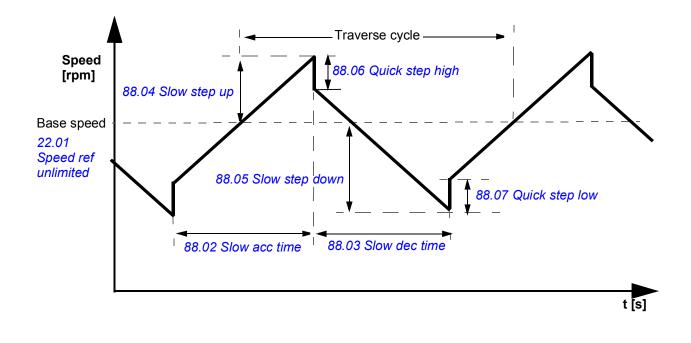
The traverse drives are used in textile machines to guide the yarn into a yarn package.

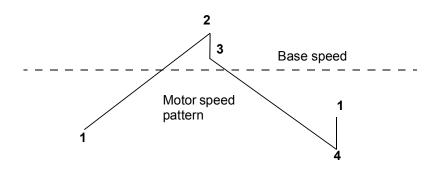
- To get an even winding of the yarn, the drives decrease/increase the speed smoothly depending on the package form and the movement direction of the yarn guide.
- To avoid layering at the reversal points of the yarn guide, the drive performs an instantaneous speed change. i.e. P-jump.



Operating traverse control

The traverse drive repeats the saw tooth speed pattern until the yarn package is builtup. The following figures and table describe the operation of speed pattern with reference to the base speed.





Phase	Action	Parameter
12	Drive accelerates along the traverse acceleration ramp to the maximum traverse speed.	88.02 Slow acc time 88.04 Slow step up
23	Drive stops the acceleration and drops the speed reference by an instantaneous step.	88.06 Quick step high
34	Drive decelerates along the traverse deceleration ramp towards the minimum traverse speed.	88.03 Slow dec time 88.05 Slow step down
41	Drive stops the deceleration and increases the speed by an instantaneous step.	88.07 Quick step low

5

Standard program features

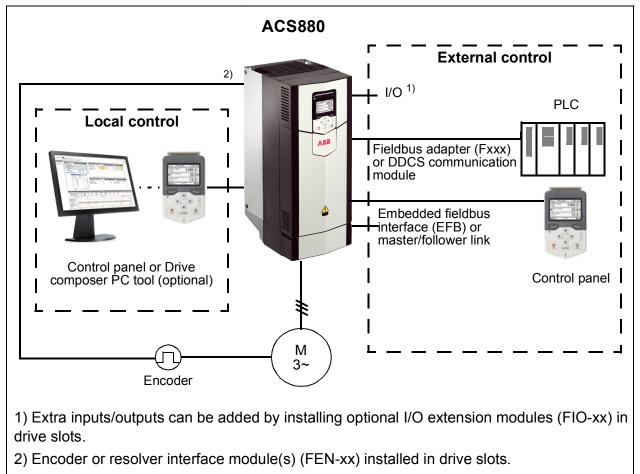
Contents of this chapter

The chapter describes

- the control locations and operating modes supported by the control program
- some of the more important functions in the control program that are not specific to spinning applications, such as motor control.

Local control vs. external control

The ACS880 has two main control locations: external and local. The control location is selected with the Loc/Rem key on the control panel or in the PC tool.



Local control

The control commands are given from the control panel keypad or from a PC equipped with Drive composer when the drive is set to local control. Speed and torque control modes are available for local control; frequency mode is available when scalar motor control mode is used (see parameter *19.16 Local control mode*).

Local control is mainly used during commissioning and maintenance. The control panel always overrides the external control signal sources when used in local control. Changing the control location to local can be prevented by parameter *19.17 Local control disable*.

The user can select by a parameter (49.05 Communication loss action) how the drive reacts to a control panel or PC tool communication break. (The parameter has no effect in external control.)

External control

When the drive is in external control, control commands are given through

- the I/O terminals (digital and analog inputs), or optional I/O extension modules
- · the embedded fieldbus interface or an optional fieldbus adapter module
- the external (DDCS) controller interface
- the master/follower link, and/or
- the control panel.

Two external control locations, EXT1 and EXT2, are available. The user can select the sources of the start and stop commands separately for each location by parameters 20.01...20.10. The operating mode can be selected separately for each location (in parameter group 19 Operation mode), which enables quick switching between different operating modes, for example speed and torque control. Selection between EXT1 and EXT2 is done via any binary source such as a digital input or fieldbus control word (see parameter 19.11 Ext1/Ext2 selection). The source of reference is selectable for each operating mode separately.

The control location selection is checked on a 2 ms time level.

Using the control panel as an external control source

The control panel can also be used as a source of start/stop commands and/or reference in external control. Selections for the control panel are available in the start/stop command source and reference source selection parameters.

Reference source selection parameters (except PID setpoint selectors) have two selections for the control panel. The difference between the two selections is in the initial reference value after the reference source switches to the control panel.

The panel reference is saved whenever another reference source is selected. If the reference source selection parameter is set to *Control panel (ref saved)*, the saved value is used as the initial reference when control switches back to the panel. Note that only one type of reference can be saved at a time: for example, attempting to use the same saved reference with different operating modes (speed, torque, etc.) causes the drive to trip on *7083 Panel reference conflict*. The panel reference can be separately limited by parameters in group *49 Panel port communication*.

With the reference source selection parameter set to *Control panel (ref copied)*, the initial panel reference value depends on whether the operating mode changes with the reference source. If the source switches to the panel and the operating mode does not change, the last reference from the previous source is adopted. If the operating mode changes, the drive actual value corresponding to the new mode is adopted as the initial value.

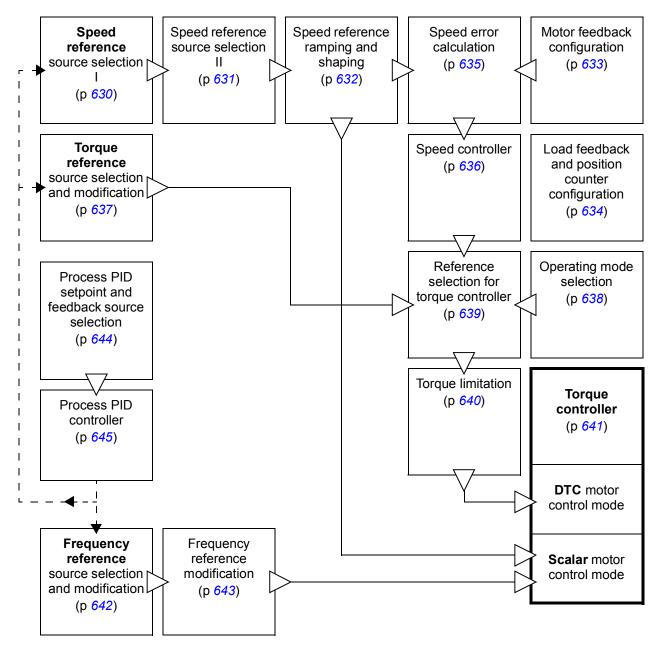
The process PID setpoint selectors in parameter groups *40 Process PID set 1* and *41 Process PID set 2* only have one setting for the control panel. Whenever the control

panel is selected as the setpoint source, operation resumes using the previous setpoint.

Operating modes of the drive

The drive can operate in several operating modes with different types of reference. The mode is selectable for each control location (Local, EXT1 and EXT2) in parameter group *19 Operation mode*.

The following is a general representation of the reference types and control chains. The page numbers refer to detailed diagrams in chapter *Control chain diagrams*.



Speed control mode

The motor follows a speed reference given to the drive. This mode can be used either with estimated speed as feedback, or with an encoder or resolver for better speed control accuracy.

Speed control mode is available in both local and external control. It is also available both in DTC (Direct Torque Control) and scalar motor control modes.

Torque control mode

Motor torque follows a torque reference given to the drive. Torque control is possible without feedback, but is much more dynamic and accurate when used in conjunction with a feedback device such as an encoder or a resolver. It is recommended that a feedback device is used in crane, winch or lift control situations.

Torque control mode is available in DTC motor control mode for both local and external control locations.

Frequency control mode

The motor follows a frequency reference given to the drive. Frequency control is only available in scalar motor control mode.

Special control modes

In addition to the control modes mentioned above, the following special control modes are available:

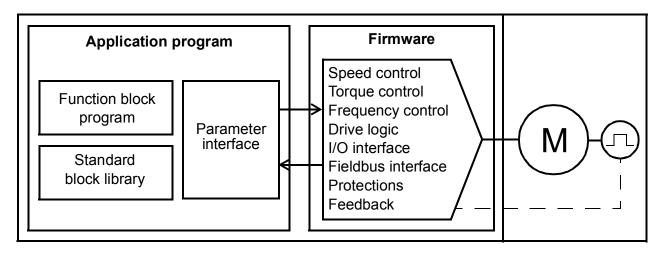
- Process PID control. For more information, see section *Process PID control* (page 100).
- Emergency stop modes Off1 and Off3: Drive stops along the defined deceleration ramp and drive modulation stops.
- Jogging mode: Drive starts and accelerates to the defined speed when the jogging signal is activated. For more information, see section *Jogging* (page *89*).

Drive configuration and programming

The drive control program is divided into two parts:

- firmware program
- application program.

Drive control program



The firmware program performs the main control functions, including speed and torque control, drive logic (start/stop), I/O, feedback, communication and protection functions. Firmware functions are configured and programmed with parameters, and can be extended by application programming.

Programming via parameters

Parameters configure all of the standard drive operations and can be set via

- the control panel, as described in chapter Using the control panel
- the Drive composer PC tool, as described in *Drive composer user's manual* (3AUA0000094606 [English]), or
- the fieldbus interface, as described in chapters *Fieldbus control through the embedded fieldbus interface (EFB)* and *Fieldbus control through a fieldbus adapter*.

All parameter settings are stored automatically to the permanent memory of the drive. However, if an external +24 V DC power supply is used for the drive control unit, it is highly recommended to force a save by using parameter *96.07 Parameter save manually* before powering down the control unit after any parameter changes have been made.

If necessary, the default parameter values can be restored by parameter *96.06 Parameter restore*.

Adaptive programming

Conventionally, the user can control the operation of the drive by parameters. However, the standard parameters have a fixed set of choices or a setting range. To further customize the operation of the drive, an adaptive program can be constructed out of a set of function blocks.

The Drive composer pro PC tool (version 1.9 or later, available separately) has an Adaptive programming feature with a graphical user interface for building the custom program. The function blocks include the usual arithmetic and logical functions, as well as eg. selection, comparison and timer blocks. The program can a maximum of 30 blocks. The adaptive program is executed on a 10 ms time level.

For selecting input to the program, the user interface has pre-selections for the physical inputs, common actual values, and other status information of the drive. Parameter values as well as constants can also be defined as inputs. The output of the program can be used eg. as a start signal, external event or reference, or connected to the drive outputs. Note that connecting the output of the adaptive program to a selection parameter will write-protect the parameter.

The status of the adaptive program is shown by parameter *07.30 Adaptive program status*. The adaptive program can be disabled by *96.70 Disable adaptive program*.

For more information, see the *Adaptive programming application guide* (3AXD50000028574 [English]).

Control interfaces

Programmable analog inputs

The control unit has two programmable analog inputs. Each of the inputs can be independently set as a voltage (0/2...10 V or -10...10 V) or current (0/4...20 mA) input by a jumper or switch on the control unit. Each input can be filtered, inverted and scaled. The analog inputs on the control unit are read on a 0.5 ms time level.

The number of analog inputs can be increased by installing FIO-11 or FAIO-01 I/O extensions (see *Programmable I/O extensions* below).

The drive can be set to perform an action (for example, to generate a warning or fault) if the value of an analog input moves out of a predefined range.

Settings

Parameter group 12 Standard AI (page 181).

Programmable analog outputs

The control unit has two current (0...20 mA) analog outputs. Each output can be filtered, inverted and scaled. The analog inputs on the control unit are read on a 0.5 ms time level.

The number of analog outputs can be increased by installing FIO-11 or FAIO-01 I/O extensions (see *Programmable I/O extensions* below). The analog outputs on extension modules are updated on a 2 ms time level.

Settings

Parameter group 13 Standard AO (page 185).

Programmable digital inputs and outputs

The control unit has six digital inputs, a digital start interlock input, and two digital input/outputs (I/O that can be set as either an input or an output). The digital inputs on the control unit are read on a 0.5 ms time level.

One digital input (DI6) doubles as a PTC thermistor input. See section *Motor thermal protection* (page *113*).

Digital input/output DIO1 can be used as a frequency input, DIO2 as a frequency output.

The number of digital inputs/outputs can be increased by installing FIO-01, FIO-11 or FDIO-01 I/O extensions (see *Programmable I/O extensions* below). The digital inputs on extension modules are read on a 2 ms time level.

Settings

Parameter groups 10 Standard DI, RO (page 169) and 11 Standard DIO, FI, FO (page 176).

Programmable relay outputs

The control unit has three relay outputs. The signal to be indicated by the outputs can be selected by parameters. The relay outputs on the control unit are updated on a 0.5 ms time level.

Relay outputs can be added by installing FIO-01 or FDIO-01 I/O extensions. The relay outputs on extension modules are updated on a 2 ms time level.

Settings

Parameter group 10 Standard DI, RO (page 169).

Programmable I/O extensions

Inputs and outputs can be added by using I/O extension modules. One to three modules can be mounted on the slots of the control unit. Slots can be added by connecting an FEA-0x I/O extension adapter.

The table below shows the number of I/O on the control unit as well as optional FIO-xx I/O extension modules.

Location	Digital inputs (DI)	Digital I/Os (DIO)	Analog inputs (Al)	Analog outputs (AO)	Relay outputs (RO)
Control unit	6 + DIIL	2	2	2	3
FIO-01	-	4	-	-	2
FIO-11	-	2	3	1	-
FAIO-01	-	-	2	2	-
FDIO-01	3	-	-	-	2

Three I/O extension modules can be activated and configured using parameter groups 14...16.

Note: Each configuration parameter group contains parameters that display the values of the inputs on that particular extension module. These parameters are the only way of utilizing the inputs on I/O extension modules as signal sources. To connect to an input, choose the setting *Other* in the source selector parameter, then specify the appropriate value parameter (and bit, for digital signals) in group 14, 15 or 16.

Settings

- Parameter groups 14 I/O extension module 1 (page 189), 15 I/O extension module 2 (page 208), 16 I/O extension module 3 (page 212).
- Parameter 60.41 (page 385).

Fieldbus control

The drive can be connected to several different automation systems through its fieldbus interfaces. See chapters *Fieldbus control through the embedded fieldbus interface (EFB)* (page 589) and *Fieldbus control through a fieldbus adapter* (page 613).

Settings

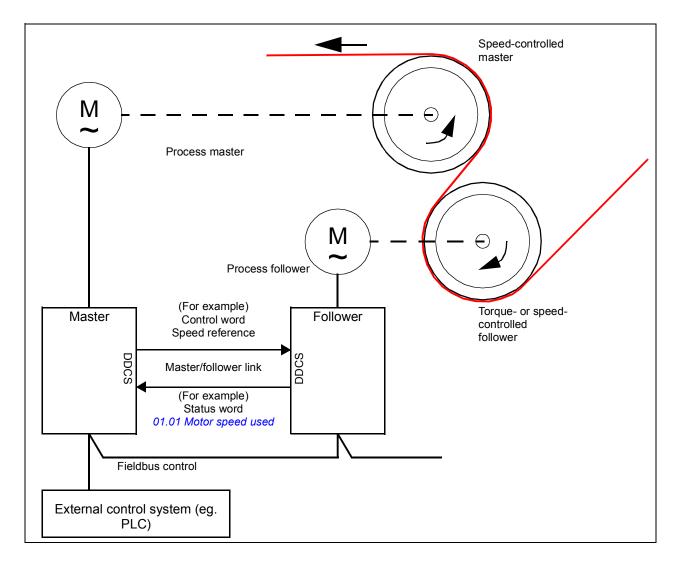
Parameter groups 50 Fieldbus adapter (FBA) (page 357), 51 FBA A settings (page 365), 52 FBA A data in (page 367), and 53 FBA A data out (page 367), 54 FBA B settings (page 368), 55 FBA B data in (page 369), 56 FBA B data out (page 369), and 58 Embedded fieldbus (page 370).

Master/follower functionality

General

The master/follower functionality can be used to link several drives together so that the load can be evenly distributed between the drives. This is ideal in applications where the motors are coupled to each other via gearing, chain, belt, etc.

The external control signals are typically connected to one drive only which acts as the master. The master controls up to 10 followers by sending broadcast messages over an electrical cable or fiber optic link. The master can read feedback signals from up to 3 selected followers.



The master drive is typically speed-controlled and the other drives follow its torque or speed reference. In general, a follower should be

- torque-controlled when the motor shafts of the master and the follower are rigidly coupled by gearing, chain etc. so that no speed difference between the drives is possible
- speed-controlled when the motor shafts of the master and the follower are flexibly coupled so that a slight speed difference is possible. When both the master and

the follower are speed-controlled, drooping is also typically used (see parameter *25.08 Drooping rate*). The distribution of load between the master and follower can alternatively be adjusted as described under *Load share function with a speed-controlled follower* below.

Note:

- With a speed-controlled follower (without load sharing), pay attention to the acceleration and deceleration ramp times of the follower. If the ramp times are set longer than in the master, the follower will follow its own acceleration/deceleration ramp times rather than those from the master. Any ramp shape settings (see parameters 23.16...23.19) should only be applied in the master.
- In some applications, both speed control and torque control of the follower are required. In those cases, the operating mode can be switched by parameter (19.12 Ext1 control mode or 19.14 Ext2 control mode). Another method is to set one external control location to speed control mode, the other to torque control mode. Then, a digital input of the follower can be used to switch between the control locations. See sections Local control vs. external control (page 54) and Operating modes of the drive (page 57).
- With torque control, follower parameter 26.15 Load share can be used to scale the incoming torque reference for optimal load sharing between the master and the follower. Some torque-controlled follower applications, eg. where the torque is very low, or very low speed operation is required, may require encoder feedback.
- If a drive needs to quickly switch between master and follower statuses, one user parameter set (see page 123) can be saved with the master settings, another with the follower settings. The suitable settings can then be activated using eg. digital inputs.

Load share function with a speed-controlled follower

Load sharing between the master and a speed-controlled follower can be used in various applications. The load share function is implemented by fine-tuning the follower speed reference with an additional trim signal based on a torque reference. The torque reference is selected by parameter 23.42 Follower speed corr torq source (by default, reference 2 received from the master). Load share is adjusted by parameter 26.15 Load share and activated by the source selected by 23.40 Follower speed correction enable. Parameter 23.41 Follower speed correction gain provides a gain adjustment for the speed correction. The final correction signal added to the speed reference is shown by 23.39 Follower speed correction out. See the block diagram on page 635.

Notes:

- The function can be enabled only when the drive is a speed-controlled follower in remote control mode.
- Drooping (25.08 Drooping rate) is ignored when the load share function is active.
- The master and follower should have the same speed control tuning values.
- The speed correction term is limited by the speed error window parameters 24.44 Speed error window low and 24.43 Speed error window high. An active limitation is indicated by 06.19 Speed control status word.

Communication

A master/follower link can be built by connecting the drives together with fiber optic cables (may require additional equipment depending on existing drive hardware), or by wiring together the XD2D connectors of the drives. The medium is selected by parameter *60.01 M/F communication port*.

Parameter 60.03 *M/F mode* defines whether the drive is the master or a follower on the communication link. Typically, the speed-controlled process master drive is also configured as the master in the communication.

The communication on the master/follower link is based on the DDCS protocol, which employs data sets (specifically, data set 41). One data set contains three 16-bit words. The contents of the data set are freely configurable using parameters 61.01...61.03. The data set broadcast by the master typically contains the control word, speed reference and torque reference, while the followers return a status word with two actual values.

The default setting of parameter 61.01 *M/F* data 1 selection is Follower CW. With this setting in the master, a word consisting of bits 0...11 of 06.01 Main control word and four bits selected by parameters 06.45...06.48 is broadcast to the followers. However, bit 3 of the follower control word is modified so that it remains on as long as the master is modulating, and its switching to 0 causes the follower to coast to a stop. This is to synchronize the stopping of both master and follower.

Note: When the master is ramping down to a stop, the follower observes the decreasing reference but receives no stop command until the master stops modulating and clears bit 3 of the follower control word. Because of this, the maximum and minimum speed limits on the follower drive should not have the same sign – otherwise the follower would be pushing against the limit until the master finally stops.

Three words of additional data can optionally be read from each follower. The followers from which data is read are selected by parameter 60.14 *M/F follower selection* in the master. In each follower drive, the data to be sent is selected by parameters 61.01...61.03. The data is transferred in integer format over the link, and displayed by parameters 62.28...62.36 in the master. The data can then be forwarded to other parameters using 62.04...62.12.

To indicate faults in the followers, each follower must be configured to transmit its status word as one of the above-mentioned data words. In the master, the corresponding target parameter must be set to *Follower SW*. The action to be taken when a follower is faulted is selected by *60.17 Follower fault action*. External events (see parameter group *31 Fault functions*) can be used to indicate the status of other bits of the status word.

Block diagrams of the master/follower communication are presented on pages 646 and 647.

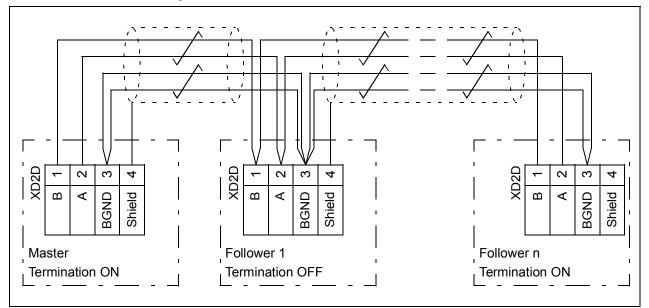
Construction of the master/follower link

The master/follower link is formed by connecting the drives together using either

- shielded twisted-pair cable between the XD2D terminals of the drives*, or
- fiber optic cables. Drives with a ZCU control unit require an additional FDCO DDCS communication module; drives with a BCU control unit require an RDCO module.

*This connection cannot co-exist with, and is not to be confused with, drive-to-drive (D2D) communication implemented by application programming (detailed in *Drive application programming manual (IEC 61131-3)*, 3AUA0000127808 [English]).

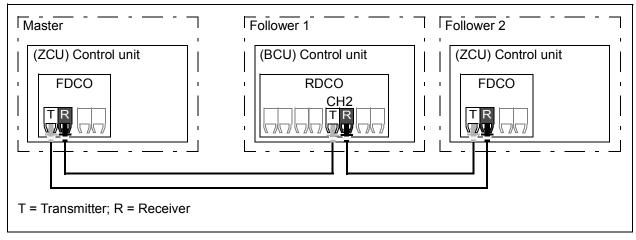
Connection examples are shown below. Note that a star configuration using fiber optic cables requires an NDBU-95C DDCS branching unit.



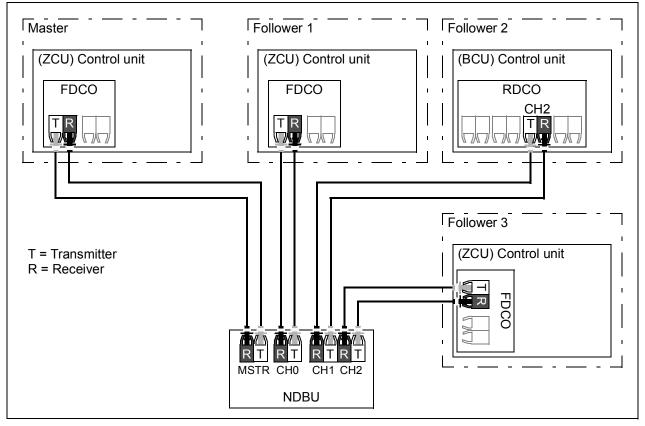
Master/follower wiring with electrical cable

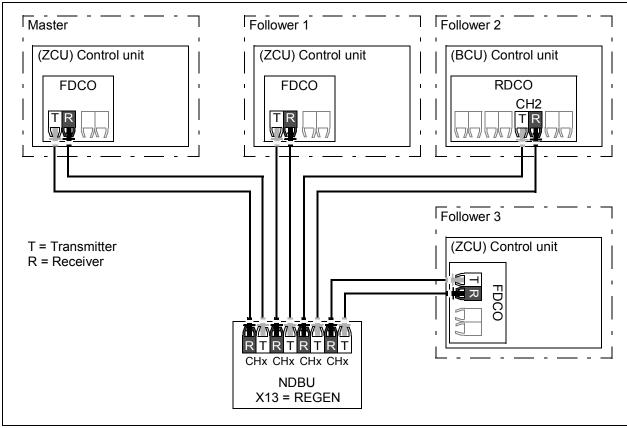
See the hardware manual of the drive for wiring and termination details.

Ring configuration with fiber optic cables



Star configuration with fiber optic cables (1)





Star configuration with fiber optic cables (2)

Example parameter settings

The following is a checklist of parameters that need to be set when configuring the master/follower link. In this example, the master broadcasts the Follower control word, a speed reference and a torque reference. The follower returns a status word and two actual values (this is not compulsory but is shown for clarity).

Master settings:

- Master/follower link activation
 - 60.01 M/F communication port (fiber optic channel or XD2D selection)
 - (60.02 *M/F* node address = 1)
 - 60.03 M/F mode = DDCS master (for both fiber optic and wire connection)
 - 60.05 M/F HW connection (*Ring* or *Star* for fiber optic, *Star* for wire)
- Data to be broadcast to the followers
 - 61.01 M/F data 1 selection = Follower CW (Follower control word)
 - 61.02 M/F data 2 selection = Used speed reference
 - 61.03 M/F data 3 selection = Torque reference act 5
- Data to be read from the followers (optional)
 - 60.14 M/F follower selection (selection of followers that data is read from)
 - 62.04 Follower node 2 data 1 sel ... 62.12 Follower node 4 data 3 sel (mapping of data received from followers)

Follower settings:

- Master/follower link activation
 - 60.01 M/F communication port (fiber optic channel or XD2D selection)
 - 60.02 M/F node address = 2...60
 - 60.03 M/F mode = DDCS follower (for both fiber optic and wire connection)
 - 60.05 M/F HW connection (Ring or Star for fiber optic, Star for wire)
- Mapping of data received from master
 - 62.01 M/F data 1 selection = CW 16bit
 - 62.02 M/F data 2 selection = Ref1 16bit
 - 62.03 M/F data 3 selection = Ref2 16bit
- Selection of operating mode and control location
 - 19.12 Ext1 control mode = Speed or Torque
 - 20.01 Ext1 commands = M/F link
 - 20.02 Ext1 start trigger type = Level
- Selection of reference sources
 - 22.11 Speed ref1 source = M/F reference 1
 - 26.11 Torque ref1 source = M/F reference 2
- Selection of data to be sent to master (optional)
 - 61.01 M/F data 1 selection = SW 16bit
 - 61.02 M/F data 2 selection = Act1 16bit
 - 61.03 M/F data 3 selection = Act2 16bit

Specifications of the master/follower link

- Maximum fiber optic cable length:
 - FDCO-01/02 or RDCO-04 with POF (Plastic Optic Fiber): 30 m
 - FDCO-01/02 or RDCO-04 with HCS (Hard-clad Silica Fiber): 200 m
 - For distances up to 1000 m, use two NOCR-01 optical converter/repeaters with glass optic cable (GOF, 62.5 micrometers, Multi-Mode)
- Maximum shielded twisted-pair cable length: 50 m
- Transmission rate: 4 Mbit/s
- Total performance of the link: < 5 ms to transfer references between the master and followers.
- Protocol: DDCS (Distributed Drives Communication System)

Settings and diagnostics

Parameter groups 60 DDCS communication (page 377), 61 D2D and DDCS transmit data (page 390) and 62 D2D and DDCS receive data (page 394).

External controller interface

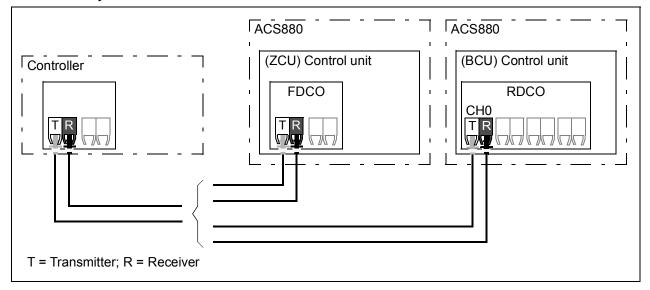
General

The drive can be connected to an external controller (such as the ABB AC 800M) using either fiber optic or twisted cables. The ACS880 is compatible with both the ModuleBus and DriveBus connections. Note that some features of DriveBus (such as BusManager) are not supported.

Topology

An example connection with either a ZCU-based or BCU-based drive using fiber optic cables is shown below.

Drives with a *ZCU* control unit require an additional FDCO DDCS communication module; drives with a *BCU* control unit require an RDCO or FDCO module. The BCU has a dedicated slot for the RDCO – an FDCO module can also be used with a BCU control unit but it will reserve one of the three universal option module slots. Ring and star configurations are also possible much in the same way as with the master/follower link (see section *Master/follower functionality* on page *64*); the notable difference is that the external controller connects to channel CH0 on the RDCO module instead of CH2. The channel on the FDCO communication module can be freely selected.



The external controller can also be wired to the D2D (RS-485) connector using shielded, twisted-pair cable. The selection of the connection is made by parameter 60.51 DDCS controller comm port.

The transfer rate can be selected by parameter 60.56 DDCS controller baud rate.

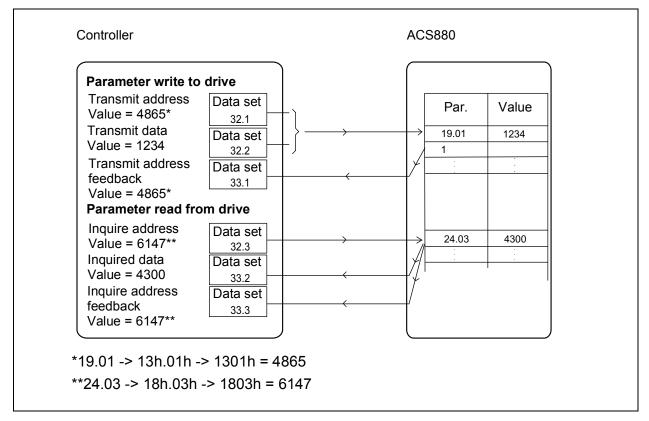
Communication

The communication between the controller and the drive consists of data sets of three 16-bit words each. The controller sends a data set to the drive, which returns the next data set to the controller.

The communication uses data sets 10...33. The contents of the data sets are freely configurable, but data set 10 typically contains the control word and one or two references, while data set 11 returns the status word and selected actual values. For ModuleBus communication, the ACS880 can be set up as a "standard drive" or an "engineered drive" by parameter *60.50 DDCS controller drive type*. ModuleBus communication uses data sets 1...4 with a "standard drive" and data sets 10...33 with an "engineered drive".

The word that is defined as the control word is internally connected to the drive logic; the coding of the bits is as presented in section *Contents of the fieldbus Control word* (page 619). Likewise, the coding of the status word is as shown in section *Contents of the fieldbus Status word* (page 621).

By default, data sets 32 and 33 are dedicated for the mailbox service, which enables the setting or inquiry of parameter values as follows:



By parameter 60.64 Mailbox dataset selection, data sets 24 and 25 can be selected instead of data sets 32 and 33.

The update intervals of the data sets are as follows:

- Data sets 10...11: 2 ms
- Data sets 12...13: 4 ms
- Data sets 14...17: 10 ms
- Data sets 18...25, 32, 33: 100 ms.

Settings

Parameter groups 60 DDCS communication (page 377), 61 D2D and DDCS transmit data (page 390) and 62 D2D and DDCS receive data (page 390).

Control of a supply unit (LSU)

General

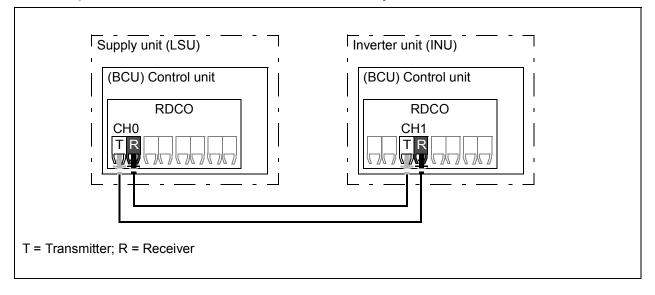
With drives that consist of a supply unit and one inverter unit, the supply unit can be controlled through the inverter unit. (In drive systems consisting of multiple inverter units, this feature is not typically used.) For example, the inverter unit can send a control word and references to the supply unit, enabling the control of both units from the interfaces of one control program.

For more information, refer to the firmware manual of the other converter.

Topology

The control units of the supply unit and the inverter unit are connected by fiber optic cables. With BCU-x2 control units equipped with RDCO modules, CH1 of the inverter is connected to CH0 of the supply unit.

An example connection with a BCU-based drive system is shown below.



With single drives consisting of separate supply and inverter units, the connection is factory-wired.

The fiber optic link specifications stated under *Specifications of the master/follower link* (page 70) apply.

Communication

The communication between the converters and the drive consists of data sets of three 16-bit words each. The inverter units sends a data set to the supply unit, which returns the next data set to the inverter unit.

The communication uses data sets 10 and 11. Data sets 10 is sent by the inverter unit to the supply unit, while data set 11 is sent by the supply unit to the inverter unit. The contents of the data sets are freely configurable, but data set 10 typically contains the control word, while data set 11 returns the status word.

With ACS880 single drives with a separately-controlled supply unit, the basic communication is initialized by parameter *95.20 HW options word 1*. This will make several parameters visible (see below).

If the supply unit is regenerative, it is possible to send a DC voltage and/or reactive power reference to it from inverter parameter group *94 LSU control*. A regenerative supply unit will also send actual signals to the inverter unit which are visible in parameter group *01 Actual values*.

Settings

- Parameters 01.102...01.164 (page 140), 05.111...05.121 (page 149), 06.36...06.43 (page 156), 06.116...06.118 (page 162), 07.106...07.107 (page 165), 30.101...30.149 (page 285), 31.120...31.121 (page 297), 95.20 HW options word 1 (page 457) and 96.108 LSU control board boot (page 468).
- Parameter groups 60 DDCS communication (page 377), 61 D2D and DDCS transmit data (page 390), 62 D2D and DDCS receive data (page 394) and 94 LSU control (page 451).

Motor control

Direct torque control (DTC)

The motor control of the ACS880 is based on direct torque control (DTC), the ABB premium motor control platform. The switching of the output semiconductors is controlled to achieve the required stator flux and motor torque. The switching frequency is changed only if the actual torque and stator flux values differ from their reference values by more than the allowed hysteresis. The reference value for the torque controller comes from the speed controller or directly from an external torque reference source.

Motor control requires measurement of the DC voltage and two motor phase currents. Stator flux is calculated by integrating the motor voltage in vector space. Motor torque is calculated as a cross product of the stator flux and the rotor current. By utilizing the identified motor model, the stator flux estimate is improved. Actual motor shaft speed is not needed for the motor control.

The main difference between traditional control and DTC is that torque control operates on the same time level as the power switch control. There is no separate voltage and frequency controlled PWM modulator; the output stage switching is wholly based on the electromagnetic state of the motor.

The best motor control accuracy is achieved by activating a separate motor identification run (ID run).

See also section Scalar motor control (page 91).

Settings

Parameters 99.04 Motor control mode (page 475) and 99.13 ID run requested (page 478).

Reference ramping

Acceleration and deceleration ramping times can be set individually for speed, torque and frequency reference.

With a speed or frequency reference, the ramps are defined as the time it takes for the drive to accelerate or decelerate between zero speed or frequency and the value defined by parameter *46.01 Speed scaling* or *46.02 Frequency scaling*. The user can switch between two preset ramp sets using a binary source such as a digital input. For speed reference, also the shape of the ramp can be controlled.

With a torque reference, the ramps are defined as the time it takes for the reference to change between zero and nominal motor torque (parameter *01.30 Nominal torque scale*).

Special acceleration/deceleration ramps

The acceleration/deceleration times for the jogging function can be defined separately; see section *Jogging* (page *89*).

The change rate of the motor potentiometer function (page 91) is adjustable. The same rate applies in both directions.

A deceleration ramp can be defined for emergency stop ("Off3" mode).

Settings

- Speed reference ramping: Parameters 23.16...23.19 and 46.01 (pages 244 and 348).
- Torque reference ramping: Parameters 01.30, 26.18 and 26.19 (pages 138 and 267).
- Frequency reference ramping: 46.02 (pages 348).
- Jogging: Parameters 23.20 and 23.21 (page 244).
- Motor potentiometer: Parameter 22.75 (page 240).
- Emergency stop ("Off3" mode): Parameter 23.23 Emergency stop time (page 244).

Constant speeds/frequencies

Constant speeds and frequencies are predefined references that can be quickly activated, for example, through digital inputs. It is possible to define up to 7 constant speeds for speed control and 7 constant frequencies for frequency control.

WARNING: Constant speeds and frequencies override the normal reference irrespective of where the reference is coming from.

The constant speeds/frequencies function operates on a 2 ms time level.

Settings

Parameter groups 22 Speed reference selection (page 234) and 28 Frequency reference chain (page 270).

Critical speeds/frequencies

Critical speeds (sometimes called "skip speeds") can be predefined for applications where it is necessary to avoid certain motor speeds or speed ranges because of, for example, mechanical resonance problems.

The Critical speeds function prevents the reference from dwelling within a critical band for extended times. When a changing reference (22.87 Speed reference act 7) enters a critical range, the output of the function (22.01 Speed ref unlimited) freezes

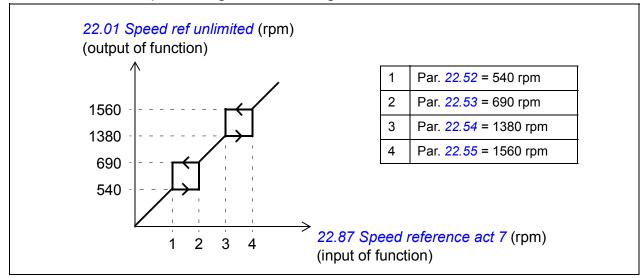
until the reference exits the range. Any instant change in the output is smoothed out by the ramping function further in the reference chain.

The function is also available for scalar motor control with a frequency reference. The input of the function is shown by 28.96 *Frequency ref act* 7, the output by 28.97 *Frequency ref unlimited*.

Example

A fan has vibrations in the range of 540 to 690 rpm and 1380 to 1560 rpm. To make the drive avoid these speed ranges,

- enable the critical speeds function by turning on bit 0 of parameter 22.51 Critical speed function, and
- set the critical speed ranges as in the figure below.



Settings

- Critical speeds: parameters 22.51...22.57 (page 239).
- Critical frequencies: parameters 28.51...28.57 (page 275).

Speed controller autotune

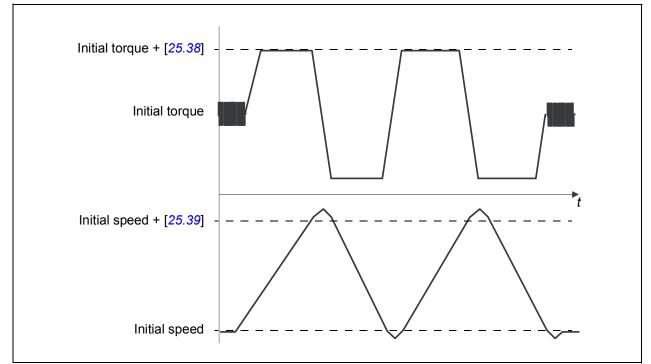
The speed controller of the drive can be automatically adjusted using the autotune function. Autotuning is based on an estimation of the mechanical time constant (inertia) of the motor and machine.

The autotune routine runs the motor through a series of acceleration/deceleration cycles, the number of which can be adjusted by parameter *25.40 Autotune repeat times*. Higher values produce more accurate results, especially if the difference between initial and maximum speeds is small.

The maximum torque reference used during autotuning is the initial torque (ie. torque when the routine is activated) plus 25.38 Autotune torque step, unless limited by the maximum torque limit (parameter group 30 Limits) or the nominal motor torque (99 Motor data). The calculated maximum speed during the routine is the initial speed (ie.

speed when the routine is activated) + 25.39 Autotune speed step, unless limited by 30.12 Maximum speed or 99.09 Motor nominal speed.

The diagram below shows the behavior of speed and torque during the autotune routine. In this example, *25.40 Autotune repeat times* is set to 2.



Notes:

- If the drive cannot produce the requested braking power during the routine, the results will be based on the acceleration stages only, and not as accurate as with full braking power.
- The motor exceeds the calculated maximum speed slightly at the end of each acceleration stage.

Before activating the autotune routine

The prerequisites for performing the autotune routine are:

- The motor identification run (ID run) has been successfully completed
- Speed and torque limits (parameter group 30 Limits) have been set
- The speed feedback has been monitored for noise, vibrations and other disturbances caused by the mechanics of the system, and
 - speed feedback filtering (parameter group 90 Feedback selection)
 - speed error filtering (24 Speed reference conditioning) and
 - zero speed (parameters 21.06 and 21.07)

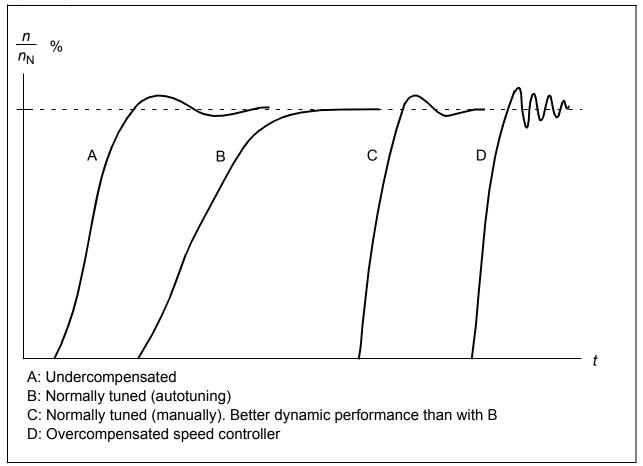
have been set to eliminate these disturbances.

• The drive has been started and is running in speed control mode.

After these conditions have been fulfilled, autotuning can be activated by parameter 25.33 Speed controller autotune (or the signal source selected by it).

Autotune modes

Autotuning can be performed in three different ways depending on the setting of parameter 25.34 Speed controller autotune mode. The selections Smooth, Normal and Tight define how the drive torque reference should react to a speed reference step after tuning. The selection Smooth will produce a slow but robust response; Tight will produce a fast response but possibly too high gain values for some applications. The figure below shows speed responses at a speed reference step (typically 1...20%).



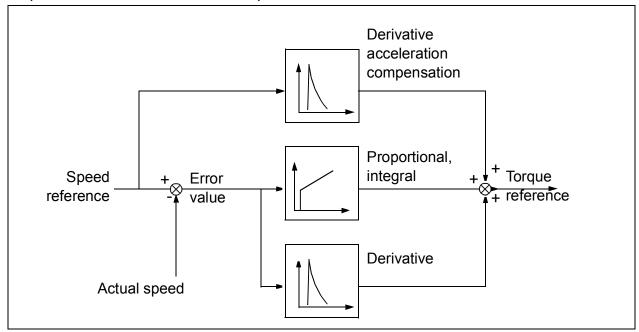
Autotune results

At the end of a successful autotune routine, its results are automatically transferred into parameters

- 25.02 Speed proportional gain (proportional gain of the speed controller)
- 25.03 Speed integration time (integration time of the speed controller)
- 25.37 *Mechanical time constant* (mechanical time constant of the motor and machine).

Nevertheless, it is still possible to manually adjust the controller gain, integration time and derivation time.

The figure below is a simplified block diagram of the speed controller. The controller output is the reference for the torque controller.



Warning indications

A warning message, *AF90 Speed controller autotuning*, will be generated if the autotune routine does not complete successfully. See chapter *Fault tracing* (page *549*) for further information.

Settings

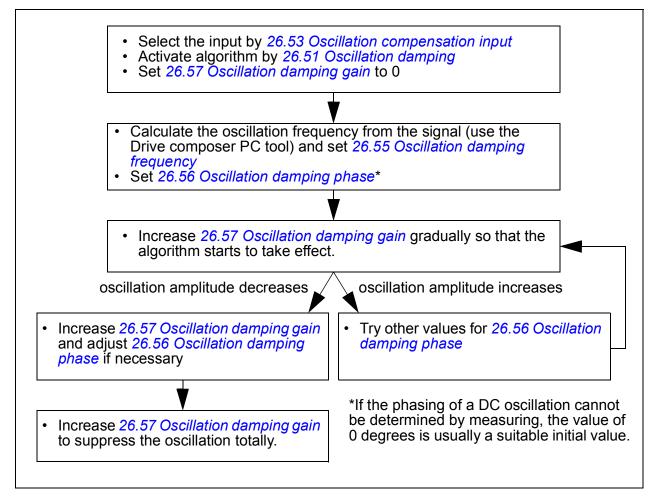
Parameters 25.33...25.40 (page 262).

Oscillation damping

The oscillation damping function can be used to cancel out oscillations caused by mechanics or an oscillating DC voltage. The input – a signal reflecting the oscillation – is selected by parameter 26.53 Oscillation compensation input. The oscillation damping function outputs a sine wave (26.58 Oscillation damping output) which can be summed with the torque reference with a suitable gain (26.57 Oscillation damping gain) and phase shift (26.56 Oscillation damping phase).

The oscillation damping algorithm can be activated without connecting the output to the reference chain, which makes it possible to compare the input and output of the function and make further adjustments before applying the result.

Tuning procedure for oscillation damping



Note: Changing the speed error low-pass filter time constant or the integration time of the speed controller can affect the tuning of the oscillation damping algorithm. It is recommended to tune the speed controller before the oscillation damping algorithm. (The speed controller gain can be adjusted after the tuning of this algorithm.)

Settings

Parameters 26.51...26.58 (page 268).

Resonance frequency elimination

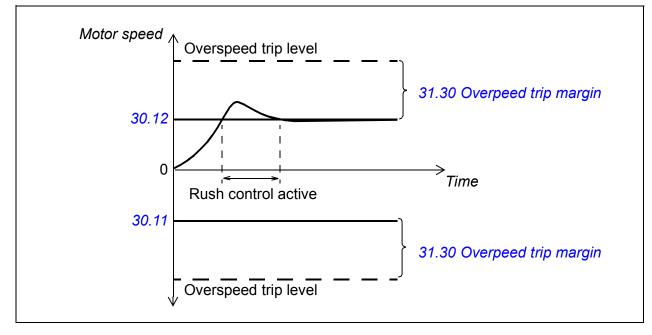
The control program contains a notch filter function for removing the resonance frequencies from the speed error signal.

Settings

Parameters 24.13...24.17 (page 248).

Rush control

In torque control, the motor could potentially rush if the load were suddenly lost. The control program has a rush control function that decreases the torque reference whenever the motor speed exceeds *30.11 Minimum speed* or *30.12 Maximum speed*.



The function is based on a PI controller. The proportional gain and integration time can be defined by parameters. Settings these to zero disables rush control.

Settings

Parameters 26.81 Rush control gain (page 270) and 26.82 Rush control integration time (page 270).

Encoder support

The program supports two single-turn or multiturn encoders (or resolvers). The following optional interface modules are available:

- TTL encoder interface FEN-01: two TTL inputs, TTL output (for encoder emulation and echo) and two digital inputs
- Absolute encoder interface FEN-11: absolute encoder input, TTL input, TTL output (for encoder emulation and echo) and two digital inputs
- Resolver interface FEN-21: resolver input, TTL input, TTL output (for encoder emulation and echo) and two digital inputs
- HTL encoder interface FEN-31: HTL encoder input, TTL output (for encoder emulation and echo) and two digital inputs.
- HTL/TTL encoder interface FSE-31 (for use with an FSO-xx safety functions module): Two HTL/TTL encoder inputs.

The interface module is to be installed onto one of the option slots on the drive control unit. The module (except the FSE-31) can also be installed onto an FEA-0x extension adapter.

Encoder echo and emulation

Both encoder echo and emulation are supported by the above-mentioned FEN-xx interfaces.

Encoder echo is available with TTL, TTL+ and HTL encoders. The signal received from the encoder is relayed to the TTL output unchanged. This enables the connection of one encoder to several drives.

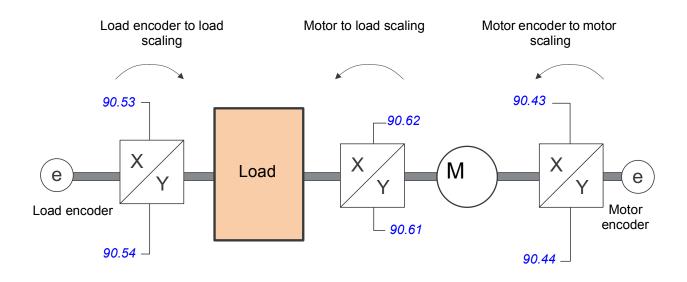
Encoder emulation also relays the encoder signal to the output, but the signal is either scaled, or position data converted to pulses. Emulation can be used when absolute encoder or resolver position needs to be converted to TTL pulses, or when the signal must be converted to a different pulse number than the original.

Load and motor feedback

Three different sources can be used as speed and position feedback: encoder 1, encoder 2, or motor position estimate. Any of these can be used for load position calculation or motor control. The load position calculation makes it possible, for example, to determine the position of a conveyor belt or the height of the load on a crane. The feedback sources are selected by parameters *90.41 Motor feedback selection* and *90.51 Load feedback selection*.

For detailed parameter connections of the motor and load feedback functions, see the block diagrams on pages 633 and 634. For more information on load position calculation, see section *Position counter* (page 84).

Any mechanical gear ratios between the components (motor, motor encoder, load, load encoder) are specified using the gear parameters shown in the diagram below.



Any gear ratio between the load encoder and the load is defined by *90.53 Load gear numerator* and *90.54 Load gear denominator*. Similarly, any gear ratio between the motor encoder and the motor is defined by *90.43 Motor gear numerator* and *90.44 Motor gear denominator*.

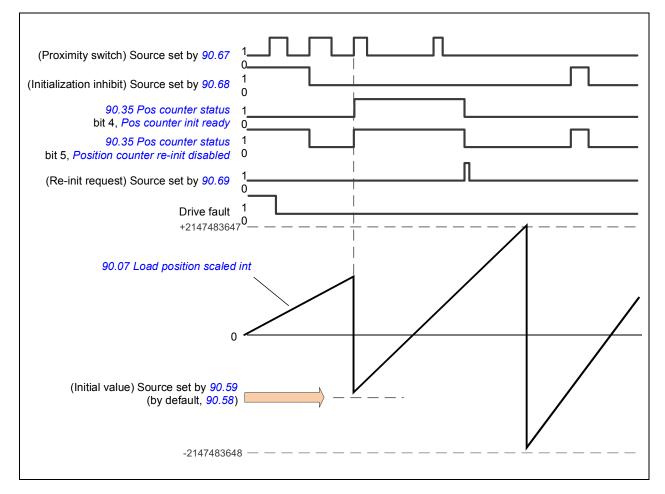
In case the internal estimated position is chosen as load feedback, the gear ratio between the motor and load can be defined by *90.61 Gear numerator* and *90.62 Gear denominator*. By default, all of the ratios mentioned above are 1:1. The ratios can only be changed with the drive stopped; new settings require validation by *91.10 Encoder parameter refresh*.

Position counter

The control program contains a position counter feature that can be used to indicate the position of the load. The output of the counter function, parameter 90.07 Load *position scaled int*, indicates the scaled number of revolutions read from the selected source (see section Load and motor feedback on page 83).

The relation between revolutions of the motor shaft and the translatory movement of the load (in any given unit of distance) is defined by parameters 90.63 Feed constant numerator and 90.64 Feed constant denominator. This gear function can be changed without the need of a parameter refresh or position counter reinitialization – however, the counter output is only updated after new position input data is received.

For detailed parameter connections of the load feedback function, see the block diagram on page 634.



The position counter is initialized by setting a known physical position of the load into the control program. The initial position (for example, the home/zero position, or the distance from it) can be entered manually in a parameter (*90.58 Pos counter init value int*), or taken from another parameter. This position is set as the value of the position counter (*90.07 Load position scaled int*) when the source selected by *90.67 Pos counter init cmd source*, such as a proximity switch connected to a digital input, is activated. A successful initialization is indicated by bit 4 of *90.35 Pos counter status*.

Any subsequent initialization of the counter must first be enabled by 90.69 Reset pos counter init ready. To define a time window for initializations, 90.68 Disable pos counter initialization can be used to inhibit the signal from the proximity switch. An active fault in the drive also prevents counter initialization.

Encoder error handling

When an encoder is used for load feedback, the action taken in case of an encoder error is specified by *90.55 Load feedback fault*. If the parameter is set to *Warning*, the calculation will continue smoothly using estimated motor position. If the encoder recovers from the error, the calculation will smoothly switch back to encoder feedback. The load position signals (*90.04*, *90.05* and *90.07*) will continue to be updated all the time, but bit 6 of *90.35 Pos counter status* will be set to indicate

potentially inaccurate position data. In addition, bit 4 of 90.35 will be cleared upon the next stop as a recommendation to reinitialize the position counter.

Parameter 90.60 Pos counter error and boot action defines whether position calculation resumes from the previous value over an encoder error or control unit reboot. By default, bit 4 of 90.35 Pos counter status is cleared after an error, indicating that reinitialization is needed. With 90.60 set to Continue from previous value, the position values are retained over an error or reboot; bit 6 of 90.35 is set however to indicate that an error occurred.

Note: With a multiturn absolute encoder, bit 6 of 90.35 is cleared at the next stop of the drive if the encoder has recovered from the error; bit 4 is not cleared. The status of the position counter is retained over a control unit reboot, after which position calculation resumes from the absolute position given by the encoder, taking into account the initial position specified by 90.58.

WARNING! If the drive is in stopped state when an encoder error occurs, or if the drive is not powered, parameters 90.04, 90.05, 90.07 and 90.35 are not updated because no movement of the load can be detected. When using previous position values (90.60 Pos counter error and boot action is set to Continue from previous value), be aware that the position data is unreliable if the load is able to move.

Reading/writing position counter values through fieldbus

The parameters of the position counter function, such as 90.07 Load position scaled *int* and 90.58 Pos counter *init value int*, can be accessed from an upper-level control system in the following formats:

- 16-bit integer (if 16 bits are sufficient for the application)
- 32-bit integer (can be accessed as two consequent 16-bit words)

For example, to read parameter 90.07 Load position scaled int through fieldbus, set the selection parameter of the desired dataset (in group 52) to Other - 90.07, and select the format. If you select a 32-bit format, the subsequent data word is also automatically reserved.

Configuration of HTL encoder motor feedback

- 1. Specify the type of the encoder interface module (parameter 91.11 Module 1 type = *FEN*-31) and the slot the module is installed into (91.12 Module 1 location).
- 2. Specify the type of the encoder (92.01 Encoder 1 type = HTL). The parameter listing will be re-read from the drive after the value is changed.
- 3. Specify the interface module that the encoder is connected to (92.02 Encoder 1 source = Module 1).
- 4. Set the number of pulses according to encoder nameplate (92.10 Pulses/revolution).

- 5. If the encoder rotates at a different speed to the motor (ie. is not mounted directly on the motor shaft), enter the gear ratio in *90.43 Motor gear numerator* and *90.44 Motor gear denominator*.
- 6. Set parameter *91.10 Encoder parameter refresh* to *Refresh* to apply the new parameter settings. The parameter will automatically revert to *Done*.
- Check that <u>91.02 Module 1 status</u> is showing the correct interface module type (*FEN-31*). Also check the status of the module; both LEDs should be glowing green.
- 8. Start the motor with a reference of eg. 400 rpm.
- 9. Compare the estimated speed (01.02 Motor speed estimated) with the measured speed (01.04 Encoder 1 speed filtered). If the values are the same, set the encoder as the feedback source (90.41 Motor feedback selection = Encoder 1).
- 10. Specify the action taken in case the feedback signal is lost (90.45 Motor feedback *fault*).

Example 1: Using the same encoder for both load and motor feedback

The drive controls a motor used for lifting a load in a crane. An encoder attached to the motor shaft is used as feedback for motor control. The same encoder is also used for calculating the height of the load in the desired unit. A gear exists between the motor shaft and the cable drum. The encoder is configured as Encoder 1 as shown in *Configuration of HTL encoder motor feedback* above. In addition, the following settings are made:

- (90.43 Motor gear numerator = 1)
- (90.44 Motor gear denominator = 1)

(No gear is needed as the encoder is mounted directly on the motor shaft.)

- 90.51 Load feedback selection = Encoder 1
- (90.53 Load gear numerator = 1)
- 90.54 Load gear denominator = 50

The cable drum turns one revolution per 50 revolutions of the motor shaft.

- (90.61 Gear numerator = 1)
- (90.62 Gear denominator = 1)

(These parameters need not be changed as position estimate is not being used for feedback.)

- 90.63 Feed constant numerator = 7
- 90.64 Feed constant denominator = 10

The load moves 70 centimeters, ie. 7/10 of a meter, per one revolution of the cable drum.

The load height in meters can be read from *90.07 Load position scaled int*, while *90.03 Load speed* displays the rotational speed of the cable drum.

Example 2: Using two encoders

One encoder (encoder 1) is used for motor feedback. The encoder is connected to the motor shaft through a gear. Another encoder (encoder 2) measures the line speed elsewhere in the machine. Each encoder is configured as shown in *Configuration of HTL encoder motor feedback* above. In addition, the following settings are made:

- (90.41 Motor feedback selection = Encoder 1)
- (90.43 Motor gear numerator = 1)
- 90.44 Motor gear denominator = 3

The encoder turns three revolutions per one revolution of the motor shaft.

• 90.51 Load feedback selection = Encoder 2

The line speed measured by encoder 2 can be read from 90.03 Load speed. This value is given in rpm which can be converted into another unit by using 90.53 Load gear numerator and 90.54 Load gear denominator. Note that the feed constant gear cannot be used in this conversion because it does not affect 90.03 Load speed.

Example 3: ACS 600 / ACS800 compatibility

With ACS 600 and ACS800 drives, both the rising and falling edges from encoder channels A and B are typically counted to achieve best possible accuracy. Thus the received pulse number per revolution equals four times the nominal pulse number of the encoder.

In this example, an HTL-type 2048-pulse encoder is fitted directly on the motor shaft. The desired initial position to correspond the proximity switch is 66770.

In the ACS880, the following settings are made:

- 92.01 Encoder 1 type = HTL
- 92.02 Encoder 1 source = Module 1
- 92.10 Pulses/revolution = 2048
- 92.13 Position estimation enable = Enable
- 90.51 Load feedback selection = Encoder 1
- 90.63 Feed constant numerator = 8192 (that is 4 × value of 92.10, as the received number of pulses is 4 times nominal. See also parameter 92.12 Resolver polepairs)
- The desired "data out" parameter is set to Other 90.58 Pos counter init value int (32-bit format). Only the high word needs to be specified the subsequent data word is reserved for the low word automatically.
- The desired sources (such as digital inputs or user bits of the control word) are selected in 90.67 Pos counter init cmd source and 90.69 Reset pos counter init ready.

In the PLC, if the initial value is set in 32-bit format using low and high words (corresponding to ACS800 parameters POS COUNT INIT LO and POS COUNT INIT HI), enter the value 66770 into these words as follows:

For example,

PROFIBUS:

- FBA data out x = POS COUNT INIT HI = 1 (as bit 16 equals 66536)
- FBA data out (x + 1) = POS COUNT INIT LO = 1234.

ABB Automation using DDCS communication, eg.:

- Data set 12.1 = POS COUNT INIT HI
- Data set 12.2 = POS COUNT INIT LO

To test the configuration of the PLC, initialize the position counter with the encoder connected. The initial value sent from the PLC should immediately be reflected by *90.07 Load position scaled int* in the drive. The same value should then appear in the PLC after having been read from the drive.

Settings

Parameter groups 90 Feedback selection (page 430), 91 Encoder module settings (page 439), 92 Encoder 1 configuration (page 442) and 93 Encoder 2 configuration (page 449).

Jogging

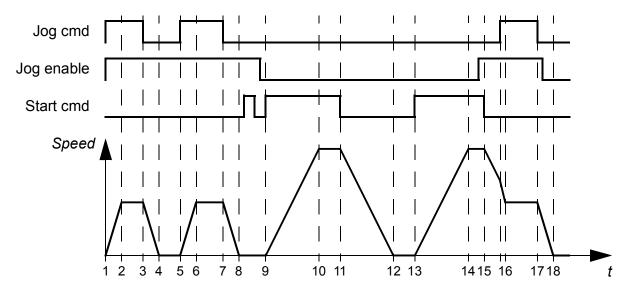
The jogging function enables the use of a momentary switch to briefly rotate the motor. The jogging function is typically used during servicing or commissioning to control the machinery locally.

Two jogging functions (1 and 2) are available, each with their own activation sources and references. The signal sources are selected by parameters 20.26 Jogging 1 start source and 20.27 Jogging 2 start source. When jogging is activated, the drive starts and accelerates to the defined jogging speed (22.42 Jogging 1 ref or 22.43 Jogging 2 ref) along the defined jogging acceleration ramp (23.20 Acc time jogging). After the activation signal switches off, the drive decelerates to a stop along the defined jogging deceleration ramp (23.21 Dec time jogging).

The figure and table below provide an example of how the drive operates during jogging. In the example, the ramp stop mode is used (see parameter *21.03 Stop mode*).

Jog cmd = State of source set by 20.26 Jogging 1 start source or 20.27 Jogging 2 start source

Jog enable = State of source set by 20.25 Jogging enable Start cmd = State of drive start command.



Phase	Jog cmd	Jog enable	Start cmd	Description
1-2	1	1	0	Drive accelerates to the jogging speed along the acceleration ramp of the jogging function.
2-3	1	1	0	Drive follows the jog reference.
3-4	0	1	0	Drive decelerates to zero speed along the deceleration ramp of the jogging function.
4-5	0	1	0	Drive is stopped.
5-6	1	1	0	Drive accelerates to the jogging speed along the acceleration ramp of the jogging function.
6-7	1	1	0	Drive follows the jog reference.
7-8	0	1	0	Drive decelerates to zero speed along the deceleration ramp of the jogging function.
8-9	0	1->0	0	Drive is stopped. As long as the jog enable signal is on, start commands are ignored. After jog enable switches off, a fresh start command is required.
9-10	х	0	1	Drive accelerates to the speed reference along the selected acceleration ramp (parameters 23.1123.19).
10-11	х	0	1	Drive follows the speed reference.
11-12	х	0	0	Drive decelerates to zero speed along the selected deceleration ramp (parameters 23.1123.19).
12-13	х	0	0	Drive is stopped.

Phase	Jog cmd	Jog enable	Start cmd	Description
13-14	х	0	1	Drive accelerates to the speed reference along the selected acceleration ramp (parameters 23.1123.19).
14-15	x	0->1	1	Drive follows the speed reference. As long as the start command is on, the jog enable signal is ignored. If the jog enable signal is on when the start command switches off, jogging is enabled immediately.
15-16	0->1	1	0	Drive accelerates to the speed reference along the selected acceleration ramp (parameters 23.1123.19).
16-17	1	1	0	Drive follows the jog reference.
17-18	0	1->0	0	Drive decelerates to zero speed along the deceleration ramp of the jogging function.

See also the block diagram on page 632.

The jogging function operates on a 2 ms time level.

Notes:

- Jogging is not available when the drive is in local control.
- Jogging cannot be enabled when the drive start command is on, or the drive started when jogging is enabled. Starting the drive after the jog enable switches off requires a fresh start command.

WARNING! If jogging is enabled and activated while the start command is on, jogging will activate as soon as the start command switches off.

- If both jogging functions are activated, the one that was activated first has priority.
- Jogging uses the speed control mode.
- Ramp shape times (parameters 23.16...23.19) do not apply to jogging acceleration/deceleration ramps.
- The inching functions activated through fieldbus (see *06.01 Main control word*, bits 8...9) use the references and ramp times defined for jogging, but do not require the jog enable signal.

Settings

Parameters 20.25 Jogging enable (page 226), 20.26 Jogging 1 start source (page 226), 20.27 Jogging 2 start source (page 227), 22.42 Jogging 1 ref (page 238), 22.43 Jogging 2 ref (page 238), 23.20 Acc time jogging (page 244) and 23.21 Dec time jogging (page 244).

Scalar motor control

It is possible to select scalar control as the motor control method instead of DTC (Direct Torque Control). In scalar control mode, the drive is controlled with a speed

reference. However, the outstanding performance of DTC is not achieved in scalar control.

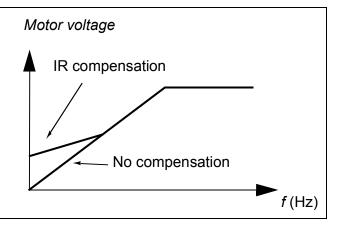
It is recommended to activate scalar motor control mode

- if the nominal current of the motor is less than 1/6 of the nominal output current of the drive
- if the drive is used without a motor connected (for example, for test purposes)
- if the drive runs a medium-voltage motor through a step-up transformer, or
- in multimotor drives, if
 - the load is not equally shared between the motors,
 - · the motors are of different sizes, or
 - the motors are going to be changed after motor identification (ID run)
- In scalar control, some standard features are not available.

See also section *Operating modes of the drive* (page 57).

IR compensation for scalar motor control

IR compensation (also known as voltage boost) is available only when the motor control mode is scalar. When IR compensation is activated, the drive gives an extra voltage boost to the motor at low speeds. IR compensation is useful in applications that require a high break-away torque. In step-up applications, voltage cannot be fed through the transformer at 0 Hz, so an additional breakpoint is available for



defining the compensation near zero frequency.

In Direct Torque Control (DTC), no IR compensation is possible or needed as it is applied automatically.

Settings

- Parameters 19.20 Scalar control reference unit (page 218), 97.12 IR comp stepup frequency (page 471), 97.13 IR compensation and 99.04 Motor control mode.
- Parameter group 28 Frequency reference chain (page 270).

Autophasing

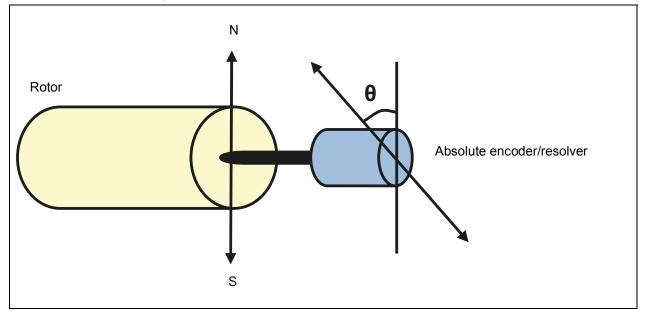
Autophasing is an automatic measurement routine to determine the angular position of the magnetic flux of a permanent magnet synchronous motor or the magnetic axis of a synchronous reluctance motor. The motor control requires the absolute position of the rotor flux in order to control motor torque accurately.

Sensors like absolute encoders and resolvers indicate the rotor position at all times after the offset between the zero angle of rotor and that of the sensor has been

established. On the other hand, a standard pulse encoder determines the rotor position when it rotates but the initial position is not known. However, a pulse encoder can be used as an absolute encoder if it is equipped with Hall sensors, albeit with coarse initial position accuracy. Hall sensors generate commutation pulses that change their state six times during one revolution, so it is only known within which 60° sector of a complete revolution the initial position is.

Many encoders give a zero pulse (also called Z-pulse) once during each rotation. The position of the zero pulse is fixed. If this position is known with respect to zero position used by motor control, the rotor position at the instant of the zero pulse is also known.

Using zero pulse improves the robustness of the rotor position measurement. The rotor position must be determined during starting because the initial value given the encoder is zero. The autophasing routine determines the position, but there is a risk of some position error. If the zero pulse position is known in advance, the position found by autophasing can be corrected as soon as the zero pulse is detected for the first time after starting.



The autophasing routine is performed with permanent magnet synchronous motors and synchronous reluctance motors in the following cases:

- 1. One-time measurement of the rotor and encoder position difference when an absolute encoder, a resolver, or an encoder with commutation signals is used
- 2. At every power-up when an incremental encoder is used
- 3. With open-loop motor control, repetitive measurement of the rotor position at every start.
- 4. When the position of the zero pulse must be measured before the first start after power-up.

Note: In closed-loop control, autophasing is performed automatically after the motor identification run (ID run). Autophasing is also performed automatically before starting when necessary.

In open-loop control, the zero angle of the rotor is determined before the starting. In closed-loop control, the actual angle of the rotor is determined with autophasing when the sensor indicates zero angle. The offset of the angle must be determined because the actual zero angles of the sensor and the rotor do not usually match. The autophasing mode determines how this operation is done both in open-loop and closed-loop control.

The rotor position offset used in motor control can also be given by the user – see parameter 98.15 Position offset user. Note that the autophasing routine also writes its result into this parameter. The results are updated even if user settings are not enabled by 98.01 User motor model mode.

Note: In open-loop mode, the motor always turns when it is started as the shaft is turned towards the remanence flux.

Bit 4 of *06.21 Drive status word 3* indicates if the rotor position has already been determined.

Autophasing modes

Several autophasing modes are available (see parameter 21.13 Autophasing mode).

The turning mode (*Turning*) is recommended especially with case 1 (see the list above) as it is the most robust and accurate method. In turning mode, the motor shaft is turned back and forward (\pm 360/polepairs)° in order to determine the rotor position. In case 3 (open-loop control), the shaft is turned only in one direction and the angle is smaller.

Another turning mode, *Turning with Z-pulse*, can be used if there is difficulty using the normal turning mode, for example, because of significant friction. With this mode, the rotor is turned slowly until a zero pulse is detected from the encoder. When the zero pulse is detected for the first time, its position is stored into parameter *98.15 Position offset user*, which can be edited for fine-tuning. Note that it is not mandatory to use this mode with a zero pulse encoder. In open-loop control, the two turning modes are identical.

The standstill modes (*Standstill 1*, *Standstill 2*) can be used if the motor cannot be turned (for example, when the load is connected). As the characteristics of motors and loads differ, testing must be done to find out the most suitable standstill mode.

The drive is capable of determining the rotor position when started into a running motor in open-loop or closed-loop control. In this situation, the setting of *21.13 Autophasing mode* has no effect.

The autophasing routine can fail and therefore it is recommended to perform the routine several times and check the value of parameter *98.15 Position offset user*.

An autophasing fault (3385 Autophasing) can occur with a running motor if the estimated angle of the motor differs too much from the measured angle. This could be caused by, for example, the following:

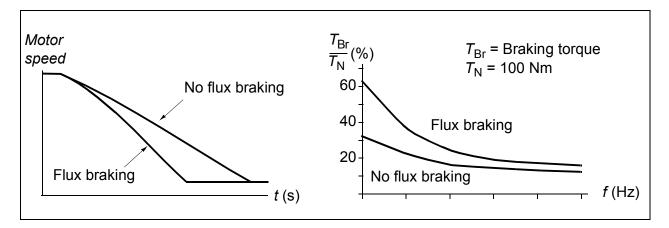
- The encoder is slipping on the motor shaft
- An incorrect value has been entered into 98.15 Position offset user
- · The motor is already turning before the autophasing routine is started
- *Turning* mode is selected in *21.13 Autophasing mode* but the motor shaft is locked
- *Turning with Z-pulse* mode is selected in *21.13 Autophasing mode*, but no zero pulse is detected within a revolution of the motor
- The wrong motor type is selected in 99.03 Motor type
- Motor ID run has failed.

Settings

Parameters 06.21 Drive status word 3 (page 154), 21.13 Autophasing mode (page 232), 98.15 Position offset user (page 475) and 99.13 ID run requested (page 478).

Flux braking

The drive can provide greater deceleration by raising the level of magnetization in the motor. By increasing the motor flux, the energy generated by the motor during braking can be converted to motor thermal energy.



The drive monitors the motor status continuously, also during flux braking. Therefore, flux braking can be used both for stopping the motor and for changing the speed. The other benefits of flux braking are:

- The braking starts immediately after a stop command is given. The function does not need to wait for the flux reduction before it can start the braking.
- The cooling of the induction motor is efficient. The stator current of the motor increases during flux braking, not the rotor current. The stator cools much more efficiently than the rotor.
- Flux braking can be used with induction motors and permanent magnet synchronous motors.

Two braking power levels are available:

- Moderate braking provides faster deceleration compared to a situation where flux braking is disabled. The flux level of the motor is limited to prevent excessive heating of the motor.
- Full braking exploits almost all available current to convert the mechanical braking energy to motor thermal energy. Braking time is shorter compared to moderate braking. In cyclic use, motor heating may be significant.

WARNING: The motor needs to be rated to absorb the thermal energy generated by flux braking.

Settings

Parameter 97.05 Flux braking (page 469).

DC magnetization

DC magnetization can be applied to the motor to

- · heat the motor to remove or prevent condensation, or
- to lock the rotor at, or near, zero speed.

Pre-heating

A motor pre-heating function is available to prevent condensation in a stopped motor, or to remove condensation from the motor before start. Pre-heating involves feeding a DC current into the motor to heat up the windings.

Pre-heating is deactivated at start, or when one of the other DC magnetization functions is activated. With the drive stopped, pre-heating is disabled by the safe torque off function, a drive fault state, or the process PID sleep function. Pre-heating can only start after one minute has elapsed from stopping the drive.

A digital source to control pre-heating is selected by parameter 21.14 Pre-heating *input source*. The heating current is set by 21.16 Pre-heating current.

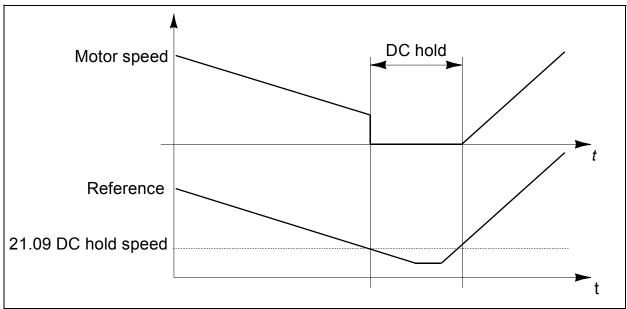
Pre-magnetization

Pre-magnetization refers to DC magnetization of the motor before start. Depending on the selected start mode (*21.01 Start mode* or *21.19 Scalar control mode*), premagnetization can be applied to guarantee the highest possible breakaway torque, up to 200% of the nominal torque of the motor. By adjusting the pre-magnetization time (*21.02 Magnetization time*), it is possible to synchronize the motor start and, for example, the release of a mechanical brake.

DC hold

The function makes it possible to lock the rotor at (near) zero speed in the middle of normal operation. DC hold is activated by parameter *21.08 DC current control*. When both the reference and motor speed drop below a certain level (parameter *21.09 DC hold speed*), the drive stops generating sinusoidal current and starts to inject DC into the motor. The current is set by parameter *21.10 DC current reference*.

When the reference exceeds parameter 21.09 DC hold speed, normal drive operation continues.



Notes:

- DC hold is only available in speed control in DTC motor control mode (see page 57).
- The function applies the DC current to one phase only, depending on the position of the rotor. The return current will be shared between the other phases.

Post-magnetization

This feature keeps the motor magnetized for a certain period (parameter 21.11 Post *magnetization time*) after stopping. This is to prevent the machinery from moving under load, for example before a mechanical brake can be applied. Post-magnetization is activated by parameter 21.08 DC current control. The magnetization current is set by parameter 21.10 DC current reference.

Note: Post-magnetization is only available in speed control in DTC motor control mode, and only when ramping is the selected stop mode (see parameter *21.03 Stop mode*).

Continuous magnetization

A digital signal, such as a user bit in the fieldbus control word, can be selected to activate continuous magnetization. This can be especially useful in processes requiring motors to be stopped (for example, to stand by until new material is processed), then quickly started without magnetizing them first.

Note: Continuous magnetization is only available in speed control in DTC motor control mode (see page 75), and only when ramping is the selected stop mode (see parameter 21.03 Stop mode).



WARNING: The motor must be designed to absorb or dissipate the thermal energy generated by continuous magnetization, for example by forced ventilation.

Settings

Parameters 06.21 Drive status word 3 (page 154), 21.01 Start mode (page 227), 21.02 Magnetization time (page 228), 21.08...21.12 (page 231), 21.14 Pre-heating input source (page 232) and 21.16 Pre-heating current (page 232).

Hexagonal motor flux pattern

Note: This feature is only available in scalar motor control mode (see page 22).

Typically, the drive controls the motor flux so that the rotating flux vector follows a circular pattern. This is ideal for most applications. However, when operating above the field weakening point (FWP), it is not possible to reach 100% of the output voltage. This reduces the peak load capacity of the drive.

Using a hexagonal motor flux vector pattern, the maximum output voltage can be reached above the field weakening point. This increases the peak load capacity compared to the circular pattern, but the continuous load capacity in the range of FWP ... $1.6 \times$ FWP is reduced because of increasing losses. With hexagonal motor flux active, the pattern changes from circular to hexagonal gradually as the frequency rises from 100% to 120% of the FWP.

Settings

Parameters 97.18 Hexagonal field weakening (page 472) and 97.19 Hexagonal field weakening point (page 473).

Application control

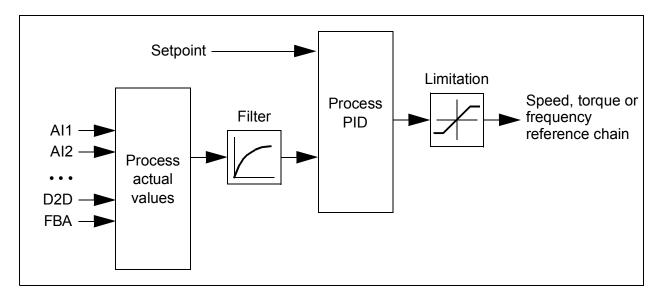
Process PID control

There is a built-in process PID controller in the drive. The controller can be used to control process variables such as pressure, flow or fluid level.

In process PID control, a process reference (setpoint) is connected to the drive instead of a speed reference. An actual value (process feedback) is also brought back to the drive. The process PID control adjusts the drive speed in order to keep the measured process quantity (actual value) at the desired level (setpoint).

Process PID control operates on a 2 ms time level.

The simplified block diagram below illustrates the process PID control. For a more detailed block diagram, see page 645.



The control program contains two complete sets of process PID controller settings that can be alternated whenever necessary; see parameter 40.57 PID set1/set2 selection.

Note: Process PID control is only available in external control; see section *Local control vs. external control* (page 54).

Quick configuration of the process PID controller

- 1. Activate the process PID controller (parameter 40.07 Set 1 PID operation mode).
- 2. Select a feedback source (parameters 40.08...40.11).

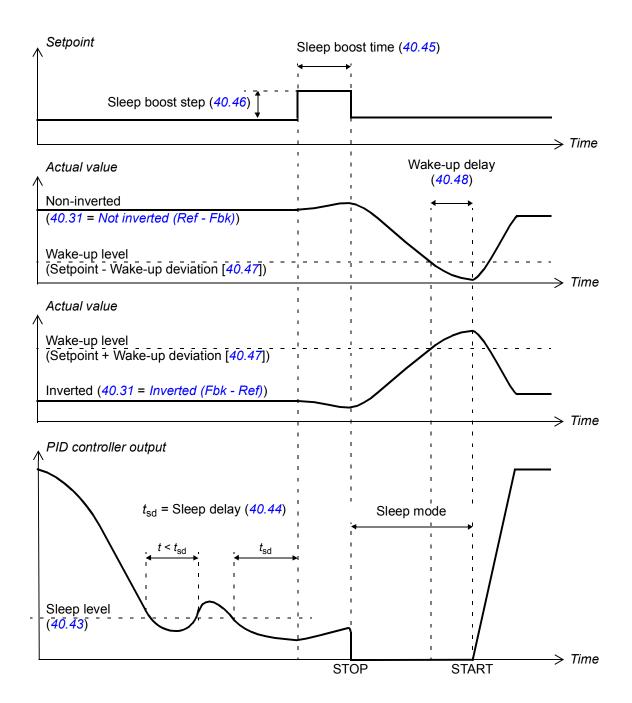
- 3. Select a setpoint source (parameters 40.16...40.25).
- 4. Set the gain, integration time, derivation time, and the PID output levels (40.32 Set 1 gain, 40.33 Set 1 integration time, 40.34 Set 1 derivation time, 40.36 Set 1 output min and 40.37 Set 1 output max).
- 5. The PID controller output is shown by parameter 40.01 Process PID output actual. Select it as the source of, for example, 22.11 Speed ref1 source.

Sleep function for process PID control

The sleep function can be used in PID control applications that involve relatively long periods of low demand (for example, a tank is at level), During such periods, the sleep function saves energy by stopping the motor completely, instead of running the motor slowly below the efficient operating range of the system. When the feedback changes, the PID controller wakes the drive up.

Note: The sleep function is disabled when mechanical brake control (see page *104*) is active.

Example: The drive controls a pressure boost pump. The water consumption falls at night. As a consequence, the process PID controller decreases the motor speed. However, due to natural losses in the pipes and the low efficiency of the centrifugal pump at low speeds, the motor would never stop rotating. The sleep function detects the slow rotation and stops unnecessary pumping after the sleep delay has passed. The drive shifts into sleep mode, still monitoring the pressure. The pumping resumes when the pressure falls under the wake-up level (setpoint - wake-up deviation) and the wake-up delay has passed.



Tracking

In tracking mode, the PID block output is set directly to the value of parameter 40.50 (or 41.50) Set 1 tracking ref selection. The internal I term of the PID controller is set so that no transient is allowed to pass on to the output, so when the tracking mode is left, normal process control operation can be resumed without a significant bump.

Settings

- Parameter 96.04 Macro select (page 460).
- Parameter groups 40 Process PID set 1 (page 325) and 41 Process PID set 2 (page 337).

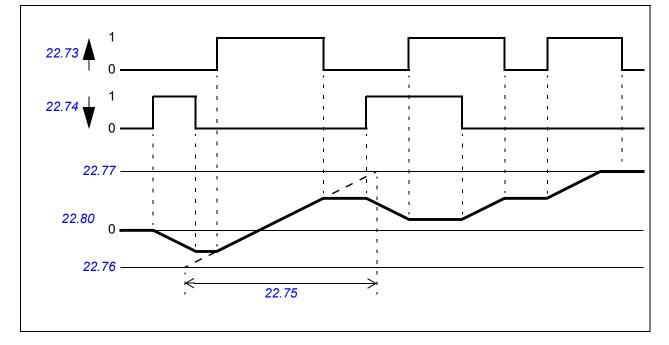
Motor potentiometer

The motor potentiometer is, in effect, a counter whose value can be adjusted up and down using two digital signals selected by parameters 22.73 *Motor potentiometer up source* and 22.74 *Motor potentiometer down source*. Note that these signals have no effect when the drive is stopped.

When enabled by 22.71 *Motor potentiometer function*, the motor potentiometer assumes the value set by 22.72 *Motor potentiometer initial value*. Depending on the mode selected in 22.71, the motor potentiometer value is either retained or reset over a power cycle.

The change rate is defined in 22.75 *Motor potentiometer ramp time* as the time it would take for the value to change from the minimum (22.76 *Motor potentiometer min value*) to the maximum (22.77 *Motor potentiometer max value*) or vice versa. If the up and down signals are simultaneously on, the motor potentiometer value does not change.

The output of the function is shown by 22.80 *Motor potentiometer ref act*, which can directly be set as the source of any selector parameter such as 22.11 *Speed ref1 source*.



The following example shows the behavior of the motor potentiometer value.

Settings

Parameters 22.71...22.80 (page 239).

Mechanical brake control

A mechanical brake can be used for holding the motor and driven machinery at zero speed when the drive is stopped, or not powered. The brake control logic observes the settings of parameter group *44 Mechanical brake control* as well as several external signals, and moves between the states presented in the diagram on page *105*. The tables below the state diagram detail the states and transitions. The timing diagram on page *107* shows an example of a close-open-close sequence.

The mechanical brake control logic operates on a 10 ms time level.

Inputs of the brake control logic

The start command of the drive (bit 5 of 06.16 Drive status word 1) is the main control source of the brake control logic. An optional external open/close signal can be selected by 44.12 Brake close request. The two signals interact as follows:

- Start command = 1 AND signal selected by 44.12 Brake close request = 0
 → Request brake to open
- Start command = 0 OR signal selected by 44.12 Brake close request = 1
 → Request brake to close

Another external signal – for example, from a higher-level control system – can be connected via parameter *44.11 Keep brake closed* to prevent the brake from opening.

Other signals that affect the state of the control logic are

- brake status acknowledgement (optional, defined by 44.07 Brake acknowledge selection),
- bit 2 of *06.11 Main status word* (indicates whether the drive is ready to follow the given reference or not),
- bit 6 of 06.16 Drive status word 1 (indicates whether the drive is modulating or not),
- optional FSO-xx safety functions module.

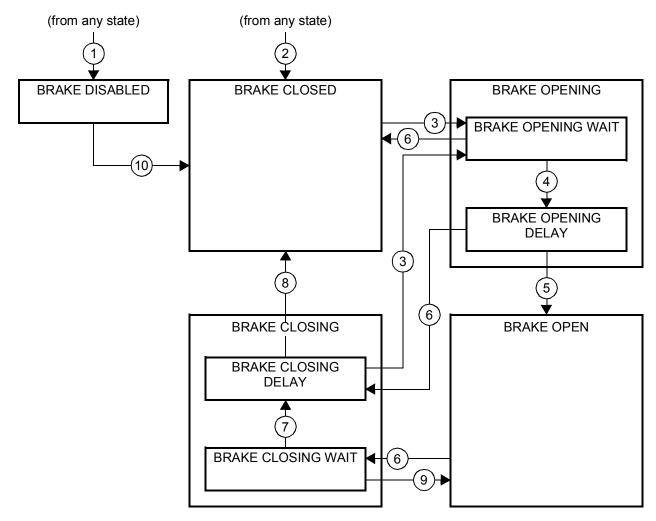
Outputs of the brake control logic

The mechanical brake is to be controlled by bit 0 of parameter *44.01 Brake control status*. This bit should be selected as the source of a relay output (or a digital input/output in output mode) which is then wired to the brake actuator through a relay. See the wiring example on page *108*.

The brake control logic, in various states, will request the drive control logic to hold the motor, increase the torque, or ramp down the speed. These requests are visible in parameter *44.01 Brake control status*.

Settings

Parameter group 44 Mechanical brake control (page 341).



Brake state diagram

State descriptions

State name	Description
BRAKE DISABLED	Brake control is disabled (parameter 44.06 Brake control enable = 0, and 44.01 Brake control status b4 = 0). The brake is closed (44.01 Brake control status $b0 = 0$).
BRAKE OPENING:	
BRAKE OPENING WAIT	Brake has been requested to open. The drive logic is requested to increase the torque up to opening torque to hold the load in place (44.01 Brake control status b1 = 1 and b2 = 1). The state of 44.11 Keep brake closed is checked; if it is not 0 within a reasonable time, the drive trips on a 71A5 Mechanical brake opening not allowed fault*.
BRAKE OPENING DELAY	Opening conditions have been met and open signal activated (44.01 Brake control status b0 is set). The opening torque request is removed (44.01 Brake control status b1 \rightarrow 0). The load is held in place by the speed control of the drive until 44.08 Brake open delay elapses.
	At this point, if <i>44.07 Brake acknowledge selection</i> is set to <i>No acknowledge</i> , the logic proceeds to <i>BRAKE OPEN</i> state. If an acknowledgement signal source has been selected, its state is checked; if the state is not "brake open", the drive trips on a <i>71A3 Mechanical brake opening failed</i> fault*.
BRAKE OPEN	The brake is open (44.01 Brake control status $b0 = 1$). Hold request is removed (44.01 Brake control status $b2 = 0$), and the drive is allowed to follow the reference.

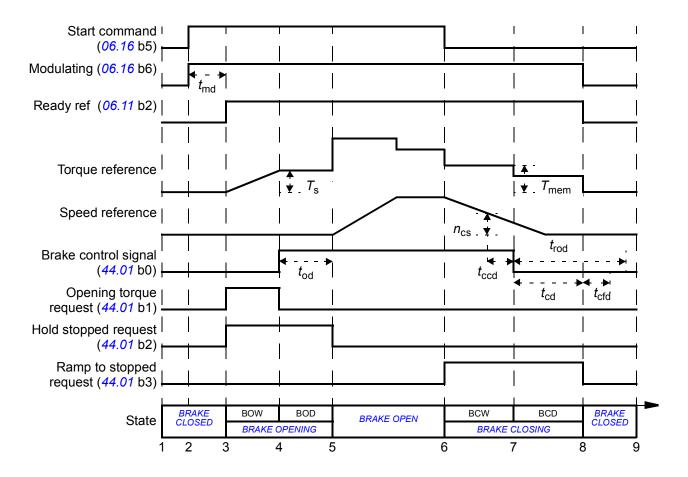
State name	Description	
BRAKE CLOSING:		
BRAKE CLOSING WAIT	Brake has been requested to close. The drive logic is requested to ramp down the speed to a stop (44.01 Brake control status $b3 = 1$). The open signal is kept active (44.01 Brake control status $b0 = 1$). The brake logic will remain in this state until the motor speed has remained below 44.14 Brake close level for the time defined by 44.15 Brake close level delay.	
BRAKE CLOSING DELAY	Closing conditions have been met. The open signal is deactivated (44.01 Brake control status $b0 \rightarrow 0$) and the closing torque written into 44.02 Brake torque memory. The ramp-down request is maintained (44.01 Brake control status b3 = 1). The brake logic will remain in this state until 44.13 Brake close delay has elapsed. At this point, if 44.07 Brake acknowledge selection is set to No acknowledge, the logic proceeds to BRAKE CLOSED state. If an acknowledgement signal source has been selected, its state is checked; if the state is not "brake closed", the drive generates an A7A1 Mechanical brake closing failed warning. If 44.17 Brake fault function = Fault, the drive will trip on a 71A2 Mechanical brake closing failed fault after 44.18 Brake fault delay.	
BRAKE CLOSED	The brake is closed (44.01 Brake control status b0 = 0). The drive is not necessarily modulating.	
	Note concerning open-loop (encoderless) applications: If the brake is kept closed by a brake close request (either from parameter <i>44.12</i> or an FSO-xx safety functions module) against a modulating drive for longer than 5 seconds, the brake is forced to closed state and the drive trips on a fault, <i>71A5 Mechanical brake opening not allowed</i> .	
*A warning can alternatively be selected by <i>44.17 Brake fault function</i> ; if so, the drive will keep modulating and remain in this state.		

State change conditions ((n))

- 1 Brake control disabled (parameter 44.06 Brake control enable \rightarrow 0).
- 2 *06.11 Main status word*, bit 2 = 0 or brake is forced to close by optional FSO-xx safety functions module.
- 3 Brake has been requested to open and *44.16 Brake reopen delay* has expired.
- 4 Brake open conditions (such as 44.10 Brake open torque) fulfilled and 44.11 Keep brake closed = 0.
- 5 *44.08 Brake open delay* has elapsed and brake open acknowledgement (if chosen by *44.07 Brake acknowledge selection*) has been received.
- 6 Brake has been requested to close.
- 7 Motor speed has remained below closing speed *44.14 Brake close level* for the duration of *44.15 Brake close level delay*.
- 8 44.13 Brake close delay for the duration of 44.15 Brake close level delay has elapsed and brake close acknowledgment (if chosen by 44.07 Brake acknowledge selection) has been received.
- 9 Brake has been requested to open.
- 10 Brake control enabled (parameter 44.06 Brake control enable \rightarrow 1).

Timing diagram

The simplified timing diagram below illustrates the operation of the brake control function. Refer to the state diagram above.



*T*_s Start torque at brake open (parameter *44.03 Brake open torque reference*)

- T_{mem} Stored torque value at brake close (44.02 Brake torque memory)
- *t*_{md} Motor magnetization delay
- *t*_{od} Brake open delay (parameter 44.08 Brake open delay)
- *n*_{cs} Brake close speed (parameter 44.14 Brake close level)
- *t*_{ccd} Brake close command delay (parameter 44.15 Brake close level delay)
- t_{cd} Brake close delay (parameter 44.13 Brake close delay)
- *t*_{cfd} Brake close fault delay (parameter 44.18 Brake fault delay)
- *t*_{rod} Brake reopen delay (parameter 44.16 Brake reopen delay)
- BOW BRAKE OPENING WAIT
- BOD BRAKE OPENING DELAY
- BCW BRAKE CLOSING WAIT
- BCD BRAKE CLOSING DELAY

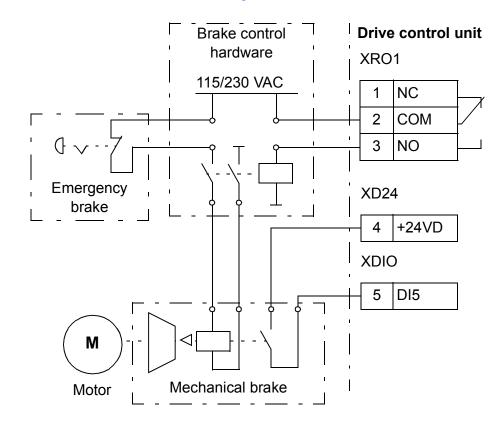
Wiring example

The figure below shows a brake control wiring example. The brake control hardware and wiring is to be sourced and installed by the customer.

WARNING! Make sure that the machinery into which the drive with brake control function is integrated fulfils the personnel safety regulations. Note that the frequency converter (a Complete Drive Module or a Basic Drive Module, as defined in IEC 61800-2), is not considered as a safety device mentioned in the European Machinery Directive and related harmonised standards. Thus, the personnel safety of the complete machinery must not be based on a specific frequency converter feature (such as the brake control function), but it has to be implemented as defined in the application specific regulations.

The brake is controlled by bit 0 of parameter 44.01 Brake control status. The source of brake acknowledge (status supervision) is selected by parameter 44.07 Brake acknowledge selection. In this example,

• parameter 10.24 RO1 source is set to Open brake command (ie. bit 0 of 44.01 Brake control status), and



• parameter 44.07 Brake acknowledge selection is set to DI5.

DC voltage control

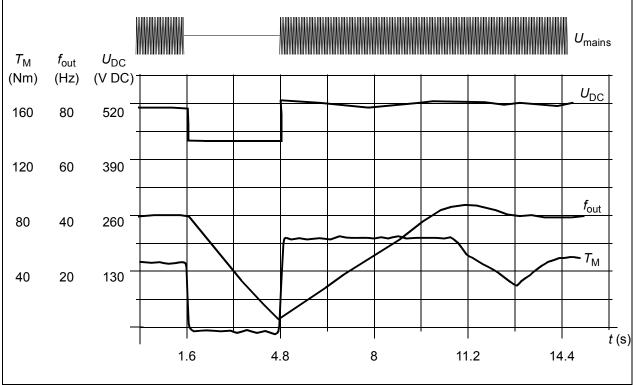
Overvoltage control

Overvoltage control of the intermediate DC link is typically needed when the motor is in generating mode. The motor can generate when it decelerates or when the load overhauls the motor shaft, causing the shaft to turn faster than the applied speed or frequency. To prevent the DC voltage from exceeding the overvoltage control limit, the overvoltage controller automatically decreases the generating torque when the limit is reached. The overvoltage controller also increases any programmed deceleration times if the limit is reached; to achieve shorter deceleration times, a brake chopper and resistor may be required.

Undervoltage control (power loss ride-through)

If the incoming supply voltage is cut off, the drive will continue to operate by utilizing the kinetic energy of the rotating motor. The drive will be fully operational as long as the motor rotates and generates energy to the drive. The drive can continue operation after the break if the main contactor (if present) remained closed.

Note: Units equipped with a main contactor must be equipped with a hold circuit (e.g. UPS) to keep the contactor control circuit closed during a short supply break.



 U_{DC} = intermediate circuit voltage of the drive, f_{out} = output frequency of the drive, T_{M} = motor torque Loss of supply voltage at nominal load (f_{out} = 40 Hz). The intermediate circuit DC voltage drops to the minimum limit. The controller keeps the voltage steady as long as the mains is switched off. The drive runs the motor in generator mode. The motor speed falls but the drive is operational as long as the motor has enough kinetic energy.

Automatic restart

It is possible to restart the drive automatically after a short (max. 5 seconds) power supply failure by using the Automatic restart function provided that the drive is allowed to run for 5 seconds without the cooling fans operating.

When enabled, the function takes the following actions upon a supply failure to enable a successful restart:

- The undervoltage fault is suppressed (but a warning is generated)
- · Modulation and cooling is stopped to conserve any remaining energy
- DC circuit pre-charging is enabled.

If the DC voltage is restored before the expiration of the period defined by parameter *21.18 Auto restart time* and the start signal is still on, normal operation will continue. However, if the DC voltage remains too low at that point, the drive trips on a fault, *3280 Standby timeout*.

WARNING! Before you activate the function, make sure that no dangerous situations can occur. the function restarts the drive automatically and continues operation after a supply break.

Voltage control and trip limits

The control and trip limits of the intermediate DC voltage regulator are relative to the supply voltage as well as drive/inverter type. The DC voltage is approximately 1.35 times the line-to-line supply voltage, and is displayed by parameter *01.11 DC voltage*.

All levels are relative to the supply voltage range selected in parameter 95.01 Supply voltage. The following table shows the values of selected DC voltage levels in volts and in percent of U_{DCmax} (the DC voltage at the upper bound of the supply voltage range).

	Supply voltage range [V AC] (see 95.01 Supply voltage)				age)	
Level [V DC (% of U _{DCmax})]	208240	380415	440480	500	525600	660690
Overvoltage fault limit	489/440*	800	878	880	1113	1218
Overvoltage control limit	405 (125)	700 (125)	810 (125)	810 (120)	1013 (125)	1167 (125)
Internal brake chopper at 100% pulse width	403 (124)	697 (124)	806 (124)	806 (119)	1008 (124)	1159 (124)
Internal brake chopper at 0% pulse width	375 (116)	648 (116)	749 (116)	780 (116)	936 (116)	1077 (116)
Overvoltage warning limit	373 (115)	644 (115)	745 (115)	776 (115)	932 (115)	1071 (115)
U _{DCmax} = DC voltage at upper bound of supply voltage range	324 (100)	560 (100)	648 (100)	675 (100)	810 (100)	932 (100)

	Supply voltage range [V AC] (see 95.01 Supply voltage)				age)	
Level [V DC (% of U _{DCmax})]	208240	380415	440480	500	525600	660690
DC voltage at lower bound of supply voltage range	281	513	594	675	709	891
Undervoltage control and warning limit	239 (85)	436 (85)	505 (85)	574 (85)	602 (85)	757 (85)
Charging activation/standby limit	225 (80)	410 (80)	475 (80)	540 (80)	567 (80)	713 (80)
Undervoltage fault limit	168 (60)	308 (60)	356 (60)	405 (60)	425 (60)	535 (60)

*489 V with frames R1...R3, 440 V with frames R4...R8.

Settings

Parameters 01.11 DC voltage (page 137), 30.30 Overvoltage control (page 285), 30.31 Undervoltage control (page 285), 95.01 Supply voltage (page 453) and 95.02 Adaptive voltage limits (page 453).

Brake chopper

A brake chopper can be used to handle the energy generated by a decelerating motor. When the DC voltage rises high enough, the chopper connects the DC circuit to an external brake resistor. The chopper operates on the pulse width modulation principle.

Some ACS880 drives have an internal brake chopper as standard, some have a brake chopper available as an internal or external option. See the appropriate hardware manual or sales catalog.

The internal brake choppers of ACS880 drives start conducting when the DC link voltage reaches $1.156 \times U_{DCmax}$. 100% pulse width is reached at approximately $1.2 \times U_{DCmax}$, depending on supply voltage range – see table under *Voltage control and trip limits* above. (U_{DCmax} is the DC voltage corresponding to the maximum of the AC supply voltage range.) For information on external brake choppers, refer to their documentation.

Note: For runtime braking, overvoltage control (parameter 30.30 Overvoltage control) needs to be disabled for the chopper to operate.

Settings

Parameters 01.11 DC voltage (page 137), 30.30 Overvoltage control (page 285).

Parameter group 43 Brake chopper (page 339).

Safety and protections

Emergency stop

The emergency stop signal is connected to the input selected by parameter 21.05 *Emergency stop source*. An emergency stop can also be generated through the fieldbus interface (parameter 06.01 *Main control word*, bits 0...2).

The mode of the emergency stop is selected by parameter *21.04 Emergency stop mode*. The following modes are available:

- Off1: Stop along the standard deceleration ramp defined for the particular reference type in use
- Off2: Stop by coasting
- Off3: Stop by the emergency stop ramp defined by parameter 23.23 *Emergency stop time*.

With Off1 or Off3 emergency stop modes, the ramp-down of the motor speed can be supervised by parameters *31.32 Emergency ramp supervision* and *31.33 Emergency ramp supervision delay*.

Notes:

- For SIL 3 / PL e-level emergency stop functions, the drive can be fitted with a TÜV-certified FSO-xx safety options module. The module can then be incorporated into certified safety systems.
- The installer of the equipment is responsible for installing the emergency stop devices and all additional devices needed for the emergency stop function to fulfill the required emergency stop categories. For more information, contact your local ABB representative.
- After an emergency stop signal is detected, the emergency stop function cannot be canceled even though the signal is canceled.
- If the minimum (or maximum) torque limit is set to 0%, the emergency stop function may not be able to stop the drive.
- Speed and torque reference additives (parameters 22.15, 22.17, 26.16, 26.25 and 26.41) and reference ramp shapes (23.16...23.19) are ignored in case of emergency ramp stops.

Settings

Parameters 06.17 Drive status word 2 (page 151), 06.18 Start inhibit status word (page 152), 21.04 Emergency stop mode (page 229), 21.05 Emergency stop source (page 229), 23.23 Emergency stop time (page 244), 25.13 Min torq sp ctrl em stop (page 259), 25.14 Max torq sp ctrl em stop (page 259), 25.15 Proportional gain em stop (page 259), 31.32 Emergency ramp supervision (page 294)and 31.33 Emergency ramp supervision delay (page 295).

Motor thermal protection

The control program features two separate motor temperature monitoring functions. The temperature data sources and warning/trip limits can be set up independently for each function.

The motor temperature can be monitored using

- the motor thermal protection model (estimated temperature derived internally inside the drive), or
- sensors installed in the windings. This results in a more accurate motor model.

In addition to temperature monitoring, a protection function is available for 'Ex' motors installed in a potentially explosive atmosphere.

Motor thermal protection model

The drive calculates the temperature of the motor on the basis of the following assumptions:

- When power is applied to the drive for the first time, the motor is assumed to be at ambient temperature (defined by parameter 35.50 Motor ambient temperature). After this, when power is applied to the drive, the motor is assumed to be at the estimated temperature.
- 2. Motor temperature is calculated using the user-adjustable motor thermal time and motor load curve. The load curve should be adjusted in case the ambient temperature exceeds 30 °C.

Note: The motor thermal model can be used when only one motor is connected to the inverter.

Temperature monitoring using PTC sensors



One PTC sensor can be connected to digital input DI6.

The resistance of the PTC sensor increases when its temperature rises. The increasing resistance of the sensor decreases the voltage at the input, and eventually its state switches from 1 to 0, indicating overtemperature.

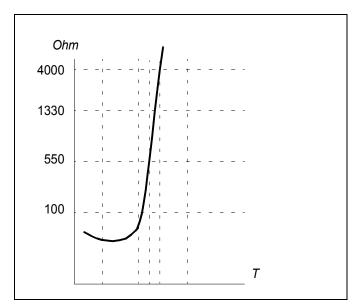
1...3 PTC sensors can also be connected in series to an analog input and an analog output. The analog output feeds a constant excitation current of 1.6 mA through the sensor. The sensor resistance increases as the motor temperature rises, as does the

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voltage over the sensor. The temperature measurement function calculates the resistance of the sensor and generates an indication if overtemperature is detected.

For wiring of the sensor, refer to the Hardware Manual of the drive.

The figure below shows typical PTC sensor resistance values as a function of temperature.



In addition to the above, optional FEN-xx encoder interfaces, and FPTC-xx modules have connections for PTC sensors. Refer to the module-specific documentation for more information.

Temperature monitoring using Pt100 sensors or Pt1000 sensors

1...3 Pt100 or Pt1000 sensors can be connected in series to an analog input and an analog output.

The analog output feeds a constant excitation current of 9.1 mA (Pt100) or 1 mA (Pt1000) through the sensor. The sensor resistance increases as the motor temperature rises, as does the voltage over the sensor. The temperature measurement function reads the voltage through the analog input and converts it into degrees Celsius.

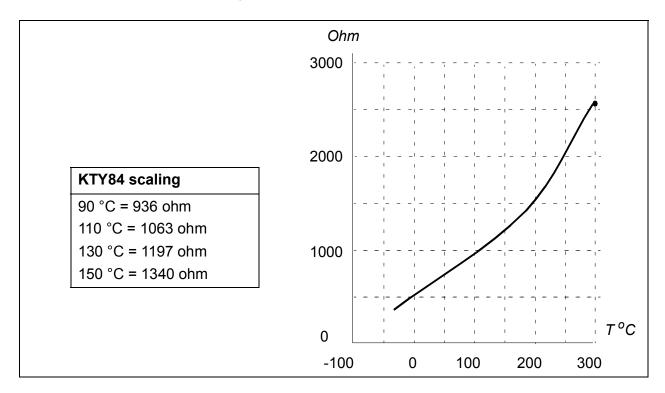
The warning and fault limits can be adjusted by parameters.

For the wiring of the sensor, refer to the *Hardware Manual* of the drive.

Temperature monitoring using KTY84 sensors

One KTY84 sensor can be connected to an analog input and an analog output on the control unit.

The analog output feeds a constant excitation current of 2.0 mA through the sensor. The sensor resistance increases as the motor temperature rises, as does the voltage over the sensor. The temperature measurement function reads the voltage through the analog input and converts it into degrees Celsius. FEN-xx encoder interfaces (optional) also have a connection for one KTY84 sensor.



The figure and table below show typical KTY84 sensor resistance values as a function of the motor operating temperature.

The warning and fault limits can be adjusted by parameters.

For the wiring of the sensor, refer to the Hardware Manual of the drive.

Motor fan control logic (parameters 35.100...35.106)

If the motor has an external cooling fan, it is possible to use a drive signal (for example, running/stopped) to control the starter of the fan via a relay or digital output. A digital input can be selected for fan feedback. A loss of the feedback signal will optionally cause a warning or a fault.

Start and stop delays can be defined for the fan. In addition, a feedback delay can be set to define the time within which feedback must be received after the fan starts.

Ex motor support (parameters 95.15, bit 0)

The control program has a temperature protection function for Ex motors located in a potentially explosive atmosphere. The protection is enabled by setting bit 0 of parameter *95.15 Special HW settings*.

Settings

Parameter groups 35 Motor thermal protection (page 308) and 91 Encoder module settings (page 439).

Parameter 95.15 Special HW settings (page 456).

Thermal protection of motor cable

The control program contains a thermal protection function for the motor cable. This function should be used, for example, when the nominal current of the drive exceeds the current-carrying capacity of the motor cable.

The program calculates the temperature of the cable on the basis of the following data:

- Measured output current (parameter 01.07 Motor current)
- Nominal continuous current rating of the cable, specified by 35.61 Cable nominal current, and
- Thermal time constant of the cable, specified by 35.62 Cable thermal rise time.

When the calculated temperature of the cable reaches 102% of the rated maximum, a warning (*A480 Motor cable overload*) is given. The drive trips on a fault (*4000 Motor cable overload*) when 106% is reached.

Settings

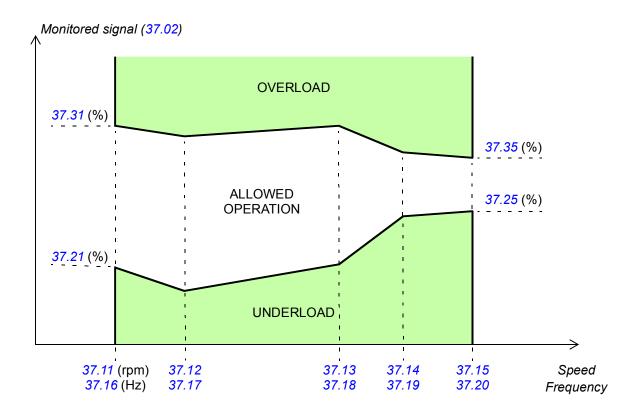
Parameters 35.60...35.62 (page 316)

User load curve

The user load curve provides a function that monitors an input signal (eg. motor torque or motor current) as a function of drive output speed or frequency. The function includes both high limit (overload) and low limit (underload) monitoring. Overload monitoring can, for example, be used to detect a pump becoming clogged or a saw blade hitting a knot. Underload monitoring can detect the load being lost, for example because of the snapping of a transmission belt.

The monitoring is effective within a motor speed and/or frequency range. The frequency range is used with a frequency reference in scalar motor control mode; otherwise, the speed range is used. The range is defined by five speed (parameters 37.11...37.15) or frequency (37.16...37.20) values. The values are positive, but the monitoring is symmetrically active in the negative direction as the sign of the monitored signal is ignored. Outside the speed/frequency range, the monitoring is disabled.

An underload (37.21...37.25) and overload (37.31...37.35) limit is set for each of the five speed or frequency points. Between these points, the limits are interpolated linearly to form overload and underload curves.



The action (none, warning or fault) taken when the signal exits the allowed operation area can be selected separately for overload and underload conditions (parameters 37.03 and 37.04 respectively). Each condition also has an optional timer to delay the selected action (37.41 and 37.42).

Settings

Parameter group 37 User load curve (page 322).

Automatic fault resets

The drive can automatically reset itself after overcurrent, overvoltage, undervoltage and external faults. The user can also specify a fault (excluding Safe torque off related faults) to be reset automatically.

By default, automatic resets are off and must be specifically activated by the user.

WARNING! Before you activate the function, make sure that no dangerous situations can occur. The function resets the drive automatically and continues operation after a fault.

Settings

Parameters 31.12...31.16 (page 289).

Other programmable protection functions

External events (parameters 31.01...31.10)

Five different event signals from the process can be connected to selectable inputs to generate trips and warnings for the driven equipment. When the signal is lost, an external event (fault, warning, or a mere log entry) is generated. The contents of the message can be edited on the control panel by selecting **Menu** - **Settings** - **Edit texts**.

Motor phase loss detection (parameter 31.19)

The parameter selects how the drive reacts whenever a motor phase loss is detected.

Earth (Ground) fault detection (parameter 31.20)

The earth fault detection function is based on sum current measurement. Note that

- an earth fault in the supply cable does not activate the protection
- in a grounded supply, the protection activates within 2 milliseconds
- in an ungrounded supply, the supply capacitance must be 1 microfarad or more
- the capacitive currents caused by shielded motor cables up to 300 meters will not activate the protection
- the protection is deactivated when the drive is stopped.

Supply phase loss detection (parameter 31.21)

The parameter selects how the drive reacts whenever a supply phase loss is detected.

Safe torque off detection (parameter 31.22)

The drive monitors the status of the Safe torque off input, and this parameter selects which indications are given when the signals are lost. (The parameter does not affect the operation of the Safe torque off function itself). For more information on the Safe torque off function, see the *Hardware manual*.

Swapped supply and motor cabling (parameter 31.23)

The drive can detect if the supply and motor cables have accidentally been swapped (for example, if the supply is connected to the motor connection of the drive). The parameter selects if a fault is generated or not. Note that the protection should be disabled in drive/inverter hardware supplied from a common DC bus.

Stall protection (parameters 31.24...31.28)

The drive protects the motor in a stall situation. It is possible to adjust the supervision limits (current, frequency and time) and choose how the drive reacts to a motor stall condition.

Overspeed protection (parameter 31.30)

The user can set overspeed limits by specifying a margin that is added to the currently-used maximum and minimum speed limits.

Ramp stop supervision (parameters 31.32, 31.33, 31.37 and 31.38)

The control program has a supervision function for both the normal and emergency stop ramps. The user can either define a maximum time for stopping, or a maximum deviation from the expected deceleration rate. If the drive fails to stop in the expected manner, a fault is generated and the drive coasts to a stop.

Main cooling fan supervision (parameter 31.35)

The parameter selects how the drive reacts to a loss of the main cooling fan.

With an inverter unit consisting of frame R8i inverter modules, it may be possible to continue operation even if a cooling fan of an inverter module stops. See the description of the parameter.

Custom motor current fault limit (parameter 31.42)

The control program sets a motor current limit based on drive hardware. In most cases, the default value is appropriate. However, a lower limit can be manually set by the user, for example, to protect a permanent magnet motor from demagnetization.

Local control loss detection (parameter 49.05)

The parameter selects how the drive reacts to a control panel or PC tool communication break.

Automatic fault resets

The drive can automatically reset itself after overcurrent, overvoltage, undervoltage and external faults. The user can also specify a fault (excluding Safe torque off related faults) to be reset automatically.

By default, automatic resets are off and must be specifically activated by the user.

WARNING! Before you activate the function, make sure that no dangerous situations can occur. The function resets the drive automatically and continues operation after a fault.

Settings

Parameters 31.12...31.16 (page 289).

Diagnostics

Fault and warning messages, data logging

See chapter Fault tracing (page 549).

Signal supervision

Three signals can be selected to be supervised by this function. Whenever a supervised signal exceeds or falls below predefined limits, a bit in *32.01 Supervision status* is activated, and a warning or fault generated. The contents of the message can be edited on the control panel by selecting **Menu** - **Settings** - **Edit texts**.

The supervised signal is low-pass filtered. The supervision operates on a 2 ms time level. The configuration parameters are scanned for changes on a 10 ms time level.

Settings

Parameter group 32 Supervision (page 297).

Maintenance timers and counters

The program has six different maintenance timers or counters that can be configured to generate a warning when a pre-defined limit is reached. The contents of the message can be edited on the control panel by selecting **Menu** - **Settings** - **Edit texts**.

The timer/counter can be set to monitor any parameter. This feature is especially useful as a service reminder.

There are three types of counters:

- On-time timers. Measures the time a binary source (for example, a bit in a status word) is on.
- Signal edge counters. The counter is incremented whenever the monitored binary source changes state.
- Value counters. The counter measures, by integration, the monitored parameter. A warning is given when the calculated area below the signal peak exceeds a user-defined limit.

Settings

Parameter group 33 Generic timer & counter (page 300).

Energy saving calculators

This feature consists of the following functionalities:

- An energy optimizer that adjusts the motor flux in such a way that the total system efficiency is maximized
- A counter that monitors used and saved energy by the motor and displays them in kWh, currency or volume of CO₂ emissions, and
- A load analyzer showing the load profile of the drive (see separate section on page 121).

Note: The accuracy of the energy savings calculation is directly dependent on the accuracy of the reference motor power given in parameter *45.19 Comparison power*.

Settings

Parameter group 45 Energy efficiency (page 345).

Load analyzer

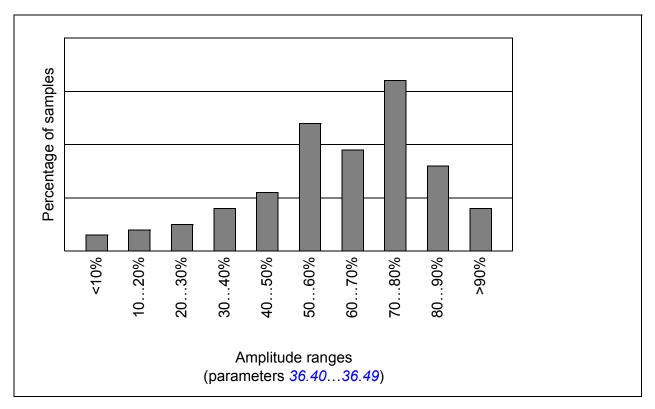
Peak value logger

The user can select a signal to be monitored by a peak value logger. The logger records the peak value of the signal along with the time the peak occurred, as well as motor current, DC voltage and motor speed at the time of the peak. The peak value is sampled at 2 ms intervals.

Amplitude loggers

The control program has two amplitude loggers.

For amplitude logger 2, the user can select a signal to be sampled at 200 ms intervals, and specify a value that corresponds to 100%. The collected samples are sorted into 10 read-only parameters according to their amplitude. Each parameter represents an amplitude range 10 percentage points wide, and displays the percentage of the collected samples that have fallen within that range. Note that the lowest range also contains the negative values (if any), while the highest range also contains the values above 100%.



Amplitude logger 1 is fixed to monitor motor current, and cannot be reset. With amplitude logger 1, 100% corresponds to the maximum output current of the drive (I_{max} as given in the hardware manual). The measured current is logged continuously. The distribution of samples is shown by parameters 36.20...36.29.

Settings

Parameter group 36 Load analyzer (page 318).

Miscellaneous

User parameter sets

The drive supports four user parameter sets that can be saved to the permanent memory and recalled using drive parameters. It is also possible to use digital inputs to switch between user parameter sets.

A user parameter set contains all editable values in parameter groups 10...99 except

- forced I/O values such as parameters 10.03 DI force selection and 10.04 DI force data
- I/O extension module settings (groups 14...16)
- fieldbus communication enable parameters (50.01 FBA A enable and 50.31 FBA B enable)
- other fieldbus communication settings (groups 51...56 and 58)
- encoder configuration settings (groups 92...93), and
- parameter 95.01 Supply voltage.

As the motor settings are included in the user parameter sets, make sure the settings correspond to the motor used in the application before recalling a user set. In an application where different motors are used with the drive, the motor ID run needs to be performed with each motor and the results saved to different user sets. The appropriate set can then be recalled when the motor is switched.

Settings

Parameters 96.10...96.13 (page 461).

Parameter checksum calculation

A parameter checksum can be calculated from a user-definable set of parameters to monitor changes in the drive configuration. The calculated checksum is compared to 1...4 reference checksums; in case of a mismatch, an event (a pure event, warning or fault) is generated.

By default, the set of parameters included in the calculation contain most parameters with the exception of

- actual signals
- parameter group 47 Data storage
- parameter that are activated to validate new settings (such as 51.27 and 96.07)
- parameters that are not saved to the flash memory (such as 96.24...96.26)
- parameters that are internally calculated from others (such as 98.09...98.14).
- dynamic parameters (eg. parameters that vary according to hardware), and
- application program parameters.

The default set can be edited using the Drive customizer PC tool.

Settings

Parameters 96.53...96.59 (page 465).

User lock

For better cybersecurity, it is highly recommended that you set a master pass code to prevent eg. the changing of parameter values and/or the loading of firmware and other files.

WARNING! ABB will not be liable for damages or losses caused by the failure to activate the user lock using a new pass code. See *Cybersecurity disclaimer* (page 18).

To activate the user lock for the first time,

- Enter the default pass code, 10000000, into 96.02 Pass code. This will make parameters 96.100...96.102 visible.
- Enter a new pass code into 96.100 Change user pass code. Always use eight digits; if using Drive composer, finish with Enter.
- Confirm the new pass code in 96.101 Confirm user pass code.



WARNING! Store the pass code in a safe place – the user lock cannot be opened even by ABB if the pass code is lost.

- In *96.102 User lock functionality*, define the actions that you want to prevent (we recommend you select all the actions unless otherwise required by the application).
- Enter an invalid (random) pass code into 96.02 Pass code.
- Activate 96.08 Control board boot, or cycle the power to the control unit.
- Check that parameters *96.100...96.102* are hidden. If they are not, enter another random pass code into *96.02*.

To reopen the lock, enter your pass code into 96.02 Pass code. This will again make parameters 96.100...96.102 visible.

Settings

Parameters 96.02 (page 459) and 96.100...96.102 (page 467).

Data storage parameters

Twenty-four (sixteen 32-bit, eight 16-bit) parameters are reserved for data storage. These parameters are unconnected by default and can be used for eg. linking, testing and commissioning purposes. They can be written to and read from using other parameters' source or target selections.

Note that "*Analog src*" type parameters (see page 484) expect a 32-bit real (floating point) source – in other words, parameters 47.01...47.08 can be used as a value source of other parameters while 47.11...47.28 cannot.

To use a 16-bit integer (received in DDCS data sets) as the source of another parameter, write the value into one of the "real32" type storage parameters (47.01...47.08). Select the storage parameter as the source, and define a suitable scaling method between the 16-bit and 32-bit values in parameters 47.31...47.38.

Settings

Parameter group 47 Data storage (page 352).

Reduced run function

A "reduced run" function is available for inverter units consisting of parallel-connected inverter modules. The function makes it possible to continue operation with limited current even if one (or more) module is out of service, for example, because of maintenance work. In principle, reduced run is possible with only one module, but the physical requirements of operating the motor still apply; for example, the modules remaining in use must be able to provide the motor with enough magnetizing current.

Activation of the reduced run function

Note: For cabinet-built drives, the wiring accessories and the air baffle needed during the procedure are available from ABB, and are included in the delivery.

 $\Lambda \Lambda$

WARNING! Obey the safety instructions provided for the drive or inverter unit in question.

- 1. Disconnect the supply voltage and all auxiliary voltages from the drive/inverter unit.
- 2. If the inverter control unit is powered from the faulty module, install an extension to the wiring and connect it to one of the remaining modules.
- 3. Remove the module to be serviced from its bay. See the appropriate hardware manual for instructions.
- 4. If the Safe torque off (STO) function is in use, install jumpering in the STO wiring in place of the missing module (unless the module was the last on the chain).
- 5. Install an air baffle to the top module guide to block the airflow through the empty module bay.
- 6. In case the inverter unit has a DC switch with a charging circuit, disable the appropriate channel on the charging monitoring unit.
- 7. Switch on the power to the drive/inverter unit.
- 8. Enter the number of inverter modules present into parameter *95.13 Reduced run mode*.
- Reset all faults and start the drive/inverter unit. The maximum current is now automatically limited according to the new inverter configuration. A mismatch between the number of detected modules (95.14) and the value set in 95.13 will generate a fault.

After all modules have been reinstalled, parameter 95.13 Reduced run mode must be reset to 0 to disable the reduced run function. In case the inverter is equipped with a charging circuit, the charging monitoring must be reactivated for all modules. If the Safe torque off (STO) function is in use, an acceptance test must be performed (see the hardware manual of the drive/inverter unit for instructions).

Settings

Parameters 06.17 (page 151) and 95.13...95.14 (page 455).

du/dt filter support

With a external du/dt filter connected to the output of the drive, bit 13 of 95.20 *HW* options word 1 must be switched on. The setting limits the output switching frequency, and forces the drive/inverter module fan to full speed. Note that the setting is not to be activated with inverter modules with internal du/dt filters.

Settings

Parameters 95.20 HW options word 1 (page 457).

Sine filter support

The control program has a setting that enables the use of sine filters (available separately from ABB and others).

With an ABB sine filter connected to the output of the drive, bit 1 of 95.15 Special HW settings must be switched on. The setting limits the switching and output frequencies to

- prevent the drive from operating at filter resonance frequencies, and
- protect the filter from overheating.

With a custom sine filter, bit 3 of *95.15 Special HW settings* must be switched on. (The setting does not limit the output frequency.) Additional parameters must be set according to the properties of the filter as listed below.

Settings

For both ABB and custom filters: Parameter 95.15 Special HW settings (page 456).

For custom filters: Parameters 97.01 *Switching frequency reference* (page 469), 97.02 *Minimum switching frequency* (page 469), 99.18 *Sine filter inductance* and 99.19 *Sine filter capacitance* (page 481).

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Default control connections

The default I/O connections of the control program are shown in section *Control connections* on page *30*.

130 Default control connections



Parameters

Contents of this chapter

The chapter describes the parameters, including actual signals, of the control program.

Terms and abbreviations

Term	Definition
Actual signal	Type of <i>parameter</i> that is the result of a measurement or calculation by the drive, or contains status information. Most actual signals are read-only, but some (especially counter-type actual signals) can be reset.
Bit pointer setting	 A parameter setting that points to the value of a bit in another parameter (usually an actual signal), or that can be fixed to 0 (FALSE) or 1 (TRUE). When adjusting a bit pointer setting on the optional control panel, "Const" is selected in order to fix the value to 0 (displayed as "C.False") or 1 ("C.True"). "Pointer" is selected to define a source from another parameter. A pointer value is given in the format P.xx.yy.zz, where xx = parameter group, yy = parameter index, zz = bit number. Pointing to a non existing bit will be interpreted as 0 (FALSE). In addition to the "Const" and "Pointer" selections, bit pointer settings may also have other pre-selected settings.
Def	 (In the following table, shown on the same row as the parameter name) The default value of a <i>parameter</i>. Note: Certain configurations or optional equipment may require specific default values. These are labeled as follows: (95.20 bx) = Default changed or write-protected by parameter 95.20, bit x.
FbEq16	 (In the following table, shown on the same row as the parameter range, or for each selection) 16-bit fieldbus equivalent: The scaling between the value shown on the panel and the integer used in communication when a 16-bit value is selected for transmission to an external system. A dash (-) indicates that the parameter is not accessible in 16-bit format. The corresponding 32-bit scalings are listed in chapter <i>Additional Parameter data</i> (page <i>483</i>).

Term	Definition	
Other	The value is taken from another parameter. Choosing "Other" displays a parameter list in which the user can spec the source parameter. Note: The source parameter must be a 32-bit real (floating point) numb To use a 16-bit integer (for example, received from an external device data sets) as the source, use data storage parameters 47.0147.08.	
Other [bit]	The value is taken from a specific bit in another parameter. Choosing "Other" displays a parameter list in which the user can specify the source parameter and bit.	
Parameter	Either a user-adjustable operating instruction for the drive, or an <i>actual signal</i> .	
p.u.	Per unit	

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20 Start/stop/direction	Start/stop/direction and run/start enable signal source selection; positive/negative reference enable signal source selection.	218
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22 Speed reference selection	Speed reference selection; motor potentiometer settings.	234
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35 Motor thermal protection	Motor thermal protection settings such as temperature measurement configuration, load curve definition and motor fan control configuration.	308
36 Load analyzer	Peak value and amplitude logger settings.	318
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52 FBA A data in	Selection of data to be transferred from drive to fieldbus controller through fieldbus adapter A.	367
53 FBA A data out	Selection of data to be transferred from fieldbus controller to drive through fieldbus adapter A.	367
54 FBA B settings	Fieldbus adapter B configuration.	368
55 FBA B data in	Selection of data to be transferred from drive to fieldbus controller through fieldbus adapter B.	369
56 FBA B data out	Selection of data to be transferred from fieldbus controller to drive through fieldbus adapter B.	369
56 FBA B data out	Selection of data to be transferred from fieldbus controller to drive through fieldbus adapter B.	369
58 Embedded fieldbus	Configuration of the embedded fieldbus (EFB) interface.	370
60 DDCS communication	All of the above utilize a fiber optic link which also requires an FDCO module (typically with ZCU control units) or an RDCO module (with BCU control units). Master/follower and external controller communication can also be implemented through shielded twisted-pair cable connected to the XD2D connector of the drive.	377
61 D2D and DDCS transmit data	Defines the data sent to the DDCS link.	390
62 D2D and DDCS receive data	Mapping of data received through the DDCS link.	394
74 Spinning control	Spinning control functions.	402
75 Pattern1	Preset values for the 16 sections in pattern1.	404
76 Pattern2	Preset values for the 16 sections in pattern2.	404
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79 Ring frame machine	Ring frame machine parameters used for actual value calculations.	418
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82 Slow speed function	Slow speed function.	421
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90 Feedback selection	Motor and load feedback configuration.	430
91 Encoder module settings	Configuration of encoder interface modules.	439
92 Encoder 1 configuration	Settings for encoder 1.	442
93 Encoder 2 configuration	Settings for encoder 2.	449

Group	Contents	Page
94 LSU control	Control of the supply unit of the drive, such as DC voltage and reactive power reference.	451
95 HW configuration	Various hardware-related settings.	453
96 System	Language selection; access levels; macro selection; parameter save and restore; control unit reboot; user parameter sets; unit selection; data logger triggering; parameter checksum calculation; user lock.	458
97 Motor control	Motor model settings.	469
98 User motor parameters	Motor values supplied by the user that are used in the motor model.	473
99 Motor data	Motor configuration settings.	475
200 Safety	FSO-xx settings.	481

Parameter listing

No.	Name/Value	Description	Def/FbEq16
01 Act	tual values	Basic signals for monitoring the drive. All parameters in this group are read-only unless otherwise noted.	
01.01	Motor speed used	Measured or estimated motor speed depending on which type of feedback is used (see parameter <i>90.41 Motor</i> <i>feedback selection</i>). A filter time constant for this signal can be defined by parameter <i>46.11 Filter time motor speed</i> .	-
	-30000.00 30000.00 rpm	Measured or estimated motor speed.	See par. 46.01
01.02	Motor speed estimated	Estimated motor speed in rpm. A filter time constant for this signal can be defined by parameter <i>46.11 Filter time motor speed</i> .	-
	-30000.00 30000.00 rpm	Estimated motor speed.	See par. 46.01
01.03	Motor speed %	Shows the value of <i>01.01 Motor speed used</i> in percent of the synchronous speed of the motor.	10 = 1%
	-1000.00 1000.00%	Measured or estimated motor speed.	See par. 46.01
01.04	Encoder 1 speed filtered	Speed of encoder 1 in rpm. A filter time constant for this signal can be defined by parameter <i>46.11 Filter time motor speed</i> .	-
	-30000.00 30000.00 rpm	Encoder 1 speed.	See par. 46.01
01.05	Encoder 2 speed filtered	Speed of encoder 2 in rpm. A filter time constant for this signal can be defined by parameter <i>46.11 Filter time motor speed</i> .	-
	-30000.00 30000.00 rpm	Encoder 2 speed.	See par. 46.01
01.06	Output frequency	Estimated drive output frequency in Hz. A filter time constant for this signal can be defined by parameter <i>46.12 Filter time output frequency</i> .	-
	-500.00 … 500.00 Hz	Estimated output frequency.	See par. 46.02
01.07	Motor current	Measured (absolute) motor current in A.	-
	0.00 30000.00 A	Motor current.	See par. 46.05
01.08	Motor current % of motor nom	Motor current (drive output current) in percent of the nominal motor current.	-
	0.0 1000.0%	Motor current.	1 = 1%
01.10	Motor torque	Motor torque in percent of the nominal motor torque. See also parameter <i>01.30 Nominal torque scale</i> . A filter time constant for this signal can be defined by parameter <i>46.13 Filter time motor torque</i> .	-
	-1600.0 1600.0%	Motor torque.	See par. 46.03

No.	Name/Value	Description	Def/FbEq16
01.11	DC voltage	Measured DC link voltage.	-
	0.00 2000.00 V	DC link voltage.	10 = 1 V
01.13	Output voltage	Calculated motor voltage in V AC.	-
	02000 V	Motor voltage.	1 = 1 V
01.14	Output power	Drive output power. The unit is selected by parameter <i>96.16</i> <i>Unit selection</i> . A filter time constant for this signal can be defined by parameter <i>46.14 Filter time power out</i> .	-
	-32768.00 … 32767.00 kW or hp	Output power.	1 = 1 unit
01.15	Output power % of motor nom	Shows the value of <i>01.14 Output power</i> in percent of the nominal power of the motor.	-
	-300.00 300.00%	Output power.	10 = 1%
01.17	Motor shaft power	Estimated mechanical power at motor shaft. The unit is selected by parameter 96.16 Unit selection. A filter time constant for this signal can be defined by parameter 46.14 <i>Filter time power out</i> .	-
	-32768.00 32767.00 kW or hp	Motor shaft power.	1 = 1 unit
01.18	Inverter GWh motoring	Amount of energy that has passed through the drive (towards the motor) in full gigawatt-hours. The minimum value is zero.	-
	032767 GWh	Motoring energy in GWh.	1 = 1 GWh
01.19	Inverter MWh motoring	Amount of energy that has passed through the drive (towards the motor) in full megawatt-hours. Whenever the counter rolls over, <i>01.18 Inverter GWh motoring</i> is incremented. The minimum value is zero.	-
	0999 MWh	Motoring energy in MWh.	1 = 1 MWh
01.20	Inverter kWh motoring	Amount of energy that has passed through the drive (towards the motor) in full kilowatt-hours. Whenever the counter rolls over, <i>01.19 Inverter MWh motoring</i> is incremented.The minimum value is zero.	-
	0999 kWh	Motoring energy in kWh.	10 = 1 kWh
01.21	U-phase current	Measured U-phase current.	-
	-30000.00 30000.00 A	U-phase current.	See par. 46.05
01.22	V-phase current	Measured V-phase current.	-
	-30000.00 30000.00 A	V-phase current.	See par. 46.05
01.23	W-phase current	Measured W-phase current.	-
	-30000.00 30000.00 A	W-phase current.	See par. 46.05
01.24	Flux actual %	Used flux reference in percent of nominal flux of motor.	-
	0200%	Flux reference.	1 = 1%
01.25	INU momentary cos fii	Momentary cosphi of the drive.	-
	-1.00 1.00	Cosphi.	100 = 1

No.	Name/Value	Description	Def/FbEq16
01.25	Speed change rate	Rate of actual speed change. Positive values indicate acceleration, negative values indicate deceleration. See also parameters 31.32 Emergency ramp supervision and 31.33 Emergency ramp supervision delay, 31.37 Ramp stop supervision and 31.38 Ramp stop supervision delay.	-
	-15000 15000 rpm/s	Rate of speed change.	1 = 1 rpm/s
01.30	Nominal torque scale	Torque that corresponds to 100% of nominal motor torque. The unit is selected by parameter <i>96.16 Unit selection</i> Note: This value is copied from parameter <i>99.12 Motor</i> <i>nominal torque</i> if entered. Otherwise the value is calculated from other motor data.	-
	0.000 N·m or lb·ft	Nominal torque.	1 = 1 unit
01.31	Ambient temperature	Measured temperature of incoming cooling air. The unit is selected by parameter <i>96.16 Unit selection</i> .	-
	-32768 32767 °C or °F	Cooling air temperature.	1 = 1°
01.32	Inverter GWh regenerating	Amount of energy that has passed through the drive (towards the supply) in full gigawatt-hours. The minimum value is zero.	-
	032767 GWh	Regenerative energy in GWh.	1 = 1 GWh
01.33	Inverter MWh regenerating	Amount of energy that has passed through the drive (towards the supply) in full megawatt-hours. Whenever the counter rolls over, <i>01.32 Inverter GWh regenerating</i> is incremented. The minimum value is zero.	-
	0999 MWh	Regenerative energy in MWh.	1 = 1 MWh
01.34	Inverter kWh regenerating	Amount of energy that has passed through the drive (towards the supply) in full kilowatt-hours. Whenever the counter rolls over, <i>01.33 Inverter MWh regenerating</i> is incremented. The minimum value is zero.	-
	0999 kWh	Regenerative energy in kWh.	10 = 1 kWh
01.35	Mot - regen energy GWh	Amount of net energy (motoring energy - regenerating energy) that has passed through the drive in full gigawatt-hours.	-
	-3276832767 GWh	Energy balance in GWh.	1 = 1 GWh
01.36	Mot - regen energy MWh	Amount of net energy (motoring energy - regenerating energy) that has passed through the drive in full megawatt-hours. Whenever the counter rolls over, <i>01.35 Mot - regenengy GWh</i> is incremented or decremented.	-
	-999999 MWh	Energy balance in MWh.	1 = 1 MWh
01.37	Mot - regen energy kWh	Amount of energy (motoring energy - regenerating energy) that has passed through the drive in full kilowatt-hours. Whenever the counter rolls over, <i>01.36 Mot - regen energy MWh</i> is incremented or decremented.	-
	-999999 kWh	Energy balance in kWh.	10 = 1 kWh
01.61	Abs motor speed used	Absolute value of 01.01 Motor speed used.	-
	0.00 30000.00 rpm	Measured or estimated motor speed.	See par. 46.01
01.62	Abs motor speed %	Absolute value of 01.03 Motor speed %.	-
	0.00 1000.00%	Measured or estimated motor speed.	10 = 1%

No.	Name/Value	Description	Def/FbEq16
01.63	Abs output frequency	Absolute value of 01.06 Output frequency.	-
	0.00 500.00 Hz	Estimated output frequency.	See par. 46.02
01.64	Abs motor torque	Absolute value of 01.10 Motor torque.	-
	0.0 1600.0%	Motor torque.	See par. 46.03
01.65	Abs output power	Absolute value of 01.14 Output power.	-
	0.00 32767.00 kW or hp	Output power.	1 = 1 unit
01.66	Abs output power % motor nom	Absolute value of 01.15 Output power % of motor nom.	-
	0.00 300.00%	Output power.	10 = 1%
01.68	Abs motor shaft power	Absolute value of 01.17 Motor shaft power.	-
	0.00 32767.00 kW or hp	Motor shaft power.	1 = 1 unit
01.70	Ambient temperature %	Measured temperature of incoming cooling air. The amplitude range of 0100% corresponds to 060 °C or 32140 °F. See also 01.31 Ambient temperature.	-
	-200.00 200.00%	Cooling air temperature.	1 = 1%
01.71	Step-up motor current	Estimated motor current in A when a step-up transformer is in use. The value is calculated from parameter <i>01.07</i> using the step-up transformer ratio (<i>95.40</i>) and sine filter values <i>99.18</i> and <i>99.19</i> .	-
	0.00 30000.00 A	Estimated motor current.	See par. 46.05
01.72	U-phase RMS current	U-phase rms current.	-
	0.00 30000.00 A	U-phase rms current.	See par. 46.05
01.73	V-phase RMS current	V-phase rms current.	-
	0.00 30000.00 A	V-phase rms current.	See par. 46.05
01.74	W-phase RMS current	W-phase rms current.	-
	0.00 30000.00 A	W-phase rms current.	See par. 46.05
01.102	Line current	(Only visible when IGBT supply unit control activated by 95.20)	-
		Estimated line current flowing through the supply unit.	
	0.00 30000.00 A	Estimated line current.	See par. 46.05

No.	Name/Value	Description	Def/FbEq16
01.104	Active current	(Only visible when IGBT supply unit control activated by 95.20) Estimated active current flowing through the supply unit.	-
	0.00 30000.00 A	Estimated active current.	See par. 46.05
01.106	Reactive current	(Only visible when IGBT supply unit control activated by 95.20) Estimated reactive current flowing through the supply unit.	-
	0.00 30000.00 A	Estimated reactive current.	See par. 46.05
01.108	Grid frequency	(Only visible when IGBT supply unit control activated by 95.20) Estimated frequency of the power supply network.	-
	0.00 100.00 Hz	Estimated supply frequency.	See par. 46.02
01.109	Grid voltage	(Only visible when IGBT supply unit control activated by 95.20) Estimated voltage of the power supply network.	-
	0.00 2000.00 V	Estimated supply voltage.	10 = 1 V
01.110	Grid apparent power	(Only visible when IGBT supply unit control activated by 95.20) Estimated apparent power being transferred through the supply unit.	-
	-30000.00 30000.00 kVA	Estimated apparent power.	See par. 46.04
01.112	Grid power	(Only visible when IGBT supply unit control activated by 95.20) Estimated power being transferred through the supply unit.	-
	-30000.00 30000.00 kW	Estimated supply power.	See par. 46.04
01.114	Grid reactive power	(Only visible when IGBT supply unit control activated by 95.20) Estimated reactive power being transferred through the supply unit.	-
	-30000.00 30000.00 kvar	Estimated reactive power.	10 = 1 kvar
01.116	LSU cos Φ	(Only visible when IGBT supply unit control activated by 95.20) Power factor of the supply unit.	-
	-1.00 1.00	Power factor.	100 = 1
01.164	LSU nominal power	(Only visible when IGBT supply unit control activated by 95.20) Nominal power of the supply unit.	-
	030000 kW	Nominal power.	1 = 1 kW
03 Inp	ut references	Values of references received from various sources. All parameters in this group are read-only unless otherwise noted.	
03.01	Panel reference	Reference given from the control panel or PC tool.	-

No.	Name/Value	Description	Def/FbEq16
	-100000.00 100000.00	Control panel or PC tool reference.	1 = 10
03.05	FB A reference 1	Reference 1 received through fieldbus adapter A. See also chapter <i>Fieldbus control through a fieldbus adapter</i> (page <i>613</i>).	-
	-100000.00 100000.00	Reference 1 from fieldbus adapter A.	1 = 10
03.06	FB A reference 2	Reference 2 received through fieldbus adapter A.	-
	-100000.00 100000.00	Reference 2 from fieldbus adapter A.	1 = 10
03.07	FB B reference 1	Reference 1 received through fieldbus adapter B.	-
	-100000.00 100000.00	Reference 1 from fieldbus adapter B.	1 = 10
03.08	FB B reference 2	Reference 2 received through fieldbus adapter B.	-
	-100000.00 100000.00	Reference 2 from fieldbus adapter B.	1 = 10
03.09	EFB reference 1	Scaled reference 1 received through the embedded fieldbus interface. The scaling is defined by 58.26 <i>EFB ref1 type</i> .	1 = 10
	-30000.00 30000.00	Reference 1 received through the embedded fieldbus interface.	1 = 10
03.10	EFB reference 2	Scaled reference 2 received through the embedded fieldbus interface. The scaling is defined by 58.27 <i>EFB ref2 type</i> .	1 = 10
	-30000.00 30000.00	Reference 2 received through the embedded fieldbus interface.	1 = 10
03.11	DDCS controller ref 1	Reference 1 received from the external (DDCS) controller. The value has been scaled according to parameter 60.60 DDCS controller ref1 type. See also section External controller interface (page 71).	1 = 10
	-30000.00 30000.00	Scaled reference 1 received from external controller.	1 = 10
03.12	DDCS controller ref 2	Reference 2 received from the external (DDCS) controller. The value has been scaled according to parameter 60.61 DDCS controller ref2 type.	1 = 10
	-30000.00 30000.00	Scaled reference 2 received from external controller.	1 = 10
03.13	M/F or D2D ref1	Master/follower reference 1 received from the master. The value has been scaled according to parameter 60.10 M/F ref1 type.	1 = 10
	-30000.00 30000.00	Scaled reference 1 received from master.	1 = 10
03.14	M/F or D2D ref2	Master/follower reference 2 received from the master. The value has been scaled according to parameter 60.11 M/F ref2 type.	1 = 10
	-30000.00 30000.00	Scaled reference 2 received from master.	1 = 10

No.	Name/Value	Description	Def/FbEq16
04 Wa	ornings and faults	Information on warnings and faults that occurred last. For explanations of individual warning and fault codes, see chapter <i>Fault tracing</i> . All parameters in this group are read-only unless otherwise noted.	
04.01	Tripping fault	Code of the 1st active fault (the fault that caused the current trip).	-
	0000hFFFFh	1st active fault.	1 = 1
04.02	Active fault 2	Code of the 2nd active fault.	-
	0000hFFFFh	2nd active fault.	1 = 1
04.03	Active fault 3	Code of the 3rd active fault.	-
	0000hFFFFh	3rd active fault.	1 = 1
04.04	Active fault 4	Code of the 4th active fault.	-
	0000hFFFFh	4th active fault.	1 = 1
04.05	Active fault 5	Code of the 5th active fault.	-
	0000hFFFFh	5th active fault.	1 = 1
04.06	Active warning 1	Code of the 1st active warning.	-
	0000hFFFFh	1st active warning.	1 = 1
04.07	Active warning 2	Code of the 2nd active warning.	-
	0000hFFFFh	2nd active warning.	1 = 1
04.08	Active warning 3	Code of the 3rd active warning.	-
	0000hFFFFh	3rd active warning.	1 = 1
04.09	Active warning 4	Code of the 4th active warning.	-
	0000hFFFFh	4th active warning.	1 = 1
04.10	Active warning 5	Code of the 5th active warning.	-
	0000hFFFFh	5th active warning.	1 = 1
04.11	Latest fault	Code of the 1st stored (non-active) fault.	-
	0000hFFFFh	1st stored fault.	1 = 1
04.12	2nd latest fault	Code of the 2nd stored (non-active) fault.	-
	0000hFFFFh	2nd stored fault.	1 = 1
04.13	3rd latest fault	Code of the 3rd stored (non-active) fault.	-
	0000hFFFFh	3rd stored fault.	1 = 1
04.14	4th latest fault	Code of the 4th stored (non-active) fault.	-
	0000hFFFFh	4th stored fault.	1 = 1
04.15	5th latest fault	Code of the 5th stored (non-active) fault.	-
	0000hFFFFh	5th stored fault.	1 = 1
04.16	Latest warning	Code of the 1st stored (non-active) warning.	-
	0000hFFFFh	1st stored warning.	1 = 1
04.17	2nd latest warning	Code of the 2nd stored (non-active) warning.	-
	0000hFFFFh	2nd stored warning.	1 = 1
04.18	3rd latest warning	Code of the 3rd stored (non-active) warning.	-
	0000hFFFFh	3rd stored warning.	1 = 1

No.	Name/V	alue	Descri	ption		Def/FbEq16
04.19	4th latest warning Cod		Code o	f the 4th stored (non-	active) warning.	-
	0000h	FFFFh	4th stor	ed warning.		1 = 1
04.20	5th latest warning		Code o	f the 5th stored (non-	active) warning.	-
	0000hFFFFh			•	, 0	1 = 1
04.21	Fault word 1 AC The WC wor are con Eac		ACS80 The bit WORD word co are acc control Each bi	th stored warning. CS800-compatible fault word 1. the bit assignments of this word correspond to FAULT VORD 1 in the ACS800. Parameter <i>04.120 Fault/Warning</i> <i>word compatibility</i> determines whether the bit assignments re according to the ACS800 Standard or ACS800 System ontrol program. Each bit can indicate several ACS880 events as listed below. this parameter is read-only.		-
	Bit	(04.120 = ACS800 Standard ctrl program)		fault name (04.120 = ACS800 System ctrl	ACS880 events indicated by this bit (see <i>Fault tracing</i> , page 549)	
				program)		
	0	SHORT CIRC		SHORT CIRC	2340	
	1	OVERCURRENT		OVERCURRENT	2310	
	2	DC OVERVOLT		DC OVERVOLT	3210	
	3	ACS800 TEMP		ACS800 TEMP	2381, 4210, 4290, 42F1, 4310, 4	4380
	4	EARTH FAULT		EARTH FAULT	2330, 2392, 3181	
	5	THERMISTOR		MOTOR TEMP M	4981	
	6	MOTOR TEMP		MOTOR TEMP	4982	
	7	SYSTEM_FAULT		SYSTEM_FAULT	6481, 6487, 64A1, 64A2, 64A3, 6881, 6882, 6883, 6885	64B1, 64E1,
	8	UNDERLOAD		UNDERLOAD	-	
	9	OVERFREQ		OVERFREQ	7310	
	3			1		
	3 10	Reserved		MPROT SWITCH	9081	
		Reserved Reserved		MPROT SWITCH CH2 COMM LOSS	9081 7582	
	10					
	10 11	Reserved		CH2 COMM LOSS	7582	
	10 11 12	Reserved Reserved		CH2 COMM LOSS SC (INU1)	7582 2340 (XXYY YY01)	

No.	Name/	/alue Desc	Description		Def/FbEq16
04.22	Fault word 2 AC The WC wo are cor Ea		ACS800-compatible fault word 2. The bit assignments of this word correspond to FAULT WORD 2 in the ACS800. Parameter <i>04.120 Fault/Warning</i> <i>word compatibility</i> determines whether the bit assignments are according to the ACS800 Standard or ACS800 System control program. Each bit can indicate several ACS880 events as listed below. This parameter is read-only.		-
		ACS80	ACS800 fault name		
	Bit	(04.120 = ACS80 Standard ctrl program)	0 (04.120 = ACS800 System ctrl program)	ACS880 events indicated by this (see <i>Fault tracing</i> , page 549)	nis bit
	0	SUPPLY PHASE	SUPPLY PHASE	3130	
	1	NO MOT DATA	NO MOTOR DATA	-	
	2	DC UNDERVOLT	DC UNDERVOLT	3220	
	3	Reserved	CABLE TEMP	4000	
	4	RUN ENABLE	RUN DISABLE	AFEB	
	5	ENCODER ERR	ENCODER ERR	7301, 7380, 7381, 73A0, 73A1	
	6	I/O COMM	IO COMM ERR	7080, 7082	
	7	CTRL B TEMP	CTRL B TEMP	-	
	8	EXTERNAL FLT	SELECTABLE	9082	
	9	OVER SWFREQ	OVER SWFREQ	-	
	10	AI < MIN FUNC	AI <min func<="" td=""><td>80A0</td><td></td></min>	80A0	
	11	PPCC LINK	PPCC LINK	5681, 5682, 5690, 5691, 5692, 5 5695	5693, 5694,
	12	COMM MODULE	COMM MODULE	6681, 7510, 7520, 7581	
	13	PANEL LOSS	PANEL LOSS	7081	
			MOTOR STALL	7121	
	14	MOTOR STALL	WOTOR STALL		

No.	Name/V	/alue Descri	Description		
04.31	The b WOR <i>word</i> accor contro Each		0-compatible warning assignments of this v 1 in the ACS800. Par ompatibility determine ing to the ACS800 Sta program. nay indicate several A arameter is read-only.	-	
		ACS800	alarm name		
	Bit	(04.120 = ACS800 Standard ctrl program)	(04.120 = ACS800 System ctrl program)	ACS880 events indicated by this bit (see <i>Fault tracing</i> , page 549)	
	0	START INHIBIT	START INHIBI	A5A0	
	1	Reserved	EM STOP	AFE1, AFE2	
	2	THERMISTOR	MOTOR TEMP M	A491	
	3	MOTOR TEMP	MOTOR TEMP	A492	
	4	ACS800 TEMP	ACS800 TEMP	A2BA, A4A9, A4B0, A4B1, A4F6	
	5	ENCODER ERR	ENCODER ERR	A797, A7B0, A7B1, A7E1	
	6	T MEAS ALM	T MEAS CIRC	A490, A5EA, A782, A8A0	
	7	Reserved	DIGITAL IO	-	
	8	Reserved	ANALOG IO	-	
	9	Reserved	EXT DIGITAL IO	-	
	10	Reserved	EXT ANALOG IO	A6E5, A7AA, A7AB	
	11	Reserved	CH2 COMM LOSS	A7CB, AF80	
	12	COMM MODULE	MPROT SWITCH	A981	
	13	Reserved	EM STOP DEC	-	
	4.4	EARTH FAULT	EARTH FAULT	A2B3	
	14 15			AFETY SWITC A983	

о.	Name/	Value	Descrip	tion		Def/FbEq16	
1.32			The bit a WORD 2 word co	ACS800-compatible warning (alarm) word 2. The bit assignments of this word correspond to ALARM WORD 2 in the ACS800. Parameter <i>04.120 Fault/Warning</i> <i>word compatibility</i> determines whether the bit assignments are according to the ACS800 Standard or ACS800 System			
				•	CS880 warnings as listed below.		
				ameter is read-only.		ļ	
		A	CS800 a	arm name			
	Bit	(04.120 = A Standard c program)		(04.120 = ACS800 System ctrl program)	ACS880 events indicated by t (see Fault tracing, page 549)	his bit	
	0	Reserved		MOTOR FAN	A781		
	1	UNDERLO		UNDERLOAD	-		
	2	Reserved			-		
	3	Reserved			- A480		
	3 4	ENCODER		ENCODER A<>B	-		
	5	Reserved		FAN OVERTEMP	 A984		
	6	Reserved		Reserved	-		
	7	POWFAIL	FILE	POWFAIL FILE	-		
	8	ALM (OS_		POWDOWN FILE	-		
	9	MOTOR S		MOTOR STALL	A780 A8A0 A6D1, A6D2, A7C1, A7C2, A7CA, A7CE		
	10	AI < MIN F					
	10	Reserved					
	12	Reserved		BATT FAILURE	-		
	13	PANEL LO	SS	PANEL LOSS	A7EE		
	14	Reserved		DC UNDERVOLT	A3A2		
	15	Reserved		RESTARTED	-		
	0000h.	FFFFh	ACS800	-compatible warning	g (alarm) word 2.	1 = 1	
40	Event	eve		User-defined event word. This word collects the status of the - events (warnings, faults or pure events) selected by parameters <i>04.4104.72</i> .			
			for filteri	each event, an auxiliary code can optionally be specified Itering. parameter is read-only.			
	Bit	Name		Description			
	0	User bit 0		•	ed by parameters 04.41 (and 04.4	2) is active	
	1	User bit 1			ed by parameters 04.43 (and 04.4	,	
	15	User bit 15		1 = Event selecte	ed by parameters 04.71 (and 04.7	2) is active	
	0000h.	FFFFh	User-de	fined event word.		1 = 1	
		word 1 bit 0	Selects	the hexadecimal coo	de of an event (warning, fault or	0000h	
.41	code			The event codes are	shown as bit 0 of <i>04.40 Event</i> e listed in chapter <i>Fault tracing</i>		

No.	Name/Value	Description	Def/FbEq16
04.42	Event word 1 bit 0 aux code	Specifies an auxiliary code for the event selected by the previous parameter. The selected event is indicated by the event word only if its auxiliary code matches the value of this parameter. With a value of 0000 0000h, the event word will indicate the event regardless of the auxiliary code.	0000 0000h
	0000 0000h FFFF FFFFh	Code of warning, fault or pure event.	1 = 1
04.43	Event word 1 bit 1 code	Selects the hexadecimal code of an event (warning, fault or pure event) whose status is shown as bit 1 of 04.40 Event word 1. The event codes are listed in chapter Fault tracing (page 549).	0000h
	0000hFFFFh	Code of event.	1 = 1
04.44	Event word 1 bit 1 aux code	Specifies an auxiliary code for the event selected by the previous parameter. The selected event is indicated by the event word only if its auxiliary code matches the value of this parameter. With a value of 0000 0000h, the event word will indicate the event regardless of the auxiliary code.	0000 0000h
	0000 0000h FFFF FFFFh	Code of warning, fault or pure event.	1 = 1
04.71	Event word 1 bit 15 code	Selects the hexadecimal code of an event (warning, fault or pure event) whose status is shown as bit 15 of 04.40 Event word 1. The event codes are listed in chapter Fault tracing (page 549).	0000h
	0000hFFFFh	Code of event.	1 = 1
04.72	Event word 1 bit 15 aux code	Specifies an auxiliary code for the event selected by the previous parameter. The selected event is indicated by the event word only if its auxiliary code matches the value of this parameter. With a value of 0000 0000h, the event word will indicate the event regardless of the auxiliary code.	0000 0000h
	0000 0000h FFFF FFFFh	Code of warning, fault or pure event.	1 = 1
04.120	Fault/Warning word compatibility	Selects whether the bit assignments of parameters 04.2104.32 correspond to the ACS800 Standard control program or the ACS800 System control program.	False
	ACS800 Standard ctrl program	The bit assignments of parameters 04.2104.32 correspond to the ACS800 Standard control program as follows: 04.21 Fault word 1: 03.05 FAULT WORD 1 04.22 Fault word 2: 03.06 FAULT WORD 2 04.31 Warning word 1: 03.08 ALARM WORD 1 04.32 Warning word 2: 03.09 ALARM WORD 2	0
	ACS800 System ctrl program	The bit assignments of parameters 04.2104.32 correspond to the ACS800 System control program as follows: 04.21 Fault word 1: 09.01 FAULT WORD 1 04.22 Fault word 2: 09.02 FAULT WORD 2 04.31 Warning word 1: 09.04 ALARM WORD 1 04.32 Warning word 2: 09.05 ALARM WORD 2	1

No.	Name/V	alue	Descrip	otion	Def/FbEq16
05 Dia	ngnostics	5	drive m	run-time-type counters and measurements related to aintenance. meters in this group are read-only unless otherwise	
05.01	On-time	counter	On-time powere	e counter. The counter runs when the drive is d.	-
	06553	5 d	On-time	e counter.	1 = 1 d
05.02	Run-time	e counter	Motor ru modula	un-time counter. The counter runs when the inverter tes.	-
	06553	5 d	Motor r	un-time counter.	1 = 1 d
05.04	Fan on-t counter	ime		g time of the drive cooling fan. Can be reset from the panel by keeping Reset depressed for over 3 s.	-
	06553	5 d	Cooling	fan run-time counter.	1 = 1 d
05.11	Inverter tempera	ture	limit var 0.0% =	ed drive temperature in percent of fault limit. The fault ries according to the type of the drive. 0 °C (32 °F) = Fault limit	-
	-40.0	160.0%	Drive te	mperature in percent.	1 = 1%
05.22	2 Diagnostic word 3		Diagnos	stic word 3.	-
	Bit	Name	ĺ	Value	
	010	Reserved			
	11	Fan comm	and	1 = Drive fan is rotating above idle speed	
	1215	Reserved			
	0000h	FFFFh	Diagnos	stic word 3.	1 = 1
05.41	0000hFFFFh 05.41 Main fan service counter		its estin operatir fan. Wh service Can be	s the age of the main cooling fan as a percentage of nated lifetime. The estimate is based on the duty, ng conditions and other operating parameters of the ien the counter reaches 100%, a warning (<i>A8C0 Fan</i> <i>counter</i>) is generated. reset from the control panel by keeping Reset sed for over 3 seconds.	-
			Main co	ooling fan age.	1 = 1%
	0150%	ó			
05.42	0150% Aux. fan counter		of its es operatir fan. Wh service Can be	s the age of the auxiliary cooling fan as a percentage stimated lifetime. The estimate is based on the duty, ng conditions and other operating parameters of the ten the counter reaches 100%, a warning (<i>A8C0 Fan</i> <i>counter</i>) is generated. reset from the control panel by keeping Reset sed for over 3 seconds.	-

No.	Name/Value	Description	Def/FbEq16
05.111	Line converter temperature	(Only visible when IGBT supply unit control activated by 95.20) Estimated supply unit temperature in percent of fault limit. 0.0% = 0 °C (32 °F) 94% approx. = Warning limit 100.0% = Fault limit	-
	-40.0 160.0%	Supply unit temperature in percent.	1 = 1%
05.121	MCB closing counter	(Only visible when IGBT supply unit control activated by 95.20) Counts the closures of the main circuit breaker of the supply unit.	-
	04294967295	Count of closures of main circuit breaker.	1 = 1

06 00	ntrol and status	Drive control and status words	
words	ntrol and status	Drive control and status words.	
06.01	Main control word	The main control word of the drive. This parameter shows the control signals as received from the selected sources (such as digital inputs, the fieldbus interfaces and the application program). The bit assignments of the word are as described on page 619. The related status word and state diagram are presented on pages 621 and 622 respectively. Note: Bits 1215 can be used to carry additional control data, and used as a signal source by any binary-source selector parameter. This parameter is read-only.	-
	0000hFFFFh	Main control word.	1 = 1
06.02	Application control word	The drive control word received from the application program (if any). The bit assignments are described on page <i>619</i> . This parameter is read-only.	-
	0000hFFFFh	Application program control word.	1 = 1
06.03	FBA A transparent control word	Displays the unaltered control word received from the PLC through fieldbus adapter A when a transparent communication profile is selected eg. by parameter group 51 <i>FBA A settings</i> . This parameter is read-only.	-
	00000000h FFFFFFFh	Control word received through fieldbus adapter A.	-
06.04	FBA B transparent control word	Displays the unaltered control word received from the PLC through fieldbus adapter B when a transparent communication profile is selected eg. by parameter group 54 <i>FBA B settings</i> . This parameter is read-only.	-
	00000000h FFFFFFFh	Control word received through fieldbus adapter B.	1 = 1
06.05	EFB transparent control word	Displays the unaltered control word received from the PLC through the embedded fieldbus interface when a transparent communication profile is selected in parameter 58.25 Control profile. This parameter is read-only.	-
	00000000h FFFFFFFh	Control word received through the embedded fieldbus interface.	1 = 1

No.	Name/\	/alue	Description	Def/FbEq16		
06.11 Main status word			Main status word of the driveThe bit assignments are described on page 621. The related control word and state diagram are presented on pages 619 and 622 respectively.This parameter is read-only.			
	0000h	.FFFFh	Main status word.	1 = 1		
06.16	Drive st		Drive status word 1. This parameter is read-only.	-		
	Bit	Name	Description			
	0	Enabled	 Both run enable (see par. 20.12) and start enable (20.19) present, and Safe torque off has not been activated. Notes: In I/O or local control, clearing this bit makes the drive ento SWITCH-ON INHIBITED state (see page 621). This bit is not affected by the presence of a fault. 	-		
	1	Inhibited	bited 1 = Start inhibited. See parameters <i>06.18</i> and <i>06.25</i> for the source of the inhibiting signal.			
	2	DC charged	 1 = DC circuit has been charged. If present, the DC switch is closed, and charging switch is open. 0 = Charging not complete. If the inverter unit is not equipped with a DC switch (option +F286), check setting of 95.09. 			
	3	Ready to start	1 = Drive is ready to receive a start command			
	4	Following reference	1 = Drive is ready to follow given reference			
	5	Started	1 = Drive has been started			
	6	Modulating	1 = Drive is modulating (output stage is being controlled)			
	7	Limiting	1 = Any operating limit (speed, torque, etc.) is active			
	8	Local control	1 = Drive is in local control			
	9	Network ctrl	1 = Drive is in <i>network control</i> (see page 17)			
	10	Ext1 active				
	11	Ext2 active	1 = Control location EXT2 active			
	12	Reserved	•			
	13	Start request	1 = Start requested			
	1415	Reserved				
	0000h	.FFFFh	Drive status word 1.	1 = 1		

		status word 2. arameter is read-only.	-		
	This p	arameter is read-only.			
	I				
			I		
Bit	Name	Description			
0		one 1 = Motor identification (ID) run has been perform	ed		
1		· · · · · · · · · · · · · · · · · · ·			
2	Torque control	1 = Torque control mode active			
3	Speed control	1 = Speed control mode active			
4	Power control	Reserved			
5	Safe reference act	ve 1 = A "safe" reference is applied by functions such parameters 49.05 and 50.02	1 = A "safe" reference is applied by functions such as parameters 49.05 and 50.02		
6	Last speed active	1 = A "last speed" reference is applied by functions such as parameters 49.05 and 50.02			
7	Loss of reference	1 = Reference signal lost	1 = Reference signal lost		
8	Emergency stop fa	iled 1 = Emergency stop failed (see parameters 31.32	and 31.33)		
9	Jogging active	1 = Internally used by the control program	, , , ,		
10	Above limit	1 = Actual speed, frequency or torque equals or e (defined by parameters 46.3146.33. Valid in bot rotation.			
11	Emergency stop a	tive 1 = An emergency stop command signal is active, stopping after receiving an emergency stop comm			
12	Reduced run	1 = Reduced run active (see section <i>Reduced run</i> page <i>126</i>)	1 = Reduced run active (see section <i>Reduced run function</i> on page <i>126</i>)		
13	Reserved				
14	Stop failed	1 = Supply failed (see parameters 31.37 and 31.3	8)		
15	Reserved				
	2 2 3 4 5 7 3 7 3 9 10 11 12 13 14	Magnetized 2 Torque control 3 Speed control 4 Power control 5 Safe reference active 6 Last speed active 7 Loss of reference 8 Emergency stop fa 9 Jogging active 10 Above limit 11 Emergency stop active 12 Reduced run 13 Reserved 14 Stop failed	Magnetized 1 = The motor has been magnetized Portion 1 = Torque control mode active Speed control 1 = Speed control mode active Power control Reserved Safe reference active 1 = A "safe" reference is applied by functions such parameters 49.05 and 50.02 Last speed active 1 = A "last speed" reference is applied by function parameters 49.05 and 50.02 Loss of reference 1 = Reference signal lost Emergency stop failed 1 = Emergency stop failed (see parameters 31.32) Jogging active 1 = Internally used by the control program Above limit 1 = An emergency stop command signal is active, stopping after receiving an emergency stop command signal is active, stopping after receiving an emergency stop command signal is active, stopping after receiving an emergency stop command signal is active, stopping after receiving an emergency stop command signal is active, stopping after receiving an emergency stop command signal is active, stopping after receiving an emergency stop command signal is active, stopping after receiving an emergency stop command signal is active, stopping after receiving an emergency stop command signal is active, stopping after receiving an emergency stop command signal is active, stopping after receiving an emergency stop command signal is active, stopping after receiving an emergency stop command signal is active, stopping after receiving an emergency stop command signal is active, stopping after receiving an emergency stop command signal is active, stopping after receiving an emergency stop command signal is active, stopping af		

No.	Name/\	/alue	Descriptio	on	Def/FbEq16		
06.18	Start inhibit status word		inhibiting of After the c cycled. Se See also p 06.16 Driv	Start inhibit status word. This word specifies the source of the hhibiting condition that is preventing the drive from starting. After the condition is removed, the start command must be ycled. See bit-specific notes. See also parameter <i>06.25 Drive inhibit status word 2</i> , and <i>06.16 Drive status word 1</i> , bit 1. This parameter is read-only.			
	Bit	Name		Description	Note		
	0	Not ready r	un	1 = DC voltage is missing or drive has not been parametrized correctly. Check the parameters in groups 95 and 99.	а		
	1	Ctrl location	changed	1 = Control location has changed	a, c		
	2	SSW inhibit		1 = Control program is keeping itself in inhibited state	а		
	3	Fault reset		1 = A fault has been reset	a, c		
	4	Lost start enable		1 = Start enable signal missing	а		
	5	Lost run en	able	1 = Run enable signal missing	а		
	6	FSO inhibit		1 = Operation prevented by FSO-xx safety functions module	b		
	7	STO		1 = Safe torque off active	b		
	8	Current cali ended	bration	1 = Current calibration routine has finished	b, c		
	9	ID run ende	d	1 = Motor identification run has finished	b, c		
	10	Auto phase	ended	1 = Autophasing routine has finished	b, c		
	11	Em Off1		1 = Emergency stop signal (mode Off1)	b		
	12	Em Off2		1 = Emergency stop signal (mode Off2)	b		
	13	Em Off3		1 = Emergency stop signal (mode Off3)	b		
	14	Auto reset i	nhibit	1 = The autoreset function is inhibiting operation			
	15	Jogging act	ive	1 = The jogging enable signal is inhibiting operation	b		
	Notes:						
	а						
	b	a fresh risin	g-edge star	atus word 1 is still set after the removal of the inhibitin rt signal is required.	g condition,		
	С	Informative	bit. The inh	ibiting condition need not be removed by the user.			
	0000h	.FFFFh	Start inhih	it status word.	1 = 1		

No.	Name/\	alue	Description		Def/FbEq16
06.19	Speed control status word			ol status word. ter is read-only.	-
	Bit	Name		Description	
	0	Zero speer	1	 1 = Drive is running at zero speed, ie. the absolute value of par 90.01 Motor speed for control has remained below 21.06 Zero speed limit for longer than 21.07 Zero speed delay. Notes: This bit is not updated when mechanical brake control is 	
	0 Zero speed		4	 enabled by par. 44.06 and the drive is modula During a ramp stop when the drive is running delay count runs whenever [90.01] < [21.06]. reverse direction, the delay count runs whene [21.06]. 	forward, the From the
	1	Forward		1 = Drive is running in forward direction above zero speed limit ie. $[90.01] > +[21.06]$.	
	2	Reverse		1 = Drive is running in reverse direction above zero speed limit, ie. $[90.01] < -[21.06]$.	
	3	Out of wind	wol	1 = Speed error window control active (see par.	24.41)
	4	Internal speed feedback		1 = Estimated speed feedback used in motor control, that is estimated speed is selected by par. 90.41 or 90.46 , or the selected encoder has faulted (par. 90.45) 0 = Encoder 1 or 2 is used for speed feedback.	
	5	Encoder 1	feedback	1 = Encoder 1 used for speed feedback in motor control 0 = Encoder 1 faulted or not selected as source of speed feedback (see par. 90.41 and 90.46)	
	6	Encoder 2	feedback	1 = Encoder 2 used for speed feedback in motor control 0 = Encoder 2 faulted or not selected as source of speed feedback (see par. 90.41 and 90.46)	
	7	Any consta request	int speed	1 = A constant speed or frequency has been selected; see par. 06.20 .	
	8	Follower sp lim	beed corr min	1 = Minimum limit of speed correction (in a spee follower) has been reached (see par. 23.3923	
	9	Follower sp lim	beed corr max	1 = Maximum limit of speed correction (in a spee follower) has been reached (see par. 23.3923	
	1015	Reserved		•	
			1		1
	0000h	FFFFh	Speed control	ol status word.	1 = 1

No.	Name/\	/alue	Descripti	on	Def/FbEq16
06.20	Constai status v	nt speed vord	constant s parameter <i>Constant</i>	speed/frequency status word. Indicates which speed or frequency is active (if any). See also r 06.19 Speed control status word, bit 7, and section speeds/frequencies (page 76). meter is read-only.	-
	Bit	Name		Description	
	0	Constant sp	beed 1	1 = Constant speed or frequency 1 selected	
	1	Constant sp	beed 2	1 = Constant speed or frequency 2 selected	
	2	Constant speed 3 Constant speed 4		1 = Constant speed or frequency 3 selected	
	3			1 = Constant speed or frequency 4 selected	
	4	Constant sp	beed 5	1 = Constant speed or frequency 5 selected	
	5	Constant sp	beed 6	1 = Constant speed or frequency 6 selected	
	6	6 Constant speed 7		1 = Constant speed or frequency 7 selected	
	715	Reserved			
	0000hFFFFh Constant		Constant	speed/frequency status word.	1 = 1
21	Drive st	atus word 3		us word 3. meter is read-only.	-
	Bit	Name		Description	
	0	DC hold ac	tive	1 = DC hold is active (see par. 21.08)	
	1	Post-magn active	etizing	1 = Post-magnetizing is active (see par. 21.08)	
	2	Motor pre-h active	neating	1 = Motor pre-heating is active (see par. 21.14)	
	3	Smooth sta	irt active	Reserved.	
	4	Rotor posit	ion known	1 = Rotor position has been determined (autophasing not needed). See section <i>Parameter group 28 Frequency reference chain (page 270).</i> (page 92).	
	515	Reserved		·	
	0000h	.FFFFh	Drive state	us word 3.	1 = 1

	Name/V	alue	Descriptio	on	Def/FbEq16	
06.25	Drive inhibit status word 2		Drive inhibit status word 2. This word specifies the source of the inhibiting signal that is preventing the drive from starting. After the condition is removed, the start command must be cycled. See bit-specific notes. See also parameters <i>06.18 Start inhibit status word</i> , and <i>06.16 Drive status word 1</i> , bit 1. This parameter is read-only.		-	
	Bit	Name		Description	Note	
	0	Follower dr	ive	1 = A follower is preventing the master from starting.	а	
	1	Application		1 = The application program is preventing the drive from starting.	b	
	2	Reserved		·		
	3	Encoder fee	edback	1 = The encoder feedback configuration is preventing the drive from starting.	а	
	4	Ref source parametriza	ation	1 = A reference source parametrization conflict is preventing the drive from starting. See warning <i>A6DA Reference source parametrization</i> (page 559).	b	
	515	Reserved				
	Notes:					
	а	condition, a	If bit 1 of 06.16 Drive status word 1 is still set after the removal of the inhibit condition, and edge triggering is selected for the active external control loca rising-edge start signal is required. See parameters 20.02, 20.07 and 20.19		tion, a fresh	
	b If bit 1 of <i>06.16 Drive status word 1</i> is still set after the removal of the inhibiting condition, a fresh rising-edge start signal is required.					
			fresh rising	g-edge start signal is required.		
	0000h	condition, a	fresh rising		1 = 1	
06.29	0000h MSW bit	condition, a	fresh rising Start inhibi Selects a t	g-edge start signal is required.		
06.29		condition, a	fresh rising Start inhibi Selects a t	y-edge start signal is required. it status word 2. binary source whose status is transmitted as bit 10	1 = 1	
06.29	MSW bi	condition, a	fresh rising Start inhibi Selects a t of 06.11 M	y-edge start signal is required. it status word 2. binary source whose status is transmitted as bit 10	1 = 1 Above limit	
06.29	MSW bit	condition, a .FFFFh <i>t 10 sel</i>	fresh rising Start inhibi Selects a t of <i>06.11 M</i> 0. 1.	y-edge start signal is required. it status word 2. binary source whose status is transmitted as bit 10	1 = 1 <i>Above limit</i> 0	
06.29	MSW bit False True	condition, a .FFFFh <i>t 10 sel</i> mit	fresh rising Start inhibi Selects a t of <i>06.11 M</i> 0. 1. Bit 10 of <i>0</i>	it status word 2. binary source whose status is transmitted as bit 10 dain status word.	1 = 1 <i>Above limit</i> 0 1	
	MSW bit False True Above li	condition, a .FFFFh <i>t 10 sel</i> mit	fresh rising Start inhibi Selects a b of 06.11 M 0. 1. Bit 10 of 0 Source sel Selects a b	 j-edge start signal is required. it status word 2. binary source whose status is transmitted as bit 10 <i>lain status word</i>. 6.17 Drive status word 1 (see page 151).	1 = 1 <i>Above limit</i> 0 1	
	MSW bin False True Above li Other [b	condition, a .FFFFh <i>t 10 sel</i> mit	fresh rising Start inhibi Selects a b of 06.11 M 0. 1. Bit 10 of 0 Source sel Selects a b	 j-edge start signal is required. it status word 2. binary source whose status is transmitted as bit 10 <i>lain status word</i>. 6.17 Drive status word 1 (see page 151). lection (see Terms and abbreviations on page 131). binary source whose status is transmitted as bit 11 	1 = 1 <i>Above limit</i> 0 1 2 -	
	MSW bin False True Above li Other [b MSW bin	condition, a .FFFFh <i>t 10 sel</i> mit	fresh rising Start inhibit Selects a to of 06.11 M 0. 1. Bit 10 of 0 Source sel Selects a to of 06.11 M	 j-edge start signal is required. it status word 2. binary source whose status is transmitted as bit 10 <i>lain status word</i>. 6.17 Drive status word 1 (see page 151). lection (see Terms and abbreviations on page 131). binary source whose status is transmitted as bit 11 	1 = 1 <i>Above limit</i> 0 1 2 - <i>Ext ctrl loc</i>	
	MSW bin False True Above li Other [b MSW bin False	condition, a .FFFFh <i>t 10 sel</i> mit <i>it]</i> <i>t 11 sel</i>	fresh rising Start inhibit Selects a to of 06.11 M 0. 1. Bit 10 of 0 Source sel Selects a to of 06.11 M 0. 1.	 j-edge start signal is required. it status word 2. binary source whose status is transmitted as bit 10 <i>lain status word</i>. 6.17 Drive status word 1 (see page 151). lection (see Terms and abbreviations on page 131). binary source whose status is transmitted as bit 11 	1 = 1 <i>Above limit</i> 0 1 2 - <i>Ext ctrl loc</i> 0	
	MSW bin False True Above li Other [b MSW bin False True	condition, a .FFFFh <i>t 10 sel</i> mit <i>it]</i> <i>t 11 sel</i> oc	fresh rising Start inhibit Selects a to of 06.11 M 0. 1. Bit 10 of 0 Source sel Selects a to of 06.11 M 0. 1. Bit 11 of 0 Bit 11 of 0	 a status word 2. b inary source whose status is transmitted as bit 10 train status word. 6.17 Drive status word 1 (see page 151). a lection (see Terms and abbreviations on page 131). b inary source whose status is transmitted as bit 11 train status word. 	1 = 1 <i>Above limit</i> 0 1 2 - <i>Ext ctrl loc</i> 0 1	
06.30	MSW bin False True Above li Other [b MSW bin False True Ext ctrl l	condition, a .FFFFh <i>t 10 sel</i> mit <i>it[</i>] <i>t 11 sel</i> oc <i>it[</i>]	fresh rising Start inhibit Selects a to of 06.11 M 0. 1. Bit 10 of 0 Source sel Selects a to of 06.11 M 0. 1. Bit 11 of 0 A specific to Selects a to Selects a to of 0.	 j-edge start signal is required. it status word 2. binary source whose status is transmitted as bit 10 <i>fain status word</i>. 6.17 Drive status word 1 (see page 151). lection (see Terms and abbreviations on page 131). binary source whose status is transmitted as bit 11 <i>fain status word</i>. 6.01 Main control word (see page 149). 	1 = 1 <i>Above limit</i> 0 1 2 - <i>Ext ctrl loc</i> 0 1	
06.30	MSW bin False True Above li Other [b MSW bin False True Ext ctrl li Other [b	condition, a .FFFFh <i>t 10 sel</i> mit <i>it[</i>] <i>t 11 sel</i> oc <i>it[</i>]	fresh rising Start inhibit Selects a to of 06.11 M 0. 1. Bit 10 of 0 Source sel Selects a to of 06.11 M 0. 1. Bit 11 of 0 A specific to Selects a to Selects a to of 0.	 ait status word 2. binary source whose status is transmitted as bit 10 tain status word. 6.17 Drive status word 1 (see page 151). lection (see Terms and abbreviations on page 131). binary source whose status is transmitted as bit 11 tain status word. 6.01 Main control word (see page 149). bit in another parameter. binary source whose status is transmitted as bit 12 	1 = 1 <i>Above limit</i> 0 1 2 - <i>Ext ctrl loc</i> 0 1 2 - <i>Ext ctrl loc</i> 1 2 - <i>Ext ctrl loc</i>	
06.30	MSW bin False True Above li Other [b MSW bin False True Ext ctrl li Other [b MSW bin	condition, a .FFFFh <i>t 10 sel</i> mit <i>it[</i>] <i>t 11 sel</i> oc <i>it[</i>]	fresh rising Start inhibit Selects a to of 06.11 M 0. 1. Bit 10 of 0 Source sel Selects a to of 06.11 M 0. 1. Bit 11 of 0 A specific I Selects a to of 06.11 M	 ait status word 2. binary source whose status is transmitted as bit 10 tain status word. 6.17 Drive status word 1 (see page 151). lection (see Terms and abbreviations on page 131). binary source whose status is transmitted as bit 11 tain status word. 6.01 Main control word (see page 149). bit in another parameter. binary source whose status is transmitted as bit 12 	1 = 1 <i>Above limit</i> 0 1 2 - <i>Ext ctrl loc</i> 0 1 2 - <i>Ext ctrl loc</i> 0 1 2 - <i>Ext ctrl loc</i>	
06.29 06.30 06.31	MSW bin False True Above lii Other [b MSW bin False True Ext ctrl li Other [b MSW bin False	condition, a .FFFFh <i>t 10 sel</i> mit <i>it]</i> <i>t 11 sel</i> oc <i>it]</i> <i>t 12 sel</i>	fresh rising Start inhibit Selects a to of 06.11 M 0. 1. Bit 10 of 0 Source sel Selects a to of 06.11 M 0. 1. Bit 11 of 0 A specific to Selects a to of 06.11 M 0. 1.	 j-edge start signal is required. it status word 2. binary source whose status is transmitted as bit 10 <i>fain status word</i>. 6.17 Drive status word 1 (see page 151). lection (see Terms and abbreviations on page 131). binary source whose status is transmitted as bit 11 <i>fain status word</i>. 6.01 Main control word (see page 149). bit in another parameter. binary source whose status is transmitted as bit 12 <i>fain status word</i>. 	1 = 1 <i>Above limit</i> 0 1 2 - <i>Ext ctrl loc</i> 0 1 2 - <i>Ext run</i> <i>enable</i> 0	

	Name/V	alue	Description Def/FbEq		
06.32	32 MSW bit 13 sel		Selects a binary source whose status is transmitted as bit 13 of 06.11 Main status word.	False	
	False		0.	0	
	True		1.	1	
	Other [b	it]	A specific bit in another parameter.	-	
06.33	MSW bit	t 14 sel	Selects a binary source whose status is transmitted as bit 14 of <i>06.11 Main status word</i> .	False	
	False		0.	0	
	True		1.	1	
	Other [b	it]	A specific bit in another parameter.	-	
06.36	LSU Sta	tus Word	<i>(Only visible when supply unit control activated by 95.20)</i> Shows the status of the supply unit. See also section <i>Control of a supply unit (LSU)</i> (page 73), and parameter group <i>60 DDCS communication</i> . This parameter is read-only.	-	
	Bit	Name	Description		
	0	Ready on	1 = Ready to switch on		
	1	Ready run	1 = Ready to operate, DC link charged		
	2				
		Ready ref	1 = Operation enabled		
	3	Ready ref Tripped	1 = Operation enabled 1 = A fault is active		
	3 46	,	•		
		Tripped Reserved Alarm	1 = A fault is active 1 = A warning is active		
	46	Tripped Reserved	1 = A fault is active 1 = A warning is active 1 = The supply unit is modulating		
	46 7	Tripped Reserved Alarm	1 = A fault is active 1 = A warning is active		
	46 7 8	Tripped Reserved Alarm Modulating	 1 = A fault is active 1 = A warning is active 1 = The supply unit is modulating 1 = Remote control (EXT1 or EXT2) 		
	46 7 8 9	Tripped Reserved Alarm Modulating Remote	1 = A fault is active 1 = A warning is active 1 = The supply unit is modulating 1 = Remote control (EXT1 or EXT2) 0 = Local control		
	46 7 8 9 10	Tripped Reserved Alarm Modulating Remote Net ok	1 = A fault is active 1 = A warning is active 1 = The supply unit is modulating 1 = Remote control (EXT1 or EXT2) 0 = Local control 1 = Supply network voltage OK		
	46 7 8 9 10 1112	Tripped Reserved Alarm Modulating Remote Net ok Reserved Charging or	1 = A fault is active 1 = A warning is active 1 = The supply unit is modulating 1 = Remote control (EXT1 or EXT2) 0 = Local control 1 = Supply network voltage OK		
	46 7 8 9 10 1112 13	Tripped Reserved Alarm Modulating Remote Net ok Reserved Charging or ready run	1 = A fault is active 1 = A warning is active 1 = The supply unit is modulating 1 = Remote control (EXT1 or EXT2) 0 = Local control 1 = Supply network voltage OK 1 = Bit 1 or bit 14 active 1 = Charging contactor closed		
	46 7 8 9 10 1112 13 14	Tripped Reserved Alarm Modulating Remote Net ok Reserved Charging or ready run Charging	1 = A fault is active 1 = A warning is active 1 = The supply unit is modulating 1 = Remote control (EXT1 or EXT2) 0 = Local control 1 = Supply network voltage OK 1 = Bit 1 or bit 14 active 1 = Charging contactor closed		

No.	Name/\	/alue	Description	Def/FbEq16	
06.39	Internal machin	state e LSU CW	<i>(Only visible when supply unit control activated by 95.20)</i> Shows the control word sent to the supply unit from the INU- LSU (inverter unit/supply unit) state machine. This parameter is read-only.	-	
	Bit	Name	Description		
	0	ON/OFF	1 = Start charging 0 = Open main contactor (switch power off)		
	1	OFF 2	0 = Emergency stop (Off2)		
	2	OFF 3	0 = Emergency stop (Off3)		
	3	START	1 = Start modulating 0 = Stop modulating		
	46	Reserved			
	7	RESET	0 -> 1 = Reset an active fault. A fresh start command is requir	ed after reset.	
	811	Reserved			
	12	USER BIT (•		
	13	USER BIT ?			
	14	USER BIT 2			
	15	USER BIT 3	3 See parameter 06.43 LSU CW user bit 3 selection.		
	0000hFFFFh		Supply unit control word.	1 = 1	
06.40	LSU CW user bit 0 selection		(Only visible when supply unit control activated by 95.20) Selects a binary source whose status is transmitted as bit 12 of 06.39 Internal state machine LSU CW to the supply unit.	MCW user bit 0	
	False		0.	0	
	True		1.	1	
	MCW user bit 0		Bit 12 of 06.01 Main control word (see page 149).	2	
	MCW user bit 1		Bit 13 of 06.01 Main control word (see page 149).	3	
	MCW u	ser bit 2	Bit 14 of 06.01 Main control word (see page 149).	4	
	MCW u	ser bit 3	Bit 15 of 06.01 Main control word (see page 149).	5	
	Other [l	bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-	
06.41	LSU CW user bit 1 selection		(Only visible when supply unit control activated by 95.20) Selects a binary source whose status is transmitted as bit 13 of 06.39 Internal state machine LSU CW to the supply unit.	MCW user bit 1	
	False		0.	0	
	True		1.	1	
	MCW u	ser bit 0	Bit 12 of 06.01 Main control word (see page 149).	2	
	MCW u	ser bit 1	Bit 13 of 06.01 Main control word (see page 149).	3	
	MCW u	ser bit 2	Bit 14 of 06.01 Main control word (see page 149).	4	
	MCW u	ser bit 3	Bit 15 of 06.01 Main control word (see page 149).	5	
	Other [l	oit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-	
06.42	LSU CV selectio	V user bit 2 n	(Only visible when supply unit control activated by 95.20) Selects a binary source whose status is transmitted as bit 14 of 06.39 Internal state machine LSU CW to the supply unit.	MCW user bit 2	
	False		0.	0	
	True		1.	1	

No.	Name/Value	Description	Def/FbEq16
	MCW user bit 0	Bit 12 of 06.01 Main control word (see page 149).	2
	MCW user bit 1	Bit 13 of 06.01 Main control word (see page 149).	3
	MCW user bit 2	Bit 14 of 06.01 Main control word (see page 149).	4
	MCW user bit 3	Bit 15 of 06.01 Main control word (see page 149).	5
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
06.43	LSU CW user bit 3 selection	<i>(Only visible when supply unit control activated by 95.20)</i> Selects a binary source whose status is transmitted as bit 15 of <i>06.39 Internal state machine LSU CW</i> to the supply unit.	MCW user bit 3
	False	0	
	True	1.	1
	MCW user bit 0	Bit 12 of 06.01 Main control word (see page 149).	2
	MCW user bit 1	Bit 13 of 06.01 Main control word (see page 149).	3
	MCW user bit 2	Bit 14 of 06.01 Main control word (see page 149).	4
	MCW user bit 3	Bit 15 of 06.01 Main control word (see page 149).	5
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
06.45	Follower CW user bit 0 selection	Selects a binary source whose status is transmitted as bit 12 of the Follower control word to follower drives. (Bits 011 of the Follower control word are taken from 06.01 Main control word.) See also section Master/follower functionality (page 64).	MCW user bit 0
	False 0.		0
	True 1.		1
	MCW user bit 0 Bit 12 of 06.01 Main control word (see page 149).		2
	MCW user bit 1	Bit 13 of 06.01 Main control word (see page 149).	3
	MCW user bit 2	Bit 14 of 06.01 Main control word (see page 149).	4
	MCW user bit 3	Bit 15 of 06.01 Main control word (see page 149).	5
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
06.46	Follower CW user bit 1 selection	Selects a binary source whose status is transmitted as bit 13 of the Follower control word to follower drives. (Bits 011 of the Follower control word are taken from 06.01 Main control word.)	MCW user bit 1
	False	0.	0
	True	1.	1
	MCW user bit 0	Bit 12 of 06.01 Main control word (see page 149).	2
	MCW user bit 1	Bit 13 of 06.01 Main control word (see page 149).	3
	MCW user bit 2	Bit 14 of 06.01 Main control word (see page 149).	4
	MCW user bit 3	Bit 15 of 06.01 Main control word (see page 149).	5
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
06.47	Follower CW user bit 2 selection	Selects a binary source whose status is transmitted as bit 14 of the Follower control word to follower drives. (Bits 011 of the Follower control word are taken from 06.01 Main control word.)	MCW user bit 2
	False	0.	0
	True	1.	1
	MCW user bit 0	Bit 12 of 06.01 Main control word (see page 149).	2

No.	Name/Value		Descriptio	on	Def/FbEq16	
	MCW user bit 1		Bit 13 of O	6.01 Main control word (see page 149).	3	
	MCW us	ser bit 2	Bit 14 of O	6.01 Main control word (see page 149).	4	
	MCW user bit 3 Other [bit]		Bit 15 of O	6.01 Main control word (see page 149).	5	
			Source sel	ection (see Terms and abbreviations on page 131).	-	
06.48	Follower bit 3 sel	r CW user ection	of the Follo	binary source whose status is transmitted as bit 15 ower control word to follower drives. (Bits 011 of er control word are taken from <i>06.01 Main control</i>	MCW user bit 3	
	False		0.		0	
	True		1.		1	
	MCW us	ser bit 0	Bit 12 of O	6.01 Main control word (see page 149).	2	
	MCW us	ser bit 1	Bit 13 of O	6.01 Main control word (see page 149).	3	
	MCW us	ser bit 2	Bit 14 of 0	6.01 Main control word (see page 149).	4	
	MCW us	ser bit 3	Bit 15 of 0	6.01 Main control word (see page 149).	5	
	Other [b	it]	Source sel	ection (see Terms and abbreviations on page 131).	-	
06.50	User status word 1		User-defin binary sou	ed status word. This word shows the status of the rces selected by parameters <i>06.6006.75</i> . This is read-only.	-	
	Bit	Name		Description		
	0 User status		bit 0	51		
	1	User status	s bit 1	Status of source selected by parameter 06.61		
	 15 User status		bit 15 Status of source selected by parameter 06.75			
	0000h		Lleer defin		1 = 1	
00.00				ed status word.		
06.60	User status word 1 bit 0 sel		Selects a binary source whose status is shown as bit 0 of 06.50 User status word 1.		False	
	False		0.		0	
	True		1.		1	
	Other [b	it]	Source selection (see <i>Terms and abbreviations</i> on page 131).		-	
06.61	User sta bit 1 sel	tus word 1	Selects a binary source whose status is shown as bit 1 of 06.50 User status word 1.		Out of window	
	False		0.		0	
	True		1.		1	
	Out of w	vindow	Bit 3 of 06.19 Speed control status word (see page 153).		2	
	Other [b	it]	Source sel	ection (see <i>Terms and abbreviations</i> on page 131).	-	
06.62	User sta bit 2 sel	tus word 1		binary source whose status is shown as bit 2 of r status word 1.	Emergency stop failed	
	False		0.		0	
	True		1.		1	
	Emerge failed	ncy stop	Bit 8 of 06.	17 Drive status word 2 (see page 151).	2	
			1			

No.	Name/Value	Description	Def/FbEq16		
06.63	User status word 1 bit 3 sel	Selects a binary source whose status is shown as bit 3 of 06.50 User status word 1.	Magnetized		
	False	0.	0		
	True	1.	1		
	Magnetized	Bit 1 of 06.17 Drive status word 2 (see page 151).	2		
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-		
06.64	User status word 1 bit 4 sel	Selects a binary source whose status is shown as bit 4 of 06.50 User status word 1.	Run disable		
	False	0.	0		
	True	1.	1		
	Run disable	Bit 5 of 06.18 Start inhibit status word (see page 152).	2		
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-		
06.65	User status word 1 bit 5 sel	Selects a binary source whose status is shown as bit 5 of 06.50 User status word 1.	False		
	False	0.	0		
	True	1.	1		
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-		
06.66	User status word 1 bit 6 sel	 Selects a binary source whose status is shown as bit 6 of 06.50 User status word 1. 			
	False	0.			
	True	1.	1		
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-		
06.67	User status word 1 bit 7 sel	Selects a binary source whose status is shown as bit 7 of 06.50 User status word 1.	Identification run done		
	False	0.	0		
	True	1.	1		
	Identification run done	Bit 0 of 06.17 Drive status word 2 (see page 151).	2		
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-		
06.68	User status word 1 bit 8 sel	Selects a binary source whose status is shown as bit 8 of 06.50 User status word 1.	Start inhibition		
	False	0.	0		
	True	1.	1		
	Start inhibition	Bit 7 of 06.18 Start inhibit status word (see page 152).	2		
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-		
06.69	User status word 1 bit 9 sel	Selects a binary source whose status is shown as bit 9 of 06.50 User status word 1.	Limiting		
	False	0.	0		
	True	1.	1		
	Limiting	Bit 7 of 06.16 Drive status word 1 (see page 150).	2		
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-		
06.70	User status word 1 bit 10 sel	Selects a binary source whose status is shown as bit 10 of 06.50 User status word 1.	Torque control		
	False	0.	0		

No.	Name/Value		Description	Def/FbEq16
	True		1.	1
	Torque o	control	Bit 2 of 06.17 Drive status word 2 (see page 151).	2
	Other [b	oit]	Source selection (see Terms and abbreviations on page	e 131)
06.71	User sta bit 11 se	atus word 1 el	Selects a binary source whose status is shown as bit 1 ^o 06.50 User status word 1.	1 of Zero speed
	False		0.	0
	True		1.	1
	Zero spe	eed	Bit 0 of 06.19 Speed control status word (see page 153	3). 2
	Other [b	oit]	Source selection (see Terms and abbreviations on page	e 131)
06.72	User sta bit 12 se	atus word 1 el	Selects a binary source whose status is shown as bit 12 06.50 User status word 1.	2 of Internal speed feedback
	False		0.	0
	True		1.	1
	Internal feedbac		Bit 4 of 06.19 Speed control status word (see page 153	3). 2
	Other [bit]		Source selection (see Terms and abbreviations on page	e 131)
06.73	User status word 1 bit 13 sel		Selects a binary source whose status is shown as bit 13 06.50 User status word 1.	3 of False
	False		0.	0
	True		1.	1
	Other [bit]		Source selection (see Terms and abbreviations on page	e 131)
06.74	User status word 1 bit 14 sel		Selects a binary source whose status is shown as bit 1- 06.50 User status word 1.	4 of False
	False		0.	0
	True		1.	1
	Other [b	oit]	Source selection (see Terms and abbreviations on page	e 131)
06.75	User sta bit 15 se	atus word 1 el	Selects a binary source whose status is shown as bit 19 06.50 User status word 1.	5 of False
	False		0.	0
	True		1.	1
	Other [b	oit]	Source selection (see Terms and abbreviations on page	e 131)
06.100	User control word 1		User-defined control word 1. This parameter is read-only.	-
	Bit	Name	Description	
	0		word 1 bit 0 User-defined bit.	
	1	User contro	word 1 bit 1 User-defined bit.	
	 15	 User contro	word 1 bit 15 User-defined bit.	
	0000h	.FFFFh	User-defined control word 1.	1 = 1

No.	Name/Value		Description		Def/FbEq1		
06.101	User control word 2			control word 2.	-		
			This paramete	er is read-only.			
	Bit	Name		Description			
	0	User contro	l word 2 bit 0	User-defined bit.			
	1	User contro	l word 2 bit 1	User-defined bit.			
	15	User contro	l word 2 bit 15	User-defined bit.			
	0000		Llaan da£nad	e e strel uver el Q	4 - 4		
	0000h			control word 2.	1 = 1		
06.116	LSU driv	e status		when IGBT supply unit control activated by	-		
	word 1		95.20) Drive status w	ord 1 received from the supply unit.			
				ion <i>Control of a supply unit (LSU)</i> (page 73),			
				r group 60 DDCS communication.			
			This paramete	er is read-only.			
			I		Ι		
	Bit	Name	Descriptio	n			
	0	Enabled	-	able and start enable signals are present			
	1	Inhibited	1 = Start in				
	2	Operation		s ready to operate			
		allowed					
	3	Ready to st	art 1 = Drive is	t 1 = Drive is ready to receive a start command			
	4	Running	1 = Drive is	1 = Drive is ready to follow given reference			
	5	Started	1 = Drive h	as been started			
	6	Modulating	1 = Drive is	1 = Drive is modulating (output stage is being controlled)			
	7	Limiting	1 = Any op	1 = Any operating limit is active			
	8	Local contro	ol 1 = Drive is	1 = Drive is in local control			
	9	Network	1 = Drive is	s in network control			
	10	control	4 0 0 0 0				
	10	Ext1 active		1 = Control location Ext1 active			
	11	Ext2 active		rol location Ext2 active			
	12	Charging re	,	ng relay is closed			
	13	MCB relay	T = MCB re	elay is closed			
	1415	Reserved					

No.	Name/Value	Description		Def/FbEq16
06.118 LSU start inhibit status word		95.20) This word specifies t s preventing the sup See also section Co	<i>GBT supply unit control activated by</i> he source of the inhibiting condition that pply unit from starting. <i>ntrol of a supply unit (LSU)</i> (page 73), 6 60 DDCS communication. ad-only.	-
		Bit Name		7
		0 Not ready r	un	
		1 Ctrl location	-]
		2 SSW inhibi	t	
		3 Fault reset		_
		4 Lost start e		_
		5 Lost run en 68 Reserved	able	4
		-	verload	-
		9 Charging o 1011 Reserved	Verioad	-
		12 Em Off2		_
		13 Em Off3		-
		14 Auto reset	inhibit	-
		15 Reserved		
	0000hFFFFh	Start inhibit status w	ord of supply unit.	1 = 1
07 Sys	stem info	program.	hardware, firmware and application s group are read-only.	
07.03	Drive rating id	Type of the drive/inv	erter unit.	-
07.04	Firmware name	Firmware identification The format is AINFX (2 = BCU-x2, 6 = ZC	, where X denotes the control unit type	-
07.05	Firmware version		e firmware. C.D, where A = major version, B = minor e. firmware variant code), D = 0.	-
07.06	Loading package name	Name of the firmwar The format is AINLX (2 = BCU-x2, 6 = ZC	, where X denotes the control unit type	-
07.07	Loading package version	Version number of th See parameter 07.03	e firmware loading package. 5.	-
07.08	Boot loader version	Version number of th	e firmware bootloader.	-
07.11	Cpu usage	Microprocessor load	in percent.	-
	0100%	Microprocessor load		1 = 1%
07.13	PU logic version number		dicates that the version numbers of ower units are different. See the drive	-

No.	Name/V	/alue	Description		Def/FbEq16		
07.21	Applicat environi status 1	ment	programm Shows whi See the Dr	<i>le with option +N8010 [application ability])</i> ich tasks of the application program are running. <i>rive (IEC 61131-3) application programming</i> AUA0000127808 [English]).	-		
	Bit	Name		Description			
	0	Pre task		1 = Pre-task running.			
	1	Appl task1		1 = Task 1 running.			
	2	Appl task2		1 = Task 2 running.			
	3	Appl task3		1 = Task 3 running.			
	414	Reserved					
	15	Task monit	oring	1 = Task monitoring enabled.			
	<u>.</u>						
	0000h	.FFFFh	Application	n program task status.	1 = 1		
07.22	Applicat environi status 2	ment	programm Shows the See the Dr	<i>le with option +N8010 [application ability])</i> status of the openings in the application program. <i>rive (IEC 61131-3) application programming</i> AUA0000127808 [English]).	-		
	Bit	Name		Description			
	0	Opening1		Status of opening 1 in the application program.			
	1	Opening2		Status of opening 2 in the application program.			
	15	Opening16		Status of opening 16 in the application program.			
	0000h	FFFFh	Application	n program opening status.	1 = 1		
07.00							
07.23	program First five program under Sy PC tool.		programm First five A program in under Syst	SCII letters of the name given to the application the programming tool. The full name is visible em info on the control panel or the Drive composer	-		
07.24	pro Ap pro		programma Application program in	le with option +N8010 [application ability]) n program version number given to the application the programming tool. Also visible under System control panel or the Drive composer PC tool.	-		
07.25	package name package. control pa		package. 7	SCII letters of the name given to the customization The full name is visible under System info on the nel or the Drive composer PC tool. one.	-		
07.26	Custom package	ization e version		tion package version number. Also visible under o on the control panel or the Drive composer PC	-		

No.	Name/Va	alue	Descriptio	n	Def/FbEq16
07.30	Adaptive status	e program		status of the adaptive program. n <i>Adaptive programming</i> (page <i>60</i>).	-
	Bit	Name		Description	
	0	Initialized		1 = Adaptive program initialized	
	1	Editing		1 = Adaptive program is being edited	
	2	Edit done		1 = Editing of adaptive program finished	
	3	Running		1 = Adaptive program running	
	413	Reserved			
	14	State chang	ging	1 = State change in progress in adaptive programn	ning engine
	15	Faulted		1 = Error in adaptive program	
			i		1
	0000h	FFFFh	Adaptive p	rogram status.	1 = 1
07.40	07.40 IEC application Cpu usage peak 0.0 100.0%		programma Displays th the applica used to ch functionalit The value Can be res	le with option +N8010 [application ability]) he peak loading of the microprocessor caused by tion program. This parameter can, for example, be eck the effect of a given application program y on the CPU load. his in percent of an internally-defined quota. het from the control panel by keeping Reset for over 3 seconds.	-
			Peak micro	pprocessor loading caused by application program.	10 = 1%
07.41	IEC appl load ave	ication Cpu rage	<i>programma</i> Displays th	le average loading of the microprocessor caused lication program. The value is in percent of an	-
	0.0 10	0.0%	Average m program.	icroprocessor loading caused by application	10 = 1%
07.106	LSU load package	•	95.20)	le when IGBT supply unit control activated by le loading package of the supply unit firmware.	-
07.107	LSU loading package version Version		(Only visib. 95.20)	le when IGBT supply unit control activated by mber of the loading package of the supply unit	-
09 Spi	nning ac	ctual	•	als of the spinning control program. ters in this group are read-only.	
09.01	Average speed1	spindle		value based on machine parameters, section time values set for pattern1.	-
	099999	9 rpm	Calculated	average speed	1 = 1 rpm (max. 32767)
09.02	Average speed2	spindle		value based on machine parameters, section time values set for pattern2.	-
	099999	9 rpm	Calculated	average speed	1 = 1 rpm (max. 32767)

No.	Name/Value	Description	Def/FbEq16
09.03	Average spindle speed3	Calculated value based on machine parameters, section time and speed values set for pattern3.	-
	099999 rpm	Calculated average speed	1 = 1 rpm (max. 32767)
09.04	Average spindle speed4	Calculated value based on machine parameters, section time and speed values set for pattern4.	-
	099999 rpm	Calculated average speed	1 = 1 rpm (max. 32767)
09.05	Current pattern	Shows active pattern.	Pattern1
	Pattern1	Pattern1 is selected.	1 = 1
09.06	Future pattern	Next-to-be-run pattern.	Pattern1
	Pattern1	Pattern1 is selected.	1 = 1
09.07	Shift selected	Status of shift selection.	No
	No	Shift function is not selected.	0
	Yes	Shift function is selected.	1
09.08	Running section	Running section inside the active pattern.	No section running
	No section running	Running section is not selected.	1 = 1
09.09	Pattern total run time	Shows the real time difference between end time of current pattern and start time of current pattern.	-
	0.009999.00 min	Total run time of current pattern.	100 = 1 min (max. 32767)
09.10	Pattern stop time	Shows the total time for which the pattern is paused /stopped during current pattern run.	-
	0.009999.00 min	Total stop time of current pattern.	100 = 1 min (max. 32767)
09.11	Pattern completed time	Shows the completed time from beginning of current pattern.	-
	0.009999.00 min	Completed time of current pattern.	100 = 1 min (max. 32767)
09.12	Remaining pattern time	Shows the remaining time to complete the current pattern.	-
	0.009999.00 min	Current pattern remaining time.	100 = 1 min (max. 32767)
09.13	Pattern production Kg	Shows the current pattern production in Kilograms.	-
	0.03000.0 Kg	Production of current pattern in Kg.	10 = 1 Kg
09.14	Pattern production hank	Shows the current pattern production in Hank.	-
	0.00 30000.00 Hank	Production of current pattern in Hank.	100 = 1 Hank (max. 32767)
09.15	Pattern KWH	Shows the energy (unit) consumed in current pattern.	-
	0.03000.0 KWh	Energy consumed in KWh.	10 = 1 KWh (max. 32767)

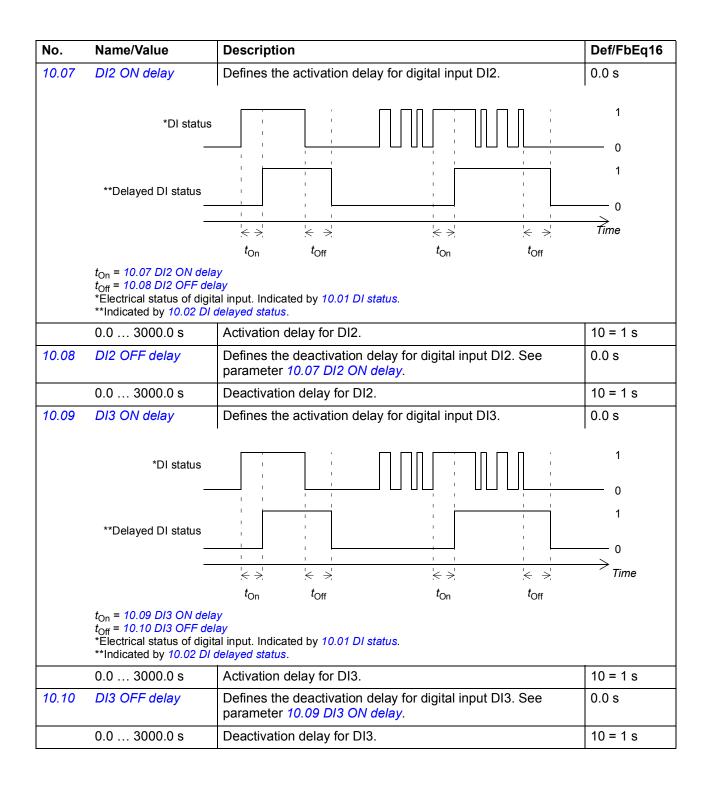
No.	Name/Value	Description	Def/FbEq16
09.16	Pattern KWh/Kg	Shows the energy (unit) consumed per Kg production in current pattern.	-
	0.0 3000.0 KWh/Kg	Energy consumed in KWh/Kg.	100 = 1 KWh/Kg
09.17	Current shift production Kg	Shows the production in kilograms produced during current shift.	-
	0.09000.0 Kg	Production of current shift in Kg.	10 = 1 Kg (max. 32767)
09.18	Current shift production Hank	Shows the production in hank during current shift.	-
	0.00 30000.00 Hank	Current shift production in Hank.	100 = 1 Hank (max. 32767)
09.19	Current shift run time	Shows the total run time of the machine during current shift.	-
	0.03000.0 min	Current shift run time.	10 = 1 min
09.20	Current shift stop time	Shows the total stop time of the machine during current shift.	-
	0.03000.0 min	Current shift stop time.	10 = 1 min
09.21	Current shift KWh consumption	Shows the total energy (unit) consumed during current shift.	-
	0.09000.0 KWh	Current shift total KWh consumption.	10 = 1 KWh (max. 32767)
09.22	Current shift KWh per Kg	Shows the energy (units) per kilogram production during current shift.	-
	0.09000.0 KWh/Kg	Current shift KWh/Kg.	10 = 1 KWh/Kg (max. 32767)
09.23	Current shift GPS	Shows the production in grams per active spindle during current shift.	-
	03000 g	Current shift production in GPS.	1 = 1 g
09.24	Current shift pattern count	Shows the total number of completed patterns during current shift.	-
	010000	Current shift total completed patterns.	1 = 1
09.35	Spinning speed	Shows the filtered speed of the bobbins.	-
	099999 rpm	Bobbin speed.	1 = 1 rpm (max. 32767)
09.36	Delivery length	Shows the actual delivery length.	-
	0.099999.0 m	Length in meters.	10 = 1 m (max. 32767)
09.37	Remaining length	Shows the remaining length.	-
	0.099999.0 m	Length in meters.	10 = 1 m (max. 32767)
09.38	Sliding average speed	Shows the average sliding speed based on delivery length and time elapsed.	-
	099999 rpm	Actual sliding speed.	1 = 1 rpm (max. 32767)

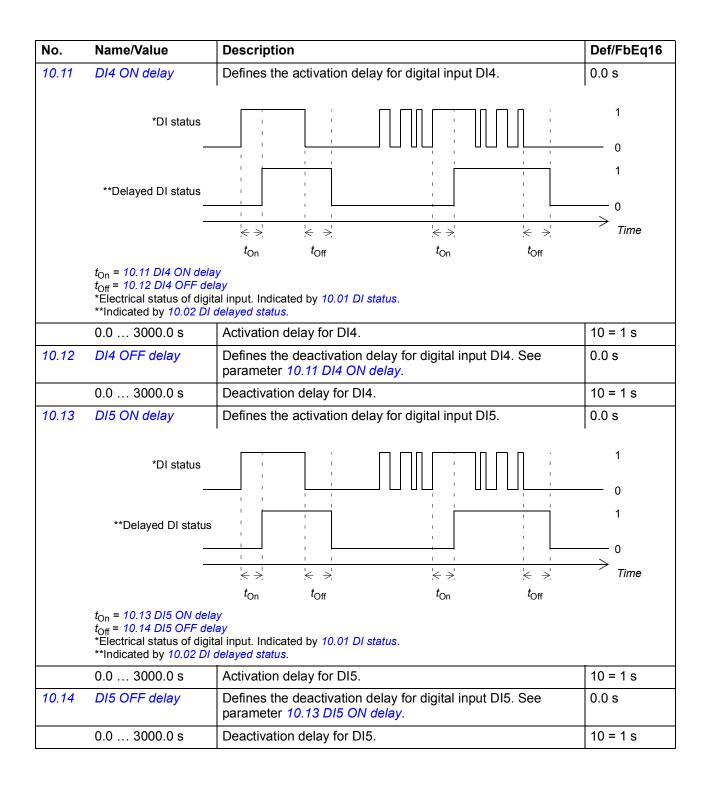
No.	Name/Value	Description	Def/FbEq16
09.35	Actual TPI	Shows actual twist(s) per inch. If speed measurement of front roller in parameter 79.15 Front roller measurement is used and the drive is running, the parameter displays the measured TPI value, otherwise this value indicates given TPI value of active pattern (parameters 75.34, 76.34, 77.34 or 78.34).	-
	0.0030000.00 TPT	Twist(s) per inch.	100 = 1 TPI (max. 32767)
09.40	Front roller speed	Measured front roller speed if speed measurement of front roller in parameter 79.15 Front roller measurement is used; otherwise this value is zero.	-
	099999 rpm	Front roller speed.	1 = 1 rpm (max. 32767)
09.41	Spinning status word	Spinning status word.	

Bit	Name		Description	
0	Pattern running Pattern is running.			
1	Pattern pau	sed	Pattern passed.	
2	Doff end alarm		 Active when in time mode, the remaining time is less than the in parameter <i>81.06 Doff end alarm time</i> or in length m or length% modes, the remaining le than the length defined in parameter <i>81.07 Doff length</i>. 	ngth is less
3	End of man	ual doff	Active for 100 ms after the time defined in paramet Manual doff time has elapsed.	er 81.05
4	Doff end alarm blink		 Active (ON for 0.5 seconds and OFF for 0.5 secon in time mode, the remaining time is less than the in parameter <i>81.06 Doff end alarm time</i> or in length m or length % modes, the remaining le than the length defined in parameter <i>81.07 Doff length</i>. 	e time defined ength is less
515	Reserved			
0000hFFFFh Status word		Statuo	and the second	1 = 1

No.	Name	Value	Description	Def/FbEq16
09.42	Spinni word1	ng status	Spinning status word1.	
	Bit	Name	Description	
	В іс 0	Section 1	Section 1 running.	
	1	Section 2	Section 2 running.	
	2	Section 2	Section 3 running.	
	2	Section 3	Section 4 running.	
	4	Section 5	Section 5 running.	
	5	Section 6	Section 6 running.	
	6	Section 7	Section 7 running.	
	7	Section 8	Section 8 running.	
	8	Section 9	Section 9 running.	
	9	Section 10	Section 10 running.	
	10	Section 11	Section 11 running.	—
	11	Section 12	Section 12 running.	
	12	Section 13	Section 13 running.	
	13	Section 14	Section 14 running.	
	14	Section 15	Section 15 running.	
	15	Section 16	Section 16 running.	
	0000h	FFFFh	Status word1	1 = 1
09.43	Spinni	ng reference	Shows the spinning speed reference before gear box.	-
	0999	999 rpm	Spinning speed reference.	1 = 1 rpm (max. 32767)
09.44	Currer	nt shift time	Shows the current total shift hours.	-
	0.00	100.00 h	Current shift total hours.	100 = 1 h
09.45	Currer elapse		Shows the elapsed time of current shift.	-
	0.00	100.00 h	Current shift elapsed time.	100 = 1 h
10 Sta	ndard	DI, RO	Configuration of digital inputs and relay outputs.	
10.01	DI stat	tus	Displays the electrical status of digital inputs DIIL and DI6DI1. The activation/deactivation delays of the inputs (if any are specified) are ignored. A filtering time can be defined by parameter <i>10.51 DI filter time</i> . Bits 05 reflect the status of DI1DI6; bit 15 reflects the status of the DIIL input. Example: 100000000010011b = DIIL, DI5, DI2 and DI1 are on, DI3, DI4 and DI6 are off. This parameter is read-only.	-
	0000h	FFFFh	Status of digital inputs.	1 = 1
10.02	DI dela	ayed status	Displays the status of digital inputs DIIL and DI6DI1. This word is updated only after activation/deactivation delays (if any are specified). Bits 05 reflect the delayed status of DI1DI6; bit 15 reflects the delayed status of the DIIL input. This parameter is read-only.	-
	00006	FFFFh	Delayed status of digital inputs.	1 = 1

No.	Name/	Value	Description	Def/FbEq16
10.03	DI force	e selection	The electrical statuses of the digital inputs can be overridden for eg. testing purposes. A bit in parameter <i>10.04 DI force</i> <i>data</i> is provided for each digital input, and its value is applied whenever the corresponding bit in this parameter is 1.	0000h
	Bit	Value		
	0	1 = Force [DI1 to value of bit 0 of parameter 10.04 DI force data.	
	1	1 = Force I	DI2 to value of bit 1 of parameter 10.04 DI force data.	
	2	1 = Force [DI3 to value of bit 2 of parameter 10.04 DI force data.	
	3	1 = Force [DI4 to value of bit 3 of parameter 10.04 DI force data.	
	4	1 = Force I	DI5 to value of bit 4 of parameter 10.04 DI force data.	
	5	1 = Force I	DI6 to value of bit 5 of parameter 10.04 DI force data.	
	614	Reserved		
	15	1 = Force [DIL to value of bit 15 of parameter 10.04 DI force data.	
	0000h.	FFFFh	Override selection for digital inputs.	1 = 1
10.04	DI force	e data	Contains the values that the digital inputs are forced to when selected by <i>10.03 DI force selection</i> . Bit 0 is the forced value for DI1; bit 15 is the forced value for the DIIL input.	0000h
	0000h.	FFFFh	Forced values of digital inputs.	1 = 1
10.05	DI1 ON	l delay	Defines the activation delay for digital input DI1.	0.0 s
	**Dela	*DI status — yed DI status — —	$\begin{array}{c ccccccccccccccccccccccccccccccccccc$	1 0 1
	t _{Off} = 10. *Electric		ay	
	0.0 3	3000.0 s	Activation delay for DI1.	10 = 1 s
10.06	DI1 OF	F delay	Defines the deactivation delay for digital input DI1. See parameter 10.05 DI1 ON delay.	0.0 s
		3000.0 s	Deactivation delay for DI1.	10 = 1 s

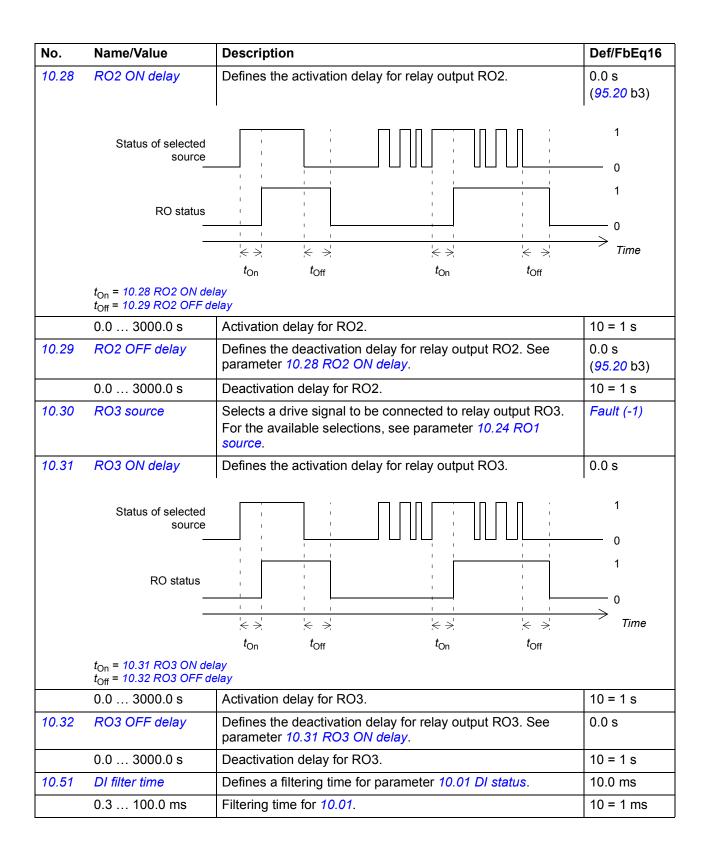




No.	Name/Value	Description	Def/FbEq16
10.15	DI6 ON delay	Defines the activation delay for digital input DI6.	0.0 s
	*DI status **Delayed DI status t _{On} = 10.15 DI6 ON dela t _{Off} = 10.16 DI6 OFF del *Electrical status of digit **Indicated by 10.02 DI	ay al input. Indicated by <i>10.01 DI status</i> .	1 0 1 $Time$
	0.0 3000.0 s	Activation delay for DI6.	10 = 1 s
10.16	DI6 OFF delay	Defines the deactivation delay for digital input DI6. See parameter <i>10.15 DI6 ON delay</i> .	0.0 s
	0.0 3000.0 s	Deactivation delay for DI6.	10 = 1 s
10.21	RO status	Status of relay outputs RO8RO1. Example: 0000001b = RO1 is energized, RO2RO8 are de-energized.	-
	0000hFFFFh	Status of relay outputs.	1 = 1
10.24	RO1 source	Selects a drive signal to be connected to relay output RO1.	Ready run; 10.01 b3 (-1) (95.20 b2); 35.105 b1 (95.20 b6); 06.16 b6 (95.20 b9)
	Not energized	Output is not energized.	0
	Energized	Output is energized.	1
	Ready run	Bit 1 of 06.11 Main status word (see page 150).	2
	Enabled	Bit 0 of 06.16 Drive status word 1 (see page 150).	4
	Started	Bit 5 of 06.16 Drive status word 1 (see page 150).	5
	Magnetized	Bit 1 of 06.17 Drive status word 2 (see page 151).	6
	Running	Bit 6 of 06.16 Drive status word 1 (see page 150).	7
	Ready ref	Bit 2 of 06.11 Main status word (see page 150).	8
	At setpoint	Bit 8 of 06.11 Main status word (see page 150).	9
	Reverse	Bit 2 of 06.19 Speed control status word (see page 153).	10
	Zero speed	Bit 0 of 06.19 Speed control status word (see page 153).	11
	Above limit	Bit 10 of 06.17 Drive status word 2 (see page 151).	12
	Warning	Bit 7 of 06.11 Main status word (see page 150).	13
	Fault	Bit 3 of 06.11 Main status word (see page 150).	14
	Fault (-1)	Inverted bit 3 of 06.11 Main status word (see page 150).	15
	Open brake command	Bit 0 of 44.01 Brake control status (see page 341).	22
	Ext2 active	Bit 11 of 06.16 Drive status word 1 (see page 150).	23

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No.	Name/Value	Description	Def/FbEq16
	Remote control	Bit 9 of 06.11 Main status word (see page 150).	24
	Supervision 1	Bit 0 of 32.01 Supervision status (see page 297).	33
	Supervision 2	Bit 1 of 32.01 Supervision status (see page 297).	34
	Supervision 3	Bit 2 of 32.01 Supervision status (see page 297).	35
	RO/DIO control word bit0	Bit 0 of 10.99 RO/DIO control word (see page 176).	40
	RO/DIO control word bit1	Bit 1 of 10.99 RO/DIO control word (see page 176).	41
	RO/DIO control word bit2	Bit 2 of 10.99 RO/DIO control word (see page 176).	42
	RO/DIO control word bit8	Bit 8 of 10.99 RO/DIO control word (see page 176).	43
	RO/DIO control word bit9	Bit 9 of 10.99 RO/DIO control word (see page 176).	44
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
10.25	RO1 ON delay	Defines the activation delay for relay output RO1.	0.0 s
	Status of selected source RO status ton = 10.25 RO1 ON de	$\begin{array}{c ccccccccccccccccccccccccccccccccccc$	$ \begin{array}{c} 1 \\ 0 \\ 1 \\ \hline 0 \\ \hline Time \end{array} $
	$t_{\rm Off} = 10.26 \text{ RO1 OFF d}$ 0.0 3000.0 s		10 - 1 0
10.00		Activation delay for RO1.	10 = 1 s
10.26	RO1 OFF delay	Defines the deactivation delay for relay output RO1. See parameter <i>10.25 RO1 ON delay</i> .	0.0 s
	0.0 3000.0 s	Deactivation delay for RO1.	10 = 1 s
10.27	RO2 source	Selects a drive signal to be connected to relay output RO2. For the available selections, see parameter <i>10.24 RO1 source</i> .	<i>Running</i> (95.20 b3)



No.	Name/Va	alue	Description	Def/FbEq16
10.99	RO/DIO word	control	Storage parameter for controlling the relay outputs and digital input/outputs eg. through the embedded fieldbus interface. To control the relay outputs (RO) and the digital input/outputs (DIO) of the drive, send a control word with the bit assignments shown below as Modbus I/O data. Set the target selection parameter of that particular data (<i>58.10158.124</i>) to <i>RO/DIO control word</i> . In the source selection parameter of the desired output, select the appropriate bit of this word.	0000h
	Bit	Name	Description	
	0	RO1	Source bits for relay outputs RO1RO3 (see parameters 10.2 10.30).	24, 10.27 and
	1	RO2	10.30).	
	1 2	RO2 RO3	<u>10.30</u>).	
	1 2 37		10.30).	
		RO3	Source bits for digital input/outputs DIO1DIO3 (see parame	eters 11.06
	- 37	RO3 Reserved		eters <i>11.06</i>
	- 37 8 9	RO3 Reserved DIO1	Source bits for digital input/outputs DIO1DIO3 (see parame	eters 11.06
	- 37 8 9	RO3 Reserved DIO1 DIO2	Source bits for digital input/outputs DIO1DIO3 (see parame	eters 11.06

		I	
11 Sta	ndard DIO, FI, FO	Configuration of digital input/outputs and frequency inputs/outputs.	
11.01	DIO status	Displays the status of digital input/outputs DIO2 and DIO1. The activation/deactivation delays (if any are specified) are ignored. A filtering time (for input mode) can be defined by parameter <i>10.51 DI filter time</i> . Example: 0010 = DIO2 is on and DIO1 is off. This parameter is read-only.	-
	0000b0011b	Status of digital input/outputs.	1 = 1
11.02	DIO delayed status	Displays the delayed status of digital input/outputs DIO2 and DIO1. This word is updated only after activation/deactivation delays (if any are specified). Example: 0010 = DIO2 is on and DIO1 is off. This parameter is read-only.	-
	0000b0011b	Delayed status of digital input/outputs.	1 = 1
11.05	DIO1 function	Selects whether DIO1 is used as a digital output or input, or a frequency input.	Output
	Output	DIO1 is used as a digital output.	0
	Input	DIO1 is used as a digital input.	1
	Frequency	DIO1 is used as a frequency input.	2
11.06	DIO1 output source	Selects a drive signal to be connected to digital input/output DIO1 when parameter <i>11.05 DIO1 function</i> is set to <i>Output</i> .	Ready run
	Not energized	Output is off.	0
	Energized	Output is on.	1
	Ready run	Bit 1 of 06.11 Main status word (see page 150).	2
	Enabled	Bit 0 of 06.16 Drive status word 1 (see page 150).	4
	Started	Bit 5 of 06.16 Drive status word 1 (see page 150).	5
	Magnetized	Bit 1 of 06.17 Drive status word 2 (see page 151).	6

No.	Name/Value	Description	Def/FbEq16
	Running	Bit 6 of 06.16 Drive status word 1 (see page 150).	7
	Ready ref	Bit 2 of 06.11 Main status word (see page 150).	8
	At setpoint	Bit 8 of 06.11 Main status word (see page 150).	9
	Reverse	Bit 2 of 06.19 Speed control status word (see page 153).	10
	Zero speed	Bit 0 of 06.19 Speed control status word (see page 153).	11
	Above limit	Bit 10 of 06.17 Drive status word 2 (see page 151).	12
	Warning	Bit 7 of 06.11 Main status word (see page 150).	13
	Fault	Bit 3 of 06.11 Main status word (see page 150).	14
	Fault (-1)	Inverted bit 3 of 06.11 Main status word (see page 150).	15
	Open brake command	Bit 0 of 44.01 Brake control status (see page 341).	22
	Ext2 active	Bit 11 of 06.16 Drive status word 1 (see page 150).	23
	Remote control	Bit 9 of 06.11 Main status word (see page 150).	24
	Supervision 1	Bit 0 of 32.01 Supervision status (see page 297).	33
	Supervision 2	Bit 1 of 32.01 Supervision status (see page 297).	34
	Supervision 3	Bit 2 of 32.01 Supervision status (see page 297).	35
	RO/DIO control word bit0	Bit 0 of 10.99 RO/DIO control word (see page 176).	40
	RO/DIO control word bit1	Bit 1 of 10.99 RO/DIO control word (see page 176).	41
	RO/DIO control word bit2	Bit 2 of 10.99 RO/DIO control word (see page 176).	42
	RO/DIO control word bit8	Bit 8 of 10.99 RO/DIO control word (see page 176).	43
	RO/DIO control word bit9	Bit 9 of 10.99 RO/DIO control word (see page 176).	44
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
11.07	DIO1 ON delay	Defines the activation delay for digital input/output DIO1 (when used as a digital output or digital input).	0.0 s
	*DIO status —		1 0 1
	**Delayed DIO status — —	$\begin{array}{c ccccccccccccccccccccccccccccccccccc$	──── 0 ───────── Time
	t _{On} = 11.07 DIO1 ON de t _{Off} = 11.08 DIO1 OFF of *Electrical status of DIO **Indicated by 11.02 DIO	e <i>lay</i> <i>lelay</i> (in input mode) or status of selected source (in output mode). Indicated by	11.01 DIO statu
	0.0 3000.0 s	Activation delay for DIO1.	10 = 1 s

No.	Name/Value	Description	Def/FbEq16
11.08	DIO1 OFF delay	Defines the deactivation delay for digital input/output DIO1 (when used as a digital output or digital input). See parameter <i>11.07 DIO1 ON delay</i> .	0.0 s
	0.0 3000.0 s	Deactivation delay for DIO1.	10 = 1 s
11.09	DIO2 function	Selects whether DIO2 is used as a digital output or input, or a frequency output.	Output
	Output	DIO2 is used as a digital output.	0
	Input	DIO2 is used as a digital input.	1
	Frequency	DIO2 is used as a frequency output.	2
11.10	DIO2 output source	Selects a drive signal to be connected to digital input/output DIO2 when parameter <i>11.09 DIO2 function</i> is set to <i>Output</i> . For the available selections, see parameter <i>11.06 DIO1 output source</i> .	Running
11.11	DIO2 ON delay	Defines the activation delay for digital input/output DIO2 (when used as a digital output or digital input).	0.0 s
	*DIO status 		1 0 1
	**Delayed DIO status 	$\begin{array}{c ccccccccccccccccccccccccccccccccccc$	0 Time
	t _{On} = 11.11 DIO2 ON de t _{Off} = 11.12 DIO2 OFF d *Electrical status of DIO **Indicated by 11.02 DIO	<i>lay</i> <i>elay</i> (in input mode) or status of selected source (in output mode). Indicated by	11.01 DIO status
	0.0 3000.0 s	Activation delay for DIO2.	10 = 1 s
11.12	DIO2 OFF delay	Defines the deactivation delay for digital input/output DIO2 (when used as a digital output or digital input). See parameter <i>11.11 DIO2 ON delay</i> .	0.0 s
	0.0 3000.0 s	Deactivation delay for DIO2.	10 = 1 s
11.38	Freq in 1 actual value	Displays the value of frequency input 1 (via DIO1 when it is used as a frequency input) before scaling. See parameter <i>11.42 Freq in 1 min</i> . This parameter is read-only.	-
	0 16000 Hz	Unscaled value of frequency input 1.	1 = 1 Hz
11.39	Freq in 1 scaled	Displays the value of frequency input 1 (via DIO1 when it is used as a frequency input) after scaling. See parameter <i>11.42 Freq in 1 min</i> . This parameter is read-only.	-
	-32768.000 32767.000	Scaled value of frequency input 1.	1 = 1

No.	Name/Value	Description	Def/FbEq16
11.42	Freq in 1 min	Defines the minimum input frequency for frequency input 1 (DIO1 when it is used as a frequency input). The incoming frequency signal (<i>11.38 Freq in 1 actual value</i>) is scaled into an internal signal (<i>11.39 Freq in 1 scaled</i>) by parameters <i>11.4211.45</i> as follows: <i>11.39</i> <i>11.45</i> <i>11.44</i> <i>11.44</i> <i>11.44</i> <i>11.44</i> <i>11.45</i> <i>11.45</i> <i>11.45</i> <i>11.45</i>	0 Hz
	0 16000 Hz	Minimum frequency of frequency input 1 (DIO1).	1 = 1 Hz
11.43	Freq in 1 max	Defines the maximum input frequency for frequency input 1 (DIO1 when it is used as a frequency input). See parameter 11.42 Freq in 1 min.	16000 Hz
	0 16000 Hz	Maximum frequency for frequency input 1 (DIO1).	1 = 1 Hz
11.44	Freq in 1 at scaled min	Defines the value that corresponds to the minimum input frequency defined by parameter <i>11.42 Freq in 1 min</i> . See diagram at parameter <i>11.42 Freq in 1 min</i> .	0.000
	-32768.000 32767.000	Value corresponding to minimum of frequency input 1.	1 = 1
11.45	Freq in 1 at scaled max	Defines the value that is required to correspond internally to the maximum input frequency defined by parameter <i>11.43</i> <i>Freq in 1 max.</i> See diagram at parameter <i>11.42 Freq in 1 min.</i>	1500.000; 1800.000 (95.20 b0)
	-32768.000 32767.000	Value corresponding to maximum of frequency input 1.	1 = 1
11.54	Freq out 1 actual value	Displays the value of frequency output 1 after scaling. See parameter <i>11.58 Freq out 1 src min</i> . This parameter is read-only.	-
	0 16000 Hz	Value of frequency output 1.	1 = 1
11.55	Freq out 1 source	Selects a signal to be connected to frequency output 1.	Motor speed used
	Zero	None.	0
	Motor speed used	01.01 Motor speed used (page 136).	1
	Output frequency	01.06 Output frequency (page 136).	3
	Motor current	01.07 Motor current (page 136).	4
	Motor torque	01.10 Motor torque (page 136).	6
	DC voltage	01.11 DC voltage (page 137).	7
	Power inu out	01.14 Output power (page 137).	8

No.	Name/Value	Description	Def/FbEq16
	Speed ref ramp in	23.01 Speed ref ramp input (page 242).	10
	Speed ref ramped	23.02 Speed ref ramp output (page 242).	11
	Speed ref used	24.01 Used speed reference (page 248).	12
	Torq ref used	26.02 Torque reference used (page 264).	13
	Freq ref used	40.01 Process PID output actual (page 325).	14
	Process PID out	40.02 Process PID feedback actual (page 325).	16
	Process PID fbk	40.03 Process PID setpoint actual (page 325).	17
	Process PID act	40.04 Process PID deviation actual (page 325).	18
	Process PID dev	40.01 Process PID output actual (page 325).	19
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
11.58	Freq out 1 src min	Defines the real value of the signal (selected by parameter 11.55 Freq out 1 source and shown by parameter 11.54 Freq out 1 actual value) that corresponds to the minimum value of frequency output 1 (defined by parameter 11.60 Freq out 1 at src min). f _{out} (11.54) f _{out} (11.54) f _{out} (11.54) f _{out} (11.54) f _{out} (11.54) 11.60 11.60 11.59 11.58 Signal (real) selected by par. 11.55 Signal (real)	0.000
	-32768.000 32767.000	Real signal value corresponding to minimum value of frequency output 1.	1 = 1
11 50			1500.000
11.59	Freq out 1 src max	Defines the real value of the signal (selected by parameter 11.55 Freq out 1 source and shown by parameter 11.54 Freq out 1 actual value) that corresponds to the maximum value of frequency output 1 (defined by parameter 11.61 Freq out 1 at src max). See parameter 11.58 Freq out 1 src min.	1500.000; 1800.000 (<i>95.20</i> b0)
	-32768.000 32767.000	Real signal value corresponding to maximum value of frequency output 1.	1 = 1

No.	Name/Value	Description	Def/FbEq16
11.60	Freq out 1 at src min	Defines the minimum value of frequency output 1. See diagrams at parameter <i>11.58 Freq out 1 src min</i> .	0 Hz
	016000 Hz	Minimum value of frequency output 1.	1 = 1 Hz
11.61	Freq out 1 at src max	Defines the maximum value of frequency output 1. See diagrams at parameter <i>11.58 Freq out 1 src min</i> .	16000 Hz
	016000 Hz	Maximum value of frequency output 1.	1 = 1 Hz
11.81	DIO filter time	Defines a filtering time for parameter <i>11.01 DIO status</i> . The filtering time will only affect the DIOs that are in input mode.	10.0 ms
	0.3 100.0 ms	Filtering time for 11.01.	10 = 1 ms
12 Sta	Indard Al	Configuration of standard analog inputs.	
12.01	AI tune	Triggers the analog input tuning function. Connect the signal to the input and select the appropriate tuning function.	
	No action	Al tune is not activated.	0
	AI1 min tune	Current analog input AI1 signal value is set as minimum value of AI1 into parameter <i>12.17 AI1 min</i> . The value reverts back to <i>No action</i> automatically.	1
	AI1 max tune	Current analog input Al1 signal value is set as maximum value of Al1 into parameter <i>12.18 Al1 max</i> . The value reverts back to <i>No action</i> automatically.	2
	AI2 min tune	Current analog input AI2 signal value is set as minimum value of AI2 into parameter <i>12.27 AI2 min</i> . The value reverts back to <i>No action</i> automatically.	3
	AI2 max tune	Current analog input Al2 signal value is set as maximum value of Al2 into parameter <i>12.28 Al2 max</i> . The value reverts back to <i>No action</i> automatically.	4
12.03	Al supervision function	 Selects how the drive reacts when an analog input signal moves out of the minimum and/or maximum limits specified for the input. The inputs and the limits to be observed are selected by parameter 12.04 AI supervision selection. Note: Analog input signal supervision is only active when the analog input is set as the source (using the AI1 scaled or AI2 scaled selection) in parameter 22.11, 22.12, 22.15, 22.17, 23.42, 26.11, 26.12, 26.16, 26.25, 28.11, 28.12, 30.21, 30.22, 40.16, 40.17, 40.50, 41.16, 41.17, 41.50 or 44.09, and is being used as the active source, or supervision is forced using parameter 12.05 AI supervision force. 	No action
	No action	No action taken.	0
	Fault	Drive trips on 80A0 AI supervision.	1
	Warning	Drive generates an A8A0 AI supervision warning.	2
	Last speed	Drive generates a warning (<i>A8A0 AI supervision</i>) and freezes the speed (or frequency) to the level the drive was operating at. The speed/frequency is determined on the basis of actual speed using 850 ms low-pass filtering. WARNING! Make sure that it is safe to continue operation in case of a communication break.	3

No.	Name/V	/alue	Description	Def/FbEq16
	Speed r	ef safe	Drive generates a warning (<i>A8A0 AI supervision</i>) and sets the speed to the speed defined by parameter 22.41 Speed ref safe (or 28.41 Frequency ref safe when frequency reference is being used). WARNING! Make sure that it is safe to continue operation in case of a communication break.	4
12.04	Al super selection		Specifies the analog input limits to be supervised. See parameter <i>12.03 AI supervision function</i> .	0000b
	Bit	Name	Description	
	0	AI1 < MIN	1 = Minimum limit supervision of AI1 active.	
	1	AI1 > MAX		
	2	AI2 < MIN	1 = Minimum limit supervision of AI2 active.	
	3	AI2 > MAX	1 = Maximum limit supervision of AI2 active.	
	415	Reserved		
	0000b	.1111b	Activation of analog input supervision.	1 = 1
12.05		rvision force	Activates analog input supervision separately for each control location (see section <i>Local control vs. external control</i> on page 54). The parameter is primarily intended for analog input supervision when the input is connected to the application	0000 0000b
			program and not selected as a control source by drive parameters.	
	Bit	Name	program and not selected as a control source by drive parameters. Description	
	0	AI1 Ext1	program and not selected as a control source by drive parameters. Description 1 = Al1 supervision active when EXT1 is being used.	
	0 1	AI1 Ext1 AI1 Ext2	program and not selected as a control source by drive parameters. Description 1 = Al1 supervision active when EXT1 is being used. 1 = Al1 supervision active when EXT2 is being used.	
	0 1 2	Al1 Ext1 Al1 Ext2 Al1 Local	program and not selected as a control source by drive parameters. Description 1 = Al1 supervision active when EXT1 is being used.	ed.
	0 1 2 3	Al1 Ext1 Al1 Ext2 Al1 Local Reserved	program and not selected as a control source by drive parameters. Description 1 = AI1 supervision active when EXT1 is being used. 1 = AI1 supervision active when EXT2 is being used. 1 = AI1 supervision active when Iocal control is being used.	ed.
	0 1 2 3 4	AI1 Ext1 AI1 Ext2 AI1 Local Reserved AI2 Ext1	program and not selected as a control source by drive parameters. Description 1 = Al1 supervision active when EXT1 is being used. 1 = Al1 supervision active when EXT2 is being used. 1 = Al1 supervision active when Iocal control is being used. 1 = Al2 supervision active when EXT1 is being used.	ed.
	0 1 2 3 4 5	AI1 Ext1 AI1 Ext2 AI1 Local Reserved AI2 Ext1 AI2 Ext2	program and not selected as a control source by drive parameters. Description 1 = Al1 supervision active when EXT1 is being used. 1 = Al1 supervision active when EXT2 is being used. 1 = Al1 supervision active when local control is being used. 1 = Al2 supervision active when EXT1 is being used. 1 = Al2 supervision active when EXT1 is being used. 1 = Al2 supervision active when EXT1 is being used.	
	0 1 2 3 4 5 6	AI1 Ext1 AI1 Ext2 AI1 Local Reserved AI2 Ext1 AI2 Ext2 AI2 Local	program and not selected as a control source by drive parameters. Description 1 = Al1 supervision active when EXT1 is being used. 1 = Al1 supervision active when EXT2 is being used. 1 = Al1 supervision active when Iocal control is being used. 1 = Al2 supervision active when EXT1 is being used.	
	0 1 2 3 4 5	AI1 Ext1 AI1 Ext2 AI1 Local Reserved AI2 Ext1 AI2 Ext2	program and not selected as a control source by drive parameters. Description 1 = Al1 supervision active when EXT1 is being used. 1 = Al1 supervision active when EXT2 is being used. 1 = Al1 supervision active when local control is being used. 1 = Al2 supervision active when EXT1 is being used. 1 = Al2 supervision active when EXT1 is being used. 1 = Al2 supervision active when EXT1 is being used.	
	0 1 2 3 4 5 6	AI1 Ext1 AI1 Ext2 AI1 Local Reserved AI2 Ext1 AI2 Ext2 AI2 Local Reserved	program and not selected as a control source by drive parameters. Description 1 = Al1 supervision active when EXT1 is being used. 1 = Al1 supervision active when EXT2 is being used. 1 = Al1 supervision active when local control is being used. 1 = Al2 supervision active when EXT1 is being used. 1 = Al2 supervision active when EXT1 is being used. 1 = Al2 supervision active when EXT1 is being used.	
12.11	0 1 2 3 4 5 6 715 0000 00 0111 01	AI1 Ext1 AI1 Ext2 AI1 Local Reserved AI2 Ext1 AI2 Ext2 AI2 Local Reserved	Description 1 = Al1 supervision active when EXT1 is being used. 1 = Al1 supervision active when EXT2 is being used. 1 = Al1 supervision active when EXT2 is being used. 1 = Al1 supervision active when local control is being used. 1 = Al2 supervision active when EXT1 is being used. 1 = Al2 supervision active when EXT1 is being used. 1 = Al2 supervision active when EXT2 is being used. 1 = Al2 supervision active when EXT1 is being used. 1 = Al2 supervision active when EXT2 is being used. 1 = Al2 supervision active when Iocal control is being used.	ed.
12.11	0 1 2 3 4 5 6 715 0000 00 0111 01 <i>Al1 actu</i>	AI1 Ext1 AI1 Ext2 AI1 Local Reserved AI2 Ext1 AI2 Ext2 AI2 Local Reserved	Description 1 = Al1 supervision active when EXT1 is being used. 1 = Al1 supervision active when EXT2 is being used. 1 = Al1 supervision active when Iocal control is being used. 1 = Al2 supervision active when EXT1 is being used. 1 = Al2 supervision active when EXT1 is being used. 1 = Al2 supervision active when EXT1 is being used. 1 = Al2 supervision active when EXT2 is being used. 1 = Al2 supervision active when Iocal control is being used. 1 = Al2 supervision active when local control is being used. 1 = Al2 supervision active when local control is being used. 1 = Al2 supervision active when local control is being used. 1 = Al2 supervision active when local control is being used. 1 = Al2 supervision active when local control is being used. 1 = Al2 supervision active when local control is being used. 1 = Al2 supervision selection. Displays the value of analog input Al1 in mA or V (depending on whether the input is set to current or voltage by a hardware setting).	ed. 1 = 1 -
12.11	0 1 2 3 4 5 6 715 0000 00 0111 01 <i>Al1 actu</i> -22.000 mA or V	AI1 Ext1 AI1 Ext2 AI1 Local Reserved AI2 Ext1 AI2 Ext2 AI2 Local Reserved	Description 1 = Al1 supervision active when EXT1 is being used. 1 = Al1 supervision active when EXT2 is being used. 1 = Al1 supervision active when local control is being used. 1 = Al2 supervision active when EXT1 is being used. 1 = Al2 supervision active when EXT2 is being used. 1 = Al2 supervision active when EXT1 is being used. 1 = Al2 supervision active when EXT2 is being used. 1 = Al2 supervision active when Iocal control is being used. 1 = Al2 supervision active when local control is being used. 1 = Al2 supervision active when local control is being used. 1 = Al2 supervision active when local control is being used. 1 = Al2 supervision active when local control is being used. 1 = Al2 supervision active when local control is being used. 1 = Al2 supervision active when local control is being used. 1 = Al2 supervision selection. Displays the value of analog input Al1 in mA or V (depending on whether the input is set to current or voltage by a hardware setting). This parameter is read-only.	ed. 1 = 1 - 1000 = 1 m/

No.	Name/Value	Description	Def/FbEq16
12.15	Al1 unit selection	Selects the unit for readings and settings related to analog input Al1. Note: This setting must match the corresponding hardware setting on the drive control unit (see the hardware manual of the drive). Control board reboot (either by cycling the power or through parameter <i>96.08 Control board boot</i>) is required to validate any changes in the hardware settings.	V
	V	Volts.	2
	mA	Milliamperes.	10
12.16	Al1 filter time	Defines the filter time constant for analog input Al1. $ \begin{array}{c} & \\ & \\ & \\ & \\ & \\ & \\ & \\ & $	0.100 s
	0.000 30.000 s	be changed by any parameter. Filter time constant.	1000 = 1 s
12.17	Al1 min	Defines the minimum site value for analog input AI1. Set the value actually sent to the drive when the analog signal from plant is wound to its minimum setting. See also parameter <i>12.01 AI tune</i> .	0.000 mA or V
	-22.000 22.000 mA or V	Minimum value of Al1.	1000 = 1 mA or V
12.18	Al1 max	Defines the maximum site value for analog input Al1. Set the value actually sent to the drive when the analog signal from plant is wound to its maximum setting. See also parameter <i>12.01 Al tune</i> .	20.000 mA or 10.000 V
	-22.000 22.000 mA or V	Maximum value of AI1.	1000 = 1 mA or V

No.	Name/Value	Description	Def/FbEq16
12.19	AI1 scaled at AI1 min	Defines the real internal value that corresponds to the minimum analog input Al1 value defined by parameter 12.17 Al1 min. (Changing the polarity settings of 12.19 and 12.20 can effectively invert the analog input. Al _{scaled} (12.12) 12.20 12.17 12.18 Al _{in} (12.11) 12.18	0.000
	-32768.000 32767.000	Real value corresponding to minimum Al1 value.	1 = 1
12.20	Al1 scaled at Al1 max	Defines the real internal value that corresponds to the maximum analog input Al1 value defined by parameter <i>12.18 Al1 max</i> . See the drawing at parameter <i>12.19 Al1 scaled at Al1 min</i> .	1500.000; 1800.000 (95.20 b0)
	-32768.000 32767.000	Real value corresponding to maximum AI1 value.	1 = 1
12.21	AI2 actual value	Displays the value of analog input Al2 in mA or V (depending on whether the input is set to current or voltage by a hardware setting). This parameter is read-only.	-
	-22.000 22.000 mA or V	Value of analog input AI2.	1000 = 1 mA or V
12.22	AI2 scaled value	Displays the value of analog input Al2 after scaling. See parameters 12.29 Al2 scaled at Al2 min and 12.30 Al2 scaled at Al2 max. This parameter is read-only.	-
	-32768.000 32767.000	Scaled value of analog input Al2.	1 = 1
12.25	AI2 unit selection	Selects the unit for readings and settings related to analog input Al2. Note: This setting must match the corresponding jumper setting on the drive control unit (see the hardware manual of the drive). Control board reboot (either by cycling the power or through parameter 96.08 Control board boot) is required to validate any changes in the hardware settings.	mA
	V	Volts.	2
	mA	Milliamperes.	10
12.26	AI2 filter time	Defines the filter time constant for analog input Al2. See parameter <i>12.16 Al1 filter time</i> .	0.100 s
	0.000 30.000 s	Filter time constant.	1000 = 1 s

No.	Name/Value	Description	Def/FbEq16
12.27	AI2 min	Defines the minimum site value for analog input Al2. Set the value actually sent to the drive when the analog signal from plant is wound to its minimum setting. See also parameter <i>12.01 Al tune</i> .	0.000 mA or V
	-22.000 22.000 mA or V	Minimum value of AI2.	1000 = 1 mA or V
12.28	Al2 max	Defines the maximum site value for analog input Al2. Set the value actually sent to the drive when the analog signal from plant is wound to its maximum setting. See also parameter <i>12.01 Al tune</i> .	20.000 mAor 10.000 V
	-22.000 22.000 mA or V	Maximum value of AI2.	1000 = 1 mA or V
12.29	AI2 scaled at AI2 min	Defines the real value that corresponds to the minimum analog input Al2 value defined by parameter 12.27 Al2 min. (Changing the polarity settings of 12.29 and 12.30 can effectively invert the analog input. AI_{scaled} (12.22) 12.30 12.27 12.28 12.28	0.000
	-32768.000 32767.000	Real value corresponding to minimum AI2 value.	1 = 1
12.30	AI2 scaled at AI2 max	Defines the real value that corresponds to the maximum analog input AI2 value defined by parameter <i>12.28 AI2 max</i> . See the drawing at parameter <i>12.29 AI2 scaled at AI2 min</i> .	100.000
	-32768.000 32767.000	Real value corresponding to maximum AI2 value.	1 = 1
13 Sta	ndard AO	Configuration of standard analog outputs.	
13.11	AO1 actual value	Displays the value of AO1 in mA. This parameter is read-only.	-
	0.000 22.000 mA	Value of AO1.	1000 = 1 mA
13.12	AO1 source	Selects a signal to be connected to analog output AO1. Alternatively, sets the output to excitation mode to feed a constant current to a temperature sensor.	Motor speed used
	Zero	None.	0
	Motor speed used	01.01 Motor speed used (page 136).	1
	Output frequency	01.06 Output frequency (page 136).	3
	Motor current	01.07 Motor current (page 136).	4

No.	Name/Value	Description	Def/FbEq16
	Motor torque	01.10 Motor torque (page 136).	6
	DC voltage	01.11 DC voltage (page 137).	7
	Power inu out	01.14 Output power (page 137).	8
	Speed ref ramp in	23.01 Speed ref ramp input (page 242).	10
	Speed ref ramp out	23.02 Speed ref ramp output (page 242).	11
	Speed ref used	24.01 Used speed reference (page 248).	12
	Torq ref used	26.02 Torque reference used (page 264).	13
	Freq ref used	28.02 Frequency ref ramp output (page 270).	14
	Process PID out	40.01 Process PID output actual (page 325).	16
	Process PID fbk	40.02 Process PID feedback actual (page 325).	17
	Process PID act	40.03 Process PID setpoint actual (page 325).	18
	Process PID dev	40.04 Process PID deviation actual (page 325).	19
	Force PT100 excitation	The output is used to feed an excitation current to 13 Pt100 sensors. See section <i>Motor thermal protection</i> (page <i>113</i>).	20
	Force KTY84 excitation	The output is used to feed an excitation current to a KTY84 sensor. See section <i>Motor thermal protection</i> (page <i>113</i>).	21
	Force PTC excitation	The output is used to feed an excitation current to 13 PTC sensors. See section <i>Motor thermal protection</i> (page 113).	22
	Force Pt1000 excitation	The output is used to feed an excitation current to 13 Pt1000 sensors. See section <i>Motor thermal protection</i> (page <i>113</i>).	23
	AO1 data storage	13.91 AO1 data storage (page 189).	37
	AO2 data storage	13.92 AO2 data storage (page 189).	38
	Other	The value is taken from another parameter.	-
13.16	AO1 filter time	Defines the filtering time constant for analog output AO1. $ \begin{array}{c} & \\ & \\ & \\ & \\ & \\ & \\ & \\ & $	0.100 s
	0.000 30.000 s	Filter time constant.	1000 = 1 s

No.	Name/Value	Description	Def/FbEq16
13.17	AO1 source min	Defines the real minimum value of the signal (selected by parameter 13.12 AO1 source) that corresponds to the minimum required AO1 output value (defined by parameter 13.19 AO1 out at AO1 src min).	0.0
		13.19 13.17 13.18 Signal (real) selected by 13.12	
		Programming <i>13.17</i> as the maximum value and <i>13.18</i> as the minimum value inverts the output.	
		I _{AO1} (mA)	
		13.19	
		13.18 13.17 Signal (real) selected by 13.12	
	-32768.0 32767.0	Real signal value corresponding to minimum AO1 output value.	1 = 1
13.18	AO1 source max	Defines the real maximum value of the signal (selected by parameter <i>13.12 AO1 source</i>) that corresponds to the maximum required AO1 output value (defined by parameter <i>13.20 AO1 out at AO1 src max</i>). See parameter <i>13.17 AO1 source min</i> .	1500.0; 1800.0 (95.20 b0)
	-32768.0 32767.0	Real signal value corresponding to maximum AO1 output value.	1 = 1
13.19	AO1 out at AO1 src min	Defines the minimum output value for analog output AO1. See also drawing at parameter <i>13.17 AO1 source min</i> .	0.000 mA
	0.000 22.000 mA	Minimum AO1 output value.	1000 = 1 mA
13.20	AO1 out at AO1 src max	Defines the maximum output value for analog output AO1. See also drawing at parameter <i>13.17 AO1 source min</i> .	20.000 mA
	0.000 22.000 mA	Maximum AO1 output value.	1000 = 1 mA

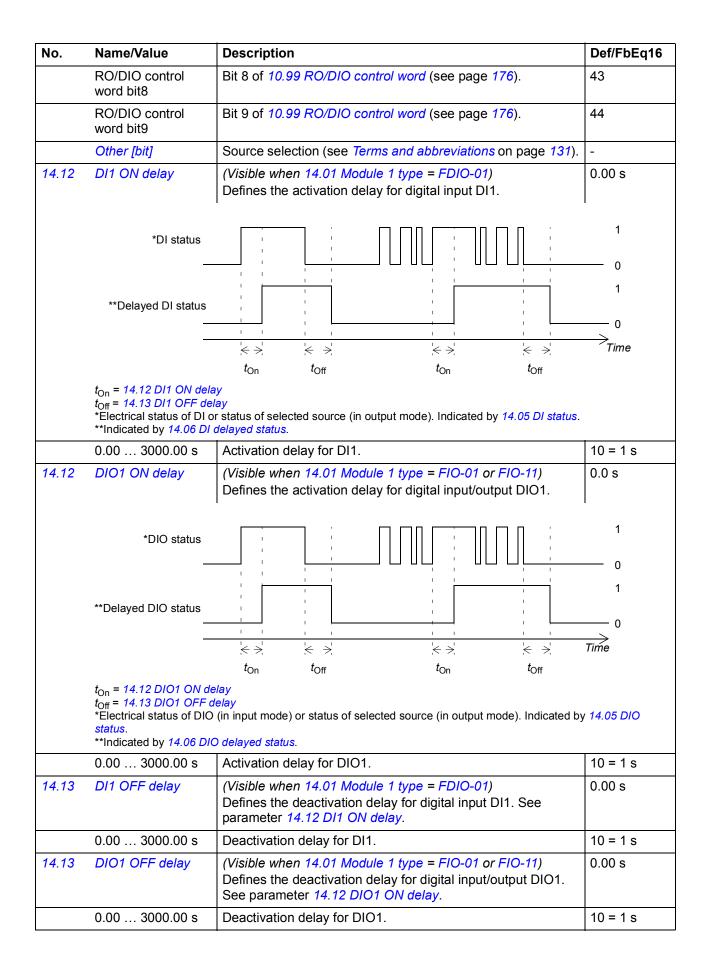
No.	Name/Value	Description	Def/FbEq16
13.21	AO2 actual value	Displays the value of AO2 in mA. This parameter is read-only.	-
	0.000 22.000 mA	Value of AO2.	1000 = 1 mA
13.22	AO2 source	Selects a signal to be connected to analog output AO2. Alternatively, sets the output to excitation mode to feed a constant current to a temperature sensor. For the selections, see parameter <i>13.12 AO1 source</i> .	Motor current
13.26	AO2 filter time	Defines the filtering time constant for analog output AO2. See parameter <i>13.16 AO1 filter time</i> .	0.100 s
	0.000 30.000 s	Filter time constant.	1000 = 1 s
13.27	AO2 source min	Defines the real minimum value of the signal (selected by parameter 13.22 AO2 source) that corresponds to the minimum required AO2 output value (defined by parameter 13.29 AO2 out at AO2 src min). I _{AO2} (mA)	0.0
		13.30 13.29 13.27 13.28 Signal (real) selected by 13.22	
		Programming 13.27 as the maximum value and 13.28 as the minimum value inverts the output. I_{AO2} (mA) 13.30	
		13.29+	
	-32768.0 32767.0	Real signal value corresponding to minimum AO2 output value.	1 = 1

No.	Name/Value	Description	Def/FbEq16
13.28	AO2 source max	Defines the real maximum value of the signal (selected by parameter 13.22 AO2 source) that corresponds to the maximum required AO2 output value (defined by parameter 13.30 AO2 out at AO2 src max). See parameter 13.27 AO2 source min.	100.0
	-32768.0 32767.0	Real signal value corresponding to maximum AO2 output value.	1 = 1
13.29	AO2 out at AO2 src min	Defines the minimum output value for analog output AO2. See also drawing at parameter <i>13.27 AO2 source min</i> .	0.000 mA
	0.000 22.000 mA	Minimum AO2 output value.	1000 = 1 mA
13.30	AO2 out at AO2 src max	Defines the maximum output value for analog output AO2. See also drawing at parameter <i>13.27 AO2 source min</i> .	20.000 mA
	0.000 22.000 mA	Maximum AO2 output value.	1000 = 1 mA
13.91	AO1 data storage	Storage parameter for controlling analog output AO1 eg. through fieldbus. In <i>13.12 AO1 source</i> , select <i>AO1 data storage</i> . Then set this parameter as the target of the incoming value data. With the embedded fieldbus interface, simply set the target selection parameter of that particular data (<i>58.10158.124</i>) to <i>AO1 data storage</i> .	0.00
	-327.68 327.67	Storage parameter for AO1.	100 = 1
13.92	AO2 data storage	Storage parameter for controlling analog output AO2 eg. through fieldbus. In <i>13.22 AO2 source</i> , select <i>AO2 data storage</i> . Then set this parameter as the target of the incoming value data. With the embedded fieldbus interface, simply set the target selection parameter of that particular data (<i>58.10158.124</i>) to <i>AO2 data storage</i> .	0.00
	-327.68 327.67	Storage parameter for AO2.	100 = 1

14 I/O extension module 1		Configuration of I/O extension module 1. See also section <i>Programmable I/O extensions</i> (page 62). Note: The contents of the parameter group vary according to the selected I/O extension module type.	
14.01	Module 1 type	Activates (and specifies the type of) I/O extension module 1.	None
	None	Inactive.	0
	FIO-01	FIO-01.	1
	FIO-11	FIO-11.	2
	FDIO-01	FDIO-01.	3
	FAIO-01	FAIO-01.	4
14.02	Module 1 location	Specifies the slot (13) on the control unit of the drive into which the I/O extension module is installed. Alternatively, specifies the node ID of the slot on a FEA-0x extension adapter.	Slot 1
	Slot 1	Slot 1.	1
	Slot 2	Slot 2.	2
	Slot 3	Slot 3.	3
	4254	Node ID of the slot on the FEA-0x extension adapter.	1 = 1

No.	Name/Value	Description	Def/FbEq16
14.03	Module 1 status	Displays the status of I/O extension module 1.	No option
	No option	No module detected in the specified slot.	0
	No communication	A module has been detected but cannot be communicated with.	1
	Unknown	The module type is unknown.	2
	FIO-01	An FIO-01 module has been detected and is active.	15
	FIO-11	An FIO-11 module has been detected and is active.	20
	FAIO-01	An FAIO-01 module has been detected and is active.	24
14.05	DI status	 (Visible when 14.01 Module 1 type = FDIO-01) Displays the status of the digital input/outputs on the extension module. The activation/deactivation delays (if any are specified) are ignored. A filtering time (for input mode) can be defined by parameter 14.08 DIO filter time. Bit 0 indicates the status of DIO1. Note: The number of active bits in this parameter depends on the number of digital input/outputs on the extension module. Example: 0101b = DI1 and DI3 are on, remainder are off. This parameter is read-only. 	-
	0000h1111b	Status of digital inputs.	1 = 1
14.05	DIO status	 (Visible when 14.01 Module 1 type = FIO-01 or FIO-11) Displays the status of the digital input/outputs on the extension module. The activation/deactivation delays (if any are specified) are ignored. A filtering time (for input mode) can be defined by parameter 14.08 DIO filter time. Bit 0 indicates the status of DIO1. Note: The number of active bits in this parameter depends on the number of digital input/outputs on the extension module. Example: 1001b = DIO1 and DIO4 are on, remainder are off. This parameter is read-only. 	-
	0000b1111b	Status of digital input/outputs.	1 = 1
14.06	DI delayed status	 (Visible when 14.01 Module 1 type = FDIO-01) Displays the delayed status of the digital inputs on the extension module. The word is updated only after activation/deactivation delays (if any are specified). Bit 0 indicates the status of DI1. Note: The number of active bits in this parameter depends on the number of digital inputs on the extension module. Example: 0101b = DI1 and DI3 are on, remainder are off. This parameter is read-only. 	-
	0000b1111b	Delayed status of digital inputs.	1 = 1
14.06	DIO delayed status	 (Visible when 14.01 Module 1 type = FIO-01 or FIO-11) Displays the delayed status of the digital input/outputs on the extension module. This word is updated only after activation/deactivation delays (if any are specified). Bit 0 indicates the status of DIO1. Note: The number of active bits in this parameter depends on the number of digital input/outputs on the extension module. Example: 1001b = DIO1 and DIO4 are on, remainder are off. This parameter is read-only. 	-
	0000h1111b	Delayed status of digital input/outputs.	1 = 1

No.	Name/Value	Description	Def/FbEq16
14.08	DI filter time	(<i>Visible when 14.01 Module 1 type = FDIO-01</i>) Defines a filtering time for parameter <i>14.05 DI status</i> .	10.0 ms
	0.8 100.0 ms	Filtering time for 14.05.	10 = 1 ms
14.08	DIO filter time	(<i>Visible when 14.01 Module 1 type = FIO-01 or FIO-11</i>) Defines a filtering time for parameter <i>14.05 DIO status</i> . The filtering time will only affect the DIOs that are in input mode.	10.0 ms
	0.8 100.0 ms	Filtering time for 14.05.	10 = 1 ms
14.09	DIO1 function	(<i>Visible when 14.01 Module 1 type = FIO-01 or FIO-11</i>) Selects whether DIO1 of the extension module is used as a digital input or output.	Input
	Output	DIO1 is used as a digital output.	0
	Input	DIO1 is used as a digital input.	1
14.11	DIO1 output source	(Visible when 14.01 Module 1 type = FIO-01 or FIO-11) Selects a drive signal to be connected to digital input/output DIO1 of the extension module when parameter 14.09 DIO1 function is set to Output.	Not energized
	Not energized	Output is not energized.	0
	Energized	Output is energized.	1
	Ready run	Bit 1 of 06.11 Main status word (see page 150).	2
	Enabled	Bit 0 of 06.16 Drive status word 1 (see page 150).	4
	Started	Bit 5 of 06.16 Drive status word 1 (see page 150).	5
	Magnetized	Bit 1 of 06.17 Drive status word 2 (see page 151).	6
	Running	Bit 6 of 06.16 Drive status word 1 (see page 150).	7
	Ready ref	Bit 2 of 06.11 Main status word (see page 150).	8
	At setpoint	Bit 8 of 06.11 Main status word (see page 150).	9
	Reverse	Bit 2 of 06.19 Speed control status word (see page 153).	10
	Zero speed	Bit 0 of 06.19 Speed control status word (see page 153).	11
	Above limit	Bit 10 of 06.17 Drive status word 2 (see page 151).	12
	Warning	Bit 7 of 06.11 Main status word (see page 150).	13
	Fault	Bit 3 of 06.11 Main status word (see page 150).	14
	Fault (-1)	Inverted bit 3 of 06.11 Main status word (see page 150).	15
	Open brake command	Bit 0 of 44.01 Brake control status (see page 341).	22
	Ext2 active	Bit 11 of 06.16 Drive status word 1 (see page 150).	23
	Remote control	Bit 9 of 06.11 Main status word (see page 150).	24
	Supervision 1	Bit 0 of 32.01 Supervision status (see page 297).	33
	Supervision 2	Bit 1 of 32.01 Supervision status (see page 297).	34
	Supervision 3	Bit 2 of 32.01 Supervision status (see page 297).	35
	RO/DIO control word bit0	Bit 0 of 10.99 RO/DIO control word (see page 176).	40
	RO/DIO control word bit1	Bit 1 of 10.99 RO/DIO control word (see page 176).	41
	RO/DIO control word bit2	Bit 2 of 10.99 RO/DIO control word (see page 176).	42



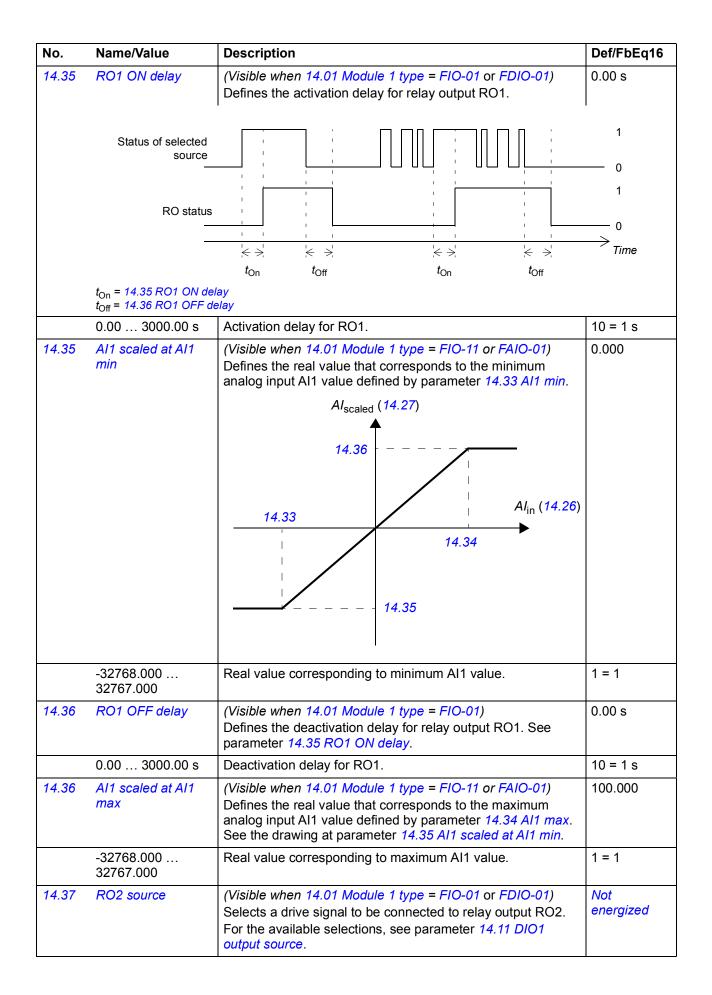
No.	Name/Value	Description	Def/FbEq16
14.14	DIO2 function	(<i>Visible when 14.01 Module 1 type = FIO-01 or FIO-11</i>) Selects whether DIO2 of the extension module is used as a digital input or output.	Input
	Output	DIO2 is used as a digital output.	0
	Input	DIO2 is used as a digital input.	1
14.16	DIO2 output source	(Visible when 14.01 Module 1 type = FIO-01 or FIO-11) Selects a drive signal to be connected to digital input/output DIO2 when parameter 14.14 DIO2 function is set to Input. For the available selections, see parameter 14.11 DIO1 output source.	Not energized
14.17	DI2 ON delay	(<i>Visible when 14.01 Module 1 type = FDIO-01</i>) Defines the activation delay for digital input DI2. See parameter <i>14.12 DI1 ON delay</i> .	0.00 s
	0.00 3000.00 s	Activation delay for DI2.	10 = 1 s
14.17	DIO2 ON delay	(<i>Visible when 14.01 Module 1 type = FIO-01 or FIO-11</i>) Defines the activation delay for digital input/output DIO2. See parameter 14.12 DIO1 ON delay.	0.00 s
	0.00 3000.00 s	Activation delay for DIO2.	10 = 1 s
14.18	DI2 OFF delay	(<i>Visible when 14.01 Module 1 type = FDIO-01</i>) Defines the deactivation delay for digital input DI2. See parameter <i>14.12 DI1 ON delay</i> .	0.00 s
	0.00 3000.00 s	Deactivation delay for DI2.	10 = 1 s
14.18	DIO2 OFF delay	(<i>Visible when 14.01 Module 1 type = FIO-01 or FIO-11</i>) Defines the deactivation delay for digital input/output DIO2. See parameter <i>14.12 DIO1 ON delay</i> .	0.00 s
	0.00 3000.00 s	Deactivation delay for DIO2.	10 = 1 s
14.19	DIO3 function	(<i>Visible when 14.01 Module 1 type = FIO-01</i>) Selects whether DIO3 of the extension module is used as a digital input or output.	Input
	Output	DIO3 is used as a digital output.	0
	Input	DIO3 is used as a digital input.	1
14.19	AI supervision function	(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Selects how the drive reacts when an analog input signal moves out of the minimum and/or maximum limits specified for the input. The inputs and the limits to be observed are selected by parameter 14.20 AI supervision selection.	No action
	No action	No action taken.	0
	Fault	Drive trips on 80A0 AI supervision.	1
	Warning	Drive generates an A8A0 AI supervision warning.	2
	Last speed	Drive generates a warning (<i>A8A0 AI supervision</i>) and freezes the speed (or frequency) to the level the drive was operating at. The speed/frequency is determined on the basis of actual speed using 850 ms low-pass filtering. WARNING! Make sure that it is safe to continue operation in case of a communication break.	3

No.	Name/V	alue	Desci	ription	Def/FbEq16
	Speed re	ef safe	speed safe (generates a warning (<i>A8A0 AI supervision</i>) and sets the I to the speed defined by parameter 22.41 Speed ref or 28.41 Frequency ref safe when frequency reference ing used). WARNING! Make sure that it is safe to continue operation in case of a communication break.	4
14.20	Al super selection		Specit param Note:	<i>le when 14.01 Module 1 type = FIO-11 or FAIO-01)</i> fies the analog input limits to be supervised. See heter <i>14.19 AI supervision function</i> . The number of active bits in this parameter depends on umber of inputs on the extension module.	0000 0000b
	Bit	Name		Description	
	0	AI1 < MIN		1 = Minimum limit supervision of AI1 active.	
	1	AI1 > MAX		1 = Maximum limit supervision of AI1 active.	
	2	AI2 < MIN		1 = Minimum limit supervision of Al2 active.	
	3	AI2 > MAX		1 = Maximum limit supervision of Al2 active.	
	4	AI3 < MIN		1 = Minimum limit supervision of AI3 active (FIO-11 only)	
	5	AI3 > MAX		1 = Maximum limit supervision of AI3 active (FIO-11 only	
	615	Reserved			,-
14.21	0000 00 0011 11 ⁻ DIO3 ou		(Visibi	tion of analog input supervision. <i>Ie when 14.01 Module 1 type = FIO-01)</i>	1 = 1 Not
			DIO3 For th	ts a drive signal to be connected to digital input/output when parameter 14.19 DIO3 function is set to Input. e available selections, see parameter 14.11 DIO1 t source.	energized
14.21	Al tune		Trigge use of input Apply the ap	We when 14.01 Module 1 type = $FIO-11$ or $FAIO-01$) ers the analog input tuning function, which enables the f actual measurements as the minimum and maximum values instead of potentially inaccurate estimates. the minimum or maximum signal to the input and select opropriate tuning function. Iso the drawing at parameter 14.35 All scaled at All	No action
	No action		The p	g action completed or no action has been requested. arameter automatically reverts to this value after any g action.	0
	AI1 min	tune		neasured value of AI1 is set as the minimum value of to parameter <i>14.33 AI1 min</i> .	1
	Al1 max	tune		neasured value of AI1 is set as the maximum value of to parameter <i>14.34 AI1 max</i> .	2
	AI2 min	tune		neasured value of AI2 is set as the minimum value of to parameter <i>14.48 AI2 min</i> .	3
	Al2 max	tune		neasured value of AI2 is set as the maximum value of to parameter <i>14.49 AI2 max</i> .	4
	Al3 min	tune	The m	le when 14.01 Module 1 type = FIO-11) neasured value of AI3 is set as the minimum value of to parameter 14.63 AI3 min.	5

No.	Name/Value		Description	Def/FbEq16
	AI3 max	tune	(<i>Visible when 14.01 Module 1 type = FIO-11</i>) The measured value of AI3 is set as the maximum value of AI3 into parameter <i>14.64 AI3 max</i> .	6
14.22	DI3 ON (delay	(<i>Visible when 14.01 Module 1 type = FDIO-01</i>) Defines the activation delay for digital input DI3. See parameter <i>14.12 DI1 ON delay</i> .	0.00 s
	0.00 3	3000.00 s	Activation delay for DI3.	10 = 1 s
14.22	DIO3 OI	l delay	(<i>Visible when 14.01 Module 1 type = FIO-01 or FIO-11</i>) Defines the activation delay for digital input/output DIO3. See parameter 14.12 DIO1 ON delay.	0.00 s
	0.00 3	3000.00 s	Activation delay for DIO3.	10 = 1 s
14.22	Al force	selection	(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) The true readings of the analog inputs can be overridden for eg. testing purposes. A forced value parameter is provided for each analog input, and its value is applied whenever the corresponding bit in this parameter is 1.	0000b
	Bit	Name	Description	
	0	Al1	1 = Force mode: Force Al1 to value of parameter 14.28 Al1 for	orce data.
	1	Al2	1 = Force mode: Force Al2 to value of parameter 14.43 Al2 for	
	2	AI3	1 = Force mode: Force Al3 to value of parameter 14.58 Al3 for (FIO-11 only).	orce data
	315	Reserved	·	
	0000b	0111b	Forced values selector for analog inputs.	1 = 1
14.23	DI3 OFF	delay	(<i>Visible when 14.01 Module 1 type = FDIO-01</i>) Defines the deactivation delay for digital input DI3. See parameter <i>14.12 DI1 ON delay</i> .	0.00 s
	0.00 3	3000.00 s	Deactivation delay for DI3.	10 = 1 s
14.23	DIO3 OF	FF delay	(<i>Visible when 14.01 Module 1 type = FIO-01</i>) Defines the deactivation delay for digital input/output DIO3. See parameter <i>14.22 DIO3 ON delay</i> .	0.0 s
	0.0 30	000.0 s	Deactivation delay for DIO3.	10 = 1 s
14.24	DIO4 fur	nction	(<i>Visible when 14.01 Module 1 type = FIO-01</i>) Selects whether DIO4 of the extension module is used as a digital input or output.	Input
	Output		DIO4 is used as a digital output.	0
	Input		DIO4 is used as a digital input.	1
14.26	6 DIO4 output source		(Visible when 14.01 Module 1 type = FIO-01) Selects a drive signal to be connected to digital input/output DIO4 when parameter 14.24 DIO4 function is set to Output. For the available selections, see parameter 14.11 DIO1 output source.	Not energized
14.26	Al1 actual value		(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Displays the value of analog input AI1 in mA or V (depending on whether the input is set to current or voltage). This parameter is read-only.	-
	-22.000 mA or V	22.000	Value of analog input AI1.	1000 = 1 mA or V

No.	Name/Value	Description	Def/FbEq16
14.27	DIO4 ON delay	(Visible when 14.01 Module 1 type = FIO-01 or FIO-11) Defines the activation delay for digital input/output DIO4. See parameter 14.12 DIO1 ON delay.	0.00 s
	0.00 3000.00 s	Activation delay for DIO4.	10 = 1 s
14.27	AI1 scaled value	(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Displays the value of analog input AI1 after scaling. See parameter 14.35 AI1 scaled at AI1 min. This parameter is read-only.	-
	-32768.000 32767.000	Scaled value of analog input Al1.	1 = 1
14.28	DIO4 OFF delay	(<i>Visible when 14.01 Module 1 type = FIO-01</i>) Defines the deactivation delay for digital input/output DIO4. See parameter <i>14.12 DIO1 ON delay</i> .	0.00 s
	0.00 3000.00 s	Deactivation delay for DIO4.	10 = 1 s
14.28	AI1 force data	(<i>Visible when 14.01 Module 1 type = FIO-11 or FAIO-01</i>) Forced value that can be used instead of the true reading of the input. See parameter <i>14.22 AI force selection</i> .	0.000 mA
	-22.000 22.000 mA or V	Forced value of analog input Al1.	1000 = 1 mA or V
14.29	AI1 HW switch position	 (Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Shows the position of the hardware current/voltage selector on the I/O extension module. Note: The setting of the current/voltage selector must match the unit selection made in parameter 14.30 AI1 unit selection. I/O module reboot either by cycling the power or through parameter 96.08 Control board boot is required to validate any changes in the hardware settings. 	-
	V	Volts.	2
	mA	Milliamperes.	10
14.30	Al1 unit selection	(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Selects the unit for readings and settings related to analog input AI1. Note: This setting must match the corresponding hardware setting on the I/O extension module (see the manual of the I/O extension module). The hardware setting is shown by parameter 14.29 AI1 HW switch position. I/O module reboot either by cycling the power or through parameter 96.08 <i>Control board boot</i> is required to validate any changes in the hardware settings.	mA
	V	Volts.	2
	mA	Milliamperes.	10
14.31	RO status	(<i>Visible when 14.01 Module 1 type = FIO-01</i> or <i>FDIO-01</i>) Status of relay outputs on the I/O extension module. Example: 0001b = RO1 is energized, RO2 is de-energized.	-
	0000b1111b	Status of relay outputs.	1 = 1
14.31	AI1 filter gain	(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Selects a hardware filtering time for AI1. See also parameter 14.32 AI1 filter time.	1 ms
	No filtering	No filtering.	0
	125 us	125 microseconds.	1

No.	Name/Value	Description	Def/FbEq16
	250 us	250 microseconds.	2
	500 us	500 microseconds.	3
	1 ms	1 millisecond.	4
	2 ms	2 milliseconds.	5
	4 ms	4 milliseconds.	6
	7.9375 ms	7.9375 milliseconds.	7
14.32	Al1 filter time	(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Defines the filter time constant for analog input Al1. $ \begin{array}{c} & \\ & \\ & \\ & \\ & \\ & \\ & \\ & $	0.100 s
	0.000 30.000 s	Filter time constant.	1000 = 1 s
14.33	Al1 min	(<i>Visible when 14.01 Module 1 type = FIO-11 or FAIO-01</i>) Defines the minimum value for analog input Al1. See also parameter <i>14.21 Al tune</i> .	0.000 mA or V
	-22.000 22.000 mA or V	Minimum value of Al1.	1000 = 1 mA or V
14.34	RO1 source	(Visible when 14.01 Module 1 type = FIO-01 or FDIO-01) Selects a drive signal to be connected to relay output RO1. For the available selections, see parameter 14.11 DIO1 output source.	Not energized
14.34	Al1 max	(<i>Visible when 14.01 Module 1 type = FIO-11 or FAIO-01</i>) Defines the maximum value for analog input Al1. See also parameter <i>14.21 Al tune</i> .	10.000 mA or V
	-22.000 22.000 mA or V	Maximum value of Al1.	1000 = 1 mA or V



14.38 RO2 ON delay (Visible when 14.01 Module 1 type = FIO-01 or FDIO-01) befines the activation delay for RO2. 0.00 s. 14.39 RO2 OFF delay (Visible when 14.01 Module 1 type = FIO-01 or FDIO-01) Defines the deactivation delay for relay output RO2. See parameter 14.35 RO1 ON delay. 0.00 s. 0.00 3000.00 s Deactivation delay for RO2. 10 = 1 s 14.41 Al2 actual value (Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Displays the value of analog input Al2 in mA or V (depending on whether the input is set to current or voltage). This parameter is read-only. 1000 = 1 mA or V -22.000 22.000 Value of analog input Al2 after scaling. See parameter 14.50 Al2 scaled at Al2 min. This parameter is read-only. - -32768.000 32767.000 Scaled value of analog input Al2. 1000 = 1 mA or V 14.43 Al2 force data (Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Displays the value of analog input Al2. 1 = 1 14.43 Al2 force data (Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Forced value that can be used instead of the true reading of the input. See parameter 14.22 Al force selection. - -22.000 22.000 Forced value of analog input Al2. 1000 = 1 mA or V 14.43 Al2 force data (Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Forced value for analog input Al2. <th>No.</th> <th>Name/Value</th> <th>Description</th> <th>Def/FbEq16</th>	No.	Name/Value	Description	Def/FbEq16
14.39 RO2 OFF delay (Visible when 14.01 Module 1 type = FIO-01 or FDIO-01) Defines the deactivation delay for relay output RO2. See parameter 14.35 RO1 ON delay. 0.00 s 0.00 3000.00 s Deactivation delay for RO2. 10 = 1 s 14.41 Al2 actual value (Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Displays the value of analog input Al2 in mA or V (depending on whether the input is set to current or voltage). This parameter is read-only. 1000 = 1 mA or V -22.000 222.000 (Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Displays the value of analog input Al2. 1000 = 1 mA or V 14.42 Al2 scaled value (Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Displays the value of analog input Al2. 1000 = 1 mA or V 14.43 Al2 scaled value (Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Forced value of analog input Al2. 1 = 1 .32767.000 Scaled value of analog input Al2. 1000 = 1 mA or V .44.3 Al2 force data (Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Forced value of analog input Al2. 0.000 mA .22.000 22.000 Forced value of analog input Al2. 1000 = 1 mA or V 14.43 Al2 force data (Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Shows the position of the inparameter 14.22 Al force selection. 0 14.44	14.38	RO2 ON delay	Defines the activation delay for relay output RO2. See	0.00 s
Defines the deactivation delay for relay output RO2. See parameter 14.35 RO1 ON delay.10 = 1 s14.41Al2 actual value(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Displays the value of analog input Al2 in mA or V (depending on whether the input isset to current or voltage). This parameter is read-only.1000 = 1 mA or V-22.000 22.000 mA or VValue of analog input Al2.1000 = 1 mA or V14.42Al2 scaled value(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Displays the value of analog input Al2 after scaling. See parameter 14.50 Al2 scaled at Al2 min. This parameter is read-only.1-32768.000 32768.000 32768.000 32768.000 32768.000 32768.000 Scaled value of analog input Al2.0.000 mA14.43Al2 force data M (Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Forced value that can be used instead of the ture reading of the input. See parameter 14.22 Al force selection.0.000 mA14.44Al2 force data M (Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Shows the position of the hardware current/voltage selector not the I/O extension module. Note: The setting of the current/voltage selector not the I/O extension module. Note: The setting of the current/voltage selector not the I/O extension module. Note: This setting of the current/voltage selector must match the unit selection not the I/O extension module.10014.45Al2 unit selection Note: The setting of the current/voltage selector not the I/O extension module. Note: This setting of the current/voltage selector not the I/O extension module. Note: This setting of the current/voltage selector not the I/O extension module. N		0.00 3000.00 s	Activation delay for RO2.	10 = 1 s
14.41 Al2 actual value (Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Displays the value of analog input Al2 in mA or V (depending on whether the input is set to current or voltage). This parameter is read-only. 1000 = 1 mA -22.000 22.000 Value of analog input Al2. 1000 = 1 mA mA or V Value of analog input Al2. 1000 = 1 mA 14.42 Al2 scaled value (Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Displays the value of analog input Al2 after scaling. See parameter 14.50 Al2 scaled at Al2 min. -32768.000 Scaled value of analog input Al2. 1 = 1 -32767.000 Scaled value of analog input Al2. 0.000 mA -22.000 Croce data (Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) 0.000 mA mA or V Forced value that can be used instead of the true reading of the input. See parameter 14.22 Al force selection. 1000 = 1 mA or V 14.44 Al2 HW switch position of the hardware current/voltage selector on the I/O extension module. 1000 = 1 mA or V 14.44 Al2 HW switch position of the hardware settings. V 1000 = 1 mA or V 14.44 Al2 HW switch position of the hardware settings. 1000 = 1 mA or V 1000 = 1 mA or V 14.44 Al2 HW switch position of the hardware settings. 1000	14.39	RO2 OFF delay	Defines the deactivation delay for relay output RO2. See	0.00 s
Displays the value of analog input A12 in mA or V (depending on whether the input is set to current or voltage). This parameter is read-only.1000 = 1 mA or V14.42Al2 scaled value(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Displays the value of analog input A12 after scaling. See parameter 14.50 A12 scaled at A12 min. This parameter is read-only32767.000Scaled value of analog input A12.1 = 114.43Al2 force data(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Forced value that can be used instead of the true reading of the input. See parameter 14.22 Al force selection.0.000 mA-22.000 22.000 mA or VForced value of analog input A12.1000 = 1 mA or V14.44Al2 HW switch position(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Shows the position of the hardware current/voltage selector on the I/O extension module.1000 = 1 mA or V14.44Al2 HW switch position(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Shows the position of the hardware current/voltage selector mot the U octansion module.1000 = 1 mA or V14.45Al2 unit selection(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Selects the unit for readings and settings related to analog input A12.10014.45Al2 unit selection(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Selects the unit for readings and settings related to analog input A12.1014.45Al2 unit selection(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Selects the unit for readings and settings related to analog input A12.1014.45 <t< th=""><th></th><th>0.00 3000.00 s</th><th>Deactivation delay for RO2.</th><th>10 = 1 s</th></t<>		0.00 3000.00 s	Deactivation delay for RO2.	10 = 1 s
mA or Vor V14.42Al2 scaled value(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Displays the value of analog input Al2 after scaling. See parameter 14.50 Al2 scaled at Al2 min. This parameter is read-only32768.000 32767.000Scaled value of analog input Al2.1 = 114.43Al2 force data(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Forced value that can be used instead of the true reading of the input. See parameter 14.22 Al force selection.0.000 mA-22.000 22.000Forced value of analog input Al2.1000 = 1 mA or V14.44Al2 HW switch position(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Shows the position of the hardware current/voltage selector on the I/O extension module. Note: The setting of the current/voltage selector must here on the U or extension module. Note: The setting of the current/voltage selector or used any changes in the hardware settings.2VVolts.2mAMilliamperes.1014.45Al2 unit selection Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Selects the unit for readings and settings related to analog input Al2.mAVVolts.2MAMilliamperes.1014.45Al2 unit selection Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Selects the unit for readings and settings related to analog input Al2.mAVVolts.2mAMilliamperes.1014.45Al2 unit selection(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Selects the unit for readings and settings related to analo	14.41	AI2 actual value	Displays the value of analog input AI2 in mA or V (depending on whether the input is set to current or voltage).	-
Displays the value of analog input Al2 after scaling. See parameter 14.50 Al2 scaled at Al2 min. This parameter is read-only.1 = 1-32768.000Scaled value of analog input Al2. 32767.0001 = 114.43Al2 force data(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Forced value that can be used instead of the true reading of the input. See parameter 14.22 Al force selection.0.000 mA-22.000 22.000 mA or VForced value of analog input Al2.1000 = 1 mA or V-22.001 22.000 mA or VForced value of analog input Al2.1000 = 1 mA or V14.44Al2 HW switch position(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Shows the position of the hardware current/voltage selector on the I/O extension moduleNote: The setting of the current/voltage selector must match the unit selection made in parameter 14.45 Al2 unit selection. I/O module reboot either by cycling the power or through parameter 96.08 Control board boot is required to validate any changes in the hardware settings.2VVolts.2MAMilliamperes.1014.45Al2 unit selection V colts.MAVVolts.2Note: This setting must match the corresponding hardware setting on the I/O extension module (see the manual of the I/O extension module). The hardware setting is shown by parameter 14.44 Al2 HW switch position. I/O module reboot either by cycling the power or through parameter 96.08 Control board boot is required to validate any changes in the hardware settings.2VVolts.214.46Al2 filter gain(Vis			Value of analog input AI2.	
32767.000Ministration of the set of the s	14.42	AI2 scaled value	Displays the value of analog input AI2 after scaling. See parameter 14.50 AI2 scaled at AI2 min.	-
Forced value that can be used instead of the true reading of the input. See parameter 14.22 Al force selection.1000 = 1 mA-22.000 22.000 mA or VForced value of analog input Al2.1000 = 1 mA or V14.44Al2 HW switch position(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Shows the position of the hardware current/voltage selector on the I/O extension module. Note: The setting of the current/voltage selector must match the unit selection made in parameter 14.45 Al2 unit selection. I/O module reboot either by cycling the power or through parameter 96.08 Control board boot is required to validate any changes in the hardware settings.2VVolts.2mAMilliamperes.1014.45Al2 unit selection Volts.(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Selects the unit for readings and settings related to analog input Al2.mAVVolts.2Note: This setting must match the corresponding hardware setting on the I/O extension module (see the manual of the hardware setting is nown by parameter 14.44 Al2 HW switch position. I/O module reboot either by cycling the power or through parameter 96.08 Control board boot is required to validate any changes in the hardware settings.2VVolts.2mAMilliamperes.1014.45Al2 filter gain(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Selects a hardware filtering time for Al2. See also parameter 14.47 Al2 filter time.11			Scaled value of analog input AI2.	1 = 1
mA or Vor V14.44AI2 HW switch position(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Shows the position of the hardware current/voltage selector on the I/O extension module. Note: The setting of the current/voltage selector must match the unit selection made in parameter 14.45 AI2 unit selection. I/O module reboot either by cycling the power or through parameter 96.08 Control board boot is required to validate any changes in the hardware settings.2VVolts.2mAMilliamperes.1014.45AI2 unit selection Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Selects the unit for readings and settings related to analog input AI2. Note: This setting must match the corresponding hardware setting on the I/O extension module (see the manual of the I/O extension module). The hardware setting is shown by parameter 14.44 AI2 HW switch position. I/O module reboot either by cycling the power or through parameter 96.08 Control board boot is required to validate any changes in the hardware settings.2VVolts.2Image: Note: This setting must match the corresponding hardware setting on the I/O extension module (see the manual of the I/O extension module). The hardware setting is shown by parameter 14.44 AI2 HW switch position. I/O module reboot either by cycling the power or through parameter 96.08 Control board boot is required to validate any changes in the hardware settings.2VVolts.2Image: Note: This setting must match the corresponding hardware setting on the I/O extension module (see the manual of the hardware settings.10I/A for All 2 filter gain(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01	14.43	AI2 force data	Forced value that can be used instead of the true reading of	0.000 mA
positionShows the position of the hardware current/voltage selector on the I/O extension module. Note: The setting of the current/voltage selector must match the unit selection made in parameter 14.45 Al2 unit selection. I/O module reboot either by cycling the power or through parameter 96.08 Control board boot is required to validate any changes in the hardware settings.2VVolts.2mAMilliamperes.1014.45Al2 unit selection(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Selects the unit for readings and settings related to analog input Al2. Note: This setting must match the corresponding hardware setting on the I/O extension module (see the manual of the I/O extension module). The hardware setting is shown by parameter 14.44 Al2 HW switch position. I/O module reboot either by cycling the power or through parameter 96.08 Control board boot is required to validate any changes in the hardware settings.2VVolts.2mAMilliamperes.1014.46Al2 filter gain(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Selects a hardware filtering time for Al2. See also parameter 14.47 Al2 filter time.10			Forced value of analog input AI2.	
mAMilliamperes.1014.45Al2 unit selection(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Selects the unit for readings and settings related to analog input Al2. Note: This setting must match the corresponding hardware setting on the I/O extension module (see the manual of the I/O extension module). The hardware setting is shown by parameter 14.44 Al2 HW switch position. I/O module reboot either by cycling the power or through parameter 96.08 Control board boot is required to validate any changes in the hardware settings.2VVolts.2mAMilliamperes.1014.46Al2 filter gain(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Selects a hardware filtering time for Al2. See also parameter 14.47 Al2 filter time.1 ms	14.44		Shows the position of the hardware current/voltage selector on the I/O extension module. Note: The setting of the current/voltage selector must match the unit selection made in parameter <i>14.45 AI2 unit selection</i> . I/O module reboot either by cycling the power or through parameter <i>96.08 Control board boot</i> is required to validate	-
14.45Al2 unit selection(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Selects the unit for readings and settings related to analog input Al2. Note: This setting must match the corresponding hardware setting on the I/O extension module (see the manual of the I/O extension module). The hardware setting is shown by parameter 14.44 Al2 HW switch position. I/O module reboot either by cycling the power or through parameter 96.08 Control board boot is required to validate any changes in the hardware settings.2VVolts.2mAMilliamperes.1014.46Al2 filter gain(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Selects a hardware filtering time for Al2. See also parameter 14.47 Al2 filter time.1 ms		V	Volts.	2
Selects the unit for readings and settings related to analog input Al2.Note: This setting must match the corresponding hardware setting on the I/O extension module (see the manual of the I/O extension module). The hardware setting is shown by parameter 14.44 Al2 HW switch position. I/O module reboot either by cycling the power or through parameter 96.08 Control board boot is required to validate any changes in the hardware settings.2VVolts.2mAMilliamperes.1014.46Al2 filter gain(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Selects a hardware filtering time for Al2. See also parameter 14.47 Al2 filter time.1 ms		mA	Milliamperes.	10
mAMilliamperes.1014.46Al2 filter gain(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Selects a hardware filtering time for Al2. See also parameter 14.47 Al2 filter time.1 ms	14.45	AI2 unit selection	Selects the unit for readings and settings related to analog input Al2. Note: This setting must match the corresponding hardware setting on the I/O extension module (see the manual of the I/O extension module). The hardware setting is shown by parameter <i>14.44 Al2 HW switch position</i> . I/O module reboot either by cycling the power or through parameter <i>96.08</i> <i>Control board boot</i> is required to validate any changes in the	mA
14.46AI2 filter gain(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Selects a hardware filtering time for AI2. See also parameter 14.47 AI2 filter time.1 ms		V	Volts.	2
Selects a hardware filtering time for AI2. See also parameter 14.47 AI2 filter time.		mA	Milliamperes.	10
No filtering No filtering. 0	14.46	AI2 filter gain	Selects a hardware filtering time for AI2.	1 ms
		No filtering	No filtering.	0

No.	Name/Value	Description	Def/FbEq16
	125 us	125 microseconds.	1
	250 us	250 microseconds.	2
	500 us	500 microseconds.	3
	1 ms	1 millisecond.	4
	2 ms	2 milliseconds.	5
	4 ms	4 milliseconds.	6
	7.9375 ms	7.9375 milliseconds.	7
14.47	Al2 filter time	(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Defines the filter time constant for analog input Al2. Unfiltered signal 100 63 filtered signal T $O = I \times (1 - e^{-t/T})$ I = filter input (step) O = filter output t = time T = filter time constant Note: The signal is also filtered due to the signal interface hardware. See parameter 14.46 Al2 filter gain.	0.100 s
	0.000 30.000 s	Filter time constant.	1000 = 1 s
14.48	AI2 min	(<i>Visible when 14.01 Module 1 type = FIO-11 or FAIO-01</i>) Defines the minimum value for analog input AI2. See also parameter <i>14.21 AI tune</i> .	0.000 mA or V
	-22.000 22.000 mA or V	Minimum value of Al2.	1000 = 1 mA or V
14.49	Al2 max	(<i>Visible when 14.01 Module 1 type = FIO-11 or FAIO-01</i>) Defines the maximum value for analog input AI2. See also parameter <i>14.21 AI tune</i> .	10.000 mA or V
	-22.000 22.000 mA or V	Maximum value of AI2.	1000 = 1 mA or V

No.	Name/Value	Description	Def/FbEq16
14.50	AI2 scaled at AI2 min	(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Defines the real value that corresponds to the minimum analog input Al2 value defined by parameter 14.48 Al2 min. $AI_{scaled} (14.42)$ 14.51 14.48 14.49 14.49	0.000
	-32768.000 32767.000	Real value corresponding to minimum Al2 value.	1 = 1
14.51	AI2 scaled at AI2 max	(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Defines the real value that corresponds to the maximum analog input AI2 value defined by parameter 14.49 AI2 max. See the drawing at parameter 14.50 AI2 scaled at AI2 min.	100.000
	-32768.000 32767.000	Real value corresponding to maximum Al2 value.	1 = 1
14.56	Al3 actual value	(Visible when 14.01 Module 1 type = FIO-11) Displays the value of analog input AI3 in mA or V (depending on whether the input is set to current or voltage). This parameter is read-only.	-
	-22.000 22.000 mA or V	Value of analog input AI3.	1000 = 1 mA or V
14.57	AI3 scaled value	(Visible when 14.01 Module 1 type = FIO-11) Displays the value of analog input AI3 after scaling. See parameter 14.65 AI3 scaled at AI3 min. This parameter is read-only.	-
	-32768.000 32767.000	Scaled value of analog input AI3.	1 = 1
14.58	AI3 force data	(Visible when 14.01 Module 1 type = FIO-11) Forced value that can be used instead of the true reading of the input. See parameter 14.22 Al force selection.	0.000 mA
	-22.000 22.000 mA or V	Forced value of analog input Al3.	1000 = 1 mA or V
14.59	AI3 HW switch position	 (Visible when 14.01 Module 1 type = FIO-11) Shows the position of the hardware current/voltage selector on the I/O extension module. Note: The setting of the current/voltage selector must match the unit selection made in parameter 14.60 AI3 unit selection. I/O module reboot either by cycling the power or through parameter 96.08 Control board boot is required to validate any changes in the hardware settings. 	-
	V	Volts.	2

No.	Name/Value	Description	Def/FbEq16
	mA	Milliamperes.	10
14.60	AI3 unit selection	(Visible when 14.01 Module 1 type = FIO-11) Selects the unit for readings and settings related to analog input AI3. Note: This setting must match the corresponding hardware setting on the I/O extension module (see the manual of the I/O extension module). The hardware setting is shown by parameter 14.59 AI3 HW switch position. I/O module reboot either by cycling the power or through parameter 96.08 Control board boot is required to validate any changes in the hardware settings.	mA
	V	Volts.	2
	mA	Milliamperes.	10
14.61	Al3 filter gain	(<i>Visible when 14.01 Module 1 type = FIO-11</i>) Selects a hardware filtering time for Al3. See also parameter <i>14.62 Al3 filter time</i> .	1 ms
	No filtering	No filtering.	0
	125 us	125 microseconds.	1
	250 us	250 microseconds.	2
	500 us	500 microseconds.	3
	1 ms	1 millisecond.	4
	2 ms	2 milliseconds.	5
	4 ms	4 milliseconds.	6
	7.9375 ms	7.9375 milliseconds.	7
14.62	Al3 filter time	(Visible when 14.01 Module 1 type = FIO-11) Defines the filter time constant for analog input AI3.	0.100 s
	0.000 20.000 -	hardware. See parameter <i>14.61 AI3 filter gain</i> .	1000 - 1 -
	0.000 30.000 s	Filter time constant.	1000 = 1 s

No.	Name/V	/alue	Description	Def/FbEq16
14.63	AI3 min		(Visible when 14.01 Module 1 type = FIO-11) Defines the minimum value for analog input AI3. See also parameter 14.21 AI tune.	0.000 mA or V
	-22.000 mA or V	22.000	Minimum value of AI3.	1000 = 1 mA or V
14.64	AI3 max	((Visible when 14.01 Module 1 type = FIO-11) Defines the maximum value for analog input AI3. See also parameter 14.21 AI tune.	10.000 mA or V
	-22.000 mA or V	22.000	Maximum value of Al3.	1000 = 1 mA or V
14.65	Al3 sca min	led at AI3	(Visible when 14.01 Module 1 type = FIO-11) Defines the real value that corresponds to the minimum analog input AI3 value defined by parameter 14.63 AI3 min. AI_{scaled} (14.57) 14.66 14.63 14.64 14.64 14.65	0.000
	-32768. 32767.0		Real value corresponding to minimum AI3 value.	1 = 1
14.66	AI3 sca max	led at AI3	(<i>Visible when 14.01 Module 1 type = FIO-11</i>) Defines the real value that corresponds to the maximum analog input AI3 value defined by parameter <i>14.64 AI3 max</i> . See the drawing at parameter <i>14.65 AI3 scaled at AI3 min</i> .	100.000
	-32768. 32767.0		Real value corresponding to maximum Al3 value.	1 = 1
14.71	AO forc	e selection	(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) The value of the analog output can be overridden for eg. testing purposes. A forced value parameter (14.78 AO1 force data) is provided for the analog output, and its value is applied whenever the corresponding bit in this parameter is 1.	00b
	Bit	Name	Description	
	0	AO1	1 = Force mode: Force AO1 to value of parameter 14.78 AO	1 force data.
	1	AO2	1 = Force mode: Force AO2 to value of parameter 14.88 AO2 (FAIO-01 only).	
	315	Reserved		
	315	Reserved		

No.	Name/Value	Description	Def/FbEq16
14.76	AO1 actual value	(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Displays the value of AO1 in mA. This parameter is read-only.	-
	0.000 22.000 mA	Value of AO1.	1000 = 1 mA
14.77	AO1 source	(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Selects a signal to be connected to analog output AO1. Alternatively, sets the output to excitation mode to feed a constant current to a temperature sensor.	Zero
	Zero	None.	0
	Motor speed used	01.01 Motor speed used (page 136).	1
	Output frequency	01.06 Output frequency (page 136).	3
	Motor current	01.07 Motor current (page 136).	4
	Motor torque	01.10 Motor torque (page 136).	6
	DC voltage	01.11 DC voltage (page 137).	7
	Power inu out	01.14 Output power (page 137).	8
	Speed ref ramp in	23.01 Speed ref ramp input (page 242).	10
	Speed ref ramp out	23.02 Speed ref ramp output (page 242).	11
	Speed ref used	24.01 Used speed reference (page 248).	12
	Torq ref used	26.02 Torque reference used (page 264).	13
	Freq ref used	28.02 Frequency ref ramp output (page 270).	14
	Process PID out	40.01 Process PID output actual (page 325).	16
	Process PID fbk	40.02 Process PID feedback actual (page 325).	17
	Process PID act	40.03 Process PID setpoint actual (page 325).	18
	Process PID dev	40.04 Process PID deviation actual (page 325).	19
	Force PT100 excitation	The output is used to feed an excitation current to 13 Pt100 sensors. See section <i>Motor thermal protection</i> (page 113).	20
	Force KTY84 excitation	The output is used to feed an excitation current to a KTY84 sensor. See section <i>Motor thermal protection</i> (page <i>113</i>).	21
	Force PTC excitation	The output is used to feed an excitation current to 13 PTC sensors. See section <i>Motor thermal protection</i> (page <i>113</i>).	22
	Force Pt1000 excitation	The output is used to feed an excitation current to 13 Pt1000 sensors. See section <i>Motor thermal protection</i> (page <i>113</i>).	23
	AO1 data storage	13.91 AO1 data storage (page 189).	37
	AO2 data storage	13.92 AO2 data storage (page 189).	38
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
14.78	AO1 force data	(<i>Visible when 14.01 Module 1 type = FIO-11 or FAIO-01</i>) Forced value that can be used instead of the selected output signal. See parameter 14.71 AO force selection.	0.000 mA
	0.000 22.000 mA	Forced value of analog output AO1.	1000 = 1 mA
	0.000 22.000 mA	Forced value of analog output AO1.	1000 = 1 n

No.	Name/Value	Description	Def/FbEq16
14.79	AO1 filter time	(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Defines the filtering time constant for analog output AO1.	0.100 s
	0.000 30.000 s	Filter time constant.	1000 = 1 s

No.	Name/Value	Description	Def/FbEq16
14.80	AO1 source min	(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Defines the real value of the signal (selected by parameter 14.77 AO1 source) that corresponds to the minimum AO1 output value (defined by parameter 14.82 AO1 out at AO1 src min). I _{AO1} (mA) 14.82 14.80 14.81 I _{AO1} (mA) I _A	0.0
	-32768.0 32767.0	Real signal value corresponding to minimum AO1 output value.	1 = 1
14.81	AO1 source max	(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Defines the real value of the signal (selected by parameter 14.77 AO1 source) that corresponds to the maximum AO1 output value (defined by parameter 14.83 AO1 out at AO1 src max). See parameter 14.80 AO1 source min.	1500.0
	-32768.0 32767.0	Real signal value corresponding to maximum AO1 output value.	1 = 1
14.82	AO1 out at AO1 src min	(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Defines the minimum output value for analog output AO1. See also drawing at parameter 14.80 AO1 source min.	0.000 mA
	0.000 22.000 mA	Minimum AO1 output value.	1000 = 1 mA
14.83	AO1 out at AO1 src max	(Visible when 14.01 Module 1 type = FIO-11 or FAIO-01) Defines the maximum output value for analog output AO1. See also drawing at parameter 14.80 AO1 source min.	10.000 mA
	0.000 22.000 mA	Maximum AO1 output value.	1000 = 1 mA

No.	Name/Value	Description	Def/FbEq16
14.86	AO2 actual value	(Visible when 14.01 Module 1 type = FAIO-01) Displays the value of AO2 in mA. This parameter is read-only.	-
	0.000 22.000 mA	Value of AO2.	1000 = 1 mA
14.87	AO2 source	(Visible when 14.01 Module 1 type = FAIO-01) Selects a signal to be connected to analog output AO2. Alternatively, sets the output to excitation mode to feed a constant current to a temperature sensor. For the selections, see parameter 14.77 AO1 source.	Zero
14.88	AO2 force data	(<i>Visible when 14.01 Module 1 type = FAIO-01</i>) Forced value that can be used instead of the selected output signal. See parameter <i>14.71 AO force selection</i> .	0.000 mA
	0.000 22.000 mA	Forced value of analog output AO2.	1000 = 1 mA
14.89	AO2 filter time	(<i>Visible when 14.01 Module 1 type = FAIO-01</i>) Defines the filtering time constant for analog output AO2. See parameter <i>14.79 AO1 filter time</i> .	0.100 s
	0.000 30.000 s	Filter time constant.	1000 = 1 s
14.90	AO2 source min	(Visible when 14.01 Module 1 type = FAIO-01) Defines the real value of the signal (selected by parameter 14.87 AO2 source) that corresponds to the minimum AO2 output value (defined by parameter 14.92 AO2 out at AO2 src min). I_{AO2} (mA) 14.92 I_{AO2} (mA) I_{AO2} (mA)	0.0
	-32768.0	Real signal value corresponding to minimum AO2 output	1 = 1
	32767.0	value.	

No.	Name/Value	Description	Def/FbEq16
14.91	AO2 source max	(Visible when 14.01 Module 1 type = FAIO-01) Defines the real value of the signal (selected by parameter 14.87 AO2 source) that corresponds to the maximum AO2 output value (defined by parameter 14.93 AO2 out at AO2 src max). See parameter 14.90 AO2 source min.	100.0
	-32768.0 32767.0	Real signal value corresponding to maximum AO2 output value.	1 = 1
14.92	AO2 out at AO2 src min	(<i>Visible when 14.01 Module 1 type = FAIO-01</i>) Defines the minimum output value for analog output AO2. See also drawing at parameter <i>14.90 AO2 source min</i> .	0.000 mA
	0.000 22.000 mA	Minimum AO2 output value.	1000 = 1 mA
14.93	AO2 out at AO2 src max	(Visible when 14.01 Module 1 type = FAIO-01) Defines the maximum output value for analog output AO2. See also drawing at parameter 14.90 AO2 source min.	10.000 mA
	0.000 22.000 mA	Maximum AO2 output value.	1000 = 1 mA

<i>15 I/O extension module 2</i>		Configuration of I/O extension module 2. See also section Programmable I/O extensions (page 62). Note: The contents of the parameter group vary according to the selected I/O extension module type.	
15.01	Module 2 type	See parameter 14.01 Module 1 type.	None
15.02	Module 2 location	See parameter 14.02 Module 1 location.	Slot 1
15.03	Module 2 status	See parameter 14.03 Module 1 status.	No option
15.05	DI status	(Visible when 15.01 Module 2 type = FIO-01 or FIO-11) See parameter 14.05 DI status.	-
15.05	DIO status	(Visible when 15.01 Module 2 type = FIO-01 or FIO-11) See parameter 14.05 DIO status.	-
15.06	DIO delayed status	(Visible when 15.01 Module 2 type = FDIO-01) See parameter 14.06 DIO delayed status.	-
15.06	DIO delayed status	(Visible when 15.01 Module 2 type = FIO-01 or FIO-11) See parameter 14.06 DIO delayed status.	-
15.08	DI filter time	(Visible when 15.01 Module 2 type = FDIO-01) See parameter 14.08 DI filter time.	10.0 ms
15.08	DIO filter time	(Visible when 15.01 Module 2 type = FIO-01 or FIO-11) See parameter 14.08 DIO filter time.	10.0 ms
15.09	DIO1 function	(Visible when 15.01 Module 2 type = FIO-01 or FIO-11) See parameter 14.09 DIO1 function.	Input
15.11	DIO1 output source	(Visible when 15.01 Module 2 type = FIO-01 or FIO-11) See parameter 14.11 DIO1 output source.	Not energized
15.12	DI1 ON delay	(Visible when 15.01 Module 2 type = FDIO-01) See parameter 14.12 DI1 ON delay.	0.00 s
15.12	DIO1 ON delay	(Visible when 15.01 Module 2 type = FIO-01 or FIO-11) See parameter 14.12 DIO1 ON delay.	0.00 s
15.13	DI1 OFF delay	(Visible when 15.01 Module 2 type = FDIO-01) See parameter 14.13 DI1 OFF delay.	0.00 s
15.13	DIO1 OFF delay	(Visible when 15.01 Module 2 type = FIO-01 or FIO-11) See parameter 14.13 DIO1 OFF delay.	0.00 s

No.	Name/Value	Description	Def/FbEq16
15.14	DIO2 function	(Visible when 15.01 Module 2 type = FIO-01 or FIO-11) See parameter 14.14 DIO2 function.	Input
15.16	DIO2 output source	(Visible when 15.01 Module 2 type = FIO-01 or FIO-11) See parameter 14.16 DIO2 output source.	Not energized
15.17	DI2 ON delay	(<i>Visible when 15.01 Module 2 type = FDIO-01</i>) See parameter <i>14.17 DI2 ON delay</i> .	0.00 s
15.17	DIO2 ON delay	(Visible when 15.01 Module 2 type = FIO-01 or FIO-11) See parameter 14.17 DIO2 ON delay.	0.00 s
15.18	DI2 OFF delay	(Visible when 15.01 Module 2 type = FDIO-01) See parameter 14.18 DI2 OFF delay.	0.00 s
15.18	DIO2 OFF delay	(Visible when 15.01 Module 2 type = FIO-01 or FIO-11) See parameter 14.18 DIO2 OFF delay.	0.00 s
15.19	DIO3 function	(Visible when 15.01 Module 2 type = FIO-01) See parameter 14.19 DIO3 function.	Input
15.19	AI supervision function	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.19 AI supervision function.	No action
15.20	AI supervision selection	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.20 AI supervision selection.	0000 0000b
15.21	DIO3 output source	(Visible when 15.01 Module 2 type = FIO-01) See parameter 14.21 DIO3 output source.	Not energized
15.21	Al tune	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.21 AI tune.	No action
15.22	DI3 ON delay	(Visible when 15.01 Module 2 type = FDIO-01) See parameter 14.22 DI3 ON delay.	0.00 s
15.22	DIO3 ON delay	(Visible when 15.01 Module 2 type = FIO-01) See parameter 14.22 DIO3 ON delay.	0.00 s
15.22	Al force selection	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.22 AI force selection.	0000b
15.23	DI3 OFF delay	(Visible when 15.01 Module 2 type = FDIO-01) See parameter 14.23 DI3 OFF delay.	0.00 s
15.23	DIO3 OFF delay	(Visible when 15.01 Module 2 type = FIO-01) See parameter 14.23 DIO3 OFF delay.	0.00 s
15.24	DIO4 function	(Visible when 15.01 Module 2 type = FIO-01) See parameter 14.24 DIO4 function.	Input
15.26	DIO4 output source	(Visible when 15.01 Module 2 type = FIO-01) See parameter 14.26 DIO4 output source.	Not energized
15.26	Al1 actual value	(<i>Visible when 15.01 Module 2 type = FIO-11 or FAIO-01</i>) See parameter <i>14.26 AI1 actual value</i> .	-
15.27	DIO4 ON delay	(<i>Visible when 15.01 Module 2 type = FIO-01</i>) See parameter <i>14.27 DIO4 ON delay</i> .	0.00 s
15.27	Al1 scaled value	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.27 AI1 scaled value.	-
15.28	DIO4 OFF delay	(Visible when 15.01 Module 2 type = FIO-01) See parameter 14.28 DIO4 OFF delay.	0.00 s
15.28	Al1 force data	(<i>Visible when 15.01 Module 2 type = FIO-11 or FAIO-01</i>) See parameter <i>14.28 AI1 force data</i> .	0.000 mA

No.	Name/Value	Description	Def/FbEq16
15.29	AI1 HW switch position	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.29 AI1 HW switch position.	-
15.30	Al1 unit selection	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.30 Al1 unit selection.	mA
15.31	RO status	(Visible when 15.01 Module 2 type = FIO-01 or FDIO-01) See parameter 14.31 RO status.	-
15.31	Al1 filter gain	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.31 AI1 filter gain.	1 ms
15.32	Al1 filter time	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.32 AI1 filter time.	0.100 s
15.33	Al1 min	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.33 Al1 min.	0.000 mA or V
15.34	RO1 source	(Visible when 15.01 Module 2 type = FIO-01 or FDIO-01) See parameter 14.34 RO1 source.	Not energized
15.34	Al1 max	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.34 Al1 max.	10.000 mA or V
15.35	RO1 ON delay	(Visible when 15.01 Module 2 type = FIO-01 or FDIO-01) See parameter 14.35 RO1 ON delay.	0.00 s
15.35	Al1 scaled at Al1 min	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.35 AI1 scaled at AI1 min.	0.000
15.36	RO1 OFF delay	(Visible when 15.01 Module 2 type = FIO-01 or FDIO-01) See parameter 14.36 RO1 OFF delay.	0.00 s
15.36	Al1 scaled at Al1 max	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.36 AI1 scaled at AI1 max.	100.000
15.37	RO2 source	(Visible when 15.01 Module 2 type = FIO-01 or FDIO-01) See parameter 14.37 RO2 source.	Not energized
15.38	RO2 ON delay	(Visible when 15.01 Module 2 type = FIO-01 or FDIO-01) See parameter 14.38 RO2 ON delay.	0.00 s
15.39	RO2 OFF delay	(Visible when 15.01 Module 2 type = FIO-01 or FDIO-01) See parameter 14.39 RO2 OFF delay.	0.00 s
15.41	Al2 actual value	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.41 AI2 actual value.	-
15.42	AI2 scaled value	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.42 AI2 scaled value.	-
15.43	AI2 force data	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.43 AI2 force data.	0.000 mA
15.44	AI2 HW switch position	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.44 AI2 HW switch position.	-
15.45	AI2 unit selection	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.45 AI2 unit selection.	mA
15.46	AI2 filter gain	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.46 AI2 filter gain.	1 ms
15.47	AI2 filter time	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.47 AI2 filter time.	0.100 s
15.48	AI2 min	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.48 AI2 min.	0.000 mA or V

No.	Name/Value	Description	Def/FbEq16
15.49	Al2 max	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.49 AI2 max.	10.000 mA or V
15.50	AI2 scaled at AI2 min	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.50 AI2 scaled at AI2 min.	0.000
15.51	AI2 scaled at AI2 max	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.51 AI2 scaled at AI2 max.	100.000
15.56	Al3 actual value	(<i>Visible when 15.01 Module 2 type = FIO-11</i>) See parameter <i>14.56 AI3 actual value</i> .	-
15.57	AI3 scaled value	(<i>Visible when 15.01 Module 2 type = FIO-11</i>) See parameter <i>14.57 AI3 scaled value</i> .	-
15.58	AI3 force data	(Visible when 15.01 Module 2 type = FIO-11) See parameter 14.58 AI3 force data.	0.000 mA
15.59	AI3 HW switch position	(Visible when 15.01 Module 2 type = FIO-11) See parameter 14.59 AI3 HW switch position.	-
15.60	AI3 unit selection	(Visible when 15.01 Module 2 type = FIO-11) See parameter 14.60 AI3 unit selection.	mA
15.61	AI3 filter gain	(Visible when 15.01 Module 2 type = FIO-11) See parameter 14.61 AI3 filter gain.	1 ms
15.62	AI3 filter time	(Visible when 15.01 Module 2 type = FIO-11) See parameter 14.62 AI3 filter time.	0.100 s
15.63	AI3 min	(Visible when 15.01 Module 2 type = FIO-11) See parameter 14.63 AI3 min.	0.000 mA or V
15.64	AI3 max	(Visible when 15.01 Module 2 type = FIO-11) See parameter 14.64 AI3 max.	10.000 mA or V
15.65	AI3 scaled at AI3 min	(Visible when 15.01 Module 2 type = FIO-11) See parameter 14.65 AI3 scaled at AI3 min.	0.000
15.66	AI3 scaled at AI3 max	(Visible when 15.01 Module 2 type = FIO-11) See parameter 14.66 AI3 scaled at AI3 max.	100.000
15.71	AO force selection	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.71 AO force selection.	00b
15.76	AO1 actual value	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.76 AO1 actual value.	-
15.77	AO1 source	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.77 AO1 source.	Zero
15.78	AO1 force data	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.78 AO1 force data.	0.000 mA
15.79	AO1 filter time	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.79 AO1 filter time.	0.100 s
15.80	AO1 source min	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.80 AO1 source min.	0.0
15.81	AO1 source max	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.81 AO1 source max.	100.0
15.82	AO1 out at AO1 src min	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.82 AO1 out at AO1 src min.	0.000 mA
15.83	AO1 out at AO1 src max	(Visible when 15.01 Module 2 type = FIO-11 or FAIO-01) See parameter 14.83 AO1 out at AO1 src max.	10.000 mA

No.	Name/Value	Description	Def/FbEq16
15.86	AO2 actual value	(Visible when 15.01 Module 2 type = FAIO-01) See parameter 14.86 AO2 actual value.	-
15.87	AO2 source	(Visible when 15.01 Module 2 type = FAIO-01) See parameter 14.87 AO2 source.	Zero
15.88	AO2 force data	(Visible when 15.01 Module 2 type = FAIO-01) See parameter 14.88 AO2 force data.	0.000 mA
15.89	AO2 filter time	(Visible when 15.01 Module 2 type = FAIO-01) See parameter 14.89 AO2 filter time.	0.100 s
15.90	AO2 source min	(Visible when 15.01 Module 2 type = FAIO-01) See parameter 14.90 AO2 source min.	0.0
15.91	AO2 source max	(Visible when 15.01 Module 2 type = FAIO-01) See parameter 14.91 AO2 source max.	100.0
15.92	AO2 out at AO2 src min	(Visible when 15.01 Module 2 type = FAIO-01) See parameter 14.92 AO2 out at AO2 src min.	0.000 mA
15.93	AO2 out at AO2 src max	(Visible when 15.01 Module 2 type = FAIO-01) See parameter 14.93 AO2 out at AO2 src max.	10.000 mA
16 I/O modul	extension e 3	Configuration of I/O extension module 3. See also section <i>Programmable I/O extensions</i> (page 62). Note: The contents of the parameter group vary according to the selected I/O extension module type.	
16.01	Module 3 type	See parameter 14.01 Module 1 type.	None
16.02	Module 3 location	See parameter 14.02 Module 1 location.	Slot 1
16.03	Module 3 status	See parameter 14.03 Module 1 status.	No option
16.05	DI status	(Visible when 16.01 Module 3 type = FDIO-01) See parameter 14.05 DI status.	-
16.05	DIO status	(Visible when 16.01 Module 3 type = FIO-01 or FIO-11) See parameter 14.05 DIO status.	-
16.06	DI delayed status	(Visible when 16.01 Module 3 type = FDIO-01) See parameter 14.06 DI delayed status.	-
16.06	DIO delayed status	(Visible when 16.01 Module 3 type = FIO-01 or FIO-11) See parameter 14.06 DIO delayed status.	-
16.08	DI filter time	(Visible when 16.01 Module 3 type = FDIO-01) See parameter 14.08 DI filter time.	10.0 ms
16.08	DIO filter time	(Visible when 16.01 Module 3 type = FIO-01 or FIO-11) See parameter 14.08 DIO filter time.	10.0 ms
16.09	DIO1 function	(Visible when 16.01 Module 3 type = FIO-01 or FIO-11) See parameter 14.09 DIO1 function.	Input
16.11	DIO1 output source	(Visible when 16.01 Module 3 type = FIO-01 or FIO-11) See parameter 14.11 DIO1 output source.	Not energized
16.12	DI1 ON delay	(Visible when 16.01 Module 3 type = FDIO-01) See parameter 14.12 DI1 ON delay.	0.00 s
16.12	DIO1 ON delay	(Visible when 16.01 Module 3 type = FIO-01 or FIO-11) See parameter 14.12 DIO1 ON delay.	0.00 s
16.13	DI1 OFF delay	(Visible when 16.01 Module 3 type = FDIO-01) See parameter 14.13 DI1 OFF delay.	0.00 s

No.	Name/Value	Description	Def/FbEq16
16.13	DIO1 OFF delay	(Visible when 16.01 Module 3 type = FIO-01 or FIO-11) See parameter 14.13 DIO1 OFF delay.	0.00 s
16.14	DIO2 function	(Visible when 16.01 Module 3 type = FIO-01 or FIO-11) See parameter 14.14 DIO2 function.	Input
16.16	DIO2 output source	(Visible when 16.01 Module 3 type = FIO-01 or FIO-11) See parameter 14.16 DIO2 output source.	Not energized
16.17	DI2 ON delay	(Visible when 16.01 Module 3 type = FDIO-01) See parameter 14.17 DI2 ON delay.	0.00 s
16.17	DIO2 ON delay	(Visible when 16.01 Module 3 type = FIO-01 or FIO-11) See parameter 14.17 DIO2 ON delay.	0.00 s
16.18	DI2 OFF delay	(Visible when 16.01 Module 3 type = FDIO-01) See parameter 14.18 DI2 OFF delay.	0.00 s
16.18	DIO2 OFF delay	(Visible when 16.01 Module 3 type = FIO-01 or FIO-11) See parameter 14.18 DIO2 OFF delay.	0.00 s
16.19	DIO3 function	(Visible when 16.01 Module 3 type = FIO-01) See parameter 14.19 DIO3 function.	Input
16.19	AI supervision function	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.19 AI supervision function.	No action
16.20	AI supervision selection	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.20 AI supervision selection.	0000 0000b
16.21	DIO3 output source	(Visible when 16.01 Module 3 type = FIO-01) See parameter 14.21 DIO3 output source.	Not energized
16.21	Al tune	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.21 AI tune.	No action
16.22	DI3 ON delay	(Visible when 16.01 Module 3 type = FDIO-01) See parameter 14.22 DI3 ON delay.	0.00 s
16.22	DIO3 ON delay	(Visible when 16.01 Module 3 type = FIO-01) See parameter 14.22 DIO3 ON delay.	0.00 s
16.22	Al force selection	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.22 AI force selection.	0000b
16.23	DI3 OFF delay	(Visible when 16.01 Module 3 type = FDIO-01) See parameter 14.23 DI3 OFF delay.	0.00 s
16.23	DIO3 OFF delay	(Visible when 16.01 Module 3 type = FIO-01) See parameter 14.23 DIO3 OFF delay.	0.00 s
16.24	DIO4 function	(Visible when 16.01 Module 3 type = FIO-01) See parameter 14.24 DIO4 function.	Input
16.26	DIO4 output source	(Visible when 16.01 Module 3 type = FIO-01) See parameter 14.26 DIO4 output source.	Not energized
16.26	Al1 actual value	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.26 Al1 actual value.	-
16.27	DIO4 ON delay	(Visible when 16.01 Module 3 type = FIO-01) See parameter 14.27 DIO4 ON delay.	0.00 s
16.27	Al1 scaled value	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.27 Al1 scaled value.	-
16.28	DIO4 OFF delay	(Visible when 16.01 Module 3 type = FIO-01) See parameter 14.28 DIO4 OFF delay.	0.00 s

No.	Name/Value	Description	Def/FbEq16
16.28	Al1 force data	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.28 Al1 force data.	0.000 mA
16.29	AI1 HW switch position	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.29 AI1 HW switch position.	-
16.30	Al1 unit selection	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.30 Al1 unit selection.	mA
16.31	RO status	(Visible when 16.01 Module 3 type = FIO-11 or FDIO-01) See parameter 14.31 RO status.	-
16.31	Al1 filter gain	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.31 AI1 filter gain.	1 ms
16.32	Al1 filter time	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.32 AI1 filter time.	0.100 s
16.33	Al1 min	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.33 Al1 min.	0.000 mA or V
16.34	RO1 source	(Visible when 16.01 Module 3 type = FIO-01) See parameter 14.34 RO1 source.	Not energized
16.34	Al1 max	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.34 Al1 max.	10.000 mA or V
16.35	RO1 ON delay	(Visible when 16.01 Module 3 type = FIO-01) See parameter 14.35 RO1 ON delay.	0.00 s
16.35	Al1 scaled at Al1 min	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.35 AI1 scaled at AI1 min.	0.000
16.36	RO1 OFF delay	(Visible when 16.01 Module 3 type = FIO-01) See parameter 14.36 RO1 OFF delay.	0.00 s
16.36	Al1 scaled at Al1 max	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.36 AI1 scaled at AI1 max.	100.000
16.37	RO2 source	(Visible when 16.01 Module 3 type = FIO-01 or FDIO-01) See parameter 14.37 RO2 source.	Not energized
16.38	RO2 ON delay	(Visible when 16.01 Module 3 type = FIO-01) See parameter 14.38 RO2 ON delay.	0.00 s
16.39	RO2 OFF delay	(Visible when 16.01 Module 3 type = FIO-01) See parameter 14.39 RO2 OFF delay.	0.00 s
16.41	Al2 actual value	(Visible when 16.01 Module 3 type = FIO-11) See parameter 14.41 AI2 actual value.	-
16.42	AI2 scaled value	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.42 AI2 scaled value.	-
16.43	AI2 force data	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.43 AI2 force data.	0.000 mA
16.44	AI2 HW switch position	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.44 AI2 HW switch position.	-
16.45	AI2 unit selection	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.45 AI2 unit selection.	mA
16.46	AI2 filter gain	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.46 AI2 filter gain.	1 ms
16.47	AI2 filter time	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.47 AI2 filter time.	0.100 s

No.	Name/Value	Description	Def/FbEq16
16.48	AI2 min	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.48 AI2 min.	0.000 mA or V
16.49	Al2 max	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.49 AI2 max.	10.000 mA or V
16.50	AI2 scaled at AI2 min	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.50 AI2 scaled at AI2 min.	0.000
16.51	AI2 scaled at AI2 max	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.51 AI2 scaled at AI2 max.	100.000
16.56	Al3 actual value	(<i>Visible when 16.01 Module 3 type = FIO-11</i>) See parameter <i>14.56 AI3 actual value</i> .	-
16.57	AI3 scaled value	(Visible when 16.01 Module 3 type = FIO-11) See parameter 14.57 AI3 scaled value.	-
16.58	AI3 force data	(Visible when 16.01 Module 3 type = FIO-11) See parameter 14.58 AI3 force data.	0.000 mA
16.59	AI3 HW switch position	(Visible when 16.01 Module 3 type = FIO-11) See parameter 14.59 AI3 HW switch position.	-
16.60	AI3 unit selection	(Visible when 16.01 Module 3 type = FIO-11) See parameter 14.60 AI3 unit selection.	mA
16.61	AI3 filter gain	(Visible when 16.01 Module 3 type = FIO-11) See parameter 14.61 AI3 filter gain.	1 ms
16.62	AI3 filter time	(Visible when 16.01 Module 3 type = FIO-11) See parameter 14.62 AI3 filter time.	0.100 s
16.63	AI3 min	(Visible when 16.01 Module 3 type = FIO-11) See parameter 14.63 AI3 min.	0.000 mA or V
16.64	Al3 max	(Visible when 16.01 Module 3 type = FIO-11) See parameter 14.64 AI3 max.	10.000 mA or V
16.65	AI3 scaled at AI3 min	(Visible when 16.01 Module 3 type = FIO-11) See parameter 14.65 AI3 scaled at AI3 min.	0.000
16.66	AI3 scaled at AI3 max	(Visible when 16.01 Module 3 type = FIO-11) See parameter 14.66 AI3 scaled at AI3 max.	100.000
16.71	AO force selection	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.71 AO force selection.	00b
16.76	AO1 actual value	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.76 AO1 actual value.	-
16.77	AO1 source	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.77 AO1 source.	Zero
16.78	AO1 force data	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.78 AO1 force data.	0.000 mA
16.79	AO1 filter time	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.79 AO1 filter time.	0.100 s
16.80	AO1 source min	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.80 AO1 source min.	0.0
16.81	AO1 source max	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.81 AO1 source max.	100.0
16.82	AO1 out at AO1 src min	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.82 AO1 out at AO1 src min.	0.000 mA

No.	Name/Value	Description	Def/FbEq16
16.83	AO1 out at AO1 src max	(Visible when 16.01 Module 3 type = FIO-11 or FAIO-01) See parameter 14.83 AO1 out at AO1 src max.	10.000 mA
16.86	AO2 actual value	(Visible when 16.01 Module 3 type = FAIO-01) See parameter 14.86 AO2 actual value.	-
16.87	AO2 source	(Visible when 16.01 Module 3 type = FAIO-01) See parameter 14.87 AO2 source.	Zero
16.88	AO2 force data	(Visible when 16.01 Module 3 type = FAIO-01) See parameter 14.88 AO2 force data.	0.000 mA
16.89	AO2 filter time	(Visible when 16.01 Module 3 type = FAIO-01) See parameter 14.89 AO2 filter time.	0.100 s
16.90	AO2 source min	(Visible when 16.01 Module 3 type = FAIO-01) See parameter 14.90 AO2 source min.	0.0
16.91	AO2 source max	(Visible when 16.01 Module 3 type = FAIO-01) See parameter 14.91 AO2 source max.	100.0
16.92	AO2 out at AO2 src min	(Visible when 16.01 Module 3 type = FAIO-01) See parameter 14.92 AO2 out at AO2 src min.	0.000 mA
16.93	AO2 out at AO2 src max	(Visible when 16.01 Module 3 type = FAIO-01) See parameter 14.93 AO2 out at AO2 src max.	10.000 mA
19 Op	eration mode	Selection of local and external control location sources and operating modes. See also section <i>Operating modes of the drive</i> (page 57).	
19.01	Actual operation mode	Displays the operating mode currently used. See parameters <i>19.1119.14</i> . This parameter is read-only.	-
	Zero	None.	1
	Speed	Speed control (in DTC motor control mode).	2
	Torque	Torque control (in DTC motor control mode).	3
	Min	The torque selector is comparing the output of the speed controller (25.01 Torque reference speed control) and torque reference (26.74 Torque ref ramp out) and the smaller of the two is used.	4
	Max	The torque selector is comparing the output of the speed controller (25.01 Torque reference speed control) and torque reference (26.74 Torque ref ramp out) and the greater of the two is used.	5
	Add	The speed controller output is added to the torque reference.	6
	Scalar (Hz)	Frequency control in scalar motor control mode.	10
	Scalar (rpm)	Speed control in scalar motor control mode.	11
	Forced magn.	Motor is in magnetizing mode.	20
19.11	Ext1/Ext2 selection	Selects the source for external control location EXT1/EXT2 selection. 0 = EXT1 1 = EXT2	EXT1
	EXT1	EXT1 (permanently selected).	0
	EXT2	EXT2 (permanently selected).	1
	FBA A MCW bit 11	Control word bit 11 received through fieldbus interface A.	2
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	3

No.	Name/Value	Description	Def/FbEq16
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	4
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	5
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	6
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	7
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	8
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	11
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	12
	EFB MCW bit 11	Control word bit 11 received through the embedded fieldbus interface.	32
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
19.12	Ext1 control mode	Selects the operating mode for external control location EXT1.	Speed
	Zero	None.	1
	Speed	Speed control. The torque reference used is 25.01 Torque reference speed control (output of the speed reference chain).	2
	Torque	Torque control. The torque reference used is 26.74 Torque ref ramp out (output of the torque reference chain).	3
	Minimum	Combination of selections <i>Speed</i> and <i>Torque</i> : the torque selector compares the speed controller output (<i>25.01 Torque reference speed control</i>) and the torque reference (<i>26.74 Torque ref ramp out</i>) and selects the smaller of the two. If speed error becomes negative, the drive follows the speed controller output until speed error becomes positive again. This prevents the drive from accelerating uncontrollably if the load is lost in torque control.	4
	Maximum	Combination of selections <i>Speed</i> and <i>Torque</i> : the torque selector compares the speed controller output (<i>25.01 Torque reference speed control</i>) and the torque reference (<i>26.74 Torque ref ramp out</i>) and selects the greater of the two. If speed error becomes positive, the drive follows the speed controller output until speed error becomes negative again. This prevents the drive from accelerating uncontrollably if the load is lost in torque control.	5
	Add	Combination of selections <i>Speed</i> and <i>Torque</i> : Torque selector adds the speed reference chain output to the torque reference chain output.	6
19.14	Ext2 control mode	Selects the operating mode for external control location EXT2. For the selections, see parameter <i>19.12 Ext1 control mode</i> .	Speed
19.16	Local control mode	Selects the operating mode for local control.	Speed
	Speed	Speed control. The torque reference used is <i>25.01 Torque reference speed control</i> (output of the speed reference chain).	0
	Torque	Torque control. The torque reference used is 26.74 Torque ref ramp out (output of the torque reference chain).	1
19.17	Local control disable	Enables/disables local control (start and stop buttons on the control panel, and the local controls on the PC tool). WARNING! Before disabling local control, ensure that the control panel is not needed for stopping the drive.	Νο

No.	Name/Value	Description			Def/FbEq16
	No	Local control enabled.			0
	Yes	Local control disabled.			1
19.20	20Scalar control reference unitSelects the reference type for scalar motor control mode.See also section Operating modes of the drive (page 57), ar parameter 99.04 Motor control mode.			Rpm	
	Hz	Hz. The reference is take ref ramp output (output of			0
	Rpm	Rpm. The reference is ta ramp output (speed refer	iken from paramete rence after ramping	er 23.02 Speed ref g and shaping).	1
20 Sta	nt/stop/direction	Start/stop/direction and r selection; positive/negati selection. For information on control vs. external control (page Note: When spinning ma 99.200 Application select group is disabled. This m cannot be generated by be changed with parameter	ive reference enab ol locations, see se e 54). acro is selected wit t, direction change neans negative spi this parameter gro	le signal source ction <i>Local control</i> h parameter function in this nning reference up. Direction can	
20.01	Ext1 commands	<i>mmands</i> Selects the source of start, stop and direction commands for external control location 1 (EXT1). See also parameters 20.0220.05.		on commands for	In1 Start
	Not selected	No start or stop comman	0		
	In1 Start	The source of the start a parameter 20.03 Ext1 in source bits are interpretered. State of source 1 (20. 0 -> 1 (20.02 = Edge 1 (20.02 = Level) 0	1 source. The stateed as follows:03)Command		1
In1 Start; In2 Dir		The source selected by a signal; the source select determines the direction bits are interpreted as fo	ed by 20.04 Ext1 in . The state transition	n2 source	2
		State of source 1 (20.03)	State of source (20.04)	Command	
		0	Any	Stop	
		$0 \rightarrow 1 (20.02 = Edge)$	0	Start forward	
		1 (20.02 = Level)	1	Start reverse	

No.	Name/Value	Description				Def/FbEq16
	In1 Start fwd; In2 Start rev	The source selected start signal; the sour the reverse start sigr bits are interpreted a	ce selecte nal. The st	d by 20.04 Ext1	in2 source is	3
		State of source 7 (20.03)	I Sta	te of source 2 (20.04)	Command	
		0		0	Stop	
		0 -> 1 (20.02 = Edg 1 (20.02 = Level)		0	Start forward	
		0		(20.02 = Edge 20.02 = Level)	⁽⁾ Start reverse	
		1		1	Stop	
	In1P Start; In2 Stop	The sources of the s parameters 20.03 Ex The state transitions follows:	t1 in1 sou	rce and 20.04 E	xt1 in2 source.	4
		State of source 1 (20.03)		of source 2 (<u>20.04</u>)	Command	
		0 -> 1		1	Start	
		Any		0	Stop	
	In1P Start; In2 Stop;	Note: The start signa setting regardless of The sources of the s	paramete	r 20.02 Ext1 sta	art trigger type.	5
	In3 Dir	parameters 20.03 Ex The source selected direction. The state t interpreted as follows	<i>Ext1 in2 source</i> . determines the			
		source 1 so	tate of ource 2 20.04)	State of source 3 (20.05)	Command	
		0 -> 1	1	0	Start forward	
		0 -> 1	1	1	Start reverse	
		Any	0	Any	Stop	
		Note: The start signa setting regardless of				
	In1P Start fwd; In2P Start rev; In3 Stop	The sources of the s parameters 20.03 Ex 20.05 Ext1 in3 sourc are interpreted as fol	t <mark>t1 in1 sou</mark> e. The sta	rce, 20.04 Ext1	in2 source and	6
		source 1 so	tate of ource 2 20.04)	State of source 3 (20.05)	Command	
		0 -> 1	Any	1	Start forward	
		,	0 -> 1	1	Start reverse	
		1.0.0	Any	n n	Ston	
		Any Note: The start signal setting regardless of	al is alway			

No.	Name/Value	Description	Def/FbEq16
	Fieldbus A	The start and stop commands are taken from fieldbus adapter A. Note: The start signal is always level-triggered with this setting regardless of parameter <i>20.02 Ext1 start trigger type</i> .	12
	Embedded fieldbus	The start and stop commands are taken from the embedded fieldbus interface. Note: The start signal is always level-triggered with this setting regardless of parameter <i>20.02 Ext1 start trigger type</i> .	14
	M/F link	The start and stop commands are taken from another drive through the drive-to-drive link or the master/follower link. Note: The start signal is always level-triggered with this setting regardless of parameter <i>20.02 Ext1 start trigger type</i> .	15
	DDCS controller	The start and stop commands are taken from an external (DDCS) controller. Note: The start signal is always level-triggered with this setting regardless of parameter <i>20.02 Ext1 start trigger type</i> .	16
	Application Program	The start and stop commands are taken from the application program control word (parameter <i>06.02 Application control word</i>). Note: The start signal is always level-triggered with this setting regardless of parameter <i>20.02 Ext1 start trigger type</i> .	21
	ATF	Reserved.	22
20.02	Ext1 start trigger type	Defines whether the start signal for external control location EXT1 is edge-triggered or level-triggered. Note: This parameter is only effective when parameter 20.01 <i>Ext1 commands</i> is set to <i>In1 Start</i> , <i>In1 Start</i> ; <i>In2 Dir</i> or <i>In1</i> <i>Start fwd</i> ; <i>In2 Start rev</i> , or <i>Control panel</i> .	Edge
	Edge	The start signal is edge-triggered.	0
	Level	The start signal is level-triggered.	1
20.03	Ext1 in1 source	Selects source 1 for parameter 20.01 Ext1 commands.	DI1
	Not selected	0 (always off).	0
	Selected	1 (always on).	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
20.04	Ext1 in2 source	Selects source 2 for parameter 20.01 Ext1 commands. For the available selections, see parameter 20.03 Ext1 in1 source.	DI1
20.05	Ext1 in3 source	Selects source 3 for parameter 20.01 Ext1 commands. For the available selections, see parameter 20.03 Ext1 in1 source.	Not selected

No.	Name/Value	Description				Def/FbEq16
20.06	Ext2 commands	Selects the source of sta external control location See also parameters 20	2 (E)	ΚT2).	n commands for	Not selected
	Not selected	No start or stop comma	nd so	urces selected.		0
	In1 Start	The source of the start a parameter 20.08 Ext2 in source bits are interpret	11 sol	rce. The state		1
		State of source 1 (20	-	Command		
		0 -> 1 (20.07 = Edg		Start		
		1 (20.07 = Level)		Stop		
				Stop		
	In1 Start; In2 Dir	The source selected by signal; the source selec determines the direction bits are interpreted as fo	ted by 1. The	20.09 Ext2 in: state transition	2 source	2
		State of source 1 <i>(20.08)</i>	Sta	te of source 2 (20.09)	Command	
		0		Any	Stop	
		0 -> 1 (20.07 = Edge)		0	Start forward	
		1 (20.07 = Level)		1	Start reverse	
In1 Start fwd; In2 Start rev		The source selected by start signal; the source s the reverse start signal. bits are interpreted as fo	3			
		State of source 1 (20.08)	St	ate of source : (20.09)	2 Command	
		0		0	Stop	
		0 -> 1 (20.07 = Edge) 1 (20.07 = Level)		0	Start forward	
		0		1 (20.07 = Edg (20.07 = Level		
		1		1	Stop	
	In1P Start; In2 Stop	The sources of the start parameters 20.08 Ext2 i The state transitions of follows:	in1 so	urce and 20.09	Ext2 in2 source.	4
		State of source 1 (20.08)	State	e of source 2 (20.09)	Command	
		0 -> 1		1	Start	
		Any		0	Stop	
		Note: The start signal is setting regardless of pa				

No.	Name/Value	Description				Def/FbEq16	
	In1P Start; In2 Stop; In3 Dir	parameters 20.	08 Ext2 in1 sou ected by 20.10 i tate transitions	rce and 20.09 Ext2 in3 source	are selected by <i>Ext2 in2 source</i> . e determines the bits are	5	
		State of source 1 (20.08)	State of source 2 (20.09)	State of source 3 (20.10)	Command		
		0 -> 1	1	0	Start forward		
		0 -> 1	1	1	Start reverse		
		Any	0	Any	Stop		
		Note: The start setting regardle			ed with this tart trigger type.		
	In1P Start fwd; In2P Start rev; In3 Stop	parameters 20.	08 Ext2 in1 sou source. The sta	rce, 20.09 Ext	are selected by 2 <i>in2 source</i> and of the source bits	6	
		State of source 1 (20.08)	State of source 2 <i>(</i> 20.09)	State of source 3 (20.10)	Command		
		0 -> 1	Any	1	Start forward		
		Any	0 -> 1	1	Start reverse		
		Any Note: The start	Any signal is alway	0	Stop		
					tart trigger type.		
	Control panel	The start and st panel.	top commands	are taken fron	the control	11	
	Fieldbus A	A. Note: The start	signal is alway	s level-trigger	fieldbus adapter ed with this <i>tart trigger type</i> .	12	
	Embedded fieldbus	fieldbus interfact Note: The start	e. signal is alway	s level-trigger	n the embedded ed with this <i>tart trigger type</i> .	14	
	M/F link	The start and st through the driv Note: The start setting regardle	15				
	DDCS controller	The start and st (DDCS) control Note: The start setting regardle	ler. signal is alway	s level-trigger		16	
	Application Program	program contro <i>word</i>). Note: The start	l word (parame signal is alway	ter 06.02 Appl s level-trigger		21	
	ATF	Reserved.				22	

No.	Name/Value	Description	Def/FbEq16
20.07	Ext2 start trigger type	 Defines whether the start signal for external control location EXT2 is edge-triggered or level-triggered. Note: This parameter is only effective when parameter 20.06 <i>Ext2 commands</i> is set to <i>In1 Start</i>, <i>In1 Start</i>; <i>In2 Dir</i> or <i>In1 Start fwd; In2 Start rev</i>, or <i>Control panel</i>. 	Edge
	Edge	The start signal is edge-triggered.	0
	Level	The start signal is level-triggered.	1
20.08	Ext2 in1 source	Selects source 1 for parameter 20.06 Ext2 commands. For the available selections, see parameter 20.03 Ext1 in1 source.	Not selected
20.09	Ext2 in2 source	<i>urce</i> Selects source 2 for parameter <i>20.06 Ext2 commands</i> . For the available selections, see parameter <i>20.03 Ext1 in1 source</i> .	
20.10	20.10 Ext2 in3 source Selects source 3 for parameter 20.06 Ext2 commands. For the available selections, see parameter 20.03 Ext1 in1 source.		Not selected
20.11	Run enable stop mode	Selects the way the motor is stopped when the run enable signal switches off. The source of the run enable signal is selected by parameter 20.12 Run enable 1 source.	Coast (95.20 b10)
	Coast	Stop by switching off the output semiconductors of the drive. The motor coasts to a stop. WARNING! If a mechanical brake is used, ensure it is safe to stop the drive by coasting.	0
	Ramp	Stop along the active deceleration ramp. See parameter group 23 Speed reference ramp on page 242.	1
	Torque limit	Stop according to torque limits (parameters 30.19 and 30.20).	2
20.12	Run enable 1 source	Selects the source of the external run enable signal. If the run enable signal is switched off, the drive will not start. If already running, the drive will stop according to the setting of parameter 20.11 Run enable stop mode 1 = Run enable signal on. Note: The warning that indicates a missing signal can be suppressed using parameter 20.30 Enable signals warning function. See also parameter 20.19 Enable start command.	DIIL (95.20 b10); Selected (95.20 b5); DI5 (95.20 b9)
	Not selected	0.	0
	Selected	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	FBAA MCW bit 3	Control word bit 3 received through fieldbus interface A.	30
	EFB MCW bit 3	Control word bit 3 received through the embedded fieldbus interface.	32

No.	Name/Value	Description	Def/FbEq16
	DIIL	DIIL input (10.02 DI delayed status, bit 15).	33
	Active control source MCW bit 3	 Control word bit 3 received from the active control source. Notes: If the drive is running in fieldbus control, switching bit 3 off effectively removes both the start and run enable signals. In this case, the stop mode is determined by either 20.11 Run enable stop mode or 21.03 Stop mode, whichever mode has higher priority. The order of stop modes from highest to lowest priority is Coast – Torque limit – Ramp. In case the active source is the control panel, PC tool or drive I/O, the run enable signal is always on. 	34
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
20.19			-
	Not selected	0.	0
	Selected	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	DIIL	DIIL input (10.02 DI delayed status, bit 15).	30
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-

No.	Name/Value	Description	Def/FbEq16
20.23	Positive speed enable	Selects the source of the positive speed enable command. 1 = Positive speed enabled. 0 = Positive speed interpreted as zero speed reference. In the figure below, 23.01 Speed ref ramp input is set to zero after the positive speed enable signal has cleared. Actions in different control modes: Speed control: Speed reference is set to zero and the motor ramps down along the currently active deceleration ramp. The drive keeps modulating. The rush controller prevents additional torque terms from running the motor in the positive direction. Torque control: The rush controller monitors the rotation direction of the motor.	Selected
	20.23 Positive spe	ed enable	
	20.24 Negative spe	ed enable	
	23.01 Speed ref ra	amp input	
	01.01 Motor spe	eed used	
	Not selected	0.	0
	Selected	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
20.24	Negative speed enable	Selects the source of the negative speed reference enable command. See parameter 20.23 Positive speed enable.	Selected

No.	Name/Value	Description	Def/FbEq16
20.25	Jogging enable	Selects the source for a jog enable signal. (The sources for jogging activation signals are selected by parameters 20.26 Jogging 1 start source and 20.27 Jogging 2 start source.)	Not selected
		1 = Jogging is enabled. 0 = Jogging is disabled.	
		Note: Jogging can be enabled only when no start command from an external control location is active. On the other hand, if jogging is already enabled, the drive cannot be started from an external control location (apart from inching commands through fieldbus). See section <i>Jogging</i> (page <i>89</i>).	
	Not selected	0.	0
	Selected	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
20.26	Jogging 1 start source	If enabled by parameter 20.25 Jogging enable, selects the source for the activation of jogging function 1. (Jogging function 1 can also be activated through fieldbus regardless of parameter 20.25.) 1 = Jogging 1 active. Note: If both jogging 1 and 2 are activated, the one that was activated first has priority.	Not selected
	Not selected	0.	0
	Selected	1.	1
	DI1	Digital input DI1 (<i>10.02 DI delayed status</i> , bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (<i>11.02 DIO delayed status</i> , bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page <i>131</i>).	-

No.	Name/Value	Description	Def/FbEq16
20.27	Jogging 2 start source	If enabled by parameter 20.25 Jogging enable, selects the source for the activation of jogging function 2. (Jogging function 2 can also be activated through fieldbus regardless of parameter 20.25.) 1 = Jogging 2 active. For the selections, see parameter 20.26 Jogging 1 start source. Note: If both jogging 1 and 2 are activated, the one that was activated first has priority.	Not selected
20.29	Local start trigger type	Defines whether the start signal for local control (for example, control panel or PC tool) is edge-triggered or level-triggered.	Edge
	Edge	The start signal is edge-triggered.	0
	Level	The start signal is level-triggered.	1
20.30	Enable signals warning function	Selects enable signal (eg. run enable, start enable) warnings to be suppressed. This parameter can be used to prevent these warnings from flooding the event log. Whenever a bit of this parameter is set to 1, the corresponding warning is suppressed, ie. no warning is generated even if the signal is switched off. The bits of this binary number correspond to the following warnings:	11b

Bit	Name	Warning	
0	Enable Start	AFEA Enable start signal missing	
1	Run enable 1	AFEB Run enable missing	
215	Reserved	•	

00b11b	Suppression of "enable signal missing" warnings.	1 = 1
21 Start/stop mode	Start and stop modes; emergency stop mode and signal	

	source selection; DC magnetization settings; autophasing mode selection.	
21.01 Start mode	 Selects the motor start function for the DTC motor control mode, ie. when 99.04 Motor control mode is set to DTC. Notes: The start function for the scalar motor control mode is selected by parameter 21.19 Scalar control mode. Starting into a rotating motor is not possible when DC magnetizing is selected (<i>Fast</i> or <i>Constant time</i>). With permanent magnet motors and synchronous reluctance motors, <i>Automatic</i> start mode must be used. This parameter cannot be changed while the drive is running. See also section <i>DC magnetization</i> (page 97). 	Automatic
Fast	The drive pre-magnetizes the motor before start. The pre- magnetizing time is determined automatically, being typically 200 ms to 2 s depending on motor size. This mode should be selected if a high break-away torque is required.	0

No.	Name/Value	Description		Def/FbEq16
	Constant time	pre-magnetizing time is requir be synchronized with the relea This setting also guarantees to torque when the pre-magnetiz WARNING! The drive magnetizing time has magnetization is not compared.	y parameter 21.02 e should be selected if constant ed (e.g. if the motor start must ase of a mechanical brake). he highest possible break-away zing time is set long enough. will start after the set passed even if motor ompleted. In applications where sential, ensure that the constant	1
	Automatic	It includes the flying start func- motor) and the automatic rest can be restarted immediately	art function (a stopped motor without waiting the motor flux to ontrol program identifies the flux te of the motor and starts the	2
	Flying start	This method is intended for as optimized for applications whe into a rotating motor at high fr		3
21.02	Magnetization time	DTC motor control mode),	le is set to <i>Constant time</i> (in or <i>ntrol mode</i> is set to <i>Const time</i> de). drive automatically he set time. To ensure full er to the same value as, or nstant. If not known, use the	500 ms
		Motor rated power	Constant magnetizing time	
		< 1 kW	≥ 50 to 100 ms	
		1 to 10 kW	<u>></u> 100 to 200 ms	
		10 to 200 kW	≥ 200 to 1000 ms	
		200 to 1000 kW	≥ 1000 to 2000 ms	
		Note: This parameter cannot running.	be changed while the drive is	
	0 10000 ms	Constant DC magnetizing tim	е.	1 = 1 ms
21.03	Stop mode	Selects the way the motor is s is received. Additional braking is possible parameter 97.05 Flux braking Note: This parameter has no master/follower configuration.). effect in a follower drive in a	Ramp
	Coast	The motor coasts to a stop.	ut semiconductors of the drive. anical brake is used, ensure it is by coasting.	0

No.	Name/Value	Description	Def/FbEq16
	Ramp	Stop along the active deceleration ramp. See parameter group 23 Speed reference ramp on page 242.	1
	Torque limit	Stop according to torque limits (parameters 30.19 and 30.20).	2
21.04	Emergency stop mode	Selects the way the motor is stopped when an emergency stop command is received. The source of the emergency stop signal is selected by parameter <i>21.05 Emergency stop source</i> .	Ramp stop (Off1); Coast stop (Off2) (95.20 b1); Eme ramp stop (Off3) (95.20 b2;
	Ramp stop (Off1)	 With the drive running: 1 = Normal operation. 0 = Normal stop along the standard deceleration ramp defined for the particular reference type (see section <i>Reference ramping</i> [page 75]). After the drive has stopped, it can be restarted by removing the emergency stop signal and switching the start signal from 0 to 1. With the drive stopped: 1 = Starting allowed. 0 = Starting not allowed. 	0
	Coast stop (Off2)	 With the drive running: 1 = Normal operation. 0 = Stop by coasting. The drive can be restarted by restoring the start interlock signal and switching the start signal from 0 to 1. With the drive stopped: 1 = Starting allowed. 0 = Starting not allowed. 	1
	Eme ramp stop (Off3)	 With the drive running: 1 = Normal operation. 0 = Stop by ramping along emergency stop ramp defined by parameter 23.23 Emergency stop time. After the drive has stopped, it can be restarted by removing the emergency stop signal and switching the start signal from 0 to 1. With the drive stopped: 1 = Starting allowed. 0 = Starting not allowed. 	2
21.05	Emergency stop source	Selects the source of the emergency stop signal. The stop mode is selected by parameter 21.04 Emergency stop mode. 0 = Emergency stop active 1 = Normal operation Note: This parameter cannot be changed while the drive is running.	Inactive (true); DI4 (95.20 b1), (95.20 b2)
	Active (false)	0.	0
	Inactive (true)	1.	1
	DIIL	DIIL input (10.02 DI delayed status, bit 15).	2
	DI1	Digital input DI1 (<i>10.02 DI delayed status</i> , bit 0).	3
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	4
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	5
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	6
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	7

No.	Name/Value	Description	Def/FbEq16
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	8
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	11
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	12
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
21.06	Zero speed limit	Defines the zero speed limit. The motor is stopped along a speed ramp (when ramped stop is selected) until the defined zero speed limit is reached. After the zero speed delay, the motor coasts to a stop.	30.00 rpm
	0.00 30000.00 rpm	Zero speed limit.	See par. 46.01
21.07	rpm Zero speed delay	Defines the delay for the zero speed delay function. The function is useful in applications where a smooth and quick restarting is essential. During the delay, the drive knows the rotor position accurately. <u>Without zero speed delay</u> : The drive receives a stop command and decelerates along a ramp. When actual motor speed falls below the value of parameter 21.06 Zero speed limit, inverter modulation is stopped and the motor coasts to a standstill. Speed Speed OFFICE Speed delay: With zero speed delay: The drive receives a stop command and decelerates along a ramp. When actual motor speed falls below the value of parameter 21.06 Zero speed limit. Notor coasts to a stop. 21.06 Zero speed limit Time With zero speed delay: The drive receives a stop command and decelerates along a ramp. When actual motor speed falls below the value of parameter 21.06 Zero speed limit, the zero speed delay function activates. During the delay the function keeps the speed controller live: the inverter modulates, motor is magnetized and the drive is ready for a quick restart. Speed Speed Speed controller remains active. Motor is decelerated to true zero speed. 21.06 Zero speed limit Time	0 ms
	0 30000 ms	Zero speed delay.	1 = 1 ms

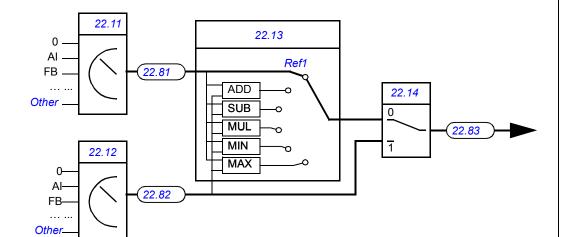
No.	Name/V	alue	Description	Def/FbEq16
21.08	DC curre	ent control	 Activates/deactivates the DC hold and post-magnetization functions. See section <i>DC magnetization</i> (page 97). Notes: These functions are only available in speed control in DTC motor control mode (see page 75). DC magnetization causes the motor to heat up. In applications where long DC magnetization times are required, externally ventilated motors should be used. If the DC magnetization period is long, DC magnetization cannot prevent the motor. 	0000b
	Bit	Value		
	0	1 = Enable	DC hold. See section <i>DC hold</i> (page 97).	
			DC hold function has no effect if the start signal is switched off.	
	1	Note: Post-	post-magnetization. See section <i>Post-magnetization</i> (page 98). magnetization is only available when ramping is the selected sto 21.03 Stop mode).	
	215	Reserved		
	0000b	.0011b	DC magnetization selection.	1 = 1
21.09	DC hold	speed	Defines the DC hold speed. See parameter 21.08 DC current control, and section DC hold (page 97).	5.00 rpm
	0.00 ⁻ rpm	1000.00	DC hold speed.	See par. 46.01
21.10	DC curre referenc		Defines the DC hold current in percent of the motor nominal current. See parameter 21.08 DC current control, and section DC magnetization (page 97).	30.0%
	0.0 10	00.0%	DC hold current.	1 = 1%
21.11	Post ma time	gnetization	Defines the length of time for which post-magnetization is active after stopping the motor. The magnetization current is defined by parameter <i>21.10 DC current reference</i> . See parameter <i>21.08 DC current control</i> .	0 s
	03000	s	Post-magnetization time.	1 = 1 s
21.12	Continuo magneti commar	zation	 Activates/deactivates (or selects a source that activates/deactivates) continuous magnetization. See section <i>Continuous magnetization</i> (page 98). The magnetization current is calculated on the basis of flux reference (see parameter group 97 <i>Motor control</i>). Notes: This function is only available when ramping is the selected stop mode (see parameter 21.03 Stop mode), and only in speed control in DTC motor control mode (see page 57). Continuous magnetization causes the motor to heat up. In applications where long magnetization times are required, externally ventilated motors should be used. Continuous magnetization may not be able to prevent the motor shaft from rotating during a long period if a constant load is applied to the motor. 	Off
	Off		0.	0

No.	Name/Value	Description	Def/FbEq16
	On	1.	1
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
21.13	Autophasing mode	Selects the way autophasing is performed. See section <i>Parameter group 28 Frequency reference chain</i> (page 270). on page 92.	Turning
	Turning	This mode gives the most accurate autophasing result. This mode can be used, and is recommended, if the motor is allowed to rotate during the ID run and the start-up is not time-critical. Note: This mode will cause the motor to rotate. The load torque must be less than 5%	0
	Standstill 1	Faster than the <i>Turning</i> mode, but not as accurate. The motor will not rotate.	1
	Standstill 2	An alternative standstill autophasing mode that can be used if the <i>Turning</i> mode cannot be used, and the <i>Standstill 1</i> mode gives erratic results. However, this mode is considerably slower than <i>Standstill 1</i> .	2
	Turning with Z- pulse	This mode should be used if the zero pulse signal of the pulse encoder is to be observed, and other modes do not give a result. The motor will turn until a zero pulse is detected.	3
21.14	Pre-heating input source	 Selects the source of the motor pre-heat on/off command. See section <i>Pre-heating</i> (page 97). Note: The pre-heating function will not activate if the Safe torque off function is active, a fault is active, less than one minute has elapsed after stopping, or PID sleep function is active. Pre-heating is deactivated when the drive is started, and overridden by pre-magnetization, post-magnetization or continuous magnetization. 0 = Pre-heating inactive Pre-heating active 	Off
	Off	0. Pre-heating is always deactivated.	0
	On	1. Pre-heating is always activated when the drive is stopped (apart from conditions stated above).	1
	DI1	Digital input DI1 (<i>10.02 DI delayed status</i> , bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	Supervision 1	Supervision 1 active (32.01 Supervision status, bit 0).	8
	Supervision 2	Supervision 2 active (32.01 Supervision status, bit 1).	9
	Supervision 3	Supervision 3 active (32.01 Supervision status, bit 2).	10
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
21.16	Pre-heating current	Defines the motor pre-heating current that is fed into the motor when the source selected by <i>21.14 Pre-heating input source</i> is on. The value is in percent of the nominal motor current.	0.0%
	0.0 30.0%	Pre-heating current.	1 = 1%

No.	Name/Value	Description	Def/FbEq16
21.18	Auto restart time	The motor can be automatically started after a short supply power failure using the automatic restart function. See section <i>Automatic restart</i> (page 110). When this parameter is set to 0.0 seconds, automatic restarting is disabled. Otherwise, the parameter defines the maximum duration of the power failure after which restarting is attempted. Note that this time also includes the DC pre- charging delay. WARNING! The function restarts the drive automatically and continues operation after a supply break. Make sure that no dangerous situations can occur.	5.0 s
	0.0 s	Automatic restarting disabled.	0
	0.1 5.0 s	Maximum power failure duration.	1 = 1 s
21.19	Scalar control mode	 Selects the motor start function for the scalar motor control mode, ie. when 99.04 Motor control mode is set to Scalar. Notes: The start function for the DTC motor control mode is selected by parameter 21.01 Start mode. With permanent magnet motors, Automatic start mode must be used. This parameter cannot be changed while the drive is running. See also section DC magnetization (page 97). 	Normal
	Normal	Immediate start from zero speed.	0
	Const time	The drive pre-magnetizes the motor before start. The pre- magnetizing time is defined by parameter 21.02 Magnetization time. This mode should be selected if constant pre-magnetizing time is required (e.g. if the motor start must be synchronized with the release of a mechanical brake). This setting also guarantees the highest possible break-away torque when the pre-magnetizing time is set long enough. Note: This mode cannot be used to start into a rotating motor. WARNING! The drive will start after the set magnetizing time has passed even if motor magnetization is not completed. In applications where a full break-away torque is essential, ensure that the constant magnetizing time is long enough to allow generation of full magnetization and torque.	1
	Automatic	This setting should be used in applications where flying starts (ie. starting into a rotating motor) are required.	2
21.20	Follower force ramp stop	In a torque-controlled follower drive, forces (or selects a source that forces) the drive to switch to speed control upon a ramp stop (Off1 or Off3) command. This is required for an independent ramp stop of the follower. See also section <i>Master/follower functionality</i> (page 64). 1 = Ramp stop forces speed control	Not selected
	Not selected	0.	0
	Selected	1.	1
	DIIL	DIIL input (10.02 DI delayed status, bit 15).	2
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	3
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	4
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	5

No.	Name/Value	Description	Def/FbEq16
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	6
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	7
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	8
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	11
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	12
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-

22 Speed reference selection		Speed reference selection; motor potentiometer settings. See the control chain diagrams on pages 628632. Note : This parameter group is not valid when spinning macro is selected with parameter 99.200 Application select.	
22.01	Speed ref unlimited	Displays the output of the speed reference selection block. See the control chain diagram on page <i>631</i> . This parameter is read-only.	-
	-30000.00 30000.00 rpm	Value of the selected speed reference.	See par. 46.01
22.11	Speed ref1 source	Selects speed reference source 1. Two signal sources can be defined by this parameter and 22.12 Speed ref2 source. A digital source selected by 22.14 Speed ref1/2 selection can be used to switch between the two sources, or a mathematical function (22.13 Speed ref1 function) applied to the two signals to create the reference.	AI1 scaled



Zero	None.	0
AI1 scaled	12.12 Al1 scaled value (see page 182).	1
AI2 scaled	12.22 Al2 scaled value (see page 184).	2
FB A ref1	03.05 FB A reference 1 (see page 141).	4
FB A ref2	03.06 FB A reference 2 (see page 141).	5
EFB ref1	03.09 EFB reference 1 (see page 141).	8
EFB ref2	03.10 EFB reference 2 (see page 141).	9
DDCS ctrl ref1	03.11 DDCS controller ref 1 (see page 141).	10
DDCS ctrl ref2	03.12 DDCS controller ref 2 (see page 141).	11
M/F reference 1	03.13 M/F or D2D ref1 (see page 141).	12
M/F reference 2	03.14 M/F or D2D ref2 (see page 141).	13

No.	Name/Value	Description	Def/FbEq16
	Motor potentiometer	22.80 Motor potentiometer ref act (output of the motor potentiometer).	15
	PID	40.01 Process PID output actual (output of the process PID controller).	16
	Control panel (ref saved)	Control panel reference, with initial value from last-used panel reference. See section <i>Using the control panel as an external control source</i> (page <i>55</i>).	18
	Control panel (ref copied)	Control panel reference, with initial value from previous source or actual value. See section <i>Using the control panel as an external control source</i> (page <i>55</i>).	19
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
22.12	Speed ref2 source	Selects speed reference source 2. For the selections, and a diagram of reference source selection, see parameter 22.11 Speed ref1 source.	Zero
22.13	Speed ref1 function	Selects a mathematical function between the reference sources selected by parameters 22.11 Speed ref1 source and 22.12 Speed ref2 source. See diagram at 22.11 Speed ref1 source.	Ref1
	Ref1	Signal selected by 22.11 Speed ref1 source is used as speed reference 1 as such (no function applied).	0
	Add (ref1 + ref2)	The sum of the reference sources is used as speed reference 1.	1
	Sub (ref1 - ref2)	The subtraction ([22.11 Speed ref1 source] - [22.12 Speed ref2 source]) of the reference sources is used as speed reference 1.	2
	Mul (ref1 × ref2)	The multiplication of the reference sources is used as speed reference 1.	3
	Min (ref1, ref2)	The smaller of the reference sources is used as speed reference 1.	4
	Max (ref1, ref2)	The greater of the reference sources is used as speed reference 1.	5
22.14	Speed ref1/2 selection	Configures the selection between speed references 1 and 2. See diagram at 22.11 Speed ref1 source. 0 = Speed reference 1 1 = Speed reference 2	Follow Ext1/Ext2 selection
	Speed reference 1	0.	0
	Speed reference 2	1.	1
	Follow Ext1/Ext2 selection	Speed reference 1 is used when external control location EXT1 is active. Speed reference 2 is used when external control location EXT2 is active. See also parameter 19.11 Ext1/Ext2 selection.	2
	DI1	Digital input DI1 (<i>10.02 DI delayed status</i> , bit 0).	3
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	4
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	5
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	6
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	7
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	8
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	11
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	12

No.	Name/V	/alue	Description	Def/FbEq16
	Other [b	oit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
22.15	Speed a source		Defines a reference to be added to the speed reference after reference selection (see page 628). For the selections, see parameter 22.11 Speed ref1 source. Note: For safety reasons, the additive is not applied when any of the stop functions are active.	Zero
22.16	Speed s		Defines a scaling factor for the selected speed reference (speed reference 1 or 2, multiplied by the defined value). Speed reference 1 or 2 is selected by parameter 22.14 Speed ref1/2 selection.	1.000
	-8.000 .	8.000	Speed reference scaling factor.	1000 = 1
22.17	Speed additive 2 I source I		Defines a reference to be added to the speed reference after the speed share function (see page 628). For the selections, see parameter 22.11 Speed ref1 source. Note: For safety reasons, the additive is not applied when any of the stop functions are active.	Zero
22.21	Constar function		Determines how constant speeds are selected, and whether the rotation direction signal is considered or not when applying a constant speed.	0000b
				1
	Bit	Name	Information	1
	Bit 0	Name Constant spe mode		ree sources
		Constant spe	eed 1 = Packed: 7 constant speeds are selectable using the th	activated by respectively.
		Constant spe	 and the sources defined by parameters 22.22, 22.23 and 22.24. b = Separate: Constant speeds 1, 2 and 3 are separately a the sources defined by parameters 22.22, 22.23 and 22.24. c = Separate: Constant speeds 1, 2 and 3 are separately a the sources defined by parameters 22.22, 22.23 and 22.24. 	activated by respectively. nber takes speed, the 32) is . This e) constant e active
	0	Constant spe mode Direction	 1 = Packed: 7 constant speeds are selectable using the th defined by parameters 22.22, 22.23 and 22.24. 0 = Separate: Constant speeds 1, 2 and 3 are separately a the sources defined by parameters 22.22, 22.23 and 22.24 In case of conflict, the constant speed with the smaller nur priority. 1 = Start dir: To determine running direction for a constant sign of the constant speed setting (parameters 22.2622. multiplied by the direction signal (forward: +1, reverse: -1)). effectively allows the drive to have 14 (7 forward, 7 reverse speeds if all values in 22.2622.32 are positive. WARNING: If the direction signal is reverse and the constant speed is negative, the drive will run in the 	activated by respectively. nber takes speed, the 32) is . This e) constant e active forward ed is
	0	Constant spe mode Direction	 1 = Packed: 7 constant speeds are selectable using the th defined by parameters 22.22, 22.23 and 22.24. 0 = Separate: Constant speeds 1, 2 and 3 are separately a the sources defined by parameters 22.22, 22.23 and 22.24 In case of conflict, the constant speed with the smaller nur priority. 1 = Start dir: To determine running direction for a constant sign of the constant speed setting (parameters 22.2622. multiplied by the direction signal (forward: +1, reverse: -1). effectively allows the drive to have 14 (7 forward, 7 reverse speeds if all values in 22.2622.32 are positive. WARNING: If the direction signal is reverse and the constant speed is negative, the drive will run in the direction. 0 = Accord Par: The running direction for the constant speed setting (parameters by the sign of the constant speed setting (parameters will run in the direction. 	activated by respectively. nber takes speed, the 32) is . This e) constant e active forward ed is

No.	Name/\	/alue	Des	cription			Def/FbEq16
22.22	Consta sel1	nt speed	(Sep Whe (Pac spee	barate), selects a sen bit 0 of parametecked), this parametecked sel2 and 22.24	source that activate	e/3 select three	Not selected
		Source def by par. 22		Source defined by par. 22.23	Source defined by par. 22.24	Constant speed ac	ctive
		0		0	0	None	
		1		0	0	Constant speed	
		0		1	0	Constant speed	
		1		1	0	Constant speed	
		0		0	1	Constant speed Constant speed	
		0		1	1	Constant speed	
		1		1	1	Constant speed	
	Not sele	ected	0 (al	ways off).			0
	Selecte	d	1 (al	ways on).			1
	DI1		Digit	tal input DI1 (10.0	2 DI delayed statu	<mark>s</mark> , bit 0).	2
	DI2		Digit	tal input DI2 (10.0	2 DI delayed statu	<mark>s</mark> , bit 1).	3
	DI3		Digit	tal input DI3 (10.0	2 DI delayed statu	<mark>s</mark> , bit 2).	4
	DI4		Digit	tal input DI4 (10.0	2 DI delayed statu	<mark>s</mark> , bit 3).	5
	DI5		Digit	tal input DI5 (10.0	2 DI delayed statu	<mark>s</mark> , bit 4).	6
	DI6		Digit	tal input DI6 (10.0	2 DI delayed statu	<mark>s</mark> , bit 5).	7
	DIO1		Digit	tal input/output DI	01 (11.02 DIO dela	ayed status, bit 0).	10
	DIO2		Digit	tal input/output DI	O2 (11.02 DIO dela	ayed status, bit 1).	11
	Other [l	bit]	Sou	rce selection (see	Terms and abbrev	<i>iations</i> on page 131).	-
22.23	Consta sel2	nt speed	(Sep Whe (Pac spec sour at pa	barate), selects a sen bit 0 of parameteked), this parameted sel1 and 22.24 ces that are used arameter 22.22 Co	source that activate ter 22.21 Constant eter and parameters Constant speed so to activate constant constant speed sel1	e/3 select three nt speeds. See table	Not selected
22.24	Consta sel3	nt speed	(Sep Whe (Pac spec sour at pa	barate), selects a sen bit 0 of parameteked), this parameted sel1 and 22.23 ces that are used parameter 22.22 Co	source that activate ter 22.21 Constant eter and parameters Constant speed se to activate constant constant speed sel1	el2 select three nt speeds. See table	Not selected
22.26	Consta	nt speed 1		nes constant spee stant speed 1 is se		motor will turn when	300.00 rpm
	-30000. 30000.0		Con	stant speed 1.			See par. 46.01

No.	Name/Value	Description	Def/FbEq16
22.27	Constant speed 2	Defines constant speed 2.	0.00 rpm
	-30000.00 30000.00 rpm	Constant speed 2.	See par. 46.01
22.28	Constant speed 3	Defines constant speed 3.	0.00 rpm
	-30000.00 30000.00 rpm	Constant speed 3.	See par. 46.01
22.29	Constant speed 4	Defines constant speed 4.	0.00 rpm
	-30000.00 30000.00 rpm	Constant speed 4.	See par. 46.01
22.30	Constant speed 5	Defines constant speed 5.	0.00 rpm
	-30000.00 30000.00 rpm	Constant speed 5.	See par. 46.01
22.31	Constant speed 6	Defines constant speed 6.	0.00 rpm
	-30000.00 30000.00 rpm	Constant speed 6.	See par. 46.01
22.32	Constant speed 7	Defines constant speed 7.	0.00 rpm
	-30000.00 30000.00 rpm	Constant speed 7.	See par. 46.01
22.41	Speed ref safe	 Defines a safe speed reference that is used with supervision functions such as 12.03 AI supervision function 49.05 Communication loss action 50.02 FBA A comm loss func 50.32FBA B comm loss func 58.14 Communication loss action. 	0.00 rpm
	-30000.00 30000.00 rpm	Safe speed reference.	See par. 46.01
22.42	Jogging 1 ref	Defines the speed reference for jogging function 1. For more information on jogging, see page 89.	0.00 rpm
	-30000.00 30000.00 rpm	Speed reference for jogging function 1.	See par. 46.01
22.43	Jogging 2 ref	Defines the speed reference for jogging function 2. For more information on jogging, see page 89.	0.00 rpm
	-30000.00 30000.00 rpm	Speed reference for jogging function 2.	See par. 46.01

No.	Name/\	/alue	Description	Def/FbEq16
22.51	Critical functior		Enables/disables the critical speeds function. Also determines whether the specified ranges are effective in both rotating directions or not. See also section <i>Critical speeds/frequencies</i> (page 76).	0000b
	Bit	Name	Information	
	0	Enable	1 = Enable: Critical speeds enabled.	
			0 = Disable: Critical speeds disabled.	
	1	Sign mode	1 = Signed: The signs of parameters 22.5222.57 are tak account.	
			0 = Absolute: Parameters 22.5222.57 are handled as abs Each range is effective in both directions of rotation.	solute values.
	215	Reserved		
	0000b.	0011b	Critical speeds configuration word.	1 = 1
22.52	Critical	speed 1 low	Defines the low limit for critical speed range 1. Note: This value must be less than or equal to the value of 22.53 <i>Critical speed 1 high</i> .	0.00 rpm
	-30000. 30000.0		Low limit for critical speed 1.	See par. 46.01
22.53	Critical high	speed 1	Defines the high limit for critical speed range 1. Note: This value must be greater than or equal to the value of 22.52 <i>Critical speed 1 low</i> .	0.00 rpm
	-30000. 30000.0		High limit for critical speed 1.	See par. 46.01
22.54	Critical speed 2 low		Defines the low limit for critical speed range 2. Note: This value must be less than or equal to the value of 22.55 <i>Critical speed 2 high</i> .	0.00 rpm
	-30000. 30000.0		Low limit for critical speed 2.	See par. 46.01
22.55	Critical high	speed 2	Defines the high limit for critical speed range 2. Note: This value must be greater than or equal to the value of 22.54 <i>Critical speed 2 low</i> .	0.00 rpm
	-30000. 30000.0		High limit for critical speed 2.	See par. 46.01
22.56	Critical	speed 3 low	Defines the low limit for critical speed range 3. Note: This value must be less than or equal to the value of 22.57 <i>Critical speed 3 high</i> .	0.00 rpm
	-30000. 30000.0		Low limit for critical speed 3.	See par. 46.01
22.57	Critical high	speed 3	Defines the high limit for critical speed range 3. Note: This value must be greater than or equal to the value of 22.56 <i>Critical speed 3 low</i> .	0.00 rpm
	-30000. 30000.0		High limit for critical speed 3.	See par. 46.01
22.71	Motor potentic function		Activates and selects the mode of the motor potentiometer. See section <i>Motor potentiometer</i> (page <i>103</i>).	Disabled
	Disable	d	Motor potentiometer is disabled and its value set to 0.	0

No.	Name/Value	Description	Def/FbEq16
	Enabled (init at stop/power-up)	When enabled, the motor potentiometer first adopts the value defined by parameter 22.72 <i>Motor potentiometer initial value</i> . When the drive is running, the value can be adjusted from the up and down sources defined by parameters 22.73 <i>Motor potentiometer up source</i> and 22.74 <i>Motor potentiometer down source</i> . A stop or a power cycle restarts the motor potentiometer to the initial value (22.72).	1
	Enabled (resume always)	As <i>Enabled (init at stop/power-up)</i> , but the motor potentiometer value is retained over a stop or a power cycle.	2
22.72	Motor potentiometer initial value	Defines an initial value (starting point) for the motor potentiometer. See the selections of parameter 22.71 Motor potentiometer function.	0.00
	-32768.00 32767.00	Initial value for motor potentiometer.	1 = 1
22.73	Motor potentiometer up source	Selects the source of motor potentiometer up signal. 0 = No change 1 = Increase motor potentiometer value. (If both the up and down sources are on, the potentiometer value will not change.)	Not selected
	Not selected	0.	0
	Selected	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
22.74	Motor potentiometer down source	Selects the source of motor potentiometer down signal. 0 = No change 1 = Decrease motor potentiometer value. (If both the up and down sources are on, the potentiometer value will not change.) For the selections, see parameter 22.73 Motor potentiometer up source.	Not selected
22.75	Motor potentiometer ramp time	Defines the change rate of the motor potentiometer. This parameter specifies the time required for the motor potentiometer to change from minimum (22.76) to maximum (22.77). The same change rate applies in both directions.	60.0 s
	0.0 3600.0 s	Motor potentiometer change time.	10 = 1 s
22.76	Motor potentiometer min value	Defines the minimum value of the motor potentiometer.	-1500.00
	-32768.00 32767.00	Motor potentiometer minimum.	1 = 1

No.	Name/Value	Description	Def/FbEq16
22.77	Motor potentiometer max value	Defines the maximum value of the motor potentiometer.	1500.00
	-32768.00 32767.00	Motor potentiometer maximum.	1 = 1
22.80	Motor potentiometer ref act	Displays the output of the motor potentiometer function. (The motor potentiometer is configured using parameters 22.7122.74.) This parameter is read-only.	-
	-32768.00 32767.00	Value of motor potentiometer.	1 = 1
22.81	Speed reference act 1	Displays the value of speed reference source 1 (selected by parameter <i>22.11 Speed ref1 source</i>). See the control chain diagram on page 628. This parameter is read-only.	-
	-30000.00 30000.00 rpm	Value of reference source 1.	See par. 46.01
22.82	Speed reference act 2	Displays the value of speed reference source 2 (selected by parameter 22.12 Speed ref2 source). See the control chain diagram on page 628. This parameter is read-only.	-
	-30000.00 30000.00 rpm	Value of reference source 2.	See par. 46.01
22.83	Speed reference act 3	Displays the value of speed reference after the mathematical function applied by parameter 22.13 Speed ref1 function and reference 1/2 selection (22.14 Speed ref1/2 selection). See the control chain diagram on page 628. This parameter is read-only.	-
	-30000.00 30000.00 rpm	Speed reference after source selection.	See par. 46.01
22.84	Speed reference act 4	Displays the value of speed reference after application of 1st speed additive (<i>22.15 Speed additive 1 source</i>). See the control chain diagram on page <i>628</i> . This parameter is read-only.	-
	-30000.00 30000.00 rpm	Speed reference after additive 1.	See par. 46.01
22.85	Speed reference act 5	Displays the value of speed reference after the application of the speed share scaling factor (<i>22.16 Speed share</i>).See the control chain diagram on page <i>628</i> . This parameter is read-only.	-
	-30000.00 30000.00 rpm	Speed reference after speed share scaling.	See par. 46.01
22.86	Speed reference act 6	Displays the value of speed reference after application of 2nd speed additive (22.17 Speed additive 2 source). See the control chain diagram on page 628. This parameter is read-only.	-
	-30000.00 30000.00 rpm	Speed reference after additive 2.	See par. 46.01

No.	Name/Value	Description	Def/FbEq16
22.87	Speed reference act 7	Displays the value of speed reference before application of critical speeds. See the control chain diagram on page 631. The value is received from 22.86 Speed reference act 6 unless overridden by • any constant speed • a jogging reference • <i>network control</i> reference • control panel reference • safe speed reference. This parameter is read-only.	-
	-30000.00 30000.00 rpm	Speed reference before application of critical speeds.	See par. 46.01
23 Spe ramp	eed reference	Speed reference ramp settings (programming of the acceleration and deceleration rates for the drive). See the control chain diagram on page 632.	
23.01	Speed ref ramp input	Displays the used speed reference (in rpm) before it enters the ramping and shaping functions. See the control chain diagram on page 633. This parameter is read-only.	-
	-30000.00 30000.00 rpm	Speed reference before ramping and shaping.	See par. 46.01
23.02	Speed ref ramp output	Displays the ramped and shaped speed reference in rpm. See the control chain diagram on page 632. This parameter is read-only.	-
	-30000.00 30000.00 rpm	Speed reference after ramping and shaping.	See par. 46.01
23.11	Ramp set selection	This parameter is read-only. See parameter 23.200 Ramp set selection.	-
23.12	Acceleration time 1	This parameter is read-only. See parameter 23.201 Acceleration time 1.	-
23.13	Deceleration time 1	This parameter is read-only. See parameter 23.202 Deceleration time 1.	-
23.14	Acceleration time 2	This parameter is read-only. See parameter 23.203 Acceleration time 2.	-
23.15	Deceleration time 2	This parameter is read-only. See parameter 23.204 Deceleration time 2.	-

No.	Name/Value	Description	Def/FbEq16
23.16	Shape time acc 1	Defines the shape of the acceleration ramp at the beginning of the acceleration. 0.000 s: Linear ramp. Suitable for steady acceleration or deceleration and for slow ramps. 0.0011000.000 s: S-curve ramp. S-curve ramps are ideal for lifting applications. The S-curve consists of symmetrical curves at both ends of the ramp and a linear part in between. Note: For safety reasons, shape times are not applied to emergency stop ramps. Acceleration: Linear ramp: 23.17 = 0 s Speed Linear ramp: 23.16 = 0 s S-curve ramp: 23.16 > 0 s Time	0.000 s
		Deceleration:	
		S-curve ramp: 23.18 > 0 s Linear ramp: 23.18 = 0 s Linear ramp: 23.19 = 0 s Time	
	0.0001800.000 s	Ramp shape at start of acceleration.	10 = 1 s
23.17	Shape time acc 2	Defines the shape of the acceleration ramp at the end of the acceleration. See parameter 23.16 Shape time acc 1.	0.000 s
	0.0001800.000 s	Ramp shape at end of acceleration.	10 = 1 s
23.18	Shape time dec 1	Defines the shape of the deceleration ramp at the beginning of the deceleration. See parameter 23.16 Shape time acc 1.	0.000 s
	0.0001800.000 s	Ramp shape at start of deceleration.	10 = 1 s

No.	Name/Value	Description	Def/FbEq16
23.19	Shape time dec 2	Defines the shape of the deceleration ramp at the end of the deceleration. See parameter 23.16 Shape time acc 1.	0.000 s
	0.0001800.000 s	Ramp shape at end of deceleration.	10 = 1 s
23.20	Acc time jogging	Defines the acceleration time for the jogging function i.e. the time required for the speed to change from zero to the speed value defined by parameter <i>46.01 Speed scaling</i> . See section <i>Jogging</i> (page <i>89</i>).	60.000 s
	0.0001800.000 s	Acceleration time for jogging.	10 = 1 s
23.21	Dec time jogging	Defines the deceleration time for the jogging function i.e. the time required for the speed to change from the speed value defined by parameter <i>46.01 Speed scaling</i> to zero. See section <i>Jogging</i> (page <i>89</i>).	60.000 s
	0.0001800.000 s	Deceleration time for jogging.	10 = 1 s
23.23	Emergency stop time	In speed control mode, this parameter defines the deceleration rate for emergency stop Off3 as the time it would take for the speed to decrease from the value of parameter 46.01 Speed scaling to zero. This also applies to torque control because the drive switches to speed control on receiving an emergency stop Off3 command. In frequency control mode, this parameter specifies the time it would take for the frequency to decrease from the value of 46.02 Frequency scaling to zero. The emergency stop mode and activation source are selected by parameters 21.04 Emergency stop mode and 21.05 Emergency stop source respectively. Emergency stop can also be activated through fieldbus. Note: Emergency stop Off1 uses the standard deceleration ramp as defined by parameters 23.1123.19 (speed and torque control) or 28.7128.75 (frequency control).	3.000 s
	0.0001800.000 s	Emergency stop Off3 deceleration time.	10 = 1 s
23.24	Speed ramp in zero source	Selects a source that forces the speed reference to zero just before it enters the ramp function. 0 = Force speed reference to zero before the ramp function 1 = Speed reference continues towards the ramp function as normal	Inactive
	Active	0.	0
	Inactive	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see Terms and abbreviations on page 131).	-

No.	Name/Value	Description	Def/FbEq16
23.26	Ramp out balancing enable	Selects the source for enabling/disabling speed reference ramp balancing. This function is used to generate a smooth transfer from a torque- or tension-controlled motor back to being speed- controlled. The balancing output would be tracking the present "line" speed of the application and when transfer is required, the speed reference can then be quickly "seeded" to the correct line speed. Balancing is also possible in the speed controller, see parameter 25.09 Speed ctrl balancing enable. See also parameter 23.27 Ramp out balancing ref. 0 = Disabled 1 = Enabled	Not selected
	Not selected	0.	0
	Selected	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
23.27	Ramp out balancing ref	Defines the reference for speed ramp balancing. The output of the ramp generator is forced to this value when balancing is enabled by parameter <i>23.26 Ramp out balancing enable</i> .	0.00 rpm
	-30000.00 30000.00 rpm	Speed ramp balancing reference.	See par. 46.01

No.	Name/Value	Description	Def/FbEq16
23.28	Variable slope enable	Activates the variable slope function, which controls the slope of the speed ramp during a speed reference change. This allows for a constantly variable ramp rate to be generated, instead of just the standard two ramps normally available. If the update interval of the signal from an external control system and the variable slope rate (23.29 Variable slope rate) are equal, the resulting speed reference (23.02 Speed ref ramp output) is a straight line.	Off
		A Speed reference A 23.02 Speed ref ramp output Time t = update interval of signal from external control system A = speed reference change during t	
	Off	This function is active only in remote control. Variable slope disabled.	0
	On	Variable slope enabled (not available in local control).	1
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page <i>131</i>).	-
23.29	Variable slope rate	Defines the rate of the speed reference change when variable slope is enabled by parameter 23.28 Variable slope enable. For the best result, enter the reference update interval into this parameter.	50 ms
	230000 ms	Variable slope rate.	1 = 1 ms
23.39	Follower speed correction out	Displays the speed correction term for the load share function with a speed-controlled follower drive. See section <i>Load share function with a speed-controlled</i> <i>follower</i> (page 65). This parameter is read-only.	-
	-30000.00 30000.00 rpm	Speed correction term.	See par. 46.01
23.40	Follower speed correction enable	With a speed-controlled follower, selects the source for enabling/disabling the load share function. See section <i>Load share function with a speed-controlled</i> <i>follower</i> (page 65). 0 = Disabled 1 = Enabled	Not selected
	Not selected	0.	0
	Selected	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3

No.	Name/Value	Description	Def/FbEq16
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
23.41	Follower speed correction gain	Adjusts the gain of the speed correction term in a speed- controlled follower. In effect, defines how accurately the follower follows the master torque. A greater value results in a more accurate performance. See section <i>Load share function with a speed-controlled</i> <i>follower</i> (page 65).	1.00%
	0.00 100.00%	Speed correction term adjustment.	1 = 1%
23.42	Follower speed corr torq source	Selects the source of the torque reference for the load share function. See section <i>Load share function with a speed-controlled follower</i> (page 65).	MF ref 2
	NULL	None.	0
	MF ref 2	03.14 M/F or D2D ref2 (page 141).	1
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
23.200	Ramp set selection	Selects the source that switches between the two sets of acceleration/deceleration ramp times defined by parameters 23.1223.15. 0 = Acceleration time 1 and deceleration time 1 are active 1 = Acceleration time 2 and deceleration time 2 are active	DI4; Acc/Dec time 2; (95.20 b1)
	Acc/Dec time 1	0.	0
	Acc/Dec time 2	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
23.201	Acceleration time 1	Defines acceleration time 1 as the time required for the speed to change from zero to the speed defined by parameter 46.01 Speed scaling (not to parameter 30.12 Maximum speed). If the speed reference increases faster than the set acceleration rate, the motor speed will follow the acceleration rate. If the speed reference increases slower than the set acceleration rate, the motor speed will follow the reference. If the acceleration time is set too short, the drive will automatically prolong the acceleration in order not to exceed the drive torque limits.	20.000 s
	0.0001800.000 s	Acceleration time 1.	10 = 1 s

No.	Name/Value	Description	Def/FbEq16
23.202	Deceleration time 1	Defines deceleration time 1 as the time required for the speed to change from the speed defined by parameter 46.01 Speed scaling (not from parameter 30.12 Maximum speed) to zero. If the speed reference decreases slower than the set deceleration rate, the motor speed will follow the reference. If the reference changes faster than the set deceleration rate, the motor speed will follow the deceleration rate. If the deceleration rate is set too short, the drive will automatically prolong the deceleration in order not to exceed drive torque limits (or not to exceed a safe DC link voltage). If there is any doubt about the deceleration time being too short, ensure that DC overvoltage control is on (parameter 30.30 Overvoltage control). Note: If a short deceleration time is needed for a high inertia application, the drive should be equipped with braking equipment such as a brake chopper and brake resistor.	20.000 s
	0.0001800.000 s	Deceleration time 1.	10 = 1 s
23.203	Acceleration time 2	Defines acceleration time 2. See parameter 23.201 Acceleration time 1.	60.000 s
	0.0001800.000 s	Acceleration time 2.	10 = 1 s
23.204	Deceleration time 2	Defines deceleration time 2. See parameter 23.202 Deceleration time 1.	60.000 s
	0.0001800.000 s	Deceleration time 2.	10 = 1 s
-			

24 Speed reference conditioning		Speed error calculation; speed error window control configuration; speed error step. See the control chain diagrams on pages 634 and 636.	
24.01	Used speed reference	Displays the ramped and corrected speed reference (before speed error calculation).See the control chain diagram on page 634. This parameter is read-only.	-
	-30000.00 30000.00 rpm	Speed reference used for speed error calculation.	See par. 46.01
24.02	Used speed feedback	Displays the speed feedback used for speed error calculation. See the control chain diagram on page 634. This parameter is read-only.	-
	-30000.00 30000.00 rpm	Speed feedback used for speed error calculation.	See par. 46.01
24.03	Speed error filtered	Displays the filtered speed error. See the control chain diagram on page 634. This parameter is read-only.	-
	-30000.0 30000.0 rpm	Filtered speed error.	See par. 46.01
24.04	Speed error inverted	Displays the inverted (unfiltered) speed error. See the control chain diagram on page 634. This parameter is read-only.	-
	-30000.0 30000.0 rpm	Inverted speed error.	See par. 46.01

No.	Name/Value	Description	Def/FbEq16
24.11	Speed correction	 Defines a speed reference correction, ie. a value added to the existing reference between ramping and limitation. This is useful to trim the speed if necessary, for example to adjust draw between sections of a paper machine. Note: For safety reasons, the correction is not applied when an emergency stop is active. WARNING! If the speed reference correction exceeds 21.06 Zero speed limit, a ramp stop may be impossible. Make sure the correction is reduced or removed when a ramp stop is required. See the control chain diagram on page 634. 	0.00 rpm
	-10000.00 10000.00	Speed reference correction.	See par. 46.01
24.12	Speed error filter time	Defines the time constant of the speed error low-pass filter. If the used speed reference changes rapidly, the possible interferences in the speed measurement can be filtered with the speed error filter. Reducing the ripple with this filter may cause speed controller tuning problems. A long filter time constant and fast acceleration time contradict one another. A very long filter time results in unstable control.	0 ms
	010000 ms	Speed error filtering time constant. 0 = filtering disabled.	1 = 1 ms
24.13	RFE speed filter	Enables/disables resonance frequency filtering. The filtering is configured by parameters 24.1324.17. The speed error value coming to the speed controller is filtered by a common 2nd order band-elimination filter to eliminate the amplification of mechanical resonance frequencies. Note: Tuning the resonance frequency filter requires a basic understanding of frequency filters. Incorrect tuning can amplify mechanical oscillations and damage the drive hardware. To ensure the stability of the speed controller, stop the drive or disable the filtering before changing the parameter settings. 0 = Resonance frequency filtering disabled. 1 = Resonance frequency filtering enabled.	Off
	Off	0.	0
	On	1.	1

No.	Name/Value	Description	Def/FbEq16
24.14	Frequency of zero	Defines the zero frequency of the resonance frequency filter. The value must be set near the resonance frequency, which is filtered out before the speed controller. The drawing shows the frequency response. $20\log_{10} H(\omega) $	45.00 Hz
		20	
		-20 -	
		-40 -	
		0 50 100 150 f (Hz)	
	0.50 500.00 Hz	Zero frequency.	1 = 1 Hz
24.15	Damping of zero	Defines the damping coefficient for parameter 24.14. The	0.000
	g e	value of 0 corresponds to the maximum elimination of the resonance frequency.	
		20log ₁₀ <i>H</i> (ω)	
		$\begin{array}{c} 20 \\ f_{zero} = 45 \text{ Hz} \\ \xi_{zero} = 0.250 \end{array}$	
		$0 - \frac{\xi_{\text{pole}}}{\xi_{\text{pole}}} = 1$	
		-20 -	
		$f_{zero} = 45 \text{ Hz}$ $\xi_{zero} = 0$ $\xi_{pole} = 1$	
		0 50 100 150 f (Hz)	
		Note: To ensure that the resonance frequency band is filtered (rather than amplified), the value of <i>24.15</i> must be smaller than <i>24.17</i> .	
	-1.000 1.000	Damping coefficient.	100 = 1

No.	Name/Value	Description	Def/FbEq16
24.16	Frequency of pole	Defines the frequency of pole of the resonance frequency filter.	40.00 Hz
		20log ₁₀ <i>H</i> (ω)	
		40 40 40 40 40 40 40 40 40 40	
	0.50 500.00 Hz	can damage the driven machine. Frequency of pole.	1 = 1 Hz
24.17	Damping of pole	Defines the damping coefficient for parameter 24.16. The coefficient shapes the frequency response of the resonance frequency filter. A narrower bandwidth results in better dynamic properties. By setting this parameter to 1, the effect of the pole is eliminated. 20log ₁₀ <i>H</i> (ω) 40 40 20 -20 -20 -20 -20 -20 -40 -20 -20 -20 -20 -20 -20 -20 -2	0.250
		(rather than amplified), the value of 24.15 must be smaller than 24.17.	
	-1.000 1.000	Damping coefficient.	100 = 1

No.	Name/Value	Description	Def/FbEq16
24.41	Speed error window control enable	Enables/disables speed error window control, sometimes also referred to as deadband control or strip break protection. It forms a speed supervision function for a torque-controlled drive, preventing the motor from running away if the material that is being held under tension breaks. Note: Speed error window control is only effective when the Add operating mode is active (see parameters 19, 12 and 19, 14), or when the drive is a speed-controlled follower. In normal operation, window control keeps the speed controller input at zero so the drive stays in torque control. If the motor load is lost, then the motor speed will rise as the torque controller tries to maintain torque. The speed error (speed reference - actual speed) will increase until it exits the speed error window. When this is detected, the exceeding part of the error value is connected to the speed controller. The speed controller produces a reference term relative to the input and gain (25.02 Speed proportional gain) which the torque selector adds to the torque reference. The result is used as the internal torque reference for the drive. The activation of speed error window control is indicated by bit 3 of 06.19 Speed control status word. The window boundaries are defined by 24.43 Speed error window high and 24.44 Speed error window low as follows: Speed error window wigh and 24.44 Speed error window low as follows: Speed error window indow Reference + [24.44] rpm Reference - [24.43] rpm Reference - [24.44] rpm Note that it is parameter 24.44 (rather than 24.43) that defines the overspeed limit in both directions of rotation. This is because the function monitors speed error (which is negative in case of overspeed, positive in case of underspeed). Example: In a load loss condition, the internal torque reference of the drive is decreased to prevent an excessive rise of the motor speed. If window control were inactive, the motor speed would rise until a speed limit of the drive were reached. 0 = Speed error window control disabled	Disable
		1 = Speed error window control enabled	
	Disable	0.	0
	Enable	1.	1

No.	Name/Value	Description	Def/FbEq16
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
24.42	Speed window control mode	When speed error window control (see parameter 24.41 Speed error window control enable) is enabled, this parameter determines whether the speed controller only observes the proportional term instead of all three (P, I and D) terms.	Normal speed control
	Normal speed control	All three terms (parameters 25.02, 25.03 and 25.04) are observed by the speed controller.	0
	P-control	Only the proportional term (25.02) is observed by the speed controller. The integral and derivative terms are internally forced to zero.	1
24.43	Speed error window high	Defines the upper boundary of the speed error window. See parameter 24.41 Speed error window control enable.	0.00 rpm
	0.00 3000.00 rpm	Upper boundary of speed error window.	See par. 46.01
24.44	Speed error window low	Defines the lower boundary of the speed error window. See parameter 24.41 Speed error window control enable.	0.00 rpm
	0.00 3000.00 rpm	Lower boundary of speed error window.	See par. 46.01
24.46	Speed error step	Defines an additional speed error step given to the input of the speed controller (and added to the speed error value). This can be used in large drive systems for dynamic speed normalizing. WARNING! Make sure the error step value is removed when a stop command is given.	0.00 rpm
	-3000.00 3000.00 rpm	Speed error step.	See par. 46.01
25 Sp	eed control	Speed controller settings. See the control chain diagrams on pages 634 and 636.	
25.01	Torque reference	Displays the speed controller output that is transferred to the	-

25.01	Torque reference speed control	Displays the speed controller output that is transferred to the torque controller. See the control chain diagram on page 636. This parameter is read-only.	-	
	-1600.0 1600.0%	Limited speed controller output torque.	See par. 46.03	

No.	Name/Value	Description	Def/FbEq16
25.02	Speed proportional gain	Defines the proportional gain (K_p) of the speed controller. Too high a gain may cause speed oscillation. The figure below shows the speed controller output after an error step when the error remains constant.	10.00; 5.00 (95.21 b1/b2)
	q	Gain = $K_p = 1$ $T_I = Integration time = 0$ $T_D = Derivation time = 0$	
	Controller output = K _p × e		Error value me
		If gain is set to 1, a 10% change in error value (reference - actual value) causes the speed controller output to change by 10%, ie. the output value is input × gain. Note: This parameter is automatically set by the speed controller autotune function. See section <i>Speed controller autotune</i> (page 77).	
	0.00250.00	Proportional gain for speed controller.	100 = 1

No.	Name/Value	Description	Def/FbEq16
No. 25.03	Speed integration time	Defines the integration time of the speed controller. The integration time defines the rate at which the controller output changes when the error value is constant and the proportional gain of the speed controller is 1. The shorter the integration time, the faster the continuous error value is corrected. This time constant must be set to the same order of magnitude as the time constant (time to respond) of the actual mechanical system being controlled, otherwise instability will result. Setting the integration time to zero disables the I-part of the controller. This is useful to do when tuning the proportional gain; adjust the proportional gain first, then return the integration time. Anti-windup (the integrator just integrates up to 100%) stops the integrator if the controller output is limited. The figure below shows the speed controller output after an error step when the error remains constant.	2.50 s; 5.00 (95.21 b1/b2)
	К _р × е {		= 1 tion time > 0 tion time = 0
	K _p × e	e = Error value	
	Note: This parameter	$T_{\rm I}$ Time $T_{\rm I}$ Time $T_{\rm I}$ Trime	See section
	Speed controller aut	otune (page 77).	1
	0.00 1000.00 s	Integration time for speed controller.	10 = 1 s

No.	Name/Value	Description	Def/FbEq16
25.04	Speed derivation time	Defines the derivation time of the speed controller. Derivative action boosts the controller output if the error value changes. The longer the derivation time, the more the speed controller output is boosted during the change. If the derivation time is set to zero, the controller works as a PI controller, otherwise as a PID controller. The derivation makes the control more responsive for disturbances. For simple applications (especially those without a pulse encoder), derivative time is not normally required and should be left at zero. The speed error derivative must be filtered with a low pass filter to eliminate disturbances. The figure below shows the speed controller output after an error step when the error remains constant.	0.000 s
	$K_{p} \times T_{D} \times \frac{\Delta e}{T_{s}} \begin{cases} \dots \\ K_{p} \end{cases}$	$\begin{array}{c} & & \\ & & & \\ & & \\ & & \\ & & \\ & & \\ & & \\ & & & \\ & & \\ & & \\ & & & \\$	alue
		Gain = $K_p = 1$ T_1 = Integration time > 0 T_D = Derivation time > 0 T_s = Sample time period = 250 µs Δe = Error value change between two samples	
	0.000 10.000 s	Derivation time for speed controller.	1000 = 1 s
25.05	Derivation filter time	Defines the derivation filter time constant. See parameter 25.04 Speed derivation time.	8 ms
	010000 ms	Derivation filter time constant.	1 = 1 ms

No.	Name/Value	Description	Def/FbEq16
25.06	 Defines the derivation time for acceleration(/deceleration) compensation. In order to compensate for high inertia load during acceleration, a derivative of the reference is added the output of the speed controller. The principle of a derivatiation is described under parameter 25.04 Speed derivation time. Note: As a general rule, set this parameter to the value between 50 and 100% of the sum of the mechanical time constants of the motor and the driven machine. The figure below shows the speed responses when a high inertia load is accelerated along a ramp. No acceleration compensation: 	Defines the derivation time for acceleration(/deceleration) compensation. In order to compensate for high inertia load during acceleration, a derivative of the reference is added to the output of the speed controller. The principle of a derivative action is described under parameter <i>25.04 Speed derivation time</i> . Note: As a general rule, set this parameter to the value between 50 and 100% of the sum of the mechanical time constants of the motor and the driven machine. The figure below shows the speed responses when a high inertia load is accelerated along a ramp.	0.00 s
		Time	
		Acceleration compensation:	
		– – Speed reference Actual speed	
		Time	
	0.00 1000.00 s	Acceleration compensation derivation time.	10 = 1 s
25.07	Acc comp filter time	Defines the acceleration (or deceleration) compensation filter time constant. See parameters 25.04 Speed derivation time and 25.06 Acc comp derivation time.	8.0 ms
	0.0 1000.0 ms	Acceleration/deceleration compensation filter time.	1 = 1 ms

No.	Name/\	/alue	Description	Def/FbEq16
25.08	Droopin	ig rate	Defines the droop rate in percent of the nominal motor speed. Drooping decreases the drive speed slightly as the drive load increases. The actual speed decrease at a certain operating point depends on the droop rate setting and the drive load (= torque reference / speed controller output). At 100% speed controller output, drooping is at its nominal level, i.e. equal to the value of this parameter. The drooping effect decreases linearly to zero along with the decreasing load. The droop rate can be used e.g. to adjust the load sharing in a Master/Follower application run by several drives. In a Master/Follower application the motor shafts are coupled to each other. The correct droop rate for a process must be found out case by case in practice.	0.00%
	Ex 15 Sp	ample: Spee 00 rpm. eed decrease	e = Speed controller output × Drooping × Nominal speed ed controller output is 50%, droop rate is 1%, nominal speed of t e = 0.50 × 0.01 × 1500 rpm = 7.5 rpm.	he drive is
		or speed in of nominal		
			No drooping	
	100% ·		Drooping	
			Speed controller / Drive lo	ad
			10070 /	
	0.00	100.00%	Droop rate.	100 = 1%
25.09	Speed (balancii	ctrl ng enable	Selects the source for enabling/disabling speed controller output balancing. This function is used to generate a smooth, "bumpless" transfer from a torque- or tension-controlled motor back to being speed-controlled. When balancing is enabled, the output of the speed controller is forced to the value of 25.10 <i>Speed ctrl balancing ref.</i> Balancing is also possible in the ramp generator (see parameter 23.26 Ramp out balancing enable). 0 = Disabled	Not selected
			1 = Enabled	
	Not sele	ected	0.	1
	Selecte	d	1.	2
	DI1		Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2		Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3		Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4		Digital input DI4 (10.02 DI delayed status, bit 3).	5

No.	Name/Value	Description	Def/FbEq16
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
25.10	Speed ctrl balancing ref	Defines the reference used in speed controller output balancing. The output of the speed controller is forced to this value when balancing is enabled by parameter <i>25.09 Speed ctrl balancing enable</i> .	0.0%
	-300.0 300.0%	Speed control output balancing reference.	See par. 46.03
25.11	Speed control min torque	Defines the minimum speed controller output torque.	-300.0%
	-1600.0 0.0%	Minimum speed controller output torque.	See par. 46.03
25.12	Speed control max torque	Defines the maximum speed controller output torque.	300.0%
	0.0 1600.0%	Maximum speed controller output torque.	See par. 46.03
25.13	Min torq sp ctrl em stop	Defines the minimum speed controller output torque during a ramped emergency stop (Off1 or Off3).	-400.0%
	-1600.0 0.0%	Minimum speed controller output torque for ramped emergency stop.	See par. 46.03
25.14	Max torq sp ctrl em stop	Defines the maximum speed controller output torque during a ramped emergency stop (Off1 or Off3).	400.0%
	0.0 1600.0%	Maximum speed controller output torque for ramped emergency stop.	See par. 46.03
25.15	Proportional gain em stop	Defines the proportional gain for the speed controller when an emergency stop is active. See parameter 25.02 Speed proportional gain.	10.00; 5.00 (95.21 b1/b2)
	1.00 250.00	Proportional gain upon an emergency stop.	100 = 1

	Name/Value	Description	Def/FbEq16
25.18	Speed adapt min limit	Minimum actual speed for speed controller adaptation. Speed controller gain and integration time can be adapted according to actual speed (90.01 Motor speed for control). This is done by multiplying the gain (25.02 Speed proportional gain) and integration time (25.03 Speed integration time) by coefficients at certain speeds. The coefficients are defined individually for both gain and integration time. When actual speed is below or equal to 25.18 Speed adapt min limit, the gain and integration time are multiplied by 25.21 Kp adapt coef at min speed and 25.22 Ti adapt coef at min speed respectively. When actual speed is equal to or above 25.19 Speed adapt max limit, no adaptation takes place (the coefficient is 1). When actual speed is between 25.18 Speed adapt max limit, no adaptation takes place (the coefficient is 1). When actual speed is between 25.18 Speed adapt max limit, no adaptation takes place (the coefficient is 1). See also the control chain diagram on page 636. Coefficient for K _p or T ₁ K _p = Proportion	
		$T_{\rm I}$ = Integration	n time
	25.21 Kp adapt coef 25.22 Ti adapt co		Actual speed (90.01) (rpm) ►
		at min speed or ef at min speed 0 25.18 Speed 25.19 Speed adapt	•
25.19	25.22 Ti adapt co	at min speed or ref at min speed 0 25.18 Speed 25.19 Speed adapt adapt min limit max limit	(90.01) (rpm) →
25.19	25.22 Ti adapt co 030000 rpm Speed adapt max	at min speed or ef at min speed 0 25.18 Speed 25.19 Speed adapt adapt min limit max limit Minimum actual speed for speed controller adaptation. Maximum actual speed for speed controller adaptation.	(90.01) (rpm) ► 1 = 1 rpm
25.19	25.22 Ti adapt co 030000 rpm Speed adapt max limit	at min speed or ef at min speed 0 25.18 Speed 25.19 Speed adapt adapt min limit 25.19 Speed adapt max limit Minimum actual speed for speed controller adaptation. Maximum actual speed for speed controller adaptation. See parameter 25.18 Speed adapt min limit.	(90.01) (rpm) 1 = 1 rpm 0 rpm
	25.22 Ti adapt co 030000 rpm Speed adapt max limit 030000 rpm Kp adapt coef at	at min speed or ef at min speed 0 25.18 Speed 25.19 Speed adapt adapt min limit 25.19 Speed adapt max limit Minimum actual speed for speed controller adaptation. Maximum actual speed for speed controller adaptation. See parameter 25.18 Speed adapt min limit. Maximum actual speed for speed controller adaptation. See parameter 25.18 Speed adapt min limit. Maximum actual speed for speed controller adaptation. Proportional gain coefficient at minimum actual speed.	(90.01) (rpm) → 1 = 1 rpm 0 rpm 1 = 1 rpm
	25.22 Ti adapt co 030000 rpm Speed adapt max limit 030000 rpm Kp adapt coef at min speed	at min speed or ef at min speed 0 25.18 Speed 25.19 Speed adapt adapt min limit 25.19 Speed adapt max limit Minimum actual speed for speed controller adaptation. Maximum actual speed for speed controller adaptation. See parameter 25.18 Speed adapt min limit. Maximum actual speed for speed controller adaptation. See parameter 25.18 Speed adapt min limit. Maximum actual speed for speed controller adaptation. Proportional gain coefficient at minimum actual speed. See parameter 25.18 Speed adapt min limit.	(90.01) (rpm) 1 = 1 rpm 0 rpm 1 = 1 rpm 1.000

No.	Name/Value	Description	Def/FbEq16	
25.25	Torque adapt max limit	 Maximum torque reference for speed controller adaptation. Speed controller gain can be adapted according to the final unlimited torque reference (26.01 Torque reference to TC). This can be used to smooth out disturbances caused by a small load and backlashes. The functionality involves multiplying the gain (25.02 Speed proportional gain) by a coefficient within a certain torque range. When the torque reference is 0%, the gain is multiplied by the value of parameter 25.27 Kp adapt coef at min torque. When the torque reference is equal to or above 25.25 Torque adapt max limit, no adaptation takes place (the coefficient is 1). Between 0% and 25.25 Torque adapt max limit, the coefficient for the gain is calculated linearly on the basis of the breakpoints. Filtering can be applied on the torque reference using parameter 25.26 Torque adapt filt time. See also the control chain diagram on page 636. 		
	Coefficient for K _p (proportional gain)			
	25.27 Kp adapt coef			
		Final to	orque reference (26.01) (rpm)	
		0 25.25 Torque adapt max limit		
	0.0 1600.0%	Maximum torque reference for speed controller adaptation.	See par. 46.03	
25.26	Torque adapt filt time	Defines a filter time constant for the adaptation, in effect adjusting the rate of change of the gain. See parameter <i>25.25 Torque adapt max limit</i> .	0.000 s	
	0.000 100.000 s	Filter time for adaptation.	100 = 1 s	
25.27	Kp adapt coef at	Proportional gain coefficient at 0% torque reference.	1.000	
	min torque	See parameter 25.25 Torque adapt max limit.		

No.	Name/Value	Description	Def/FbEq16
25.30	Flux adaption enable	Enables/disables speed controller adaptation based on motor flux reference (01.24 Flux actual %). The proportional gain of the speed controller is multiplied by a coefficient of 01 between 0100% flux reference respectively. See also the control chain diagram on page 636. Coefficient for K _p (proportional gain)	Enable
		0.000 Flux referenc 0.000 0 100	
	Disable	Speed controller adaptation based on flux reference disabled.	0
	Enable	Speed controller adaptation based on flux reference enabled.	1
25.33	Speed controller autotune	 Activates (or selects a source that activates) the speed controller autotune function. See section Speed controller autotune (page 77). The autotune will automatically set parameters 25.02 Speed proportional gain, 25.03 Speed integration time and 25.37 Mechanical time constant. The prerequisites for performing the autotune routine are: the motor identification run (ID run) has been successfully completed the speed and torque limits (parameter group 30 Limits) have been set speed feedback filtering (parameter group 90 Feedback selection), speed error filtering (24 Speed reference conditioning) and zero speed (21 Start/stop mode) have been set, and the drive has been started and is running in speed control mode. WARNING! The motor and machinery will run against the torque and speed limits during the autotune routine contine. MAKE SURE IT IS SAFE TO ACTIVATE THE AUTOTUNE FUNCTION! The autotune routine can be aborted by stopping the drive. 0 -> 1 = Activate speed controller autotune 	Off
	Off	0.	0
	On	1.	1
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-

No.	Name/Value	Description	Def/FbEq16
25.34	Speed controller autotune mode	Defines a control preset for the speed controller autotune function. The setting affects the way the torque reference will respond to a speed reference step.	Normal
	Smooth	Slow but robust response.	0
	Normal	Medium setting.	1
	Tight	Fast response. May produce too high a gain value for some applications.	2
25.37	Mechanical time constant	Mechanical time constant of the drive and the machinery as determined by the speed controller autotune function. The value can be adjusted manually.	-
	0.00 1000.00 s	Mechanical time constant.	10 = 1 s
25.38	Autotune torque step	Defines an added torque value used by the autotune function. This value is scaled to motor nominal torque. Note that the torque used by the autotune function can also be limited by the torque limits (in parameter group <i>30 Limits</i>) and nominal motor torque.	10.00%
	0.00 100.00%	Autotune torque step.	100 = 1%
25.39	Autotune speed step	Defines a speed value added to the initial speed for the autotune routine. The initial speed (speed used when autotune is activated) plus the value of this parameter is the calculated maximum speed used by the autotune routine. The maximum speed can also be limited by the speed limits (in parameter group <i>30 Limits</i>) and nominal motor speed. The value is scaled to motor nominal speed. Note: The motor will exceed the calculated maximum speed slightly at the end of each acceleration stage.	10.00%
	0.00 100.00%	Autotune speed step.	100 = 1%
25.40	Autotune repeat times	Determines how many acceleration/deceleration cycles are performed during the autotune routine. Increasing the value will improve the accuracy of the autotune function, and allow the use of smaller torque or speed step values.	10
	110	Number of cycles during autotune routine.	1 = 1
25.53	Torque prop reference	Displays the output of the proportional (P) part of the speed controller. See the control chain diagram on page 636. This parameter is read-only.	-
	-30000.0 30000.0%	P-part output of speed controller.	See par. 46.03
25.54	Torque integral reference	Displays the output of the integral (I) part of the speed controller. See the control chain diagram on page 636. This parameter is read-only.	-
	-30000.0 30000.0%	I-part output of speed controller.	See par. 46.03
25.55	Torque deriv reference	Displays the output of the derivative (D) part of the speed controller. See the control chain diagram on page 636. This parameter is read-only.	-
	-30000.0 30000.0%	D-part output of speed controller.	See par. 46.03

No.	Name/Value	Description	Def/FbEq16
25.56	Torque acc compensation	Displays the output of the acceleration compensation function. See the control chain diagram on page 636. This parameter is read-only.	-
	-30000.0 30000.0%	Output of acceleration compensation function.	See par. 46.03
25.57	Torque reference unbalanced	Displays the acceleration-compensated output of the speed controller. See the control chain diagram on page 636. This parameter is read-only.	-
	-30000.0 30000.0%	Acceleration-compensated output of speed controller.	See par. 46.03
26 Tor chain	que reference	Settings for the torque reference chain. See the control chain diagrams on pages 637 and 639.	
26.01	<i>Torque reference to TC</i>	Displays the final torque reference given to the torque controller in percent. This reference is then acted upon by various final limiters, like power, torque, load etc. See the control chain diagrams on pages 639 and 640. This parameter is read-only.	-
	-1600.0 1600.0%	Torque reference for torque control.	See par. 46.03
26.02	Torque reference used	Displays the final torque reference (in percent of motor nominal torque) given to the DTC core, and comes after frequency, voltage and torque limitation. See the control chain diagram on page 640. This parameter is read-only.	-
	-1600.0 1600.0%	Torque reference for torque control.	See par. 46.03
26.08	Minimum torque ref	Defines the minimum torque reference. Allows for local limiting of the torque reference before it is passed on to the torque ramp controller. For absolute torque limiting, refer to parameter <i>30.19 Minimum torque 1</i> .	-300.0%
	-1000.0 0.0%	Minimum torque reference.	See par. 46.03
26.09	Maximum torque ref	Defines the maximum torque reference. Allows for local limiting of the torque reference before it is passed on to the torque ramp controller. For absolute torque limiting, refer to parameter <i>30.20 Maximum torque 1</i> .	300.0%
	0.0 1000.0%	Maximum torque reference.	See par. 46.03

No.	Name/Value	Description	Def/FbEq16
26.11	Torque ref1 source	Selects torque reference source 1. Two signal sources can be defined by this parameter and 26.12 Torque ref2 source. A digital source selected by 26.14 Torque ref1/2 selection can be used to switch between the two sources, or a mathematical function (26.13 Torque ref1 function) applied to the two signals to create the reference.	Zero
	0 - 20 AI - (FB - (Other - (AI	5.11 26.13 Ref1 26.70 MUL 0 1 26.14 0 1 26.14 0 1 26.71 26.71	<u>5.72</u>
	Zero	None.	0
	AI1 scaled	12.12 Al1 scaled value (see page 182).	1
	AI2 scaled	12.22 Al2 scaled value (see page 184).	2
	FB A ref1	03.05 FB A reference 1 (see page 141).	4
	FB A ref2	03.06 FB A reference 2 (see page 141).	5
	EFB ref1	03.09 EFB reference 1 (see page 141).	8
	EFB ref2	03.10 EFB reference 2 (see page 141).	9
	DDCS ctrl ref1	03.11 DDCS controller ref 1 (see page 141).	10
	DDCS ctrl ref2	03.12 DDCS controller ref 2 (see page 141).	11
	M/F reference 1	03.13 M/F or D2D ref1 (see page 141).	12
	M/F reference 2	03.14 M/F or D2D ref2 (see page 141).	13
	Motor potentiometer	22.80 Motor potentiometer ref act (output of the motor potentiometer).	15
	PID	40.01 Process PID output actual (output of the process PID controller).	16
	Control panel (ref saved)	Control panel reference, with initial value from last-used panel reference. See section <i>Using the control panel as an external control source</i> (page 55).	18
	Control panel (ref copied)	Control panel reference, with initial value from previous source or actual value. See section <i>Using the control panel as an external control source</i> (page 55).	19
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
26.12	Torque ref2 source	Selects torque reference source 2. For the selections, and a diagram of reference source selection, see parameter 26.11 Torque ref1 source.	Zero

No.	Name/Value	Description	Def/FbEq16
26.13	Torque ref1 function	Selects a mathematical function between the reference sources selected by parameters 26.11 Torque ref1 source and 26.12 Torque ref2 source. See diagram at 26.11 Torque ref1 source.	Ref1
	Ref1	Signal selected by <i>26.11 Torque ref1 source</i> is used as torque reference 1 as such (no function applied).	0
	Add (ref1 + ref2)	The sum of the reference sources is used as torque reference 1.	1
	Sub (ref1 - ref2)	The subtraction ([26.11 Torque ref1 source] - [26.12 Torque ref2 source]) of the reference sources is used as torque reference 1.	2
	Mul (ref1 × ref2)	The multiplication of the reference sources is used as torque reference 1.	3
	Min (ref1, ref2)	The smaller of the reference sources is used as torque reference 1.	4
	Max (ref1, ref2)	The greater of the reference sources is used as torque reference 1.	5
26.14	Torque ref1/2 selection	Configures the selection between torque references 1 and 2. See diagram at 26.11 Torque ref1 source. 0 = Torque reference 1 1 = Torque reference 2	Torque reference 1
	Torque reference 1	0.	0
	Torque reference 2	1.	1
	Follow Ext1/Ext2 selection	Torque reference 1 is used when external control location EXT1 is active. Torque reference 2 is used when external control location EXT2 is active. See also parameter <i>19.11 Ext1/Ext2 selection</i> .	2
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	3
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	4
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	5
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	6
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	7
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	8
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
26.15	Load share	Defines the scaling factor for the torque reference (the torque reference is multiplied by the value). This allows drives sharing the load between two motors on the same mechanical plant to be tailored to share the correct amount each, yet use the same master torque reference.	1.000
	-8.000 8.000	Torque reference scaling factor.	1000 = 1
26.16	Torque additive 1 source	Selects the source for torque reference additive 1. Note: For safety reasons, the additive is not applied when an emergency stop is active. See the control chain diagram on page 637. For the selections, see parameter 26.11 Torque ref1 source.	Zero
26.17	Torque ref filter time	Defines a low-pass filter time constant for the torque reference.	0.000 s
	0.000 30.000 s	Filter time constant for torque reference.	1000 = 1 s

No.	Name/Value	Description	Def/FbEq16
26.18	Torque ramp up time	Defines the torque reference ramp-up time, ie. the time for the reference to increase from zero to nominal motor torque.	0.000 s
	0.000 60.000 s	Torque reference ramp-up time.	100 = 1 s
26.19	Torque ramp down time	Defines the torque reference ramp-down time, ie. the time for the reference to decrease from nominal motor torque to zero.	0.000 s
	0.000 60.000 s	Torque reference ramp-down time.	100 = 1 s
26.25	Torque additive 2 source	 Selects the source of torque reference additive 2. The value received from the selected source is added to the torque reference after operating mode selection. Because of this, the additive can be used in speed and torque modes. Note: For safety reasons, the additive is not applied when an emergency stop is active. WARNING! If the additive exceeds the limits set by parameters 25.11 Speed control min torque and 25.12 Speed control max torque, a ramp stop may be impossible. Make sure the additive is reduced or removed when a ramp stop is required eg. by using parameter 26.26 Force torque ref add 2 zero. See the control chain diagram on page 639. For the selections, see parameter 26.11 Torque ref1 source. 	Zero
26.26	Force torque ref add 2 zero	Selects a source that forces torque reference additive 2 (see parameter 26.25 Torque additive 2 source) to zero. 0 = Normal operation 1 = Force torque reference additive 2 to zero.	Not selected
	Not selected	0.	0
	Selected	1.	1
	DI1	Digital input DI1 (<i>10.02 DI delayed status</i> , bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
26.41	Torque step	 When enabled by parameter 26.42 Torque step enable, adds an additional step to the torque reference. WARNING! If the torque step exceeds the limits set by parameters 25.11 Speed control min torque and 25.12 Speed control max torque, a ramp stop may be impossible. Make sure the torque step is reduced or removed when a ramp stop is required eg. by using parameter 26.42 Torque step enable. 	0.0%
	-300.0 300.0%	Torque step.	See par. 46.03
26.42	Torque step enable	Enables/disables a torque step (defined by parameter <i>26.41 Torque step</i>).	Disable
	Disable	Torque step disabled.	0
	Enable	Torque step enabled.	1

No.	Name/Value	Description	Def/FbEq16
26.51	Oscillation damping	Parameters 26.5126.58 configure the oscillation damping function. See section Oscillation damping (page 80), and the block diagram on page 639. This parameter enables (or selects a source that enables) the oscillation damping algorithm.	Not selected
		1 = Oscillation damping algorithm enabled	
	Not selected	0.	0
	Selected	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
26.52	Oscillation damping out enable	Determines (or selects a source that determines) whether the output of the oscillation damping function is applied to the torque reference or not. Note: Before enabling the oscillation damping output, adjust parameters $26.5326.57$. Then monitor the input signal (selected by 26.53) and the output (26.58) to make sure that the correction is safe to apply. 1 = Apply oscillation damping output to torque reference	Not selected
	Not selected	0.	0
	Selected	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
26.53	Oscillation compensation input	Selects the input signal for the oscillation damping function. Note: Before changing this parameter run-time, disable the oscillation damping output using parameter 26.52. Monitor the behavior of 26.58 before re-enabling the output.	Speed error
	Speed error	24.01 Used speed reference - 24.02 Used speed feedback. Note: This setting is not supported in scalar motor control mode.	0
	DC voltage	01.11 DC voltage. (The value is internally filtered.)	1

No.	Name/Value	Description	Def/FbEq16
26.55	Oscillation damping frequency	Defines the center frequency of the oscillation damping filter. Set the value according to the number of oscillation peaks in the monitored signal (selected by 26.53) per second. Note: Before changing this parameter run-time, disable the oscillation damping output using parameter 26.52 . Monitor the behavior of 26.58 before re-enabling the output.	31.0 Hz
	0.1 60.0 Hz	Center frequency for oscillation damping.	10 = 1 Hz
26.56	Oscillation damping phase	Defines a phase shift for the output of the filter. Note: Before changing this parameter run-time, disable the oscillation damping output using parameter 26.52. Monitor the behavior of 26.58 before re-enabling the output.	180 deg
	0360 deg	Phase shift for oscillation damping function output.	10 = 1 deg
26.57	Oscillation damping gain	 Defines a gain for the output of the oscillation damping function, ie. how much the output of the filter is amplified before it is added to the torque reference. Oscillation gain is scaled according to the speed controller gain so that changing the gain will not disturb oscillation damping. Note: Before changing this parameter run-time, disable the oscillation damping output using parameter 26.52. Monitor the behavior of 26.58 before re-enabling the output. 	1.0%
	0.0 100.0%	Gain setting for oscillation damping output.	10 = 1%
26.58	Oscillation damping output	Displays the output of the oscillation damping function. This value is added to the torque reference (as allowed by parameter <i>26.52 Oscillation damping out enable</i>). This parameter is read-only.	-
	-1600.000 1600.000%	Output of the oscillation damping function.	10 = 1%
26.70	Torque reference act 1	Displays the value of torque reference source 1 (selected by parameter <i>26.11 Torque ref1 source</i>). See the control chain diagram on page 637. This parameter is read-only.	-
	-1600.0 1600.0%	Value of torque reference source 1.	See par. 46.03
26.71	Torque reference act 2	Displays the value of torque reference source 2 (selected by parameter <i>26.12 Torque ref2 source</i>). See the control chain diagram on page 637. This parameter is read-only.	-
	-1600.0 1600.0%	Value of torque reference source 2.	See par. 46.03
26.72	Torque reference act 3	Displays the torque reference after the function applied by parameter 26.13 Torque ref1 function (if any), and after selection (26.14 Torque ref1/2 selection). See the control chain diagram on page 637. This parameter is read-only.	-
	-1600.0 1600.0%	Torque reference after selection.	See par. 46.03
26.73	<i>Torque reference act 4</i>	Displays the torque reference after application of reference additive 1. See the control chain diagram on page 637. This parameter is read-only.	-
	-1600.0 1600.0%	Torque reference after application of reference additive 1.	See par. 46.03

No.	Name/Value	Description	Def/FbEq16
26.74	Torque ref ramp out	Displays the torque reference after limiting and ramping. See the control chain diagram on page 637. This parameter is read-only.	-
	-1600.0 1600.0%	Torque reference after limiting and ramping.	See par. 46.03
26.75	<i>Torque reference act 5</i>	Displays the torque reference after control mode selection. See the control chain diagram on page 639. This parameter is read-only.	-
	-1600.0 1600.0%	Torque reference after control mode selection.	See par. 46.03
26.76	<i>Torque reference act 6</i>	Displays the torque reference after application of reference additive 2. See the control chain diagram on page 639. This parameter is read-only.	-
	-1600.0 1600.0%	Torque reference after application of reference additive 2.	See par. 46.03
26.77	Torque ref add A actual	Displays the value of the source of torque reference additive 2. See the control chain diagram on page 639. This parameter is read-only.	-
	-1600.0 1600.0%	Torque reference additive 2.	See par. 46.03
26.78	Torque ref add B actual	Displays the value of torque reference additive 2 before it is added to torque reference. See the control chain diagram on page 639. This parameter is read-only.	-
	-1600.0 1600.0%	Torque reference additive 2.	See par. 46.03
26.81	Rush control gain	Rush controller gain term. See section <i>Rush control</i> (page <i>82</i>).	10.0
	0.010000.0	Rush controller gain (0.0 = disabled).	1 = 1
26.82	Rush control integration time	Rush controller integration time term.	2.0 s
	0.010.0 s	Rush controller integration time (0.0 = disabled).	1 = 1 s
28 Fre chain	quency reference	Settings for the frequency reference chain. See the control chain diagrams on pages 642 and 643.	
28.01	Frequency ref ramp	Displays the used frequency reference before ramping.	-

28.01	Frequency ref ramp input	Displays the used frequency reference before ramping. See the control chain diagrams on pages 642. This parameter is read-only.	-
	-500.00 500.00 Hz	Frequency reference before ramping.	See par. 46.02
28.02	Frequency ref ramp output	Displays the final frequency reference (after selection, limitation and ramping). See the control chain diagrams on pages 643. This parameter is read-only.	-
	-500.00 500.00 Hz	Final frequency reference.	See par. 46.02

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No.	Name/Value	Description	Def/FbEq16	
28.11	Frequency ref1 source Selects frequency reference source 1. Two signal sources can be defined by this parameter and 28.12 Frequency ref2 source. A digital source selected by 28.14 Frequency ref1/2 selection can be used to switch between the two sources, or a mathematical function (28.13 Frequency ref1 function) applied to the two signals to create the reference. 0 28.11 0 28.90 0 28.12 0 28.12 0 28.12 0 28.10 0 28.11 0 28.12 0 28.90 0 1 0 28.12 0 28.90 0 1 0 28.90 0 28.12 0 28.90 0 1 0 28.91			
	Zero	None.	0	
	AI1 scaled	12.12 Al1 scaled value (see page 182).	1	
	AI2 scaled	12.22 Al2 scaled value (see page 184).	2	
	FB A ref1	03.05 FB A reference 1 (see page 141).	4	
	FB A ref2	03.06 FB A reference 2 (see page 141).	5	
	EFB ref1	03.09 EFB reference 1 (see page 141).	8	
	EFB ref2	03.10 EFB reference 2 (see page 141).	9	
	DDCS ctrl ref1	03.11 DDCS controller ref 1 (see page 141).	10	
	DDCS ctrl ref2	03.12 DDCS controller ref 2 (see page 141).	11	
	M/F reference 1	03.13 M/F or D2D ref1 (see page 141).	12	
	M/F reference 2	03.14 M/F or D2D ref2 (see page 141).	13	
	Motor potentiometer	22.80 Motor potentiometer ref act (output of the motor potentiometer).	15	
	PID	40.01 Process PID output actual (output of the process PID controller).	16	
	Control panel (ref saved) Control panel reference, with initial value from last-used pan reference. See section Using the control panel as an extern control source (page 55).		18	
	Control panel (ref copied)	Control panel reference, with initial value from previous source or actual value. See section <i>Using the control panel as an external control source</i> (page 55).	19	
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-	
28.12	Frequency ref2 source	Selects frequency reference source 2. For the selections, and a diagram of reference source selection, see parameter 28.11 Frequency ref1 source.	Zero	

No.	Name/Value	Description	Def/FbEq16
28.13	Frequency ref1 function	Selects a mathematical function between the reference sources selected by parameters 28.11 Frequency ref1 source and 28.12 Frequency ref2 source. See diagram at 28.11 Frequency ref1 source.	Ref1
	Ref1	Signal selected by 28.11 Frequency ref1 source is used as frequency reference 1 as such (no function applied).	0
	Add (ref1 + ref2)	The sum of the reference sources is used as frequency reference 1.	1
	Sub (ref1 - ref2)	The subtraction ([28.11 Frequency ref1 source] - [28.12 Frequency ref2 source]) of the reference sources is used as frequency reference 1.	2
	Mul (ref1 × ref2)	The multiplication of the reference sources is used as frequency reference 1.	3
	Min (ref1, ref2)	The smaller of the reference sources is used as frequency reference 1.	4
	Max (ref1, ref2)	The greater of the reference sources is used as frequency reference 1.	5
28.14	Frequency ref1/2 selection	Configures the selection between frequency references 1 and 2. See diagram at 28.11 Frequency ref1 source. 0 = Frequency reference 1 1 = Frequency reference 2	Follow Ext1/Ext2 selection
	Frequency reference 1	0.	0
	Frequency reference 2	1.	1
	Follow Ext1/Ext2 selection	Frequency reference 1 is used when external control location EXT1 is active. Frequency reference 2 is used when external control location EXT2 is active. See also parameter <i>19.11 Ext1/Ext2 selection</i> .	2
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	3
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	4
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	5
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	6
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	7
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	8
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-

	Namery	/alue	Des	cription			Def/FbEq16
1	Constar function	nt frequency	whet		tant frequencies ar irection signal is co tant frequency.		0000b
	Bit	Name		Information			
	0	Constant fre	. 5	sources defined b	y parameters 28.2	are selectable using t 2, 28.23 and 28.24.	
			k r	by the sources de	fined by parameter se of conflict, the c	1, 2 and 3 are separa rs 28.22, 28.23 and 2 constant frequency wi	8.24
	1	Direction enable	s r f	sign of the constant multiplied by the d effectively allows the frequencies if all v WARNING constant fr direction.	nt frequency settin lirection signal (for the drive to have 1- alues in 28.2628 If the direction si- equency is negative	gnal is reverse and th ve, the drive will run in	28.32) is This e) constant he active h the forward
			c			rection for the constan int speed setting (para	
	0000b	.0011b	Con	stant frequency co	onfiguration word.		1 = 1
	sel1	nt frequency			a source that activation	<i>frequency function</i> is ates constant	Not selected
	sel1		0 (Se frequ Whe 1 (Pa frequ	eparate), selects a uency 1. en bit 0 of paramet acked), this paran uency sel2 and 28 e sources whose s	a source that active er 28.21 Constant neter and paramete 8.24 Constant frequ	ates constant frequency function is ers 28.23 Constant	
	sel1	Source defi	0 (Se frequ Whe 1 (Pa frequ three follow	eparate), selects a uency 1. en bit 0 of paramet acked), this paran uency sel2 and 28 e sources whose s ws: Source defined	a source that active er 28.21 Constant neter and paramete 3.24 Constant freque states activate con	ates constant frequency function is ers 28.23 Constant uency sel3 select stant frequencies as Constant frequencies	
	sel1		0 (Se frequ Whe 1 (Pa frequ three follow	eparate), selects a uency 1. en bit 0 of paramet acked), this paran uency sel2 and 28 e sources whose s ws:	a source that active er 28.21 Constant neter and paramete 8.24 Constant freque states activate con	ates constant frequency function is ers 28.23 Constant dency sel3 select stant frequencies as Constant frequencies	
	sel1	Source defi by par. 28	0 (Se frequ Whe 1 (Pa frequ three follow	eparate), selects a uency 1. en bit 0 of paramet acked), this paran uency sel2 and 28 e sources whose s ws: Source defined by par. 28.23	a source that activa er 28.21 Constant neter and paramete 8.24 Constant frequ states activate con Source defined by par. 28.24	ates constant frequency function is ers 28.23 Constant uency sel3 select stant frequencies as Constant frequencies	ncy
	sel1	Source defi by par. 28	0 (Se frequ Whe 1 (Pa frequ three follow	eparate), selects a uency 1. en bit 0 of paramet acked), this paran uency sel2 and 28 e sources whose s ws: Source defined by par. 28.23 0	a source that activa er 28.21 Constant neter and paramete 8.24 Constant freque states activate con Source defined by par. 28.24 0	ates constant frequency function is ers 28.23 Constant uency sel3 select stant frequencies as Constant frequencies active None	ncy cy 1
	sel1	Source defi by par. 28 0 1	0 (Se frequ Whe 1 (Pa frequ three follow	eparate), selects a uency 1. en bit 0 of paramet acked), this paran <i>uency sel2</i> and 28 e sources whose s ws: Source defined by par. 28.23 0 0	a source that active er 28.21 Constant neter and paramete 3.24 Constant freque states activate con Source defined by par. 28.24 0 0	ates constant frequency function is ers 28.23 Constant uency sel3 select stant frequencies as Constant frequencies active None Constant frequencies	ncy cy 1 cy 2
	sel1	Source defi by par. 28 0 1 0	0 (Se frequ Whe 1 (Pa frequ three follow	eparate), selects a uency 1. en bit 0 of paramet acked), this paran uency sel2 and 28 e sources whose s ws: Source defined by par. 28.23 0 0 1	a source that activa er 28.21 Constant neter and parameter 8.24 Constant frequestates activate con states activate con Source defined by par. 28.24 0 0 0	ates constant frequency function is ers 28.23 Constant uency sel3 select stant frequencies as Constant frequencies Constant frequencies Constant frequencies Constant frequencies	ncy cy 1 cy 2 cy 3 cy 4
	sel1	Source defi by par. 28 0 1 0 1 0 1 0 1	0 (Se frequ Whe 1 (Pa frequ three follow	eparate), selects a uency 1. en bit 0 of paramet acked), this paran uency sel2 and 28 e sources whose s ws: Source defined by par. 28.23 0 0 1 1 0 0 0	a source that activate a source that activate and parameter and parameter and parameter and parameter activate activate activate constant frequences activate activat	ates constant frequency function is ers 28.23 Constant uency sel3 select stant frequencies as Constant frequencies None Constant frequencies Constant frequencies Constant frequencies Constant frequencies	ncy cy 1 cy 2 cy 3 cy 4 cy 5
	sel1	Source defi by par. 28. 0 1 0 1 0 1 0 1 0	0 (Se frequ Whe 1 (Pa frequ three follow	eparate), selects a uency 1. en bit 0 of paramet acked), this param uency sel2 and 28 e sources whose s ws: Source defined by par. 28.23 0 0 1 1 0 0 1 1 1 0 0 1	a source that activate a source that activate and parameter and parameter and parameters. 24 Constant frequestates activate constant states activate constant states activate	ates constant frequency function is ers 28.23 Constant jency sel3 select stant frequencies as Constant frequencies Constant frequencies Constant frequencies Constant frequencies Constant frequencies Constant frequencies Constant frequencies Constant frequencies	ncy cy 1 cy 2 cy 3 cy 4 cy 5 cy 6
	sel1	Source defi by par. 28 0 1 0 1 0 1 0 1	0 (Se frequ Whe 1 (Pa frequ three follow	eparate), selects a uency 1. en bit 0 of paramet acked), this paran uency sel2 and 28 e sources whose s ws: Source defined by par. 28.23 0 0 1 1 0 0 0	a source that activate a source that activate and parameter and parameter and parameter and parameter activate activate activate constant frequences activate activat	ates constant frequency function is ers 28.23 Constant uency sel3 select stant frequencies as Constant frequencies None Constant frequencies Constant frequencies Constant frequencies Constant frequencies	ncy cy 1 cy 2 cy 3 cy 4 cy 5 cy 6
	sel1	Source defi by par. 28 0 1 0 1 0 1 0 1 0 1	0 (Se frequ Whe 1 (Pa frequ three follow	eparate), selects a uency 1. en bit 0 of paramet acked), this param uency sel2 and 28 e sources whose s ws: Source defined by par. 28.23 0 0 1 1 0 0 1 1 1 0 0 1	a source that activate a source that activate and parameter and parameter and parameters. 24 Constant frequestates activate constant states activate constant states activate	ates constant frequency function is ers 28.23 Constant jency sel3 select stant frequencies as Constant frequencies Constant frequencies Constant frequencies Constant frequencies Constant frequencies Constant frequencies Constant frequencies Constant frequencies	ncy cy 1 cy 2 cy 3 cy 4 cy 5 cy 6
		Source defi by par. 28. 0 1 0 1 0 1 0 1 0 1 2 0 1 2 0	0 (Se frequ Whe 1 (Pa frequ three follow	eparate), selects a uency 1. en bit 0 of paramet acked), this param uency sel2 and 28 e sources whose s ws: Source defined by par. 28.23 0 0 1 1 0 0 1 1 1 0 0 1	a source that activate a source that activate and parameter and parameter and parameters. 24 Constant frequestates activate constant states activate constant states activate	ates constant frequency function is ers 28.23 Constant jency sel3 select stant frequencies as Constant frequencies Constant frequencies Constant frequencies Constant frequencies Constant frequencies Constant frequencies Constant frequencies Constant frequencies	ncy cy 1 cy 2 cy 3 cy 4 cy 5 cy 6 cy 7
	Not sele	Source defi by par. 28. 0 1 0 1 0 1 0 1 0 1 2 0 1 2 0	0 (Se frequ Whe 1 (Pa frequ three follow ned .22	eparate), selects a uency 1. en bit 0 of paramet acked), this paran uency sel2 and 28 e sources whose s ws: Source defined by par. 28.23 0 0 1 1 1 1 0 0 1 1 1	a source that activate a source that activate and parameter and parameter and parameter and parameter and parameter and parameter activate activate activate constant frequencies activate activ	ates constant frequency function is ers 28.23 Constant uency sel3 select stant frequencies as Constant frequence Constant frequence Constan	ncy cy 1 cy 2 cy 3 cy 4 cy 5 cy 6 cy 7
	Not sele Selecte	Source defi by par. 28. 0 1 0 1 0 1 0 1 0 1 2 0 1 2 0	0 (Se frequ Whe 1 (Pa frequ three follow ned .22	eparate), selects a uency 1. en bit 0 of paramet acked), this paran uency sel2 and 28 e sources whose s ws: Source defined by par. 28.23 0 0 1 1 1 0 0 1 1 1 1 1 1 1 1 1 1 1 1	a source that activate a source that activate and parameter and parameter and parameters. 24 Constant frequences activate constant states activate constant states activate ac	ates constant frequency function is ers 28.23 Constant Jency sel3 select stant frequencies as Constant frequencies Constant fr	ncy cy 1 cy 2 cy 3 cy 4 cy 5 cy 6 cy 7
	Not sele Selecte DI1	Source defi by par. 28. 0 1 0 1 0 1 0 1 0 1 2 0 1 2 0	0 (Se frequ Whe 1 (Pa frequ three follow ned .22	eparate), selects a uency 1. en bit 0 of paramet acked), this param uency sel2 and 28 e sources whose s ws: Source defined by par. 28.23 0 0 1 1 1 0 0 1 1 1 1 1 1 1 1 1 1 1 1	a source that active er 28.21 Constant neter and paramete 3.24 Constant freque states activate con Source defined by par. 28.24 0 0 0 0 1 1 1 1 1 2 DI delayed statue	ates constant frequency function is ers 28.23 Constant Jency sel3 select stant frequencies as Constant frequence Constant frequence Constan	ncy cy 1 cy 2 cy 3 cy 4 cy 5 cy 6 cy 7
	Not sele Selecte DI1 DI2	Source defi by par. 28. 0 1 0 1 0 1 0 1 0 1 2 0 1 2 0	0 (Se frequ Whe 1 (Pa frequ three follow ned .22	eparate), selects a uency 1. en bit 0 of paramet acked), this param uency sel2 and 28 e sources whose s ws: Source defined by par. 28.23 0 0 1 1 1 0 0 1 1 1 1 1 1 0 0 1 1 1 1	a source that activa er 28.21 Constant neter and parameter 24 Constant frequestates activate con Source defined by par. 28.24 0 0 0 0 0 1 1 1 1 1 2 DI delayed statues 2 DI delayed statues 2 DI delayed statues	ates constant frequency function is ers 28.23 Constant uency sel3 select stant frequencies as Constant frequence Constant frequence S, bit 0). s, bit 1). s, bit 2).	ncy cy 1 cy 2 cy 3 cy 4 cy 5 cy 6 cy 7 0 1 2 3

No.	Name/Value	Description	Def/FbEq16
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
28.23	Constant frequency sel2	 When bit 0 of parameter 28.21 Constant frequency function is 0 (Separate), selects a source that activates constant frequency 2. When bit 0 of parameter 28.21 Constant frequency function is 1 (Packed), this parameter and parameters 28.22 Constant frequency sel1 and 28.24 Constant frequency sel3 select three sources that are used to activate constant frequencies. See table at parameter 28.22 Constant frequency sel1. For the selections, see parameter 28.22 Constant frequency sel1. 	Not selected
28.24	Constant frequency sel3	 When bit 0 of parameter 28.21 Constant frequency function is 0 (Separate), selects a source that activates constant frequency 3. When bit 0 of parameter 28.21 Constant frequency function is 1 (Packed), this parameter and parameters 28.22 Constant frequency sel1 and 28.23 Constant frequency sel2 select three sources that are used to activate constant frequencies. See table at parameter 28.22 Constant frequency sel1. For the selections, see parameter 28.22 Constant frequency sel1. 	Not selected
28.26	Constant frequency 1	Defines constant frequency 1 (the frequency the motor will turn when constant frequency 1 is selected).	0.00 Hz
	-500.00 500.00 Hz	Constant frequency 1.	See par. 46.02
28.27	Constant frequency 2	Defines constant frequency 2.	0.00 Hz
	-500.00 500.00 Hz	Constant frequency 2.	See par. 46.02
28.28	Constant frequency 3	Defines constant frequency 3.	0.00 Hz
	-500.00 … 500.00 Hz	Constant frequency 3.	See par. 46.02
28.29	Constant frequency 4	Defines constant frequency 4.	0.00 Hz
	-500.00 500.00 Hz	Constant frequency 4.	See par. 46.02
28.30	Constant frequency 5	Defines constant frequency 5.	0.00 Hz
	-500.00 500.00 Hz	Constant frequency 5.	See par. 46.02
28.31	<i>Constant frequency</i> 6	Defines constant frequency 6.	0.00 Hz
	-500.00 500.00 Hz	Constant frequency 6.	See par. 46.02

No.	Name/	Value	Description	Def/FbEq16		
28.32	Consta 7	nt frequency	Defines constant frequency 7.	0.00 Hz		
	-500.00 Hz) 500.00	Constant frequency 7.	See par. 46.02		
28.41	Freque	ncy ref safe	Defines a safe frequency reference value that is used with supervision functions such as	0.00 Hz		
			12.03 AI supervision function			
			49.05 Communication loss action			
			50.02 FBA A comm loss func			
			50.32 FBA B comm loss func			
			58.14 Communication loss action.			
	-500.00 Hz) 500.00	Safe frequency reference.	See par. 46.02		
28.51	Critical functio	frequency 1	Enables/disables the critical frequencies function. Also determines whether the specified ranges are effective in both rotating directions or not. See also section <i>Critical speeds/frequencies</i> (page 76).	0000b		
	Bit	Name	Information			
	0	Enable	1 = Enable: Critical frequencies enabled.			
			0 = Disable: Critical frequencies disabled.			
	1	Sign mode	 1 = According to par: The signs of parameters 28.5228.57 are taken into account. 0 = Absolute: Parameters 28.5228.57 are handled as absolute values. Each range is effective in both directions of rotation. 			
	0000b.	0011b	Critical frequencies configuration word.	1 = 1		
28.52	Critical Iow	frequency 1	Defines the low limit for critical frequency 1. Note: This value must be less than or equal to the value of 28.53 <i>Critical frequency 1 high</i> .	0.00 Hz		
	-500.00 Hz) 500.00	Low limit for critical frequency 1.	See par. 46.02		
28.53	Critical high	frequency 1	Defines the high limit for critical frequency 1. Note: This value must be greater than or equal to the value of 28.52 <i>Critical frequency 1 low</i> .	0.00 Hz		
	-500.00 Hz) 500.00	High limit for critical frequency 1.	See par. 46.02		
28.54	Critical Iow	frequency 2	Defines the low limit for critical frequency 2. Note: This value must be less than or equal to the value of 28.55 <i>Critical frequency 2 high</i> .	0.00 Hz		
	-500.00 Hz) 500.00	Low limit for critical frequency 2.	See par. 46.02		
28.55	Critical high	frequency 2	Defines the high limit for critical frequency 2. Note: This value must be greater than or equal to the value of 28.54 <i>Critical frequency 2 low</i> .	0.00 Hz		
	-500.00 Hz) 500.00	High limit for critical frequency 2.	See par. 46.02		

No.	Name/Value	Description	Def/FbEq16
28.56	Critical frequency 3 low	Defines the low limit for critical frequency 3. Note: This value must be less than or equal to the value of 28.57 <i>Critical frequency 3 high</i> .	0.00 Hz
	-500.00 … 500.00 Hz	Low limit for critical frequency 3.	See par. 46.02
28.57	Critical frequency 3 high	Defines the high limit for critical frequency 3. Note: This value must be greater than or equal to the value of 28.56 <i>Critical frequency 3 low</i> .	0.00 Hz
	-500.00 500.00 Hz	High limit for critical frequency 3.	See par. 46.02
28.71	Freq ramp set selection	Selects a source that switches between the two sets of acceleration/deceleration times defined by parameters 28.7228.75. 0 = Acceleration time 1 and deceleration time 1 are in force 1 = Acceleration time 2 and deceleration time 2 are in force	Acc/Dec time 1
	Acc/Dec time 1	0. PID	0
	Acc/Dec time 2	1. 30.23	1
	DI1	Other Digital input DI1 (<i>10.02 DI delayed status</i> , bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (<i>10.02 DI delayed status</i> , bit 5).	7
	DIO1	Digital input/output DIO1 (<i>11.02 DIO delayed status</i> , bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
28.72	Freq acceleration time 1	Defines acceleration time 1 as the time required for the frequency to change from zero to the frequency defined by parameter 46.02 Frequency scaling (not to parameter 30.14 Maximum frequency). If the reference increases faster than the set acceleration rate, the motor will follow the acceleration rate. If the reference increases slower than the set acceleration rate, the motor frequency will follow the reference. If the acceleration time is set too short, the drive will automatically prolong the acceleration in order not to exceed the drive torque limits.	20.000 s
	0.000 1800.000 s	Acceleration time 1.	10 = 1 s
28.73	Freq deceleration time 1	Defines deceleration time 1 as the time required for the frequency to change from the frequency defined by parameter 46.02 Frequency scaling (not from parameter 30.14 Maximum frequency) to zero. If there is any doubt about the deceleration time being too short, ensure that DC overvoltage control (30.30 Overvoltage control) is on. Note: If a short deceleration time is needed for a high inertia application, the drive should be equipped with braking equipment such as a brake chopper and brake resistor.	20.000 s
	0.000 1800.000	Deceleration time 1.	10 = 1 s

No.	Name/Value	Description	Def/FbEq16
28.74	Freq acceleration time 2	Defines acceleration time 2. See parameter 28.72 Freq acceleration time 1.	60.000 s
	0.000 1800.000 s	Acceleration time 2.	10 = 1 s
28.75	Freq deceleration time 2	Defines deceleration time 2. See parameter 28.73 Freq deceleration time 1.	60.000 s
	0.000 1800.000 s	Deceleration time 2.	10 = 1 s
28.76	Freq ramp in zero source	Selects a source that forces the frequency reference to zero. 0 = Force frequency reference to zero 1 = Normal operation	Inactive
	Active	0.	0
	Inactive	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
28.77	Freq ramp hold	Selects a source that forces the output of the frequency ramp generator to actual frequency value. 0 = Force ramp output to actual frequency 1 = Normal operation	Inactive
	Active	0.	0
	Inactive	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
28.78	Freq ramp output balancing	Defines a reference for frequency ramp balancing. The output of the ramp generator is forced to this value when balancing is enabled by parameter <i>28.79 Freq ramp out balancing enable</i> .	0.00 Hz
	-500.00 500.00 Hz	Frequency ramp balancing reference.	See par. 46.02

No.	Name/Value	Description	Def/FbEq16
28.79	Freq ramp out balancing enable	Selects the source for enabling/disabling speed ramp balancing. See parameter 28.78 Freq ramp output balancing. 0 = Disabled 1 = Enabled	Not selected
	Not selected	0.	
	Selected	1.	
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
28.90	Frequency ref act 1	Displays the value of frequency reference source 1 (selected by parameter <i>28.11 Frequency ref1 source</i>). See the control chain diagram on page <i>642</i> . This parameter is read-only.	-
	-500.00 500.00 Hz	Value of frequency reference source 1.	See par. 46.02
28.91	Frequency ref act 2	Displays the value of frequency reference source 2 (selected by parameter 28.12 Frequency ref2 source). See the control chain diagram on page 642. This parameter is read-only.	-
	-500.00 500.00 Hz	Value of frequency reference source 2.	See par. 46.02
28.92	Frequency ref act 3	Displays the frequency reference after the function applied by parameter <i>28.13 Frequency ref1 function</i> (if any), and after selection (<i>28.14 Frequency ref1/2 selection</i>). See the control chain diagram on page 642. This parameter is read-only.	-
	-500.00 … 500.00 Hz	Frequency reference after selection.	See par. 46.02
28.96	Frequency ref act 7	Displays the frequency reference after application of constant frequencies, control panel reference, etc. See the control chain diagram on page 642. This parameter is read-only.	-
	-500.00 500.00 Hz	Frequency reference 7.	See par. 46.02
28.97	Frequency ref unlimited	Displays the frequency reference after application of critical frequencies, but before ramping and limiting. See the control chain diagram on page 643. This parameter is read-only.	-
	-500.00 500.00 Hz	Frequency reference before ramping and limiting.	See par. 46.02

No.	Name/	Value Des	scription	Def/FbEq16
30 Lim	nits	Driv	e operation limits.	
30.01	Limit w		olays limit word 1. s parameter is read-only.	-
	Bit	Name	Description	
	0	Torq lim	1 = Drive torque is being limited by the motor control (un control, current control, load angle control or pull-out cor torque limits defined by parameters.	
	1	Spd ctl tlim min	1 = Speed controller output is being limited by 25.11 Spe torque	ed control min
	2	Spd ctl tlim max	1 = Speed controller output is being limited by 25.12 Sp max torque	eed control
	3	Torq ref max	1 = Torque reference ramp input is being limited by 26.0 torque ref, source of 30.25 Maximum torque sel, 30.26 motoring limit or 30.27 Power generating limit. See diag 640.	Power
	4	Torq ref min	1 = Torque reference ramp input is being limited by 26.0 torque ref, source of 30.18 Minimum torque sel, 30.26 P limit or 30.27 Power generating limit. See diagram on pa	ower motoring
	5	Tlim max speed	1 = Torque reference is being limited by the rush contro maximum speed limit (<i>30.12 Maximum speed</i>)	l because of
	6	Tlim min speed	1 = Torque reference is being limited by the rush contro minimum speed limit (<i>30.11 Minimum speed</i>)	l because of
	7	Max speed ref li	m 1 = Speed reference is being limited by 30.12 Maximum maximum permanent magnet motor speed limit based of	
	8	Min speed ref lin	n 1 = Speed reference is being limited by 30.11 Minimum maximum permanent magnet motor speed limit based of	
	9	Max freq ref lim	1 = Frequency reference is being limited by 30.14 Maxir	num frequency
	10	Min freq ref lim	1 = Frequency reference is being limited by 30.13 Minin	num frequency
	11	Reserved		
	12	Sw freq ref lim	1 = Requested output frequency cannot be reached bec switching frequency limitation (because of eg. output filt related protections)	
	0000h	FFFFh Lim	it word 1.	1 = 1

No.	Name/	Value	Desc	ription	Def/FbEq16		
30.02	Torque	limit status	•	ays the torque controller limitation status word. parameter is read-only.	-		
	Bit Name			Description			
	0	Undervolta	ge	*1 = Intermediate DC circuit undervoltage			
	1	Overvoltage	Э	*1 = Intermediate DC circuit overvoltage			
	2	Minimum torque		*1 = Torque is being limited by 30.26			
				, 30.27 Power generating limit or the source of 30.18 Mir sel. See diagram on page 640.	nimum torque		
	3	Maximum t	orque	*1 = Torque is being limited by 30.26 Power motoring lim Power generating limit or the source of 30.25 Maximum See diagram on page 640.			
	4	Internal cur	rent	1 = An inverter current limit (identified by bits 811) is a	ctive		
	5 Load angle			 (With permanent magnet motors and synchronous reluctionly) 1 = Load angle limit is active, ie. the motor cannot produce 			
	6	Motor pullo	ut	torque (With asynchronous motors only) 1 = Motor pull-out limit is active, ie. the motor cannot produce anymore torque			
	7	Reserved					
	8	Thermal		1 = Input current is being limited by the main circuit thermal limit			
	9	Max curren	t	*1 = Maximum output current (I_{MAX}) is being limited			
	10	User currer	nt	*1 = Output current is being limited by 30.17 Maximum current			
	11	Thermal IG	BT	 *1 = Output current is being limited by a calculated thermal current value *1 = Output current is being limited because of estimated IGBT temperature *1 = Output current is being limited because of IGBT junction to case temperature 			
	12	IGBT overtemper	ature				
	13	IGBT overlo	bad				
	141	5 Reserved		_ ·			
				and one out of bits 913 can be on simultaneously. The ceeded first.	bit typically		
	0000h.	FFFFh	Torqu	e limitation status word.	1 = 1		
30.11	Minimu	ım speed		 es the minimum allowed speed. WARNING! This value must not be higher than 30.12 Maximum speed. WARNING! In frequency control mode, this limit is not effective. Make sure the frequency limits (30.13 and 30.14) are set appropriately if frequency control is used. WARNING! In a master/follower configuration, do not set maximum and minimum speed limits with the same sign on a follower drive. See section Master/follower functionality (page 64). 	-1500.00 rpm; -1800.00 rpn (95.20 b0)		
	-30000 30000.	0.00 00 rpm	Minin	num allowed speed.	See par. 46.01		

No.	Name/Value	Description	Def/FbEq16
30.12	Maximum speed	 Defines the maximum allowed speed. WARNING! This value must not be lower than 30.11 Minimum speed. WARNING! In frequency control mode, this limit is not effective. Make sure the frequency limits (30.13 and 30.14) are set appropriately if frequency control is used. WARNING! In a master/follower configuration, do not set maximum and minimum speed limits with the same sign on a follower drive. See section Master/follower functionality (page 64). 	1500.00 rpm; 1800.00 rpm (95.20 b0)
	-30000.00 30000.00 rpm	Maximum speed.	See par. 46.01
30.13	Minimum frequency	Defines the minimum allowed frequency. WARNING! This value must not be higher than 30.14 Maximum frequency. WARNING! This limit is effective in frequency control mode only.	-50.00 Hz; -60.00 Hz (95.20 b0)
	-500.00 500.00 Hz	Minimum frequency.	See par. 46.02
30.14	Maximum frequency	Defines the maximum allowed frequency. WARNING! This value must not be lower than 30.13 Minimum frequency. WARNING! This limit is effective in frequency control mode only.	50.00 Hz; 60.00 Hz (95.20 b0)
	-500.00 500.00 Hz	Maximum frequency.	See par. 46.02
30.15	Maximum start current enable	A temporary motor current limit specifically for starting can be defined by this parameter and <i>30.16 Maximum start current</i> . When this parameter is set to <i>Enable</i> , the drive observes the start current limit defined by <i>30.16 Maximum start current</i> . The limit is in force for 2 seconds after initial magnetization (of an asynchronous induction motor) or autophasing (of a permanent magnet motor), but not more often than once in every 7 seconds. Otherwise, the limit defined by <i>30.17 Maximum current</i> is in force. Note: The availability of a start current higher than the general limit depends on drive hardware.	Disable
	Disable	Start current limit disabled.	0
	Enable	Start current limit enabled.	1
30.16	Maximum start current	Defines a maximum start current when enabled by parameter <i>30.15 Maximum start current enable</i> .	-
	0.00 30000.00 A	Maximum start current.	1 = 1 A
30.17	Maximum current	Defines the maximum allowed motor current.	0.00 A
	0.00 30000.00 A	Maximum motor current.	1 = 1 A

No.	Name/Value	Description	Def/FbEq16
30.18	Minimum torque sel	Selects a source that switches between two different predefined minimum torque limits. 0 = Minimum torque limit defined by 30.19 is active 1 = Minimum torque limit selected by 30.21 is active The user can define two sets of torque limits, and switch between the sets using a binary source such as a digital input. The minimum limit selection (30.18) is independent of the maximum limit selection (30.25). The first set of limits is defined by parameters 30.19 and 30.20. The second set has selector parameters for both the minimum (30.21) and maximum (30.22) limits that allows the use of a selectable analog source (such as an analog input).	Minimum torque 1
		30.21 30.18 1 User-defined minimum torque limit	
		30.22 0 Al1 Al2 PID 30.24 Other 30.20 User-defined maximum torque limit	
		The limit selection parameters are updated on a 10 ms time level. Note: In addition to the user-defined limits, torque may be limited for other reasons (such as power limitation). Refer to the block diagram on page <i>640</i> .	
	Minimum torque 1	0 (minimum torque limit defined by <i>30.19</i> is active).	0
	Minimum torque 2 source	1 (minimum torque limit selected by <i>30.21</i> is active).	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see Terms and abbreviations on page 131).	-

No.	Name/Value	Description	Def/FbEq16
30.19	Minimum torque 1	 Defines a minimum torque limit for the drive (in percent of nominal motor torque). See diagram at parameter 30.18 Minimum torque sel. The limit is effective when the source selected by 30.18 Minimum torque sel is 0, or 30.18 is set to Minimum torque 1. Note: Do not set this parameter to 0% in an attempt to prevent reverse rotation. In an open-loop application, that is likely to prevent the motor from stopping altogether. To prevent reverse rotation, use the speed/frequency limits in this parameter group, or parameters 20.23/20.24. 	-300.0%
	-1600.0 1600.0%	Minimum torque limit 1.	See par. 46.03
30.20	Maximum torque 1	 Defines a maximum torque limit for the drive (in percent of nominal motor torque). See diagram at parameter 30.18 <i>Minimum torque sel</i>. The limit is effective when the source selected by 30.25 <i>Maximum torque sel</i> is 0, or 30.25 is set to <i>Maximum torque 1</i>. 	300.0%
	-1600.0 1600.0%	Maximum torque 1.	See par. 46.03
30.21	Minimum torque 2 source	 Defines the source of the minimum torque limit for the drive (in percent of nominal motor torque) when the source selected by parameter <i>30.18 Minimum torque sel</i> is 1, or <i>30.18</i> is set to <i>Minimum torque 2 source</i>. See diagram at <i>30.18 Minimum torque sel</i>. Note: Any positive values received from the selected source are inverted. 	Minimum torque 2
	Zero	None.	0
	AI1 scaled	12.12 Al1 scaled value (see page 182).	1
	Al2 scaled	12.22 Al2 scaled value (see page 184).	2
	PID	40.01 Process PID output actual (output of the process PID controller).Not in use.	5
	Minimum torque 2	30.23 Maximum torque 2.	6
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
30.22	Maximum torque 2 source	 Defines the source of the maximum torque limit for the drive (in percent of nominal motor torque) when the source selected by parameter 30.25 Maximum torque sel is 1, or 30.25 is set to Maximum torque 2 source. See diagram at 30.18 Minimum torque sel. Note: Any negative values received from the selected source are inverted. 	Maximum torque 2
	Zero	None.	0
	AI1 scaled	12.12 Al1 scaled value (see page 182).	1
	AI2 scaled	12.22 Al2 scaled value (see page 184).	2
	PID	<i>40.01 Process PID output actual</i> (output of the process PID controller).	5
	Maximum torque 2	30.24 Maximum torque 2.	6
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-

No.	Name/Value	Description	Def/FbEq16
30.23	Minimum torque 2	Defines the minimum torque limit for the drive (in percent of nominal motor torque) when	-300.0%
		• the source selected by parameter 30.18 Minimum torque	
		 se/ is 1, and 30.21 is set to Minimum torque 2. 	
		Note: Do not set this parameter to 0% in an attempt to	
		prevent reverse rotation. In an open-loop application, that is likely to prevent the motor from stopping altogether. To prevent reverse rotation, use the speed/frequency limits in	
		this parameter group, or parameters <i>20.23/20.24</i> . See diagram at <i>30.18 Minimum torque sel</i> .	
	-1600.0 0.0%	Minimum torque limit 2.	See par. 46.03
30.24	Maximum torque 2	Defines the maximum torque limit for the drive (in percent of nominal motor torque) when	300.0%
		 the source selected by parameter 30.25 Maximum torque sel is 1, and 20.22 is set to Maximum torque 2 	
		30.22 is set to Maximum torque 2. See diagram at 30.18 Minimum torque sel.	
	0.0 1600.0%	Maximum torque limit 2.	See par. 46.03
30.25	Maximum torque sel	Selects a source that switches between two different maximum torque limits. 0 = Maximum torque limit 1 defined by <i>30.20</i> is active 1 = Maximum torque limit selected by <i>30.22</i> is active	Maximum torque 1
		See also parameter 30.18 Minimum torque sel.	
	Maximum torque 1	0.	0
	Maximum torque 2 source	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
30.26	Power motoring limit	Defines the maximum shaft power in motoring mode, ie. when power is being transferred from the motor to the machinery. The value is given in percent of nominal motor power.	300.00%
	0.00 600.00%	Maximum shaft power in motoring mode.	1 = 1%
30.27	Power generating limit	Defines the maximum shaft power in generating mode, ie. when power is being transferred from the machinery to the motor. The value is given in percent of nominal motor power. Note: Do not set this parameter to 0% in an attempt to prevent reverse rotation. In an open-loop application, that is likely to prevent the motor from stopping altogether. To prevent reverse rotation, use the speed/frequency limits in this parameter group, or parameters 20.23/20.24.	-300.00%

No.	Name/Va	alue	Desc	ription	Def/FbEq16
	-600.00	0.00%	Maxin	num shaft power in generating mode.	1 = 1%
30.30	Overvolt	age control	Fast to to the from e autom	les the overvoltage control of the intermediate DC link. braking of a high inertia load causes the voltage to rise overvoltage control limit. To prevent the DC voltage exceeding the limit, the overvoltage controller natically decreases the braking torque. If the drive is equipped with a brake chopper and or, or a regenerative supply unit, the controller must be led.	Disable
	Disable		Overv	voltage control disabled.	0
	Enable		Overv	voltage control enabled.	1
30.31	Undervo control	ltage	If the under torque decre regen and p a stop	es the undervoltage control of the intermediate DC link. DC voltage drops due to input power cut off, the voltage controller will automatically decrease the motor e in order to keep the voltage above the lower limit. By asing the motor torque, the inertia of the load will cause eration back to the drive, keeping the DC link charged reventing an undervoltage trip until the motor coasts to b. This will act as a power-loss ride-through functionality tems with high inertia, such as a centrifuge or a fan.	Enable
	Disable		Unde	rvoltage control disabled.	0
	Enable		Unde	rvoltage control enabled.	1
30.101	LSU limi	t word 1	96.20 Displa	visible when IGBT supply unit control activated by) ays limit word 1 of the supply unit. parameter is read-only.	-
	Bit	Name		Description	
	0	P user ref n		1 = Power reference is being limited by supply control pr	ogram
	1	P user ref n	nin	parameters	
	2	P user max		1 = Power is being limited by parameter 30.149	
	3	P user min		1 = Power is being limited by parameter 30.148	
	4	P cooling overtemp		1 = Power reference is being limited because of coolant overtemperature	
	5	P power un overtemp		1 = Power reference is being limited because of supply u overtemperature	ınit
	615	Reserved			

	Name/Va	alue	Desc	ription	Def/FbEq1	
	96.20 Displ		96.20 Displa	ays limit word 2 of the supply unit.	-	
			11115	parameter is read-only.	I	
1	Bit	Name		Description		
	0	Q user ref r	nax	I = Reactive power reference is being limited		
	1	Q user ref min Q cooling overtemp Q power unit overtemp				
	2			1 = Reactive power reference is being limited because overtemperature	of coolant	
	3			1 = Reactive power reference is being limited because	of supply unit	
	0			overtemperature	or ouppry unit	
1	4	AC overvolt	tage	1 = AC overvoltage protection		
	56	Reserved				
	7	AC diff max	(1 = (When AC voltage-type reactive power reference is	being used)	
	8	AC diff min		Input of AC control is being limited		
	915	Reserved				
			0			
	0000h	FFFFh	Supp	ly unit limit word 2.	1 = 1	
	LSU limi	t word 3		visible when IGBT supply unit control activated by	_	
	• •		96.20			
		Displ		ays limit word 3 of the supply unit.		
	-		-			
			-	parameter is read-only.		
			-			
]	Bit	Name	-			
]	Bit 0	Undervoltag	This	parameter is read-only.	er	
	0	Undervoltag limit	This r	Description 1 = Power is being limited by the undervoltage controlle		
	0	Undervoltag limit Overvoltage	ge ge	Description 1 = Power is being limited by the undervoltage controlled 1 = Power is being limited by the overvoltage controlled		
	0 1 2	Undervoltag limit Overvoltage Motoring po	ge ge	Description 1 = Power is being limited by the undervoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller		
	0	Undervoltag limit Overvoltage	ge ge	Description 1 = Power is being limited by the undervoltage controlled 1 = Power is being limited by the overvoltage controlled		
•	0 1 2	Undervoltage limit Overvoltage Motoring po Generating	ge e limit ower	Description 1 = Power is being limited by the undervoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller	er limits (see	
-	0 1 2 3	Undervoltage limit Overvoltage Motoring po Generating power Active curre limit	This p ge e limit ower ent	Description 1 = Power is being limited by the undervoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by temperature or user power parameters 30.148 and 30.149) 1 = Active current is being limited. For details, see bits 1415.	er limits (see 69 and	
	0 1 2 3	Undervoltage limit Overvoltage Motoring po Generating power Active curre	This p ge e limit ower ent	Description 1 = Power is being limited by the undervoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Active current is being limited. For details, see bits	er limits (see 69 and	
•	0 1 2 3 4	Undervoltage limit Overvoltage Motoring po Generating power Active curre limit Reactive cu	ge e limit ower ent urrent	Description 1 = Power is being limited by the undervoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by temperature or user power parameters 30.148 and 30.149) 1 = Active current is being limited. For details, see bits 1415.	er limits (see 69 and ts 1213.	
•	0 1 2 3 4 5	Undervoltage limit Overvoltage Motoring po Generating power Active curre limit Reactive cu limit	ge e limit ower ent urrent	Description 1 = Power is being limited by the undervoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited. For details, see bits 1415. 1 = Reactive current is being limited. For details, see bits	er limits (see 69 and ts 1213. it thermal limi	
•	0 1 2 3 4 5 6	Undervoltage limit Overvoltage Motoring po Generating power Active curre limit Reactive cu limit Thermal lim SOA limit	This p ge e limit ower ent urrent iit	Description 1 = Power is being limited by the undervoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Active current is being limited. For details, see bits 1 = Reactive current is being limited. For details, see bits 1 = Active current is being limited by internal main circul	er limits (see 69 and ts 1213. it thermal limi ation area limi	
•	0 1 2 3 4 5 6 7	Undervoltage limit Overvoltage Motoring po Generating power Active curre limit Reactive cu limit Thermal lim SOA limit	This p ge e limit ower ent urrent nit	Description 1 = Power is being limited by the undervoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by temperature or user power parameters 30.148 and 30.149) 1 = Active current is being limited. For details, see bits 1 = Reactive current is being limited by internal main circu 1 = Active current is being limited by internal safe opera 1 = Active current is being limited by current limit set by program parameters 1 = Active current is being limited by current limit set by	er limits (see 69 and ts 1213. it thermal limi ation area limi supply contro	
•	0 1 2 3 4 5 6 7 8	Undervoltage limit Overvoltage Motoring po Generating power Active curre limit Reactive cu limit Thermal lim SOA limit User curren	This p ge e limit ower ent urrent nit	Description 1 = Power is being limited by the undervoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by temperature or user power parameters 30.148 and 30.149) 1 = Active current is being limited. For details, see bits 1415. 1 = Reactive current is being limited by internal main circuit 1 = Active current is being limited by internal main circuit 1 = Active current is being limited by internal safe operation 1 = Active current is being limited by current limit set by program parameters	er limits (see 69 and ts 1213. it thermal limi ation area limi supply contro	
•	0 1 2 3 4 5 6 7 8 9	Undervoltage limit Overvoltage Motoring po Generating power Active curre limit Reactive cu limit Thermal lim SOA limit User curren Thermal IG	This p ge e limit ower ent urrent nit	Description 1 = Power is being limited by the undervoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by temperature or user power parameters 30.148 and 30.149) 1 = Active current is being limited. For details, see bits 1 = Reactive current is being limited by internal main circu 1 = Active current is being limited by internal safe opera 1 = Active current is being limited by current limit set by program parameters 1 = Active current is being limited by current limit set by	er limits (see 69 and ts 1213. it thermal limi ation area limi supply contro ximum therma	
•	0 1 2 3 4 5 6 7 8 9 1011	Undervoltage limit Overvoltage Motoring po Generating power Active curre limit Reactive cu limit Thermal lim SOA limit User curren Thermal IG Reserved	This p ge e limit ower ent urrent nit	Description 1 = Power is being limited by the undervoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by temperature or user power parameters 30.148 and 30.149) 1 = Active current is being limited. For details, see bits 1 1 = Reactive current is being limited by internal main circu 1 = Active current is being limited by internal main circu 1 = Active current is being limited by internal safe opera 1 = Active current is being limited by current limit set by program parameters 1 = Active current is being limited by current limit set by program parameters 1 = Active current is being limited by set on internal main circu	er limits (see 69 and ts 1213. it thermal limi ation area limi supply contro ximum therma	
•	0 1 2 3 4 5 6 7 8 9 1011 12	Undervoltage limit Overvoltage Motoring po Generating power Active curre limit Reactive cu limit Thermal lim SOA limit User curren Thermal IG Reserved Q act neg	This p ge e limit ower ent urrent nit	Description 1 = Power is being limited by the undervoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by temperature or user power parameters 30.148 and 30.149) 1 = Active current is being limited. For details, see bits 1 = Reactive current is being limited by internal main circu 1 = Active current is being limited by internal safe opera 1 = Active current is being limited by current limit set by program parameters 1 = Active current is being limited by current limit set by program parameters 1 = Active current is being limited by current limit set by program parameters 1 = Active current is being limited by current limit set by program parameters 1 = Active current is being limited by set on internal max 1 = Active current is being limited by set on internal max 1 = Active current is being limited by by current limit set by program parameters 1 = Active current is being limited by by current limit set by program parameters 1 = Active current is being limited by	er limits (see 69 and ts 1213. it thermal limi ation area limi supply contro ximum therma um total curre im total curre	
•	0 1 2 3 4 5 6 7 8 9 1011 12 13	Undervoltage limit Overvoltage Motoring po Generating power Active curre limit Reactive cu limit Thermal lim SOA limit User curren Thermal IG Reserved Q act neg Q act pos	This p ge e limit ower ent urrent nit	Description 1 = Power is being limited by the undervoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by temperature or user power parameters 30.148 and 30.149) 1 = Active current is being limited. For details, see bits of 1415. 1 = Reactive current is being limited by internal main circul 1 = Active current is being limited by internal safe opera 1 = Active current is being limited by current limit set by program parameters 1 = Active current is being limited by current limit set by program parameters 1 = Active current is being limited by current limit set by program parameters 1 = Active current is being limited by maximu 1 = Negative reactive current is being limited by maximu 1 = Positive reactive current is being limited by maximu	er limits (see 69 and ts 1213. it thermal limi ation area limi supply contro ximum therma um total current im total current	
•	0 1 2 3 4 5 6 7 8 9 1011 12 13 14	Undervoltage limit Overvoltage Motoring po Generating power Active curre- limit Reactive cu- limit Thermal lim SOA limit User curren Thermal IG Reserved Q act neg Q act pos P act neg	This p ge e limit ower ent urrent nit	Description 1 = Power is being limited by the undervoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by temperature or user power parameters 30.148 and 30.149) 1 = Active current is being limited. For details, see bits 1415. 1 = Reactive current is being limited by internal main circu 1 = Active current is being limited by internal main circu 1 = Active current is being limited by internal main circu 1 = Active current is being limited by internal main circu 1 = Active current is being limited by internal main circu 1 = Active current is being limited by internal main circu 1 = Active current is being limited by internal main circu 1 = Active current is being limited by internal main circu 1 = Active current is being limited by current limit set by program parameters 1 = Active current is being limited by maximu 1 = Negative reactive current is being limited by maximu 1 = Negative reactive current is being limited by maximu 1 = Negative active current is being limited by maximu	er limits (see 69 and ts 1213. it thermal limi ation area limi supply contro ximum therma um total current im total current	
· · · · ·	0 1 2 3 4 5 6 7 8 9 1011 12 13 14	Undervoltage limit Overvoltage Motoring po Generating power Active curre limit Reactive cu limit Thermal lim SOA limit User curren Thermal IG Reserved Q act neg Q act pos P act pos	This p ge e limit pwer ent urrent hit BT	Description 1 = Power is being limited by the undervoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by the overvoltage controller 1 = Power is being limited by temperature or user power parameters 30.148 and 30.149) 1 = Active current is being limited. For details, see bits 1415. 1 = Reactive current is being limited by internal main circu 1 = Active current is being limited by internal main circu 1 = Active current is being limited by internal main circu 1 = Active current is being limited by internal main circu 1 = Active current is being limited by internal main circu 1 = Active current is being limited by internal main circu 1 = Active current is being limited by internal main circu 1 = Active current is being limited by internal main circu 1 = Active current is being limited by current limit set by program parameters 1 = Active current is being limited by maximu 1 = Negative reactive current is being limited by maximu 1 = Negative reactive current is being limited by maximu 1 = Negative active current is being limited by maximu	er limits (see 69 and ts 1213. it thermal limi ation area limi supply contro ximum therma um total current im total current	

No.	Name/Value		Description		Def/FbEq16
30.104	LSU limit word 4		(Only visible when IGBT supply unit control activated by 96.20) Displays limit word 4 of the supply unit. This parameter is read-only.		-
	Bit Name		Description		
	0				
	1	Udc ref mir	parameters 1 = Current is being limited by supply control program parameter		
	2	User I max			
	3	Temp I max	1 = Current is being limited based on temperature		
	415	Reserved			
	0000hFFFFh		Supply ur	nit limit word 4.	1 = 1
30.148	LSU minimum power limit		96.20) Defines a Negative	ble when IGBT supply unit control activated by minimum power limit for the supply unit. values refer to regenerating, ie. feeding power into y network.	-130.0%
	-200.0 0.0%		Minimum power limit for supply unit.		1 = 1%
30.149	LSU maximum power limit		(Only visi 96.20)	ble when IGBT supply unit control activated by maximum power limit for the supply unit.	130.0%
	0.0 200.0%		Maximum	power limit for supply unit.	1 = 1%
31 Fau	ault functions		Configuration of external events; selection of behavior of the drive upon fault situations.		
31.01	External event 1 source		See also 0 = Trigge	ne source of external event 1. parameter <i>31.02 External event 1 type</i> . er event al operation	<i>Inactive</i> (<i>true</i>); <i>DI6</i> (95.20 b8)
	Active (false)		0.		0
	Inactive (true)		1.		1
	DIIL		DIIL input	t (<i>10.02 DI delayed status</i> , bit 15).	2
	DI1		Digital inp	out DI1 (<i>10.02 DI delayed status</i> , bit 0).	3
	DI2		Digital inp	out DI2 (10.02 DI delayed status, bit 1).	4
	DI3		Digital inp	out DI3 (10.02 DI delayed status, bit 2).	5
	DI4		Digital inp	out DI4 (10.02 DI delayed status, bit 3).	6
	DI5		• •	out DI5 (<i>10.02 DI delayed status</i> , bit 4).	7
	DI6		• .	out DI6 (<i>10.02 DI delayed status</i> , bit 5).	8
	DIO1		Digital input/output DIO1 (11.02 DIO delayed status, bit 0).		11
	DIO2		Digital input/output DIO2 (<i>11.02 DIO delayed status</i> , bit 1).		12
	DIO2			Source selection (see Terms and abbreviations on page 131).	
		it]	Source se	election (see <i>Terms and abbreviations</i> on page 131).	-
31.02	DIO2 Other [b: External type	-		election (see <i>Terms and abbreviations</i> on page <i>131</i>). The type of external event 1.	<i>Fault</i> (95.20 b8)
31.02	Other [b External	-	Selects th	, , , , , , , , , , , , , , , , , , ,	

No.	Name/Value	Description	Def/FbEq16
	Warning/Fault	If the drive is modulating, the external event generates a fault. Otherwise, the event generates a warning.	3
31.03	External event 2 source	Defines the source of external event 2. See also parameter 31.04 External event 2 type. For the selections, see parameter 31.01 External event 1 source.	<i>Inactive</i> (<i>true</i>); <i>DIIL</i> (95.20 b5)
31.04	External event 2 type	Selects the type of external event 2.	
	Fault	The external event generates a fault.	0
	Warning	The external event generates a warning.	1
	Warning/Fault	If the drive is modulating, the external event generates a fault. Otherwise, the event generates a warning.	3
31.05	External event 3 source	Defines the source of external event 3. See also parameter 31.06 External event 3 type. For the selections, see parameter 31.01 External event 1 source.	Inactive (true)
31.06	External event 3 type	Selects the type of external event 3.	
	Fault	The external event generates a fault.	0
	Warning	The external event generates a warning.	1
	Warning/Fault	If the drive is modulating, the external event generates a fault. Otherwise, the event generates a warning.	3
31.07	External event 4 source	vent 4Defines the source of external event 4. See also parameter 31.08 External event 4 type. For the selections, see parameter 31.01 External event 1 source.	
31.08	External event 4 type	Selects the type of external event 4.	
	Fault	The external event generates a fault.	0
	Warning	The external event generates a warning.	1
	Warning/Fault	If the drive is modulating, the external event generates a fault. Otherwise, the event generates a warning.	3
31.09	External event 5 source		
31.10	External event 5 type	Selects the type of external event 5.	
	Fault	The external event generates a fault.	0
	Warning	The external event generates a warning.	1
	Warning/Fault	If the drive is modulating, the external event generates a fault. Otherwise, the event generates a warning.	3
31.11	Fault reset selection	 Selects the source of an external fault reset signal. This signal will be observed even if it is not the active source in the current control location (EXT1/EXT2/Local). (A reset from the active source will be observed regardless of this parameter.) 0 -> 1 = Reset 	DI2
	Not selected	0.	0

No.	Name/Va	lue	Description	Def/FbEq16
	Selected		1.	1
	DI1		Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2		Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3		Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4		Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5		Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6		Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1		Digital input/output DIO1 (<i>11.02 DIO delayed status</i> , bit 0).	10
	DIO2		Digital input/output DIO2 (<i>11.02 DIO delayed status</i> , bit 1).	11
	FBAA M		Control word bit 7 received through fieldbus interface A.	30
	EFB MC	/v dit /	Control word bit 7 received through the embedded fieldbus interface.	32
	Other [bit	t]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
1.12	Autorese	t selection	 Selects faults that are automatically reset. The parameter is a 16-bit word with each bit corresponding to a fault type. Whenever a bit is set to 1, the corresponding fault is automatically reset. The number and interval of reset attempts are defined by parameters 31.1431.16. WARNING! Before you activate the function, make sure that no dangerous situations can occur. The function resets the drive automatically and continues operation after a fault. Note: The autoreset function is only available in external control; see section <i>Local control vs. external control</i> (page 54). Faults related to the Safe torque off (STO) function cannot be automatically reset. The bits of the binary number correspond to the following faults: 	0000h
	Bit	Fault		
	0	Overcurrent	t	
	1	Overvoltage		
	2	Undervoltag	•	
	3	Al supervisi		
	4	Suupply uni	it	
	57	Reserved		
	8		fault 1 (defined in the application program)	
	9		fault 2 (defined in the application program)	
	10		fault (see parameter 31.13 User selectable fault)	
	11		It 1 (from source selected by parameter 31.01 External event 1	
	12		It 2 (from source selected by parameter 31.03 External event 2	
	13		It 3 (from source selected by parameter 31.05 External event 3	
	14		It 4 (from source selected by parameter 31.07 External event 4	
	15	External fat	It 5 (from source selected by parameter 31.09 External event 5	source)

No.	Name/Value	Description	Def/FbEq16
31.13	User selectable fault	Defines the fault that can be automatically reset using parameter <i>31.12 Autoreset selection</i> , bit 10. The faults are listed in chapter <i>Fault tracing</i> (page <i>549</i>).	0000h
	0000hFFFFh	Fault code.	10 = 1
31.14	Number of trials	Defines the maximum number of automatic resets that the drive is allowed to attempt within the time specified by 31.15 Total trials time. If the fault persists, subsequent reset attempts will be made at intervals defined by 31.16 Delay time. The faults to be automatically reset are defined by 31.12 Autoreset selection.	0
	05	Number of automatic resets.	1 = 1
31.15	Total trials time	Defines a time window for automatic fault resets. The maximum number of attempts made during any period of this length is defined by <i>31.14 Number of trials</i> . Note: If the fault condition remains and cannot be reset, each reset attempt will generate an event and start a new time window. In practice, if the specified number of resets (<i>31.14</i>) at specified intervals (<i>31.16</i>) take longer than the value of <i>31.15</i> , the drive will continue to attempt resetting the fault until the cause is eventually removed.	30.0 s
	1.0 600.0 s	Time for automatic resets.	10 = 1 s
31.16	Delay time	Defines the time that the drive will wait after a fault (or a previous reset attempt) before attempting an automatic reset. See parameter <i>31.12 Autoreset selection</i> .	0.0 s
	0.0 120.0 s	Autoreset delay.	10 = 1 s
31.19	Motor phase loss	Selects how the drive reacts when a motor phase loss is detected.	Fault
	No action	No action taken.	0
	Fault	The drive trips on fault 3381 Output phase loss.	1
31.20	Earth fault	Selects how the drive reacts when an earth fault or current unbalance is detected in the motor or the motor cable.	Fault
	No action	No action taken.	0
	Warning	The drive generates an A2B3 Earth leakage warning.	1
	Fault	The drive trips on fault 2330 Earth leakage.	2
31.21	Supply phase loss	Selects how the drive reacts when a supply phase loss is detected.	Fault
	No action	No action taken.	0
	Fault	The drive trips on fault 3130 Input phase loss.	1

No.	Name/Value	Descri	ption			Def/FbEq16
31.22	STO indication run/stop	torque of indication stopped The tab generation Notes: • This funct the so remo- both • The as it	off (ST ons als d when oles at o ted with param tion itse setting o oval of STO s loss of is inter re infor	of this parameter: a run one or both STO signal ignals are restored and only one STO signal al preted as a malfunctior	I off or lost. The he drive is running or now the indications coperation of the STO ill operate regardless of ning drive will stop upon ls, and will not start until I all faults reset. Iways generates a fault	Fault/Fault
	Fault/Fault					0
		Inp IN1	uts IN2	Indication (run	ning or stopped)	
		0	0	Fault 5091 S	Safe torque off	
		0	1		que off and FA81 Safe off 1 loss	
		1	0		que off and FA82 Safe off 2 loss	
		1	1	(Normal	operation)	
	Fault/Warning					1
		Inp	uts	Indic	ation	
		IN1	IN2	Running	Stopped	
		0	0	Fault 5091 Safe torque off	torque off	
		0	1	Faults 5091 Safe torque off and FA81 Safe torque off 1 loss	Warning <i>A5A0 Safe</i> torque off and fault FA81 Safe torque off 1 loss	
		1	0	Faults 5091 Safe torque off and FA82 Safe torque off 2 loss	Warning A5A0 Safe torque off and fault FA82 Safe torque off 2 loss	
		1	1	(Normal o	operation)	
			·			

No.	Name/Value	Descr	iption			Def/FbEq16
	Fault/Event					2
		Inp	outs	Indic	ation	
		IN1	IN2	Running	Stopped	
		0	0	Fault 5091 Safe torque off	Event <i>B5A0 Safe</i> torque off	
		0	1	Faults 5091 Safe torque off and FA81 Safe torque off 1 loss	Event <i>B5A0 Safe</i> torque off and fault <i>FA81 Safe torque off 1</i> <i>loss</i>	
		1	0	Faults 5091 Safe torque off and FA82 Safe torque off 2 loss	Event <i>B5A0 Safe</i> torque off and fault <i>FA82 Safe torque off 2</i> loss	
		1	1	(Normal o	operation)	
	Warning/Warning					3
				t		
		Inp IN1	outs IN2	Indication (run	ning or stopped)	
		0	0	Warning A5A0	Safe torque off	
		0	1	Warning A5A0 Safe to	orque off and fault FA81 le off 1 loss	
		1	0		orque off and fault FA82 le off 2 loss	
		1	1	(Normal o	operation)	
	Event/Event					4
		Inp	uts	Indiantian (mun	ing or storned)	
		IN1	IN2		ning or stopped)	
		0	0	Event B5A0) STO event	
		0	1	torque o	nt and fault FA81 Safe	
		1	0	torque o	nt and fault FA82 Safe	
		1	1	(Normal o	operation)	
	No indication/No indication			1		5
			puts	Indication (runr	ning or stopped)	
		IN1	IN2		one	
		0	1		torque off 1 loss	
		1	0		torque off 2 loss	
		1	1		operation)	
31.23	Wiring or earth fault	motor to drive Note :	cable o e moto The pr	the drive reacts to incorr connection (i.e. input pov r connection). otection must be disable oplied from a common D	wer cable is connected	Fault
	No action	No act	ion tak	en.		0

No.	Name/Value	Description	Def/FbEq16
	Fault	The drive trips on fault 3181 Wiring or earth fault.	1
31.24	Stall function	 Selects how the drive reacts to a motor stall condition. A stall condition is defined as follows: The drive exceeds the stall current limit (<i>31.25 Stall current limit</i>), and the output frequency is below the level set by parameter <i>31.27 Stall frequency limit</i> or the motor speed is below the level set by parameter <i>31.26 Stall speed limit</i>, and the conditions above have been true longer than the time set by parameter <i>31.28 Stall time</i>. 	Fault
	No action	None (stall supervision disabled).	0
	Warning	The drive generates an A780 Motor stall warning.	1
	Fault	The drive trips on fault 7121 Motor stall.	2
31.25	Stall current limit	Stall current limit in percent of the nominal current of the motor. See parameter <i>31.24 Stall function</i> .	200.0%
	0.0 1600.0%	Stall current limit.	10 = 1%
31.26	Stall speed limit	Stall speed limit in rpm. See parameter 31.24 Stall function.	150.00 rpm; 180.00 rpm (95.20 b0)
	0.00 10000.00 rpm	Stall speed limit.	See par. 46.01
31.27	Stall frequency limit	Stall frequency limit. See parameter <i>31.24 Stall function</i> . Note: Setting the limit below 10 Hz is not recommended.	15.00 rpm; 18.00 rpm (95.20 b0)
	0.00 500.00 Hz	Stall frequency limit.	See par. 46.02
31.28	Stall time	Stall time. See parameter 31.24 Stall function.	20 s
	0 3600 s	Stall time.	1 = 1 s

No.	Name/Value	Description	Def/FbEq16
31.30	Overpeed trip margin	Defines, together with 30.11 Minimum speed and 30.12 Maximum speed, the maximum allowed speed of the motor (overspeed protection). If 90.01 Motor speed for control or the estimated speed exceeds the speed limit defined by parameter 30.11 or 30.12 by more than the value of this parameter, the drive trips on the 7310 Overspeed fault. Example: If the maximum speed is 1420 rpm and speed trip margin is 300 rpm, the drive trips at 1720 rpm. Speed (90.01) Overspeed trip level 	500.00 rpm
	0.0010000.0 rpm	Overspeed trip margin.	See par. 46.01
31.32	Emergency ramp supervision	 Parameters 31.32 Emergency ramp supervision and 31.33 Emergency ramp supervision delay, together with 01.25 Speed change rate, provide a supervision function for emergency stop mode Off3. The supervision is based on either observing the time within which the motor stops, or comparing the actual and expected deceleration rates. If this parameter is set to 0%, the maximum stop time is directly set in parameter 31.33. Otherwise, 31.32 defines the maximum allowed deviation from the expected deceleration rate, which is calculated from parameter 23.23 Emergency stop time (Off3). If the actual deceleration rate (01.25) deviates too much from the expected rate, the drive trips on 73B0 Emergency ramp failed, sets bit 8 of 06.17 Drive status 	0%
		word 2, and coasts to a stop. If <i>31.32</i> is set to 0% and <i>31.33</i> is set to 0 s, the emergency stop ramp supervision is disabled. See also parameter <i>21.04 Emergency stop mode</i> .	

No.	Name/Value	Description	Def/FbEq16
31.33	Emergency ramp supervision delay	If parameter 31.32 Emergency ramp supervision is set to 0%, this parameter defines the maximum time an emergency stop (mode Off3) is allowed to take. If the motor has not stopped when the time elapses, the drive trips on 73B0 Emergency ramp failed, sets bit 8 of 06.17 Drive status word 2, and coasts to a stop. If 31.32 is set to a value other than 0%, this parameter defines a delay between the receipt of the emergency stop command and the activation of the supervision. It is recommended to specify a short delay to allow the speed change rate to stabilize.	0 s
	032767 s	Maximum ramp-down time, or supervision activation delay.	1 = 1 s
31.35	Main fan fault function	 Selects how the drive reacts when a main cooling fan fault is detected. Note: With an inverter unit consisting of one or more frame R8i inverter modules with speed-controlled fans, it may be possible to continue operation even if one main fan of a module stops. When fan failure is detected, the control program will automatically set the other fan of the module to full speed set the fans of the other modules (if any) to full speed decrease the switching frequency to a minimum, and disable the supervision of temperature difference between the modules. If this parameter is set to <i>Fault</i>, the inverter unit will trip (but still carry out the actions listed above). Otherwise, the inverter will attempt to continue operation. 	Warning
	Fault	The drive trips on fault 5080 Fan.	0
	Warning	The drive generates an A581 Fan warning.	1
	No action	No action taken.	2
31.36	Aux fan fault bypass	 (Only visible with a ZCU control unit) Temporarily suppresses auxiliary fan faults. Certain drive types (especially those protected to IP55) have an auxiliary fan built into the front cover as standard. If the fan is sticking or disconnected, the control program generates a fault (<i>5081 Auxiliary fan broken</i>). If it is necessary to operate the drive without the front cover (for example, during commissioning), this parameter can be activated to temporarily generate a warning (<i>A582 Auxiliary fan missing</i>) instead of the fault. Notes: The parameter must be activated within 2 minutes of control unit reboot (either by cycling the power or by parameter <i>96.08</i>). The parameter will be in effect until the auxiliary fan is reconnected and detected, or until the next control unit reboot. 	Off
	Off	Normal operation.	0
	Temporarily bypassed	The auxiliary fan fault indication is temporarily replaced by a warning indication. The setting will revert automatically to Off.	1

No.	Name/Value	Description	Def/FbEq16
31.37	Ramp stop supervision	 Parameters 31.37 Ramp stop supervision and 31.38 Ramp stop supervision delay, together with 01.25 Speed change rate, provide a supervision function for normal (ie. non-emergency) ramp stopping. The supervision is based on either observing the time within which the motor stops, or comparing the actual and expected deceleration rates. If this parameter is set to 0%, the maximum stop time is directly set in parameter 31.38. Otherwise, 31.37 defines the maximum allowed deviation from the expected deceleration rate, which is calculated from parameters 23.1123.19. If the actual deceleration rate (01.25) deviates too much from the expected rate, the drive trips on 73B1 Stop failed, sets bit 14 of 06.17 Drive status word 2, and coasts to a stop. If 31.37 is set to 0% and 31.38 is set to 0 s, the ramp stop supervision is disabled. 	0%
	0300%	Maximum deviation from expected deceleration rate.	1 = 1%
31.38	Ramp stop supervision delay	If parameter 31.37 Ramp stop supervision is set to 0%, this parameter defines the maximum time a ramp stop is allowed to take. If the motor has not stopped when the time elapses, the drive trips on <i>Stop failed Stop failed</i> , sets bit 14 of 06.17 <i>Drive status word 2</i> , and coasts to a stop. If 31.37 is set to a value other than 0%, this parameter defines a delay between the receipt of the stop command and the activation of the supervision. It is recommended to specify a short delay to allow the speed change rate to stabilize.	0 s
	032767 s	Maximum ramp-down time, or supervision activation delay.	1 = 1 s
31.40	Disable warning messages	Selects warnings to be suppressed. The parameter is a 16-bit word with each bit corresponding to a warning. Whenever a bit is set to 1, the corresponding warning is suppressed. The bits of this binary number correspond to the following warnings: Bit Fault 0 Overvoltage 1 Reserved 2 Encoder 1 3 Encoder 2 4 CU (Control unit) battery 515 Reserved	0000b
	0000b0001b	Warning suppression word.	1 = 1
31.42	Overcurrent fault limit	Sets a custom motor current fault limit. The drive automatically sets an internal motor current limit according to the drive hardware. The internal limit is appropriate in most cases, but this parameter can be used to set a lower current limit, for example, to protect a permanent magnet motor from demagnetization. Note : The limit defines the maximum peak current of one phase. With this parameter at 0.0 A, only the internal limit is in force.	0.00 A
	0.00 30000.00 A	Custom motor current fault limit.	See par. 46.05

No.	Name/Va	alue	Description	Def/FbEq16
31.120	LSU ean	th fault	(Only visible when IGBT supply unit control activated by 95.20)	Fault
			Selects how the supply unit reacts when an earth fault or current unbalance is detected.	
	No action	n	No action taken.	0
	Warning		The supply unit generates an AE02 Earth leakage warning.	1
	Fault		The supply unit trips on fault 2E01 Earth leakage.	2
31.121	LSU sup loss	ply phase	<i>(Only visible when IGBT supply unit control activated by</i> 95.20) Selects how the supply unit reacts when a supply phase loss	Fault
			is detected.	
	No action	n	No action taken.	0
	Fault		The supply unit trips on fault 3E00 Input phase loss.	1
32 Sup	pervisior	1	Configuration of signal supervision functions 13. Three values can be chosen to be monitored; a warning or fault is generated whenever predefined limits are exceeded. See also section <i>Signal supervision</i> (page <i>120</i>).	
32.01	Supervision status		Signal supervision status word. Indicates whether the values monitored by the signal supervision functions are within or outside their respective limits. Note: This word is independent of the drive actions defined by parameters 32.06, 32.16 and 32.26.	0000b
	Bit	Name	Description	
		Name	Description	
	0	Supervisior		6.
	1	Supervisior Supervisior	1 active1 = Signal selected by 32.07 is outside its limitsn 2 active1 = Signal selected by 32.17 is outside its limits	S.
	1 2	Supervisior Supervisior Supervisior	1 active1 = Signal selected by 32.07 is outside its limitsn 2 active1 = Signal selected by 32.17 is outside its limits	S.
	1	Supervisior Supervisior	1 active1 = Signal selected by 32.07 is outside its limitsn 2 active1 = Signal selected by 32.17 is outside its limits	S.
	1 2	Supervisior Supervisior Supervisior Reserved	1 active1 = Signal selected by 32.07 is outside its limitsn 2 active1 = Signal selected by 32.17 is outside its limits	S.
32.05	1 2 315	Supervisior Supervisior Supervisior Reserved	n 1 active1 = Signal selected by 32.07 is outside its limitsn 2 active1 = Signal selected by 32.17 is outside its limitsn 3 active1 = Signal selected by 32.27 is outside its limits	5. 5.
32.05	1 2 315 00000 <i>Supervis</i>	Supervisior Supervisior Supervisior Reserved 111b	1 active 1 = Signal selected by 32.07 is outside its limits 2 active 1 = Signal selected by 32.17 is outside its limits 3 active 1 = Signal selected by 32.27 is outside its limits Signal supervision status word. Selects the mode of signal supervision function 1. Determines how the monitored signal (see parameter 32.07) is compared to its lower and upper limits (32.09 and 32.10 respectively). The action to be taken when the condition is fulfilled is	5. 5. 1 = 1
32.05	1 2 315 00000 Supervis function	Supervisior Supervisior Supervisior Reserved 111b	1 active 1 = Signal selected by 32.07 is outside its limits 1 2 active 1 = Signal selected by 32.17 is outside its limits 1 3 active 1 = Signal selected by 32.27 is outside its limits Signal supervision status word. Selects the mode of signal supervision function 1. Determines how the monitored signal (see parameter 32.07) is compared to its lower and upper limits (32.09 and 32.10 respectively). The action to be taken when the condition is fulfilled is selected by 32.06.	5. 5. 1 = 1 <i>Disabled</i>
32.05	1 2 315 00000 Supervis function	Supervisior Supervisior Supervisior Reserved 111b	1 active 1 = Signal selected by 32.07 is outside its limits 1 2 active 1 = Signal selected by 32.17 is outside its limits 1 3 active 1 = Signal selected by 32.27 is outside its limits Signal supervision status word. Selects the mode of signal supervision function 1. Determines how the monitored signal (see parameter 32.07) is compared to its lower and upper limits (32.09 and 32.10 respectively). The action to be taken when the condition is fulfilled is selected by 32.06. Signal supervision 1 not in use.	5. 5. 1 = 1 <i>Disabled</i> 0
32.05	1 2 315 00000 Supervis function Disabled Low	Supervisior Supervisior Supervisior Reserved 111b	1 active1 = Signal selected by 32.07 is outside its limits2 active1 = Signal selected by 32.17 is outside its limits3 active1 = Signal selected by 32.27 is outside its limitsSignal supervision status word.Selects the mode of signal supervision function 1. DeterminesSelects the mode of signal supervision function 1. Determineshow the monitored signal (see parameter 32.07) is comparedto its lower and upper limits (32.09 and 32.10 respectively).The action to be taken when the condition is fulfilled isselected by 32.06.Signal supervision 1 not in use.Action is taken whenever the signal falls below its lower limit.Action is taken whenever the signal rises above its upper	5. 5. 1 = 1 <i>Disabled</i> 0 1
32.05	1 2 315 00000 Supervis function Disabled Low High	Supervisior Supervisior Supervisior Reserved 111b <i>ion 1</i>	1 active1 = Signal selected by 32.07 is outside its limits1 2 active1 = Signal selected by 32.17 is outside its limits3 active1 = Signal selected by 32.27 is outside its limitsSignal supervision status word.Selects the mode of signal supervision function 1. Determines how the monitored signal (see parameter 32.07) is compared to its lower and upper limits (32.09 and 32.10 respectively). The action to be taken when the condition is fulfilled is selected by 32.06.Signal supervision 1 not in use.Action is taken whenever the signal falls below its lower limit. Action is taken whenever the absolute value of the signal falls	 S. S. 1 = 1 <i>Disabled</i> 0 1 2
32.05	1 2 315 00000 Supervis function Disabled Low High Abs low	Supervisior Supervisior Supervisior Reserved 111b <i>ion 1</i>	1 active1 = Signal selected by 32.07 is outside its limits1 2 active1 = Signal selected by 32.17 is outside its limits3 active1 = Signal selected by 32.27 is outside its limitsSignal supervision status word.Selects the mode of signal supervision function 1. DeterminesSelects the mode of signal supervision function 1. Determineshow the monitored signal (see parameter 32.07) is comparedto its lower and upper limits (32.09 and 32.10 respectively).The action to be taken when the condition is fulfilled isselected by 32.06.Signal supervision 1 not in use.Action is taken whenever the signal falls below its lower limit.Action is taken whenever the signal rises above its upperlimit.Action is taken whenever the absolute value of the signal fallsbelow its (absolute) lower limit.Action is taken whenever the absolute value of the signal fallsbelow its (absolute) lower limit.	5. 5. 1 = 1 <i>Disabled</i> 0 1 2 3

No.	Name/Value	Description	Def/FbEq16
32.06	Supervision 1 action	Selects the action the drive takes when the value monitored by signal supervision 1 exceeds its limits. Note: This parameter does not affect the status indicated by <i>32.01 Supervision status</i> .	No action
	No action	No action taken.	0
	Warning	A warning (A8B0 Signal supervision) is generated.	1
	Fault	The drive trips on 80B0 Signal supervision.	2
	Fault if running	If running, the drive trips on 80B0 Signal supervision.	3
32.07	Supervision 1 signal	Selects the signal to be monitored by signal supervision function 1.	Zero
	Zero	None.	0
	Speed	01.01 Motor speed used (page 136).	1
	Frequency	01.06 Output frequency (page 136).	3
	Current	01.07 Motor current (page 136).	4
	Torque	01.10 Motor torque (page 136).	6
	DC voltage	01.11 DC voltage (page 137).	7
	Output power	01.14 Output power (page 137).	8
	Al1	12.11 Al1 actual value (page 182).	9
	AI2	12.21 Al2 actual value (page 184).	10
	Speed ref ramp in	23.01 Speed ref ramp input (page 242).	18
	Speed ref ramp out	23.02 Speed ref ramp output (page 242).	19
	Speed ref used	24.01 Used speed reference (page 248).	20
	Torque ref used	26.02 Torque reference used (page 264).	21
	Freq ref used	28.02 Frequency ref ramp output (page 270).	22
	Process PID output	40.01 Process PID output actual (page 325).	24
	Process PID feedback	40.02 Process PID feedback actual (page 325).	25
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
32.08	Supervision 1 filter time	Defines a filter time constant for the signal monitored by signal supervision 1.	0.000 s
	0.000 30.000 s	Signal filter time.	1000 = 1 s
32.09	Supervision 1 low	Defines the lower limit for signal supervision 1.	0.00
	-21474830.00 21474830.00	Low limit.	-
32.10	Supervision 1 high	Defines the upper limit for signal supervision 1.	0.00
	-21474830.00 21474830.00	Upper limit.	-
32.15	Supervision 2 function	Selects the mode of signal supervision function 2. Determines how the monitored signal (see parameter 32.17) is compared to its lower and upper limits (32.19 and 32.20 respectively). The action to be taken when the condition is fulfilled is selected by 32.16 .	Disabled
	Disabled	Signal supervision 2 not in use.	0
	Low	Action is taken whenever the signal falls below its lower limit.	1

No.	Name/Value	Description	Def/FbEq16
	High	Action is taken whenever the signal rises above its upper limit.	2
	Abs low	Action is taken whenever the absolute value of the signal falls below its (absolute) lower limit.	3
	Abs high	Action is taken whenever the absolute value of the signal rises above its (absolute) upper limit.	4
	Both	Action is taken whenever the signal falls below its low limit or rises above its high limit.	5
	Abs both	Action is taken whenever the absolute value of the signal falls below its (absolute) low limit or rises above its (absolute) high limit.	6
32.16	Supervision 2 action	Selects the action the drive takes when the value monitored by signal supervision 2 exceeds its limits. Note: This parameter does not affect the status indicated by 32.01 Supervision status.	No action
	No action	No action taken.	0
	Warning	A warning (A8B1 Signal supervision 2) is generated.	1
	Fault	The drive trips on 80B1 Signal supervision 2.	2
	Fault if running	If running, the drive trips on 80B0 Signal supervision.	3
32.17	Supervision 2 signal	Selects the signal to be monitored by signal supervision function 2. For the available selections, see parameter <i>32.07</i> <i>Supervision 1 signal</i> .	Zero
32.18	Supervision 2 filter time	Defines the filter time constant for the signal monitored by signal supervision 2.	0.000 s
	0.000 30.000 s	Signal filter time.	1000 = 1 s
32.19	Supervision 2 low	Defines the lower limit for signal supervision 2.	0.00
	-21474830.00 21474830.00	Low limit.	-
32.20	Supervision 2 high	Defines the upper limit for signal supervision 2.	0.00
	-21474830.00 21474830.00	Upper limit.	-
32.25	Supervision 3 function	Selects the mode of signal supervision function 3. Determines how the monitored signal (see parameter 32.27) is compared to its lower and upper limits (32.29 and 32.30 respectively). The action to be taken when the condition is fulfilled is selected by 32.26.	Disabled
	Disabled	Signal supervision 3 not in use.	0
	Low	Action is taken whenever the signal falls below its lower limit.	1
	High	Action is taken whenever the signal rises above its upper limit.	2
	Abs low	Action is taken whenever the absolute value of the signal falls below its (absolute) lower limit.	3
	Abs high	Action is taken whenever the absolute value of the signal rises above its (absolute) upper limit.	4
	Both	Action is taken whenever the signal falls below its low limit or rises above its high limit.	5

No.	Name/Value	Description	Def/FbEq16
	Abs both	Action is taken whenever the absolute value of the signal falls below its (absolute) low limit or rises above its (absolute) high limit.	6
32.26	Supervision 3 action	Selects the action the drive takes when the value monitored by signal supervision 3 exceeds its limits. Note: This parameter does not affect the status indicated by <i>32.01 Supervision status</i> .	No action
	No action	No action taken.	0
	Warning	A warning (A8B2 Signal supervision 3) is generated.	1
	Fault	The drive trips on 80B2 Signal supervision 3.	2
	Fault if running	If running, the drive trips on 80B0 Signal supervision.	3
32.27	Supervision 3 signal	Selects the signal to be monitored by signal supervision function 3. For the available selections, see parameter 32.07 Supervision 1 signal.	Zero
32.28	Supervision 3 filter time	Defines the filter time constant for the signal monitored by signal supervision 3.	0.000 s
	0.000 30.000 s	Signal filter time.	1000 = 1 s
32.29	Supervision 3 low	Defines the lower limit for signal supervision 3.	0.00
	-21474830.00 21474830.00	Low limit.	-
32.30	Supervision 3 high	Defines the upper limit for signal supervision 3.	0.00
	-21474830.00 21474830.00	Upper limit.	-

33 Generic timer & counter	Configuration of maintenance timers/counters. See also section <i>Maintenance timers and counters</i> (page 120).	
33.01 Counter status	Displays the maintenance timer/counter status word, indicating which maintenance timers/counters have exceeded their limits. This parameter is read-only.	-

Bit	Name	Description	
0	On-time1	1 = On-time timer 1 has reached its preset limit.	
1	On-time2	1 = On-time timer 2 has reached its preset limit.	
2	Edge 1	1 = Signal edge counter 1 has reached its preset limit.	
3	Edge 2	1 = Signal edge counter 2 has reached its preset limit.	
4	Value 1	1 = Value counter 1 has reached its preset limit.	
5	Value 2	1 = Value counter 2 has reached its preset limit.	
615	Reserved	· · ·	
			1
0000 0000b Maint 0011 1111b		Maintenance time/counter status word.	1 = 1

No.	Name/V	alue	Description	Def/FbEq16
33.10	On-time	1 actual	Displays the actual present value of on-time timer 1. The timer runs whenever the signal selected by parameter 33.13 On-time 1 source is on. When the timer exceeds the limit set by 33.11 On-time 1 warn limit, bit 0 of 33.01 Counter status is set to 1. The warning specified by 33.14 On-time 1 warn message is also given if enabled by 33.12 On-time 1 function. The timer can be reset from the Drive composer PC tool, or from the control panel by keeping Reset depressed for over 3	-
			seconds.	
	04294	1967295 s	Actual present value of on-time timer 1.	-
33.11	On-time	1 warn limit	Sets the warning limit for on-time timer 1.	0 s
	04294	1967295 s	Warning limit for on-time timer 1.	-
33.12	On-time	1 function	Configures on-time timer 1.	0000b
	Bit	Function		
	0	33.01) swite seconds. 1 = Saturate and remain is reset. Warning en	When the limit is reached, the counter is reset. The counter statuches to 1 for one second. The warning (if enabled) stays active for the limit is reached, the counter status (bit 0 of <i>33.01</i>) so so until <i>33.10</i> is reset. The warning (if enabled) also stays active for the second status (bit 0 of <i>33.01</i>) so so until <i>33.10</i> is reset. The warning (if enabled) also stays active for the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bit 0 of <i>33.01</i>) so the second status (bi	or at least 10 switches to 1,
	215		A warning (see <u>33.14</u>) is given when the limit is reached	
	210	Reserved		
	0000b	.0011b	On-time timer 1 configuration word.	1 = 1
33.13	On-time 1 source		Selects the signal to be monitored by on-time timer 1.	False
	False		Constant 0 (timer disabled).	0
	True		Constant 1.	1
	RO1		Bit 0 of 10.21 RO status (page 173).	2
	Other [b	it]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
33.14	On-time 1 warn message		Selects the optional warning message for on-time timer 1.	On-time 1 exceeded
	On-time 1 exceeded		A886 On-time 1. The message text can be edited on the control panel by choosing Menu – Settings – Edit texts.	0
	Clean device		A88C Device clean.	6
	Maintair cooling	n additional fan	A890 Additional cooling.	7
	Maintair fan	n cabinet	A88E Cabinet fan.	8
	Maintair capacito		A88D DC capacitor.	9
	Maintair bearing	n motor	A880 Motor bearing.	10

No.	Name/\	/alue	Description	Def/FbEq16			
33.20	On-time 2 actual		Displays the actual present value of on-time timer 2. The timer runs whenever the signal selected by parameter 33.23 On-time 2 source is on. When the timer exceeds the limit set by 33.21 On-time 2 warn limit, bit 1 of 33.01 Counter status is set to 1. The warning specified by 33.24 On-time 2 warn message is also given if enabled by 33.22 On-time 2 function. The timer can be reset from the Drive composer PC tool, or from the control panel by keeping Reset depressed for over 3 seconds.	-			
	04294	4967295 s	Actual present value of on-time timer 2.	-			
33.21	On-time	e 2 warn limit	Sets the warning limit for on-time timer 2.	0 s			
	0429	4967295 s	Warning limit for on-time timer 2.	-			
33.22	On-time	e 2 function	Configures on-time timer 2.	0000b			
	Bit	Function]			
	0	33.01) swite seconds. 1 = Saturat	ode When the limit is reached, the counter is reset. The counter statuches to 1 for one second. The warning (if enabled) stays active f e: When the limit is reached, the counter status (bit 1 of <i>33.01</i>) s s so until <i>33.20</i> is reset. The warning (if enabled) also stays active	or at least 10 switches to 1,			
	1		able No warning is given when the limit is reached A warning (see <u>33.24</u>) is given when the limit is reached				
	215	Reserved					
	00b1	1b	On-time timer 2 configuration word.	1 = 1			
33.23	On-time 2 source		Selects the signal to be monitored by on-time timer 2.	False			
	False		Constant 0 (timer disabled).	0			
	True		Constant 1.	1			
	RO1		Bit 0 of <i>10.21 RO status</i> (page <i>173</i>).	2			
	Other [bit]		Source selection (see <i>Terms and abbreviations</i> on page 131).	-			
33.24	On-time 2 warn message		Selects the optional warning message for on-time timer 2.	On-time 2 exceeded			
	On-time exceed		<i>A887 On-time 2.</i> The message text can be edited on the control panel by choosing Menu – Settings – Edit texts.	1			
	Clean device		A88C Device clean.	6			
	Maintain additional cool fan		A890 Additional cooling.	7			
	Maintai fan	n cabinet	A88E Cabinet fan.	8			
	Maintai capacite		A88D DC capacitor.	9			
	Maintai bearing		A880 Motor bearing.	10			

No.	Name/V	alue	Description	Def/FbEq16				
33.30	0 Edge counter 1 actual		Actual present value of signal edge counter 1. The counter is incremented every time the signal selected by parameter 33.33 Edge counter 1 source switches on or off (or either, depending on the setting of 33.32 Edge counter 1 function). A divisor may be applied to the count (see 33.34 Edge counter 1 divider). When the counter exceeds the limit set by 33.31 Edge counter 1 warn limit, bit 2 of 33.01 Counter status is set to 1. The warning specified by 33.35 Edge counter 1 warn message is also given if enabled by 33.32 Edge counter 1 function. The counter can be reset from the Drive composer PC tool, or from the control panel by keeping Reset depressed for over 3 seconds.	-				
	04294	967295	Actual present value of signal edge counter 1.	-				
33.31	Edge co warn lim		Sets the warning limit for signal edge counter 1.	0				
	04294	967295	Warning limit for signal edge counter 1.	-				
33.32	Edge co function	unter 1	Configures signal edge counter 1.	0000b				
	Bit	Function						
	1	33.01) swite (if enabled) 1 = Saturate	 When the limit is reached, the counter is reset. The counter statuches to 1 and remains so until the counter is again incremented. stays active for at least 10 seconds. e: When the limit is reached, the counter status (bit 2 of 33.01) s s o until 33.30 is reset. The warning (if enabled) also stays activates able 	The warning switches to 1,				
			 Disable: No warning is given when the limit is reached Enable: A warning (see 33.35) is given when the limit is reached 					
	2							
	3	0 = Disable	falling edges sable: Falling edges are not counted able: Falling edges are counted					
	415	Reserved						
	0000b	11116	Edge counter 1 configuration word.	1 = 1				
33.33	Edge co		Selects the signal to be monitored by signal edge counter 1.	False				
00.00	source							
	False		Constant 0.	0				
	True		Constant 1.	1				
	RO1		Bit 0 of 10.21 RO status (page 173).	2				
	Other [b		Source selection (see <i>Terms and abbreviations</i> on page 131).	-				
33 34	3.34 Edge counter 1 divider		Defines a divisor for signal edge counter 1. Determines how many signal edges increment the counter by 1.	1				
00.04	14294967295							
		967295	Divisor for signal edge counter 1.	-				

No.	Name/V	alue	Description	Def/FbEq16		
	Edge co exceede		A888 Edge counter 1. The message text can be edited on the control panel by choosing Menu – Settings – Edit texts.	2		
	Countec contacto	-	A884 Main contactor.	11		
	Countec relay	l output	A881 Output relay.	12		
	Counteo starts	l motor	A882 Motor starts.	13		
	Counted	power ups	A883 Power ups.	14		
	Countec charges		A885 DC charge.	15		
33.40 Edge counter 2 actual		ounter 2	Displays the actual present value of signal edge counter 2. The counter is incremented every time the signal selected by parameter 33.43 Edge counter 2 source switches on or off (or either, depending on the setting of 33.42 Edge counter 2 function). A divisor may be applied to the count (see 33.44 Edge counter 2 divider). When the counter exceeds the limit set by 33.41 Edge counter 2 warn limit, bit 3 of 33.01 Counter status is set to 1. The warning specified by 33.45 Edge counter 2 warn message is also given if enabled by 33.42 Edge counter 2 function. The counter can be reset from the Drive composer PC tool, or from the control panel by keeping Reset depressed for over 3 seconds.	-		
	04294967295		Actual present value of signal edge counter 2.	-		
33.41	Edge co warn lim		Sets the warning limit for signal edge counter 2.	0		
	04294	1967295	Warning limit for signal edge counter 2.	-		
33.42	Edge co function		Configures signal edge counter 2.	0000b		
	Bit	Function				
	0	Counter mode 0 = Loop: When the limit is reached, the counter is reset. The counter status (bit 3 of 33.01) remains 1 until the counter is again incremented. The warning (if enabled) state active for at least 10 seconds. 1 = Saturate: After the limit is reached, the counter status (bit 3 of 33.01) remains 1 until 33.40 is reset. The warning (if enabled) also stays active until 33.40 is reset.				
	1	Warning en 0 = Disable 1 = Enable:				
	2	 1 = Enable: A warning (see 33.45) is given when the limit is reached Count rising edges 0 = Disable: Rising edges are not counted 1 = Enable: Rising edges are counted 				
	3	Count falling edges 0 = Disable: Falling edges are not counted 1 = Enable: Falling edges are counted				
	415	Reserved				

No.	Name/Value	Description	Def/FbEq16
33.43	Edge counter 2 source	Selects the signal to be monitored by signal edge counter 2.	False
	False	0.	0
	True	1.	1
	RO1	Bit 0 of 10.21 RO status (page 173).	2
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
33.44	Edge counter 2 divider	Defines a divisor for signal edge counter 2. Determines how many signal edges increment the counter by 1.	1
	14294967295	Divisor for signal edge counter 2.	-
33.45	Edge counter 2 warn message	Selects the optional warning message for signal edge counter 2.	Edge counter 2 exceeded
	Edge counter 2 exceeded	A889 Edge counter 2. The message text can be edited on the control panel by choosing Menu – Settings – Edit texts.	3
	Counted main contactor	A884 Main contactor.	11
	Counted output relay	A881 Output relay.	12
	Counted motor starts	A882 Motor starts.	13
	Counted power ups	A883 Power ups.	14
	Counted DC charges	A885 DC charge.	15
33.50	Value counter 1 actual	Displays the actual present value of value counter 1. The value of the source selected by parameter 33.53 Value counter 1 source is read at one-second intervals and added to the counter. A divisor can be applied to the count (see 33.54 Value counter 1 divider). When the counter exceeds the limit set by 33.51 Value	-
		<i>counter 1 warn limit</i> , bit 4 of <i>33.01 Counter status</i> is set to 1. The warning specified by <i>33.55 Value counter 1 warn</i> <i>message</i> is also given if enabled by <i>33.52 Value counter 1</i> <i>function</i> .	
		The counter can be reset from the Drive composer PC tool, or from the control panel by keeping Reset depressed for over 3 seconds.	
	-2147483008 2147483008	Actual present value of value counter 1.	-
33.51	Value counter 1 warn limit	Sets the limit for value counter 1. With a positive limit, bit 4 of 33.01 Counter status is set to 1 (and a warning optionally generated) when the counter is equal or greater than the limit.	0
		With a negative limit, bit 4 of 33.01 Counter status is set to 1 (and a warning optionally generated) when the counter is equal or smaller than the limit. 0 = Counter disabled.	
	-2147483008 2147483008	Limit for value counter 1.	-

No.	No. Name/Value		Name/Value Description	
33.52	Value c function	ounter 1 N	Configures value counter 1.	0000b
	Bit	Function		
	0	33.01) swi seconds. 1 = Satura	node When the limit is reached, the counter is reset. The counter statu tches to 1 for one second. The warning (if enabled) stays active f ite: When the limit is reached, the counter status (bit 4 of <i>33.01</i>) s ns so until <i>33.50</i> is reset. The warning (if enabled) also stays activ	for at least 10 switches to 1,
	1		nable e: No warning is given when the limit is reached e: A warning (see <u>33.55</u>) is given when the limit is reached	
	215	Reserved		
	0000b	.0011b	Value counter 1 configuration word.	1 = 1
33.53	Value counter 1 source		Selects the signal to be monitored by value counter 1.	Not selected
	Not selected		None (counter disabled).	0
	Motor s	peed	01.01 Motor speed used (see page 136).	1
	Other		Source selection (see <i>Terms and abbreviations</i> on page <i>131</i>).	-
33.54	Value counter 1 divider		Defines a divisor for value counter 1. The value of the monitored signal is divided by this value before integration.	1.000
	0.001 214748		Divisor for value counter 1.	-
33.55	Value counter 1 warn message		Selects the optional warning message for value counter 1.	Value counter 1 exceeded
	Value counter 1 exceeded		A88A Value counter 1. The message text can be edited on the control panel by choosing Menu – Settings – Edit texts.	4
	Maintaiı bearing		A880 Motor bearing.	10
33.60	Value c actual	ounter 2	Displays the actual present value of value counter 2. The value of the source selected by parameter 33.63 Value counter 2 source is read at one-second intervals and added to the counter. A divisor can be applied to the count (see 33.64 Value counter 2 divider).	-
			When the counter exceeds the limit set by 33.61 Value counter 2 warn limit, bit 5 of 33.01 Counter status is set to 1. The warning specified by 33.65 Value counter 2 warn message is also given if enabled by 33.62 Value counter 2 function.	
			The counter can be reset from the Drive composer PC tool, or from the control panel by keeping Reset depressed for over 3 seconds.	
	-214748 214748	33008 3008	Actual present value of value counter 2.	-

00b					
00b					
00b					
it 5 of t least 10 thes to 1, ntil <u>33.60</u>					
Warning enable) = Disable: No warning is given when the limit is reached I = Enable: A warning (see <u>33.65</u>) is given when the limit is reached					
215 Reserved					
: 1					
t selected					
00					
lue unter 2 ceeded					

No.	Name/V	alue	Description		Def/FbEq16
35 Motor thermal protection			measuremen fan control co	Il protection settings such as temperature t configuration, load curve definition and motor onfiguration. tion <i>Motor thermal protection</i> (page <i>113</i>).	
35.01	Motor es tempera		motor therma 35.5035.55 selection	motor temperature as estimated by the internal al protection model (see parameters 5). The unit is selected by parameter <i>96.16 Unit</i> er is read-only.	-
	-60 … 1 °C or °F		Estimated mo	otor temperature.	1 = 1 °
35.02	Measure tempera		defined by pa selected by p Note: With a	temperature received through the source arameter 35.11 Temperature 1 source. The unit is barameter 96.16 Unit selection. PTC sensor, the unit is ohms. er is read-only.	-
	-60 1 -76 1 05000	832 °F, or	Measured ter	nperature 1.	1 = 1 unit
35.03	3 Measured temperature 2		defined by pa is selected by Note: With a	temperature received through the source arameter 35.21 Temperature 2 source. The unit y parameter 96.16 Unit selection. PTC sensor, the unit is ohms. er is read-only.	-
	-60 1 -76 1 05000	832 °F, or	Measured ter	mperature 2.	1 = 1 unit
35.04	FPTC st	tatus word	The word car The modules <i>configuration</i>	status of optional FEX-01/FPTC-01 modules. to be used as the source of eg. external events. are activated by parameter 35.30 FPTC word. there is read-only.	-
	Bit	Name		Description	
	0	Module fou	nd in slot 1	1 = Yes: An FPTC-xx module has been detected	l in slot 1.
	1	Fault active	e in slot 1	1 = Yes: The module in slot 1 has an active fault	. (4991) .
	2	Warning ac	tive in slot 1	1 = Yes: The module in slot 1 has an active warr	ning (<i>A4</i> 97).
	3	Module fou	nd in slot 2	1 = Yes: An FPTC-xx module has been detected	l in slot 2.
	4	Fault active	e in slot 2	1 = Yes: The module in slot 2 has an active fault	. (4992) .
	5		ctive in slot 21 = Yes: The module in slot 2 has an active warning (A49and in slot 31 = Yes: An FPTC-xx module has been detected in slot 3.		
	6				
	7	Fault active		1 = Yes: The module in slot 3 has an active fault	, ,
	8	Warning ac	tive in slot 3	1 = Yes: The module in slot 3 has an active warr	ning (A499).
	915	Reserved			
	0000h	FFFFh	FPTC-xx stat	us word	1 = 1
	000011		TETU-XX SIdi	uə woru.	

No.	Name/Value	Description	Def/FbEq16
35.11	Temperature 1 source	Selects the source from which measured temperature 1 is read. For wiring examples, see the hardware manual of the drive. Usually this source is from a sensor connected to the motor controlled by the drive, but it could be used to measure and monitor a temperature from other parts of the process as long as a suitable sensor is used as per the selection list.	Disabled
	Disabled	None. Temperature monitoring function 1 is disabled.	0
	Estimated temperature	Estimated motor temperature (see parameter <i>35.01 Motor</i> <i>estimated temperature</i>). The temperature is estimated from an internal drive calculation. It is important to set up the ambient temperature of the motor in <i>35.50 Motor ambient temperature</i> .	1
	KTY84 analog I/O	 KTY84 sensor connected to the analog input selected by parameter 35.14 Temperature 1 AI source and an analog output. The input and output can be on the drive control unit or on an extension module. The following settings are required: Set the hardware jumper or switch related to the analog input to <i>U</i> (voltage). Any change must be validated by a control unit reboot. Set the unit selection parameter of the input to volt. Set the source selection parameter of the analog output to <i>"Force KTY84 excitation"</i>. Select the analog input in parameter 35.14. In case the input is located on an I/O extension module, use the selection Other to point at the actual input value parameter (for example, 14.26 AI1 actual value). The analog output feeds a constant current through the sensor. As the resistance of the sensor changes along with its temperature, the voltage over the sensor changes. The voltage is read by the analog input and converted into degrees. 	2
	KTY84 encoder module 1	KTY84 sensor connected to encoder interface 1. See also parameters <i>91.21 Module 1 temp sensor type</i> and <i>91.22 Module 1 temp filter time</i> .	3
	KTY84 encoder module 2	KTY84 sensor connected to encoder interface 2. See also parameters <i>91.24 Module 2 temp sensor type</i> and <i>91.25 Module 2 temp filter time</i> .	4
	1 x Pt100 analog I/O	Pt100 sensor connected to a standard analog input selected by parameter 35.14 Temperature 1 AI source and an analog output. The input and output can be on the drive control unit or on an extension module. The required settings are the same as with selection <i>KTY84</i> <i>analog I/O</i> , except that the source selection parameter of the analog output must be set to <i>Force PT100 excitation</i> .	5
	2 x Pt100 analog I/O	As selection 1 x <i>Pt100 analog I/O</i> , but with two sensors connected in series. Using multiple sensors improves measurement accuracy significantly.	6
	3 x Pt100 analog I/O	As selection 1 x <i>Pt100 analog I/O</i> , but with three sensors connected in series. Using multiple sensors improves measurement accuracy significantly.	7

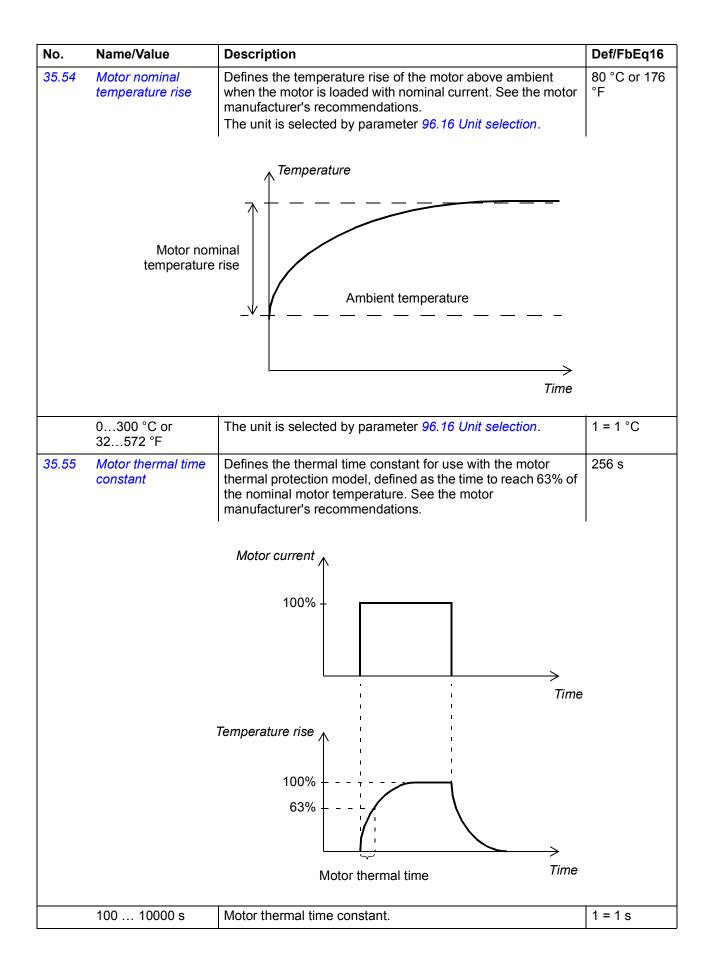
No.	Name/Value	Description	Def/FbEq16
	PTC DI6	PTC sensor connected to digital input DI6 (see the connection diagram on page <i>113</i>). Note: Either 0 ohm (normal temperature) or 4000 ohm (excessive temperature) will be shown by <i>35.02 Measured temperature 1</i> . By default, an excessive temperature will generate a warning as per parameter <i>35.13 Temperature 1 warning limit</i> . If you want a fault instead, set <i>35.12 Temperature 1 fault limit</i> to 4000 ohm.	8
	PTC analog I/O	PTC sensor connected to a standard analog input selected by parameter <i>35.14 Temperature 1 Al source</i> and an analog output. The input and output can be on the drive control unit or on an extension module. The required settings are the same as with selection <i>KTY84 analog I/O</i> , except that the source selection parameter of the analog output must be set to <i>Force PTC excitation</i> .	20
	PTC encoder module 1	PTC sensor connected to encoder interface 1. See also parameters <i>91.21 Module 1 temp sensor type</i> and <i>91.22 Module 1 temp filter time</i> .	9
	PTC encoder module 2	PTC sensor connected to encoder interface 2. See also parameters <i>91.24 Module 2 temp sensor type</i> and <i>91.25 Module 2 temp filter time</i> .	10
	Direct temperature	The temperature is taken from the source selected by parameter <i>35.14 Temperature 1 AI source</i> . The value of the source is assumed to be in the unit of temperature specified by <i>96.16 Unit selection</i> .	11
	1 × Pt1000 analog I/O	Pt1000 sensor connected to a standard analog input selected by parameter 35.14 Temperature 1 AI source and an analog output. The input and output can be on the drive control unit or on an extension module. The required settings are the same as with selection <i>KTY84</i> <i>analog I/O</i> , except that the source selection parameter of the analog output must be set to <i>Force Pt1000 excitation</i> .	13
	2 × Pt1000 analog I/O	As selection 1 × <i>Pt1000 analog I/O</i> , but with two sensors connected in series. Using multiple sensors improves measurement accuracy significantly.	14
	3 × Pt1000 analog I/O	As selection 1 × <i>Pt1000 analog I/O</i> , but with three sensors connected in series. Using multiple sensors improves measurement accuracy significantly.	15
35.12	Temperature 1 fault limit	Defines the fault limit for temperature monitoring function 1. When measured temperature 1 exceeds the limit, the drive trips on fault 4981 External temperature 1. The unit is selected by parameter 96.16 Unit selection. Note: With a PTC sensor, the unit is ohms.	130 °C, 266 °F or 4500 ohm
	-60 … 1000 °C, -76 … 1832 °F or 0…5000 ohm	Fault limit for temperature monitoring function 1.	1 = 1 unit
35.13	Temperature 1 warning limit	Defines the warning limit for temperature monitoring function 1. When measured temperature 1 exceeds this limit, the warning (<i>A491 External temperature 1</i>) is generated. The unit is selected by parameter <i>96.16 Unit selection</i> . Note: With a PTC sensor, the unit is ohms.	110 °C, 230 °F or 4000 ohm
	-60 … 1000 °C, -76 … 1832 °F or 0…5000 ohm	Warning limit for temperature monitoring function 1.	1 = 1 unit

No.	Name/Value	Description	Def/FbEq16
35.14	Temperature 1 Al source	Specifies the analog input when the setting of <i>35.11</i> <i>Temperature 1 source</i> requires measurement through an analog input. Note: If the input is located on an I/O extension module, use the selection <i>Other</i> to point to the AI actual value in group 14, 15 or 16, eg. <i>14.26 AI1 actual value</i> .	Not selected
	Not selected	None.	0
	Al1 actual value	Analog input AI1 on the control unit.	1
	Al2 actual value	Analog input Al2 on the control unit.	2
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
35.21	Temperature 2 source	Selects the source from which measured temperature 2 is read. For wiring examples, see the hardware manual of the drive. Usually this source is from a sensor connected to the motor controlled by the drive, but it could be used to measure and monitor a temperature from other parts of the process as long as a suitable sensor is used as per the selection list.	Disabled
	Disabled	None. Temperature monitoring function 2 is disabled.	0
	Estimated temperature	Estimated motor temperature (see parameter <i>35.01 Motor</i> <i>estimated temperature</i>). The temperature is estimated from an internal drive calculation. It is important to set up the ambient temperature of the motor in <i>35.50 Motor ambient temperature</i> .	1
	KTY84 analog I/O	 KTY84 sensor connected to the analog input selected by parameter 35.24 Temperature 2 AI source and an analog output. The input and output can be on the drive control unit or on an extension module. The following settings are required: Set the hardware jumper or switch related to the analog input to <i>U</i> (voltage). Any change must be validated by a control unit reboot. Set the unit selection parameter of the input to volt. Set the source selection parameter of the analog output to <i>"Force KTY84 excitation"</i>. Select the analog input in parameter 35.24. In case the input is located on an I/O extension module, use the selection Other to point at the actual input value parameter (for example, 14.26 AI1 actual value). The analog output feeds a constant current through the sensor. As the resistance of the sensor changes. The voltage is read by the analog input and converted into degrees. 	2
	KTY84 encoder module 1	KTY84 sensor connected to encoder interface 1. See also parameters <i>91.21 Module 1 temp sensor type</i> and <i>91.22 Module 1 temp filter time</i> .	3
	KTY84 encoder module 2	KTY84 sensor connected to encoder interface 2. See also parameters <i>91.24 Module 2 temp sensor type</i> and <i>91.25 Module 2 temp filter time</i> .	4

No.	Name/Value	Description	Def/FbEq16
	1 x Pt100 analog I/O	Pt100 sensor connected to a standard analog input selected by parameter 35.24 Temperature 2 AI source and an analog output. The input and output can be on the drive control unit or on an extension module. The required settings are the same as with selection <i>KTY84</i>	5
		analog I/O, except that the source selection parameter of the analog output must be set to <i>Force PT100 excitation</i> .	
	2 x Pt100 analog I/O	As selection <i>1 x Pt100 analog I/O</i> , but with two sensors connected in series. Using multiple sensors improves measurement accuracy significantly.	6
	3 x Pt100 analog I/O	As selection <i>1 x Pt100 analog I/O</i> , but with three sensors connected in series. Using multiple sensors improves measurement accuracy significantly.	7
	PTC DI6	PTC sensor connected to digital input DI6 (see the connection diagram on page <i>113</i>). Note: Either 0 ohm (normal temperature) or 4000 ohm (excessive temperature) will be shown by <i>35.03 Measured temperature 2</i> . By default, an excessive temperature will generate a warning as per parameter <i>35.23 Temperature 2 warning limit</i> . If you want a fault instead, set <i>35.22 Temperature 2 fault limit</i> to 4000 ohm.	8
	PTC analog I/O	PTC sensor connected to a standard analog input selected by parameter 35.24 Temperature 2 AI source and an analog output. The input and output can be on the drive control unit or on an extension module. The required settings are the same as with selection <i>KTY84 analog I/O</i> , except that the source selection parameter of the analog output must be set to <i>Force PTC excitation</i> .	20
	PTC encoder module 1	PTC sensor connected to encoder interface 1. See also parameters <i>91.21 Module 1 temp sensor type</i> and <i>91.22 Module 1 temp filter time</i> .	9
	PTC encoder module 2	PTC sensor connected to encoder interface 2. See also parameters 91.24 Module 2 temp sensor type and 91.25 Module 2 temp filter time.	10
	Direct temperature	The temperature is taken from the source selected by parameter 35.24 Temperature 2 Al source. The value of the source is assumed to be in the unit of temperature specifiec by 96.16 Unit selection.	11
	1 × Pt1000 analog I/O	Pt1000 sensor connected to a standard analog input selected by parameter 35.24 Temperature 2 AI source and an analog output. The input and output can be on the drive control unit or on an extension module. The required settings are the same as with selection <i>KTY84</i> analog I/O, except that the source selection parameter of the analog output must be set to Force Pt1000 excitation.	13
	2 × Pt1000 analog I/O	As selection 1 × <i>Pt1000 analog I/O</i> , but with two sensors connected in series. Using multiple sensors improves measurement accuracy significantly.	14
	3 × Pt1000 analog I/O	As selection 1 × <i>Pt1000 analog I/O</i> , but with three sensors connected in series. Using multiple sensors improves measurement accuracy significantly.	15

No.	Name/Va	alue	Description		Def/FbEq16
35.22	Tempera limit	ture 2 fault	When measu trips on fault The unit is se	ault limit for temperature monitoring function 2. red temperature 2 exceeds the limit, the drive 4982 External temperature 2. elected by parameter 96.16 Unit selection. PTC sensor, the unit is ohms.	130 °C, 266 °F or 4500 ohm
	-60 10 -76 18 05000	332 °F or	Fault limit for	temperature monitoring function 2.	1 = 1 unit
35.23	Tempera warning		2. When mea warning (<i>A4</i> 9 The unit is se	varning limit for temperature monitoring function issured temperature 2 exceeds the limit, a 22 External temperature 2) is generated. elected by parameter 96.16 Unit selection. PTC sensor, the unit is ohms.	110 °C, 230 °F or 4000 ohm
	-60 10 -76 18 05000	332 °F or	Warning limit	for temperature monitoring function 2.	1 = 1 unit
35.24	Tempera source	ture 2 Al	selections K7	Poput for parameter 35.21 <i>Temperature 2 source</i> , TY84 analog I/O, 1 x Pt100 analog I/O, 2 x Pt100 x Pt100 analog I/O and Direct temperature.	Not selected
	Not sele	cted	None.		0
	AI1 actua	al value	Analog input	Al1 on the control unit.	1
	Al2 actua	al value	Analog input	AI2 on the control unit.	2
	Other		Source selection (see <i>Terms and abbreviations</i> on page 131		-
35.30	FPTC configuration word		installed on th	X-01/FPTC-01 temperature monitoring modules ne control unit of the drive. Using this word, it is to suppress the warnings (but not faults) from	0010 1010b
	Bit	Name		Description	
	0	Module in s	lot 1	1 = Yes: Module installed in slot 1.	
	1	Disable slot	1 warning 1 = Yes: Warnings from the module in slot 1 suppres		pressed.
	2	Module in s	lot 1	1 = Yes: Module installed in slot 2.	
	3	Disable slot	1 warning 1 = Yes: Warnings from the module in slot 2 suppres		pressed.
	4	Module in s	lot 1	1 = Yes: Module installed in slot 3.	
	5	Disable slot	1 warning	1 = Yes: Warnings from the module in slot 3 sup	pressed.
	615 Reserved				
					1
	0000 000 0011 111	1b		C-01 module configuration word.	1 = 1
35.50	Motor ambient temperature		thermal prote 96.16 Unit se The motor the temperature of motor temper the load curve below the loa WARN does n	ermal protection model estimates the motor on the basis of parameters 35.5035.55. The rature increases if it operates in the region above e, and decreases if it operates in the region d curve. NING! The model cannot protect the motor if it not cool properly because of dust, dirt, etc.	20 °C or 68 °F
	-60 10 -75 2′		Ambient temp	perature.	1 = 1 °C

No.	Name/Value	Description	Def/FbEq16
35.51	Motor load curve	Defines the motor load curve together with parameters 35.52 Zero speed load and 35.53 Break point. The load curve is used by the motor thermal protection model to estimate the motor temperature. When the parameter is set to 100%, the maximum load is taken as the value of parameter 99.06 Motor nominal current (higher loads heat up the motor). The load curve level should be adjusted if the ambient temperature differs from the nominal value set in 35.50 Motor ambient temperature.	100%
	// _N (%)	/ = Motor current / _N = Nominal motor current	
	150 —		
	100	35.51	
	50 - 35.52		
	L	35.53 Drive output frequency	ut
	50 150%	Maximum load for the motor load curve.	1 = 1%
35.52	Zero speed load	Defines the motor load curve together with parameters 35.51 <i>Motor load curve</i> and 35.53 <i>Break point</i> . Defines the maximum motor load at zero speed of the load curve. A higher value can be used if the motor has an external motor fan to boost the cooling. See the motor manufacturer's recommendations. See parameter 35.51 <i>Motor load curve</i> .	100%
	50 150%	Zero speed load for the motor load curve.	1 = 1%
35.53	Break point	Defines the motor load curve together with parameters 35.51 Motor load curve and 35.52 Zero speed load. Defines the break point frequency of the load curve i.e. the point at which the motor load curve begins to decrease from the value of parameter 35.51 Motor load curve towards the value of parameter 35.52 Zero speed load. See parameter 35.51 Motor load curve.	45.00 Hz
	1.00 500.00 Hz	Break point for the motor load curve.	See par. 46.02



No.	Name/Value	Description	Def/FbEq16
35.60	Cable temperature	Shows the calculated temperature of the motor cable. See section <i>Thermal protection of motor cable</i> (page 116). 102% = overtemperature warning (<i>A480 Motor cable</i> <i>overload</i>) 106% = overtemperature fault (<i>4000 Motor cable overload</i>) This parameter is read-only.	0.0%
	0.0 200.0%	Calculated temperature of motor cable.	1 = 1%
35.61	Cable nominal current	Specifies the continuous current of the motor cable for the thermal protection function in the control program. WARNING! The value entered in this parameter must be limited according to all factors affecting the loadability of the cable, such as ambient temperature, cabling arrangement, and shrouding. Refer to the technical data from the cable manufacturer.	10000.00 A
	0.00 10000.00 A	Continuous current-carrying capacity of motor cable.	1 = 1 A
35.62	Cable thermal rise time	Specifies the thermal time of the motor cable for the thermal protection function in the control program. This value is defined as the time to reach 63% of the nominal cable temperature when the cable is loaded with nominal current (parameter 35.61 Cable nominal current). 0 s = Thermal protection of motor cable disabled Refer to the technical data from the cable manufacturer. Cable current 100% 10% 1	1 s
	_	Cable thermal time	1
	0 s	Thermal protection of motor cable disabled.	1 = 1 s
	150000 s	Motor cable thermal time constant.	1 = 1 s

No.	Name/Value	Description	Def/FbEq16
35.100	DOL starter control source	Parameters 35.10035.106 configure a monitored start/stop control logic for external equipment such as a contactor- controlled motor cooling fan. This parameter selects the signal that starts and stops the fan. 0 = Stop 1 = Start The output controlling the fan contactor is to be connected to parameter 35.105, bit 1. On and off delays can be set for the fan by 35.101 and 35.102 respectively. A feedback signal from the fan can be connected to an input selected by 35.103; the loss of the feedback will optionally trigger a warning or	Off, 06.16 b6 (95.20 b6)
	Off	fault (see 35.104 and 35.106). 0 (function disabled).	0
	On	1.	1
	Running	Bit 6 of 06.16 Drive status word 1 (see page 150).	2
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
35.101	DOL starter on delay	Defines a start delay for the motor fan. The delay timer starts when the control source selected by parameter 35.100 switches on. After the delay, bit 1 of 35.105 switches on.	0 s
	042949673 s	Motor fan start delay.	1 = 1 s
35.102	DOL starter off delay	Defines a stop delay for the motor fan. The delay timer starts when the control source selected by parameter <i>35.100</i> switches off. After the delay, bit 1 of <i>35.105</i> switches off.	20 min
	0715828 min	Motor fan stop delay.	1 = 1 min
35.103	DOL starter feedback source	Selects the input for motor fan feedback signal. 0 = Stopped 1 = Running After the fan is started (bit 1 of 35.105 switches on), feedback is expected within the time set by 35.104.	Not selected; DI5 (95.20 b6)
	Not selected	0.	0
	Selected	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-

No.	Name/\	/alue	Desc	ription	Def/FbEq16		
35.104	04 DOL starter feedback delay		The offeedbaction action Note is los	es a feedback delay for the motor fan. delay timer starts when bit 1 of <i>35.105</i> switches on. If no back is received from the fan until the delay elapses, the n selected by <i>35.106</i> is taken. This delay is only applied at start. If the feedback signal t during run, the action selected by <i>35.106</i> is taken ediately.	0 s; 5 s (95.20 b6)		
	0429	49673 s	Moto	r fan start delay.	1 = 1 s		
35.105	DOL starter status word		Bit 1 sourc The c and f	s of the motor fan control logic. is the control output for the fan, to be selected as the ce of, for example, a digital or relay output. other bits indicate the statuses of the selected control eedback sources, and the fault status. parameter is read-only.	-		
	Bit	Name		Description			
	0 Start comm 1 Delayed sta command		and	Status of fan control source selected by 35.100. 0 = Stop requested 1 = Start requested			
			art	Fan control bit (delays observed). Select this bit as the s output controlling the fan. 0 = Stopped 1 = Started	ource of the		
	2	DOL feedback		0 = Stopped 1 = Running			
	3 DOL fault (- 415 Reserved		-1)	Fault status. 0 = Fault (fan feedback missing). The action taken is sel 35.106. 1 = No fault	ected by		
				·			
	0000b	4446	Chat	a of motor for control locio	1 = 1		
35.106		arter event		s of motor fan control logic. cts the action taken when missing fan feedback is	Fault		
55.700	type			ted by the motor fan control logic.	T aun		
	No action	on	No a	ction taken.	0		
	Warning	g	The o	drive generates a warning (A781 Motor fan).	1		
	Fault		Drive	trips on 71B1 Motor fan.	2		
36 Loa	oad analyzer			value and amplitude logger settings. also section <i>Load analyzer</i> (page <i>121</i>).			
36.01	PVL signal source		The s parar The p signa The p <i>Rese</i> source	ts the signal to be monitored by the peak value logger. signal is filtered using the filtering time specified by meter $36.02 PVL$ filter time. beak value is stored, along with other pre-selected ils at the time, into parameters $36.1036.15$. beak value logger can be reset using parameter 36.09 to loggers. The logger is also reset whenever the signal be is changed. The date and time of the last reset are d into parameters 36.16 and 36.17 respectively.	Power inu out		
	Zero		None	e (peak value logger disabled).	0		

No.	Name/Value	Description	Def/FbEq16
	Motor speed used	01.01 Motor speed used (page 136).	1
	Output frequency	01.06 Output frequency (page 136).	3
	Motor current	01.07 Motor current (page 136).	4
	Motor torque	01.10 Motor torque (page 136).	6
	DC voltage	01.11 DC voltage (page 137).	7
	Power inu out	01.14 Output power (page 137).	8
	Speed ref ramp in	23.01 Speed ref ramp input (page 242).	10
	Speed ref ramped	23.02 Speed ref ramp output (page 242).	11
	Speed ref used	24.01 Used speed reference (page 248).	12
	Torq ref used	26.02 Torque reference used (page 264).	13
	Freq ref used	28.02 Frequency ref ramp output (page 270).	14
	Process PID out	40.01 Process PID output actual (page 325).	16
	Process PID fbk	40.02 Process PID feedback actual (page 325).	17
	Process PID act	40.03 Process PID setpoint actual (page 325).	18
	Process PID dev	40.04 Process PID deviation actual (page 325).	19
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
36.02	PVL filter time	Defines a filtering time for the peak value logger. See parameter 36.01 PVL signal source.	2.00 s
	0.00 120.00 s	Peak value logger filtering time.	100 = 1 s
36.06	AL2 signal source	Selects the signal to be monitored by amplitude logger 2. The signal is sampled at 200 ms intervals, and can be scaled using parameter 36.07 AL2 signal scaling. The results are displayed by parameters 36.4036.49. Each parameter represents an amplitude range, and shows what portion of the samples fall within that range. Amplitude logger 2 can be reset using parameter 36.09 Reset loggers. The logger is also reset whenever the signal source or scaling is changed. The date and time of the last reset are stored into parameters 36.50 and 36.51 respectively.	Ambient temperature
	Zero	None (amplitude logger 2 disabled).	0
	Motor speed used	01.01 Motor speed used (page 136).	1
	Output frequency	01.06 Output frequency (page 136).	3
	Motor current	01.07 Motor current (page 136).	4
	Motor torque	01.10 Motor torque (page 136).	6
	DC voltage	01.11 DC voltage (page 137).	7
	Power inu out	01.14 Output power (page 137).	8
	Speed ref ramp in	23.01 Speed ref ramp input (page 242).	10
	Speed ref ramped	23.02 Speed ref ramp output (page 242).	11
	Speed ref used	24.01 Used speed reference (page 248).	12
	Torq ref used	26.02 Torque reference used (page 264).	13
	Freq ref used	28.02 Frequency ref ramp output (page 270).	14
	Process PID out	40.01 Process PID output actual (page 325).	16
	Process PID fbk	40.02 Process PID feedback actual (page 325).	17
	Process PID act	40.03 Process PID setpoint actual (page 325).	18

No.	Name/Value	Description	Def/FbEq16	
	Process PID dev	40.04 Process PID deviation actual (page 325).	19	
	Ambient temperature	01.70 Ambient temperature % (page 139). The amplitude range of 0100% corresponds to 060 °C or 32140 °F.	20	
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-	
36.07	AL2 signal scaling	Defines the signal value that corresponds to 100% amplitude.		
	0.00 32767.00	Signal value corresponding to 100%.	1 = 1	
36.09	Reset loggers	Resets the peak value logger and/or amplitude logger 2. (Amplitude logger 1 cannot be reset.)	Done	
	Done	Reset completed or not requested (normal operation).	0	
	All	Reset both the peak value logger and amplitude logger 2.	1	
	PVL	Reset the peak value logger.	2	
	AL2	Reset amplitude logger 2.	3	
36.10	PVL peak value	Displays the peak value recorded by the peak value logger.	0.00	
	-32768.00 32767.00	Peak value.	1 = 1	
36.11	PVL peak date	Displays the date on which the peak value was recorded.	-	
	-	Peak occurrence date.	-	
36.12	PVL peak time	Displays the time at which the peak value was recorded.	-	
	-	Peak occurrence time.	-	
36.13	PVL current at peak	Displays the motor current at the moment the peak value was recorded.	0.00 A	
	-32768.00 32767.00 A	Motor current at peak.	1 = 1 A	
36.14	PVL DC voltage at peak	Displays the voltage in the intermediate DC circuit of the drive at the moment the peak value was recorded.	0.00 V	
	0.00 2000.00 V	DC voltage at peak.	10 = 1 V	
36.15	PVL speed at peak	Displays the motor speed at the moment the peak value was recorded.	0.00 rpm	
	-32768.00 32767.00 rpm	Motor speed at peak.	See par. 46.01	
36.16	PVL reset date	Displays the date on which the peak value logger was last reset.	-	
	-	Last reset date of the peak value logger.	-	
36.17	PVL reset time	Displays the time at which the peak value logger was last reset.	-	
	-	Last reset time of the peak value logger.	-	
36.20	AL1 below 10%	Displays the percentage of samples recorded by amplitude logger 1 that were below 10%. Note that this percentage also includes the samples that had a negative value.	0.00%	
	0.00 100.00%	Amplitude logger 1 samples below 10%.	1 = 1%	
36.21	AL1 10 to 20%	Displays the percentage of samples recorded by amplitude logger 1 that fall between 10 and 20%.	0.00%	
	0.00 100.00%	Amplitude logger 1 samples between 10 and 20%.	1 = 1%	
36.22	AL1 20 to 30%	Displays the percentage of samples recorded by amplitude logger 1 that fall between 20 and 30%.	0.00%	

No.	Name/Value	Description	Def/FbEq16
	0.00 100.00%	Amplitude logger 1 samples between 20 and 30%.	1 = 1%
36.23	AL1 30 to 40%	Displays the percentage of samples recorded by amplitude logger 1 that fall between 30 and 40%.	0.00%
	0.00 100.00%	Amplitude logger 1 samples between 30 and 40%.	1 = 1%
36.24	AL1 40 to 50%	Displays the percentage of samples recorded by amplitude logger 1 that fall between 40 and 50%.	0.00%
	0.00 100.00%	Amplitude logger 1 samples between 40 and 50%.	1 = 1%
36.25	AL1 50 to 60%	Displays the percentage of samples recorded by amplitude logger 1 that fall between 50 and 60%.	0.00%
	0.00 100.00%	Amplitude logger 1 samples between 50 and 60%.	1 = 1%
36.26	AL1 60 to 70%	Displays the percentage of samples recorded by amplitude logger 1 that fall between 60 and 70%.	0.00%
	0.00 100.00%	Amplitude logger 1 samples between 60 and 70%.	1 = 1%
36.27	AL1 70 to 80%	Displays the percentage of samples recorded by amplitude logger 1 that fall between 70 and 80%.	0.00%
	0.00 100.00%	Amplitude logger 1 samples between 70 and 80%.	1 = 1%
36.28	AL1 80 to 90%	Displays the percentage of samples recorded by amplitude logger 1 that fall between 80 and 90%.	0.00%
	0.00 100.00%	Amplitude logger 1 samples between 80 and 90%.	1 = 1%
36.29	AL1 over 90%	Displays the percentage of samples recorded by amplitude logger 1 that exceed 90%.	0.00%
	0.00 100.00%	Amplitude logger 1 samples over 90%.	1 = 1%
36.40	AL2 below 10%	Displays the percentage of samples recorded by amplitude logger 2 that are below 10%. Note that this percentage also includes the samples that had a negative value.	0.00%
	0.00 100.00%	Amplitude logger 2 samples below 10%.	1 = 1%
36.41	AL2 10 to 20%	Displays the percentage of samples recorded by amplitude logger 2 that fall between 10 and 20%.	0.00%
	0.00 100.00%	Amplitude logger 2 samples between 10 and 20%.	1 = 1%
36.42	AL2 20 to 30%	Displays the percentage of samples recorded by amplitude logger 2 that fall between 20 and 30%.	0.00%
	0.00 100.00%	Amplitude logger 2 samples between 20 and 30%.	1 = 1%
36.43	AL2 30 to 40%	Displays the percentage of samples recorded by amplitude logger 2 that fall between 30 and 40%.	0.00%
	0.00 100.00%	Amplitude logger 2 samples between 30 and 40%.	1 = 1%
36.44	AL2 40 to 50%	Displays the percentage of samples recorded by amplitude logger 2 that fall between 40 and 50%.	0.00%
	0.00 100.00%	Amplitude logger 2 samples between 40 and 50%.	1 = 1%
36.45	AL2 50 to 60%	Displays the percentage of samples recorded by amplitude logger 2 that fall between 50 and 60%.	0.00%
	0.00 100.00%	Amplitude logger 2 samples between 50 and 60%.	1 = 1%
36.46	AL2 60 to 70%	Displays the percentage of samples recorded by amplitude logger 2 that fall between 60 and 70%.	0.00%
	0.00 100.00%	Amplitude logger 2 samples between 60 and 70%.	1 = 1%

Fault

No.	Name/\	/alue	Descripti	on	Def/FbEq16	
36.47	AL2 70 to 80%			he percentage of samples recorded by amplitude nat fall between 70 and 80%.	0.00%	
	0.00	100.00%	Amplitude	logger 2 samples between 70 and 80%.	1 = 1%	
36.48	AL2 80	to 90%		he percentage of samples recorded by amplitude nat fall between 80 and 90%.	0.00%	
	0.00	100.00%	Amplitude	logger 2 samples between 80 and 90%.	1 = 1%	
36.49	AL2 ove	er 90%		he percentage of samples recorded by amplitude nat exceed 90%.	0.00%	
	0.00	100.00%	Amplitude	logger 2 samples over 90%.	1 = 1%	
36.50	AL2 res	et date	Displays t	he date on which amplitude logger 2 was last reset.	-	
	-		Last reset	date of amplitude logger 2.	-	
36.51	AL2 res	et time	Displays t	he time at which amplitude logger 2 was last reset.	-	
	-			time of amplitude logger 2.	-	
					l	
37 Us	er load o	curve	•	or user load curve. section <i>User load curve</i> (page <i>116</i>).		
37.01	ULC output status word		is indeper parameter	he status of the monitored signal. (The status word indent of the actions and delays selected by rs 37.03, 37.04, 37.41 and 37.42.) meter is read-only.	-	
	Bit	Name	In	formation		
	0	Under load	limit 1	= Monitored signal is below the underload curve		
	1	Reserved	L			
	2	Over load I	imit 1 = Monitored signal is above the overload curve			
	315	315 Reserved				
			i		i	
	000b	101b	Status of	the monitored signal.	1 = 1	
37.02	ULC su signal	pervision		e signal to be monitored. The function compares ite value of the signal against the load curve.	Not selected	
	Not sele	ected	No signal	selected (monitoring disabled).	0	
	Motor c	urrent %	01.07 Moi	tor current (see page 136).	2	
	Motor to	orque %	01.10 Moi	<i>tor torque</i> (see page <i>136</i>).	3	
	Output motor n	power % of ominal	01.15 Out	put power % of motor nom (see page 137).	4	
	Other		Source se	election (see <i>Terms and abbreviations</i> on page 131).	-	
	ULC overload actions			by the drive reacts if the absolute value of the	Disabled	
37.03				I signal stays above the overload curve for longer alue of 37.41 ULC overload timer.		
37.03				alue of 37.41 ULC overload timer.	0	
37.03	actions	d	than the v No action	alue of 37.41 ULC overload timer.	0	

2

Drive trips on 8002 ULC overload fault.

No.	Name/Value	Description	Def/FbEq16
	Warning/Fault	The drive generates a warning (<i>A8BE ULC overload warning</i>) if the signal stays continuously above the overload curve for half of the time defined by <i>37.41 ULC overload timer</i> . The drive trips on <i>8002 ULC overload fault</i> if the signal stays continuously above the overload curve for the time defined by <i>37.41 ULC overload timer</i> .	3
37.04	ULC underload actions	Selects how the drive reacts if the absolute value of the monitored signal stays below the underload curve for longer than the value of <i>37.42 ULC underload timer</i> .	Disabled
	Disabled	No action taken.	0
	Warning	The drive generates a warning (<i>A8BF ULC underload warning</i>).	1
	Fault	Drive trips on 8001 ULC underload fault.	2
	Warning/Fault	The drive generates a warning (<i>A8BF ULC underload</i> <i>warning</i>) if the signal stays continuously below the underload curve for half of the time defined by <i>37.42 ULC underload</i> <i>timer</i> . The drive trips on <i>8001 ULC underload fault</i> if the signal stays continuously below the underload curve for the time defined by <i>37.42 ULC underload timer</i> .	3
37.11	ULC speed table point 1	Defines the 1st speed point on the X-axis of the user load curve. The speed points are used in DTC motor control mode, and in scalar motor control mode when speed control is being used. The five points must be in order from lowest to highest. The points are defined as positive values, but the range is symmetrically effective also in the negative direction. The monitoring is not active outside these two areas.	150.0 rpm
	0.0 30000.0 rpm	Speed.	1 = 1 rpm
37.12	ULC speed table point 2	Defines the 2nd speed point on the X-axis of the user load curve.	750.0 rpm
	0.0 30000.0 rpm	Speed.	1 = 1 rpm
37.13	ULC speed table point 3	Defines the 3rd speed point on the X-axis of the user load curve.	1290.0 rpm
	0.0 30000.0 rpm	Speed.	1 = 1 rpm
37.14	ULC speed table point 4	Defines the 4th speed point on the X-axis of the user load curve.	1500.0 rpm
	0.0 30000.0 rpm	Speed.	1 = 1 rpm
37.15	ULC speed table point 5	Defines the 5th speed point on the X-axis of the user load curve.	1800.0 rpm
	0.0 30000.0 rpm	Speed.	1 = 1 rpm
37.16	ULC frequency table point 1	Defines the 1st frequency point on the X-axis of the user load curve. The frequency points are used in scalar motor control mode when frequency control is being used. The five points must be in order from lowest to highest. The points are defined as positive values, but the range is symmetrically effective also in the negative direction. The monitoring is not active outside these two areas.	5.0 Hz
	0.0 500.0 Hz	Frequency.	1 = 1 Hz

No.	Name/Value	Description	Def/FbEq16
37.17	ULC frequency table point 2	Defines the 2nd frequency point on the X-axis of the user load curve.	25.0 Hz
	0.0 500.0 Hz	Frequency.	1 = 1 Hz
37.18	ULC frequency table point 3	Defines the 3rd frequency point on the X-axis of the user load curve.	43.0 Hz
	0.0 500.0 Hz	Frequency.	1 = 1 Hz
37.19	ULC frequency table point 4	Defines the 4th frequency point on the X-axis of the user load curve.	50.0 Hz
	0.0 500.0 Hz	Frequency.	1 = 1 Hz
37.20	ULC frequency table point 5	Defines the 5th frequency point on the X-axis of the user load curve.	60.0 Hz
	0.0 500.0 Hz	Frequency.	1 = 1 Hz
37.21	ULC underload point 1	Defines the 1st point of the underload curve. Each point of the underload curve must have a lower value than the corresponding overload point.	10.0%
	0.0 1600.0%	Underload point.	1 = 1%
37.22	ULC underload point 2	Defines the 2nd point of the underload curve.	15.0%
	0.0 1600.0%	Underload point.	1 = 1%
37.23	ULC underload point 3	Defines the 3rd point of the underload curve.	25.0%
	0.0 1600.0%	Underload point.	1 = 1%
37.24	ULC underload point 4	Defines the 4th point of the underload curve.	30.0%
	0.0 1600.0%	Underload point.	1 = 1%
37.25	ULC underload point 5	Defines the 5th point of the underload curve.	30.0%
	0.0 1600.0%	Underload point.	1 = 1%
37.31	ULC overload point 1	Defines the 1st point of the overload curve. Each point of the overload curve must have a higher value than the corresponding underload point.	300.0%
	0.0 1600.0%	Overload point.	1 = 1%
37.32	ULC overload point 2	Defines the 2nd point of the overload curve.	300.0%
	0.0 1600.0%	Overload point.	1 = 1%
37.33	ULC overload point 3	Defines the 3rd point of the overload curve.	300.0%
	0.0 1600.0%	Overload point.	1 = 1%
37.34	ULC overload point 4	Defines the 4th point of the overload curve.	300.0%
	0.0 1600.0%	Overload point.	1 = 1%
37.35	ULC overload point 5	Defines the 5th point of the overload curve.	300.0%
	0.0 1600.0%	Overload point.	1 = 1%

No.	Name/Value	Description	Def/FbEq16
37.41	ULC overload timer	Defines the time for which the monitored signal must continuously stay above the overload curve before the drive takes the action selected by <i>37.03 ULC overload actions</i> .	20.0 s
	0.0 10000.0 s	Overload timer.	1 = 1 s
37.42	ULC underload timer	Defines the time for which the monitored signal must continuously stay below the underload curve before the drive takes the action selected by <i>37.04 ULC underload actions</i> .	20.0 s
	0.0 10000.0 s	Underload timer.	1 = 1 s
40 Pro	cess PID set 1	Parameter values for process PID control. The drive contains a single active PID controller for process use, however two separate complete set-ups can be programmed and stored. The first set is made up of parameters 40.0740.56*, the second set is defined by the parameters in group 41 Process PID set 2. The binary source that defines which set is used is selected by parameter 40.57 PID set1/set2 selection. *The remaining parameters in this group are common for both sets.	
40.01	Process PID output actual	Displays the output of the process PID controller. This parameter is read-only. The unit is selected by parameter <i>40.12 Set 1 unit selection</i> .	-
	-32768.00 32767.00	Process PID controller output.	1 = 1 unit
40.02	Process PID feedback actual	Displays the value of process feedback after source selection, mathematical function (parameter 40.10 Set 1 feedback function), and filtering. See the control chain diagram on page 644. This parameter is read-only. The unit is selected by parameter 40.12 Set 1 unit selection.	-
	-32768.00 32767.00	Process feedback.	1 = 1 unit
40.03	Process PID setpoint actual	Displays the value of process PID setpoint after source selection, mathematical function (<i>40.18 Set 1 setpoint function</i>), limitation and ramping. See the control chain diagram on page 645. This parameter is read-only. The unit is selected by parameter <i>40.12 Set 1 unit selection</i> .	-
	-32768.00 32767.00	Setpoint for process PID controller.	1 = 1 unit
40.04	Process PID deviation actual	Displays the process PID deviation. By default, this value equals setpoint - feedback, but deviation can be inverted by parameter 40.31 Set 1 deviation inversion. See the control chain diagram on page 645. This parameter is read-only. The unit is selected by parameter 40.12 Set 1 unit selection.	-
	-32768.00 32767.00	PID deviation.	1 = 1 unit
40.05	Process PID trim output act	Displays the trimmed reference output. See the control chain diagram on page 645. This parameter is read-only. The unit is selected by parameter 40.12 Set 1 unit selection.	-
	-32768.00 32767.00	Trimmed reference.	1 = 1 unit

No.	Name/V	alue	Descri	iption	Def/FbEq16
40.06	Process word	PID status		ys status information on process PID control. arameter is read-only.	-
	Bit	Name		Value	
	0 PID active			1 = Process PID control active.	
	1	Setpoint frozen		1 = Process PID setpoint frozen.	
	2	Output frozen		1 = Process PID controller output frozen.	
	3	PID sleep r	node	1 = Sleep mode active.	
	4	Sleep boos	t	1 = Sleep boost active.	
	5	Trim mode		1 = Trim function active.	
	6	Tracking m	ode	1 = Tracking function active.	
	7	Output limit	high	1 = PID output is being limited by par. 40.37.	
	8	Output limit	low	1 = PID output is being limited by par. 40.36.	
	9	Deadband	active	1 = Deadband active (see par. 40.39)	
	10	PID set		0 = Parameter set 1 in use. 1 = Parameter set 2 in use	•
	11	Reserved		-	
	12	Internal set active	point	1 = Internal setpoint active (see par. 40.1640.16)	
	1315 Reserved				
	0000h	FFFFh	Proces	ss PID control status word.	1 = 1
40.07	Set 1 PID operation mode		param Note:	es/deactivates process PID control. See also eter <i>40.60 Set 1 PID activation source</i> . Process PID control is only available in external ; see section <i>Local control vs. external control</i> (page	Off
			,	Process PID control inactive.	
	On		-	ss PID control active.	0
	On wher running	n drive	Proces	ss PID control is active when the drive is running.	2
40.08	Set 1 fee source	edback 1		s the first source of process feedback. See the control diagram on page 645.	AI1 scaled
	Not sele	cted	None.		0
	Al1 scal	ed	12.12	Al1 scaled value (see page 182).	1
	Al2 scal	ed	12.22	AI2 scaled value (see page 184).	2
	Freq in s	scaled	11.39 I	Freq in 1 scaled (see page 178).	3
	Motor cu	urrent	01.07 Motor current (see page 136).		5
	Power ir	nu out	01.14 Output power (see page 137).		6
	Motor to	rque	01.10 Motor torque (see page 136).		7
	Feedbac storage	ck data	40.91	Feedback data storage (see page 337).	10
	Other		Source	e selection (see <i>Terms and abbreviations</i> on page 131).	-
40.09	Set 1 fee source	edback 2		s the second source of process feedback. e selections, see parameter <i>40.08 Set 1 feedback 1</i>	Not selected

No. Name/Value Description		Description	Def/FbEq16
40.10	Set 1 feedback function	Defines how process feedback is calculated from the two feedback sources selected by parameters 40.08 Set 1 feedback 1 source and 40.09 Set 1 feedback 2 source.	In1
	ln1	Source 1.	0
	In1+In2	Sum of sources 1 and 2.	1
	In1-In2	Source 2 subtracted from source 1.	2
	In1*In2	Source 1 multiplied by source 2.	3
	In1/In2	Source 1 divided by source 2.	4
	MIN(In1,In2)	Smaller of the two sources.	5
	MAX(In1,In2)	Greater of the two sources.	6
	AVE(In1,In2)	Average of the two sources.	7
	sqrt(In1)	Square root of source 1.	8
	sqrt(In1-In2)	Square root of (source 1 - source 2).	9
	sqrt(In1+In2)	Square root of (source 1 + source 2).	10
	sqrt(In1)+sqrt(In2)	Square root of source 1 + square root of source 2.	11
40.11	Set 1 feedback filter time	Defines the filter time constant for process feedback.	0.000 s
	0.000 30.000 s	Feedback filter time.	1 = 1 s
40.12	Set 1 unit selection	Defines the unit for parameters 40.0140.05, 40.2140.24 and 40.47.	%
	rpm	rpm.	7
	%	%.	4
	Hz	Hz.	3
	PID user unit 1	User-definable unit 1. The name of the unit can be edited on the control panel by choosing Menu – Settings – Edit texts.	250
40.14	Set 1 setpoint scaling	Defines, together with parameter 40.15 Set 1 output scaling, a general scaling factor for the process PID control chain. The scaling can be utilized when, for example, the process setpoint is input in Hz, and the output of the PID controller is used as an rpm value in speed control. In this case, this parameter might be set to 50, and parameter 40.15 to the nominal motor speed at 50 Hz. In effect, the output of the PID controller = [40.15] when deviation (setpoint - feedback) = [40.14] and [40.32] = 1. Note: The scaling is based on the ratio between 40.14 and 40.15. For example, the values 50 and 1500 would produce the same scaling as 1 and 30.	100.00
	-32768.00 32767.00	Process setpoint base.	1 = 1
40.15	Set 1 output scaling	See parameter 40.14 Set 1 setpoint scaling.	1500.00; 1800.00 (95.20 b0)
	-32768.00 32767.00	Process PID controller output base.	1 = 1
40.16	Set 1 setpoint 1 source	Selects the first source of process PID setpoint. This setpoint is available in parameter <i>40.25 Set 1 setpoint selection</i> as setpoint 1. See the control chain diagram on page <i>644</i> .	Internal setpoint
	Not selected	None.	0

No.	Name/Value	Description			Def/FbEq16		
	Control panel	03.01 Panel refere control panel as al		0). See section <i>Using the source</i> (page 55).	1		
	Internal setpoint	Internal setpoint. S sel1.	See parameter 40.	19 Set 1 internal setpoint	2		
	Al1 scaled	12.12 Al1 scaled v	value (see page 18	32).	3		
	Al2 scaled	12.22 Al2 scaled v	value (see page 18	34).	4		
	Motor potentiometer	22.80 Motor poten potentiometer).	<i>tiometer ref act</i> (o	utput of the motor	8		
	Freq in scaled	11.39 Freq in 1 sc	aled (see page 17	8).	10		
	Setpoint data storage	40.92 Setpoint dat	<i>a storage</i> (see pa	ge 337).	24		
	Other	Source selection (see Terms and ab	breviations on page 131).	-		
40.17	Set 1 setpoint 2 source	is available in para setpoint 2.	ameter 40.25 Set	s setpoint. This setpoint <i>setpoint selection</i> as 0.16 Set 1 setpoint 1	Not selected		
40.18	Set 1 setpoint function	sources selected b	Selects a mathematical function between the setpoint sources selected by parameters 40.16 Set 1 setpoint 1 source and 40.17 Set 1 setpoint 2 source.				
	In1 or In2	No mathematical f parameter 40.25 S	0				
	In1+In2	Sum of sources 1	1				
	In1-In2	Source 2 subtracte	2				
	In1*In2	Source 1 multiplied by source 2.			3		
	In1/In2	Source 1 divided b	by source 2.		4		
	MIN(In1,In2)	Smaller of the two	5				
	MAX(In1,In2)	Greater of the two sources.			6		
	AVE(In1,In2)	Average of the two	o sources.		7		
	sqrt(In1)	Square root of sou	irce 1.		8		
	sqrt(In1-In2)	Square root of (so	urce 1 - source 2).		9		
	sqrt(In1+In2)	Square root of (so	Square root of (source 1 + source 2).				
	sqrt(In1)+sqrt(In2)	Square root of sou	irce 1 + square roo	ot of source 2.	11		
40.19	Set 1 internal setpoint sel1			<i>ternal setpoint sel2</i> , the efined by parameters	Not selected		
		Source defined by par. 40.19	Source defined by par. 40.20	Setpoint preset active			
		0	0	1 (par. 40.21)			
		1	0	2 (par. 40.22)			
		0	1	3 (par. 40.23)			
		1	1	4 (par. 40.24)			
	Not selected	0.			0		
	Selected	1.			1		
	DI1	Digital input DI1 (1	0.02 DI delayed s	<i>tatus</i> , bit 0).	2		

No.	Name/Value	Description	Def/FbEq16
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
40.20	Set 1 internal setpoint sel2	Selects, together with 40.19 Set 1 internal setpoint sel1, the internal setpoint out of the presets defined by parameters 40.2140.24. See table at 40.19 Set 1 internal setpoint sel1.	Not selected
	Not selected	0.	0
	Selected	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
40.21	Set 1 internal setpoint 1	Defines process setpoint preset 1. See parameter 40.19 Set 1 internal setpoint sel1. The unit is selected by parameter 40.12 Set 1 unit selection.	0.00
	-32768.00 32767.00	Process setpoint preset 1.	1 = 1 unit
40.22	Set 1 internal setpoint 2	Defines process setpoint preset 2. See parameter 40.19 Set 1 internal setpoint sel1. The unit is selected by parameter 40.12 Set 1 unit selection.	0.00
	-32768.00 32767.00	Process setpoint preset 2.	1 = 1 unit
40.23	Set 1 internal setpoint 3	Defines process setpoint preset 3. See parameter 40.19 Set 1 internal setpoint sel1. The unit is selected by parameter 40.12 Set 1 unit selection.	0.00
	-32768.00 32767.00	Process setpoint preset 3.	1 = 1 unit
40.24	Set 1 internal setpoint 4	Defines process setpoint preset 4. See parameter 40.19 Set 1 internal setpoint sel1. The unit is selected by parameter 40.12 Set 1 unit selection.	0.00
	-32768.00 32767.00	Process setpoint preset 4.	1 = 1 unit

No.	Name/Value	Description	Def/FbEq16
40.25	Set 1 setpoint selection	Configures the selection between setpoint sources 1 (40.16) and 2 (40.17). This parameter is only effective when parameter 40.18 Set 1 setpoint function is set to In1 or In2. 0 = Setpoint source 1 1 = Setpoint source 2	Setpoint source 1
	Setpoint source 1	0.	0
	Setpoint source 2	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
40.26	Set 1 setpoint min	Defines a minimum limit for the process PID controller setpoint.	0.00
	-32768.00 32767.00	Minimum limit for process PID controller setpoint.	1 = 1
40.27	Set 1 setpoint max	Defines a maximum limit for the process PID controller setpoint.	32767.00
	-32768.00 32767.00	Maximum limit for process PID controller setpoint.	1 = 1
40.28	Set 1 setpoint increase time	Defines the minimum time it takes for the setpoint to increase from 0% to 100%.	0.0 s
	0.0 1800.0 s	Setpoint increase time.	1 = 1
40.29	Set 1 setpoint decrease time	Defines the minimum time it takes for the setpoint to decrease from 100% to 0%.	0.0 s
	0.0 1800.0 s	Setpoint decrease time.	1 = 1
40.30	Set 1 setpoint freeze enable	Freezes, or defines a source that can be used to freeze, the setpoint of the process PID controller. This feature is useful when the reference is based on a process feedback connected to an analog input, and the sensor must be serviced without stopping the process. 1 = Process PID controller setpoint frozen See also parameter 40.38 Set 1 output freeze enable.	Not selected
	Not selected	Process PID controller setpoint not frozen.	0
	Selected	Process PID controller setpoint frozen.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7

No.	Name/Value	Description	Def/FbEq16
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
40.31	Set 1 deviation inversion	Inverts the input of the process PID controller. 0 = Deviation not inverted (Deviation = Setpoint - Feedback) 1 = Deviation inverted (Deviation = Feedback - Setpoint) See also section <i>Sleep function for process PID control</i> (page 101).	Not inverted (Ref - Fbk)
	Not inverted (Ref - Fbk)	0.	0
	Inverted (Fbk - Ref)	1.	1
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
40.32	Set 1 gain	Defines the gain for the process PID controller. See parameter 40.33 Set 1 integration time.	1.00
	0.10 100.00	Gain for PID controller.	100 = 1
40.33	Set 1 integration time	Defines the integration time for the process PID controller. This time needs to be set to the same order of magnitude as the reaction time of the process being controlled, otherwise instability will result. Error/Controller output $G \times I \qquad \qquad$	60.0 s
	0.0 32767.0 s	Integration time.	1 = 1 s
40.34	Set 1 derivation time	Defines the derivation time of the process PID controller. The derivative component at the controller output is calculated on basis of two consecutive error values (E_{K-1} and E_K) according to the following formula: PID DERIV TIME × ($E_K - E_{K-1}$)/ T_S , in which $T_S = 2$ ms sample time E = Error = Process reference - process feedback.	0.000 s
	0.000 10.000 s	Derivation time.	1000 = 1 s

No.	Name/Value	Description	Def/FbEq16
40.35	Set 1 derivation filter time		
	0.0 10.0 s	Filter time constant.	10 = 1 s
40.36	Set 1 output min	Defines the minimum limit for the process PID controller output. Using the minimum and maximum limits, it is possible to restrict the operation range.	0.0
	-32768.0 32767.0	Minimum limit for process PID controller output.	1 = 1
40.37	Set 1 output max	Defines the maximum limit for the process PID controller output. See parameter <i>40.36 Set 1 output min</i> .	1500.0; 1800.0 (95.20 b0)
	-32768.0 32767.0	Maximum limit for process PID controller output.	1 = 1
40.38	Set 1 output freeze enable	Freezes (or defines a source that can be used to freeze) the output of the process PID controller, keeping the output at the value it was before freeze was enabled. This feature can be used when, for example, a sensor providing process feedback must to be serviced without stopping the process. 1 = Process PID controller output frozen See also parameter <i>40.30 Set 1 setpoint freeze enable</i> .	Not selected
	Not selected	Process PID controller output not frozen.	0
	Selected	Process PID controller output frozen.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (<i>10.02 DI delayed status</i> , bit 5).	7
	DIO1	Digital input/output DIO1 (<i>11.02 DIO delayed status</i> , bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-

No.	Name/Value	Description	Def/FbEq16
40.39	Set 1 deadband range	Defines a deadband around the setpoint. Whenever process feedback enters the deadband, a delay timer starts. If the feedback remains within the deadband longer than the delay (40.40 Set 1 deadband delay), the PID controller output is frozen. Normal operation resumes after the feedback value leaves the deadband.	0.0
	40.39 Set 1		
	deadband range		
	Setpoint		
	Feedba		
	PID controll outp	but	ntroller frozen
		40.40 Set 1 deadband delay	
			Time
		-	ı ime
	0.0 32767.0	Deadband range.	1 = 1
40.40	Set 1 deadband delay	Delay for the deadband. See parameter <i>40.39 Set 1 deadband range</i> .	0.0 s
	0.0 3600.0 s	Delay for deadband area.	1 = 1 s
40.41	Set 1 sleep mode	Selects the mode of the sleep function. See also section <i>Sleep function for process PID control</i> (page <i>101</i>).	Not selected
	Not selected	Sleep function disabled.	0
	Internal	The output of the PID controller is compared to the value of 40.43 Set 1 sleep level. If the PID controller output remains below the sleep level longer than the sleep delay (40.44 Set 1 sleep delay), the drive enters sleep mode. Parameters 40.4440.48 are in force.	1
	External	The sleep function is activated by the source selected by parameter <i>40.42 Set 1 sleep enable</i> . Parameters <i>40.4440.46</i> and <i>40.48</i> are in force.	2
40.42	Set 1 sleep enable	Defines a source that is used to activate the PID sleep function when parameter 40.41 Set 1 sleep mode is set to <i>External</i> . 0 = Sleep function disabled 1 = Sleep function activated	Not selected
	Not selected	0.	0
	Selected	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4

No.	Name/Value	Description	Def/FbEq16
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
40.43	Set 1 sleep level	Defines the start limit for the sleep function when parameter 40.41 Set 1 sleep mode is set to Internal.	0.0
	0.0 32767.0	Sleep start level.	1 = 1
40.44	Set 1 sleep delay	Defines a delay before the sleep function actually becomes enabled, to prevent nuisance sleeping. The delay timer starts when the sleep condition selected by parameter 40.41 Set 1 sleep mode becomes true, and resets if the condition becomes false.	60.0 s
	0.0 3600.0 s	Sleep start delay.	1 = 1 s
40.45	Set 1 sleep boost time	Defines a boost time for the sleep boost step. See parameter 40.46 Set 1 sleep boost step.	0.0 s
	0.0 3600.0 s	Sleep boost time.	1 = 1 s
40.46	Set 1 sleep boost step	When the drive is entering sleep mode, the process setpoint is increased by this value for the time defined by parameter 40.45 Set 1 sleep boost time. If active, sleep boost is aborted when the drive wakes up.	0.0
	0.0 32767.0	Sleep boost step.	1 = 1
40.47	Set 1 wake-up deviation	When 40.41 Set 1 sleep mode is set to Internal, this parameter defines the wake-up level as deviation between process setpoint and feedback. The unit is selected by parameter 40.12 Set 1 unit selection. When the deviation exceeds the value of this parameter, and remains there for the duration of the wake-up delay (40.48 Set 1 wake-up delay), the drive wakes up. See also parameter 40.31 Set 1 deviation inversion.	0.00 rpm, % or Hz
	-32768.00 32767.00 rpm, % or Hz	Wake-up level (as deviation between process setpoint and feedback).	1 = 1 unit
40.48	Set 1 wake-up delay	Defines a wake-up delay for the sleep function to prevent nuisance wake-ups. See parameter 40.47 Set 1 wake-up deviation. The delay timer starts when the deviation exceeds the wake- up level (40.47 Set 1 wake-up deviation), and resets if the deviation falls below the wake-up level.	0.50 s
	0.00 60.00 s	Wake-up delay.	1 = 1 s
40.49	Set 1 tracking mode	Activates (or selects a source that activates) tracking mode. In tracking mode, the value selected by parameter 40.50 Set 1 tracking ref selection is substituted for the PID controller output. See also section Tracking (page 102). 1 = Tracking mode enabled	Not selected
	Not selected	0.	0
	Selected	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3

No.	Name/Value	Description	Def/FbEq16
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
40.50	Set 1 tracking ref selection	Selects the value source for tracking mode. See parameter 40.49 Set 1 tracking mode.	Not selected
	Not selected	None.	0
	Al1 scaled	12.12 Al1 scaled value (see page 182).	1
	Al2 scaled	12.22 Al2 scaled value (see page 184).	2
	FB A ref1	03.05 FB A reference 1 (see page 141).	3
	FB A ref2	03.06 FB A reference 2 (see page 141).	4
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
40.51	Set 1 trim mode	Activates the trim function and selects between direct and proportional trimming (or a combination of both). With trimming, it is possible to apply a corrective factor to the drive reference (setpoint). The output after trimming is available as parameter <i>40.05 Process PID trim output act</i> . See the control chain diagram on page <i>645</i> .	Off
	Off	The trim function is inactive.	0
	Direct	The trim function is active. The trimming factor is relative to the maximum speed, torque or frequency; the selection between these is made by parameter <i>40.52 Set 1 trim selection</i> .	1
	Proportional	The trim function is active. The trimming factor is relative to the reference selected by parameter <i>40.53 Set 1 trimmed ref pointer</i> .	2
	Combined	The trim function is active. The trimming factor is a combination of both <i>Direct</i> and <i>Proportional</i> modes; the proportions of each are defined by parameter 40.54 Set 1 trim <i>mix</i> .	3
40.52	Set 1 trim selection	Selects whether trimming is used for correcting the speed, torque or frequency reference.	Torque
	Torque	Torque reference trimming.	1
	Speed	Speed reference trimming.	2
	Frequency	Frequency reference trimming.	3
40.53	Set 1 trimmed ref pointer	Selects the signal source for the trim reference.	Not selected
	Not selected	None.	0
	Al1 scaled	12.12 Al1 scaled value (see page 182).	1
	AI2 scaled	12.22 AI2 scaled value (see page 184).	2
	FB A ref1	03.05 FB A reference 1 (see page 141).	3
	FB A ref2	03.06 FB A reference 2 (see page 141).	4
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-

No.	Name/Value	Description	Def/FbEq16
40.54	40.54Set 1 trim mixWhen parameter 40.51 Set 1 trim mode is set to Combination defines the effect of direct and proportional trim sources final trimming factor.0.000 = 100% proportional 0.500 = 50% proportional, 50% direct 1.000 = 100% direct		0.000
	0.000 1.000	Trim mix.	1 = 1
40.55	Set 1 trim adjust	Defines a multiplier for the trimming factor. This value is multiplied by the result of parameter 40.51 Set 1 trim mode. Consequently, the result of the multiplication is used to multiply the result of parameter 40.56 Set 1 trim source.	1.000
	-100.000 100.000	Multiplier for trimming factor.	1 = 1
40.56	Set 1 trim source	Selects the reference to be trimmed.	PID ref
	PID ref	PID setpoint.	1
	PID output	PID controller output.	2
40.57	PID set1/set2 selection	Selects the source that determines whether process PID parameter set 1 (parameters 40.0740.56) or set 2 (group 41 Process PID set 2) is used. 0 = Process PID parameter set 1 in use	Not selected
		1 = Process PID parameter set 2 in use	
	Not selected	0.	0
	Selected	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
40.60	Set 1 PID activation source	Selects a source that enables/disables process PID control. See also parameter 40.07 Set 1 PID operation mode. 0 = Process PID control disabled. 1 = Process PID control enabled.	On
	Off	0.	0
	On	1.	1
	Follow Ext1/Ext2 selection	Process PID control is disabled when external control location EXT1 is active, and enabled when external control location EXT2 is active. See also parameter 19.11 Ext1/Ext2 selection.	2
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	3
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	4
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	5
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	6
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	7

No.	Name/Value	Description	Def/FbEq16
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	8
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	11
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	12
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
40.91	Feedback data storage	Storage parameter for receiving a process feedback value eg. through the embedded fieldbus interface. The value can be sent to the drive as Modbus I/O data. Set the target selection parameter of that particular data (58.10158.124) to Feedback data storage. In 40.08 Set 1 feedback 1 source (or 40.09 Set 1 feedback 2 source), select Feedback data storage.	-
	-327.68 327.67	Storage parameter for process feedback.	100 = 1
40.92	Setpoint data storage	Storage parameter for receiving a process setpoint value eg. through the embedded fieldbus interface. The value can be sent to the drive as Modbus I/O data. Set the target selection parameter of that particular data (58.10158.124) to Setpoint data storage. In 40.16 Set 1 setpoint 1 source (or 40.17 Set 1 setpoint 2 source), select Setpoint data storage.	-
	-327.68 327.67	Storage parameter for process setpoint.	100 = 1
41 Pro	cess PID set 2	A second set of parameter values for process PID control. The selection between this set and first set (parameter group 40 Process PID set 1) is made by parameter 40.57 PID set1/set2 selection. See also parameters 40.0140.06, 40.91, 40.92, and the control chain diagrams on pages 644 to 645.	
41.07	Set 2 PID operation mode	See parameter 40.07 Set 1 PID operation mode.	Off
41.08	Set 2 feedback 1 source	See parameter 40.08 Set 1 feedback 1 source.	Al1 scaled
41.09	Set 2 feedback 2 source	See parameter 40.09 Set 1 feedback 2 source.	Not selected
41.10	Set 2 feedback function	See parameter 40.10 Set 1 feedback function.	In1
41.11	Set 2 feedback filter time	See parameter 40.11 Set 1 feedback filter time.	0.000 s
41.12	Set 2 unit selection	Defines the unit for parameters 41.2141.24 and 41.47.	%
	rpm	rpm.	7
	%	%.	4
	Hz	Hz.	3
	PID user unit 2	User-definable unit 2. The name of the unit can be edited on the control panel by choosing Menu – Settings – Edit texts.	249
41.14	Set 2 setpoint scaling	See parameter 40.14 Set 1 setpoint scaling.	100.00
41.15	Set 2 output scaling	See parameter 40.15 Set 1 output scaling.	1500.00; 1800.00 (95.20, b0)
41.16	Set 2 setpoint 1 source	See parameter 40.16 Set 1 setpoint 1 source.	Internal setpoint

No.	Name/Value	Description	Def/FbEq16
41.17	Set 2 setpoint 2 source	See parameter 40.17 Set 1 setpoint 2 source.	Not selected
41.18	Set 2 setpoint function	See parameter 40.18 Set 1 setpoint function.	In1 or In2
41.19	Set 2 internal setpoint sel1	See parameter 40.19 Set 1 internal setpoint sel1.	Not selected
41.20	Set 2 internal setpoint sel2	See parameter 40.20 Set 1 internal setpoint sel2.	Not selected
41.21	Set 2 internal setpoint 1	See parameter 40.21 Set 1 internal setpoint 1.	0.00
41.22	Set 2 internal setpoint 2	See parameter 40.22 Set 1 internal setpoint 2.	0.00
41.23	Set 2 internal setpoint 3	See parameter 40.23 Set 1 internal setpoint 3.	0.00
41.24	Set 2 internal setpoint 4	See parameter 40.24 Set 1 internal setpoint 4.	0.00
41.25	Set 2 setpoint selection	See parameter 40.25 Set 1 setpoint selection.	Setpoint source 1
41.26	Set 2 setpoint min	See parameter 40.26 Set 1 setpoint min.	0.00
41.27	Set 2 setpoint max	See parameter 40.27 Set 1 setpoint max.	32767.00
41.28	Set 2 setpoint increase time	See parameter 40.28 Set 1 setpoint increase time.	0.0 s
41.29	Set 2 setpoint decrease time	See parameter 40.29 Set 1 setpoint decrease time.	0.0 s
41.30	Set 2 setpoint freeze enable	See parameter 40.30 Set 1 setpoint freeze enable.	Not selected
41.31	Set 2 deviation inversion	See parameter 40.31 Set 1 deviation inversion.	Not inverted (Ref - Fbk)
41.32	Set 2 gain	See parameter 40.32 Set 1 gain.	1.00
41.33	Set 2 integration time	See parameter 40.33 Set 1 integration time.	60.0 s
41.34	Set 2 derivation time	See parameter 40.34 Set 1 derivation time.	0.000 s
41.35	Set 2 derivation filter time	See parameter 40.35 Set 1 derivation filter time.	0.0 s
41.36	Set 2 output min	See parameter 40.36 Set 1 output min.	0.0
41.37	Set 2 output max	See parameter 40.37 Set 1 output max.	1500.0; 1800.0 (95.20, b0)
41.38	Set 2 output freeze enable	See parameter 40.38 Set 1 output freeze enable.	Not selected
41.39	Set 2 deadband range	See parameter 40.39 Set 1 deadband range.	0.0
41.40	Set 2 deadband delay	See parameter 40.40 Set 1 deadband delay.	0.0 s
41.41	Set 2 sleep mode	See parameter 40.41 Set 1 sleep mode.	Not selected
41.42	Set 2 sleep enable	See parameter 40.42 Set 1 sleep enable.	Not selected
41.43	Set 2 sleep level	See parameter 40.43 Set 1 sleep level.	0.0

No.	Name/Value	Description	Def/FbEq16
41.44	Set 2 sleep delay	See parameter 40.44 Set 1 sleep delay.	60.0 s
41.45	Set 2 sleep boost time	See parameter 40.45 Set 1 sleep boost time.	0.0 s
41.46	Set 2 sleep boost step	See parameter 40.46 Set 1 sleep boost step.	0.0
41.47	Set 2 wake-up deviation	See parameter 40.47 Set 1 wake-up deviation.	0.00 rpm, % or Hz
41.48	Set 2 wake-up delay	See parameter 40.48 Set 1 wake-up delay.	0.50 s
41.49	Set 2 tracking mode	See parameter 40.49 Set 1 tracking mode.	Not selected
41.50	Set 2 tracking ref selection	See parameter 40.50 Set 1 tracking ref selection.	Not selected
41.51	Set 2 trim mode	See parameter 40.51 Set 1 trim mode.	Off
41.52	Set 2 trim selection	See parameter 40.52 Set 1 trim selection.	Torque
41.53	Set 2 trimmed ref pointer	See parameter 40.53 Set 1 trimmed ref pointer.	Not selected
41.54	Set 2 trim mix	See parameter 40.54 Set 1 trim mix.	0.000
41.55	Set 2 trim adjust	See parameter 40.55 Set 1 trim adjust.	1.000
41.56	Set 2 trim source	See parameter 40.56 Set 1 trim source.	PID ref
41.56	Set 2 PID activation source	See parameter 40.60 Set 1 PID activation source.	On
43 Bra	ke chopper	Settings for the internal brake chopper. See also section <i>Brake chopper</i> (page <i>111</i>).	
43.01	Braking resistor temperature	Displays the estimated temperature of the brake resistor, or how close the brake resistor is to being too hot. The value is given in percent where 100% is the eventual temperature the resistor would reach when loaded long enough with its rated maximum load capacity (<i>43.09 Brake</i> <i>resistor Pmax cont</i>). The temperature calculation is based on the values of parameters <i>43.08</i> , <i>43.09</i> and <i>43.10</i> , and on the assumption that the resistor is installed as instructed by the manufacturer (ie. it cools down as expected). This parameter is read-only.	-
	0.0 120.0%	Estimated brake resistor temperature.	1 = 1%
43.06	Brake chopper function	 Enables brake chopper control and selects the brake resistor overload protection method (calculation or measurement). Note: Before enabling brake chopper control, ensure that a brake resistor is connected, overvoltage control is switched off (parameter 30.30 Overvoltage control), and the supply voltage range (parameter 95.01 Supply voltage) has been selected correctly. 	Disabled
	Disabled	Brake chopper control disabled.	0
	Enabled with thermal model	Brake chopper control enabled with brake resistor protection based on a thermal model. If you select this, you must also specify the values needed by the model, ie. parameters 43.0843.12. See the resistor data sheet.	1

No.	Name/Value	Description	Def/FbEq16
	Enabled without thermal model	Brake chopper control enabled without resistor overload protection. This setting can be used, for example, if the resistor is equipped with a thermal circuit breaker that is wired to stop the drive if the resistor overheats. Note : Before using this setting, ensure that overvoltage control is switched off (parameter <i>30.30 Overvoltage control</i>).	2
	Overvoltage peak protection	 Brake chopper control enabled in an overvoltage condition. This setting is intended for situations where the braking chopper is not needed for runtime operation, that is to dissipate the inertial energy of the motor, the motor is able to store a considerable amount of magnetic energy in its windings, and the motor might, deliberately or inadvertently, be stopped by coasting. In such a situation, the motor would potentially discharge enough magnetic energy towards the drive to cause damage. To protect the drive, the brake chopper can be used with a small resistor dimensioned merely to handle the magnetic energy (not the inertial energy) of the motor. With this setting, the brake chopper is activated only whenever the DC voltage exceeds the overvoltage limit. During normal use, the brake chopper is not operating. 	3
43.07	Brake chopper run enable	Selects the source for quick brake chopper on/off control. 0 = Brake chopper IGBT pulses are cut off 1 = Normal brake chopper IGBT modulation allowed. This parameter can be used to enable chopper operation only when the supply is missing from a drive with a regenerative supply unit.	On
	Off	0.	0
	On	1.	1
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
43.08	Brake resistor thermal tc	Defines the thermal time constant for the brake resistor thermal model.	0 s
	0 10000 s	Brake resistor thermal time constant, ie. the rated time to achieve 63% temperature.	1 = 1 s
43.09	Brake resistor Pmax cont	Defines the maximum continuous load of the brake resistor which will eventually raise the resistor temperature to the maximum allowed value (= continuous heat dissipation capacity of the resistor in kW) but not above it. The value is used in the resistor overload protection based on the thermal model. See parameter <i>43.06 Brake chopper function</i> , and the brake resistor data sheet.	0.00 kW
	0.00 10000.00 kW	Maximum continuous load of the brake resistor.	1 = 1 kW
43.10	Brake resistance	Defines the resistance value of the brake resistor. The value is used for the brake chopper protection based on the thermal model. See parameter <i>43.06 Brake chopper function</i> .	0.00 ohm
	0.001000.00 ohm	Brake resistor resistance value.	1 = 1 ohm

No.	Name/V	alue	Descri	ption	Def/FbEq16
43.11	Brake resistor fault limit		on the function 7183 B The va reache	the fault limit for the brake resistor protection based thermal model. See parameter 43.06 Brake chopper n. When the limit is exceeded, the drive trips on fault <i>R</i> excess temperature. lue is given in percent of the temperature the resistor s when loaded with the power defined by parameter Brake resistor Pmax cont.	105%
	0 150	%	Brake r	esistor temperature fault limit.	1 = 1%
43.12	Brake resistor warning limit		based o choppe genera The va reache	the warning limit for the brake resistor protection on the thermal model. See parameter <i>43.06 Brake</i> <i>ar function</i> . When the limit is exceeded, the drive tes a <i>A793 BR excess temperature</i> warning. In percent of the temperature the resistor is when loaded with the power defined by parameter <i>Brake resistor Pmax cont</i> .	95%
	0 150	%	Brake r	esistor temperature warning limit.	1 = 1%
44 Mee contro	chanical I	brake	-	uration of mechanical brake control. so section <i>Mechanical brake control</i> (page 104).	
44.01	Brake co	ontrol status		rs the mechanical brake control status word. Irameter is read-only.	-
	Bit	Name		Information	
	0	Open comn		Close/open command to brake actuator (0 = close, 1 = Connect this bit to desired output.	open).
	1 Opening to request			1 = Opening torque requested from drive logic	
	2	Hold stoppe request		1 = Hold requested from drive logic	
	3	Ramp to sto	opped	1 = Ramping down to zero speed requested from drive	logic
	4	Enabled		1 = Brake control is enabled	
	5	Closed		1 = Brake control logic in BRAKE CLOSED state	
	6	Opening		1 = Brake control logic in BRAKE OPENING state	
	/	Open		1 = Brake control logic in BRAKE OPEN state	
	8 915	Closing		1 = Brake control logic in BRAKE CLOSING state	
	915	Reserved			
	0000h	FFFFh	Mecha	nical brake control status word.	1 = 1
44.02	Brake torque memory		brake of This vatorque.	rs the torque (in percent) at the instant of the previous close command. Ilue can be used as a reference for the brake open See parameters 44.09 Brake open torque source and Brake open torque.	-
	-1600.0 %	1600.0	Torque	at brake closure.	See par. 46.03
44.03	Brake open torque reference		parame open to	rs the currently active brake open torque. See eters 44.09 Brake open torque source and 44.10 Brake orque. urameter is read-only.	-
	-1600.0	1600.0%	Curren	tly active brake open torque.	See par. 46.03

No.	Name/Value	Description	Def/FbEq16
44.06	Brake control enable	Activates/deactivates (or selects a source that activates/deactivates) the mechanical brake control logic. 0 = Brake control inactive 1 = Brake control active	Selected
	Not selected	0.	0
	Selected	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
44.07	Brake acknowledge selection	Activates/deactivates (and selects the source for) brake open/close status (acknowledgement) supervision. When a brake control error (unexpected state of the acknowledgement signal) is detected, the drive reacts as defined by parameter 44.17 Brake fault function. 0 = Brake closed 1 = Brake open	No acknowledge
	Off	0.	0
	On	1.	1
	No acknowledge	Brake open/closed supervision disabled.	2
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	3
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	4
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	5
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	6
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	7
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	8
	DIO1	Digital input/output DIO1 (<i>11.02 DIO delayed status</i> , bit 0).	11
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	12
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
44.08	Brake open delay	Defines the brake open delay, ie. the delay between the internal open brake command and the release of motor speed control. The delay timer starts when the drive has magnetized the motor and increased the motor torque to the level required for brake release (parameter <i>44.03 Brake open torque reference</i>). Simultaneously with the timer start, the brake control logic energizes the brake control output and the brake starts to open. Set this parameter to the value of mechanical opening delay specified by the brake manufacturer.	0.00 s
			100 = 1 s

No.	Name/Value	Description	Def/FbEq16
44.09	Brake open torque source	 Defines a source that is used as a brake opening torque reference if its absolute value is greater than the setting of parameter 44.10 Brake open torque, and its sign is the same as the setting of 44.10 Brake open torque. See parameter 44.10 Brake open torque. 	Brake open torque
	Zero	Zero.	0
	AI1 scaled	12.12 Al1 scaled value (see page 182).	1
	AI2 scaled	12.22 Al2 scaled value (see page 184).	2
	FBA ref1	03.05 FB A reference 1 (see page 141).	3
	FBA ref2	03.06 FB A reference 2 (see page 141).	4
	Brake torque memory	Parameter 44.02 Brake torque memory.	7
	Brake open torque	Parameter 44.10 Brake open torque.	8
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
44.10	Brake open torque	Defines the sign (ie. direction of rotation) and minimum absolute value of the brake open torque (motor torque requested at brake release in percent of motor nominal torque). The value of the source selected by parameter 44.09 Brake open torque source is used as the brake open torque only if it has the same sign as this parameter and has a greater absolute value. Note: This parameter is not effective in scalar motor control mode.	0.0%
	-1600.0 1600.0%	Minimum torque at brake release.	See par. 46.03
44.11	Keep brake closed	Selects a source that prevents the brake from opening. 0 = Normal brake operation 1 = Keep brake closed Note: This parameter cannot be changed while the drive is running.	Not selected
	Not selected	0.	0
	Selected	1.	1
	DI1	Digital input DI1 (<i>10.02 DI delayed status</i> , bit 0).	2
	DI2	Digital input DI2 (<i>10.02 DI delayed status</i> , bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (<i>11.02 DIO delayed status</i> , bit 0).	10
	DIO2	Digital input/output DIO2 (<i>11.02 DIO delayed status</i> , bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-

No.	Name/Value	Description	Def/FbEq16
44.12	Brake close request	Selects a source of an external brake close request signal. When on, the signal overrides the internal logic and closes the brake.	Not selected
		0 = Normal operation/No external close signal connected 1 = Close brake Note:	
		• In an open-loop (encoderless) application, if the brake is kept closed by a brake close request against a modulating drive for longer than 5 seconds, the brake is forced to close and the drive trips on a fault, <i>71A5 Mechanical brake opening not allowed</i> .	
		 This parameter cannot be changed while the drive is running. 	
	Not selected	0.	0
	Selected	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
44.13	Brake close delay	Defines a delay between a close command (that is, when the brake control output is de-energized) and when the drive stops modulating. This is to keep the motor live and under control until the brake actually closes. Set this parameter equal to the value specified by the brake manufacturer as the mechanical make-up time of the brake.	0.00 s
	0.00 60.00 s	Brake close delay.	100 = 1 s
44.14	Brake close level	Defines the brake close speed as an absolute value. After motor speed remains below this level for the duration of the brake close level delay (44.15 Brake close level delay), a close command is given. Note : Check the compatibility of this setting with 21.03 Stop mode (and the applicable deceleration time).	10.00 rpm
	0.00 1000.00 rpm	Brake close speed.	See par. 46.01
44.15	Brake close level delay	Defines a brake close level delay. See parameter 44.14 Brake close level.	0.00 s
	0.00 10.00 s	Brake close level delay.	100 = 1 s
44.16	Brake reopen delay	Defines a minimum time between brake closure and a subsequent open command.	0.00 s
	0.00 10.00 s	Brake reopen delay.	100 = 1 s

No.	Name/Value	Description	Def/FbEq16
44.17	Brake fault function	Determines how the drive reacts upon a mechanical brake control error. Note: If parameter <i>44.07 Brake acknowledge selection</i> is set to <i>No acknowledge</i> , acknowledgement status supervision is disabled altogether and will generate no warnings or faults. However, the brake open conditions are always supervised.	Fault
	Fault	The drive trips on a 71A2 Mechanical brake closing failed / 71A3 Mechanical brake opening failed fault if the status of the acknowledgement does not match the status presumed by the brake control logic. The drive trips on a 71A5 Mechanical brake opening not allowed fault if the brake open conditions cannot be fulfilled (for example, the required motor starting torque is not achieved).	0
	Warning	The drive generates a A7A1 Mechanical brake closing failed / A7A2 Mechanical brake opening failed warning if the status of the acknowledgement does not match the status presumed by the brake control logic. The drive generates a A7A5 Mechanical brake opening not allowed warning if the brake open conditions cannot be fulfilled (for example, the required motor starting torque is not achieved).	1
	Open fault	Upon closing the brake, the drive generates a A7A1 Mechanical brake closing failed warning if the status of the acknowledgement does not match the status presumed by the brake control logic. Upon opening the brake, the drive trips on a 71A3 Mechanical brake opening failed fault if the status of the acknowledgement does not match the status presumed by the brake control logic. The drive trips on a 71A5 Mechanical brake opening not allowed fault if the brake open conditions cannot be fulfilled (for example, the required motor starting torque is not achieved).	2
44.18	Brake fault delay	Defines a close fault delay, ie. time between brake closure and brake close fault trip.	0.00 s
	0.00 60.00 s	Brake close fault delay.	100 = 1 s
45 En	ergy efficiency	Settings for the energy saving calculators. See also section <i>Energy saving calculators</i> (page 121).	
45.01	Saved GW hours	Displays the energy saved in GWh compared to direct-on-line	-

		See also section thereby saving calculators (page 121).	
45.01	Saved GW hours	Displays the energy saved in GWh compared to direct-on-line motor connection. This parameter is incremented when 45.02 <i>Saved MW hours</i> rolls over. This parameter is read-only (see parameter 45.21 Energy <i>calculations reset</i>).	-
	065535 GWh	Energy savings in GWh.	1 = 1 GWh
45.02	Saved MW hours	Displays the energy saved in MWh compared to direct-on-line motor connection. This parameter is incremented when 45.03 Saved kW hours rolls over. When this parameter rolls over, parameter 45.01 Saved GW hours is incremented. This parameter is read-only (see parameter 45.21 Energy calculations reset).	-
	0999 MWh	Energy savings in MWh.	1 = 1 MWh

No.	Name/Value	Description	Def/FbEq16
45.03	Saved kW hours	Displays the energy saved in kWh compared to direct-on-line motor connection. If the internal brake chopper of the drive is enabled, all energy fed by the motor to the drive is assumed to be converted into heat, but the calculation still records savings made by controlling the speed. If the chopper is disabled, then regenerated energy from the motor is also recorded here. When this parameter rolls over, parameter <i>45.02 Saved MW hours</i> is incremented. This parameter is read-only (see parameter <i>45.21 Energy calculations reset</i>).	-
	0.0 999.9 kWh	Energy savings in kWh.	10 = 1 kWh
45.05	Saved money x1000	Displays the monetary savings in thousands compared to direct-on-line motor connection. This parameter is incremented when 45.06 Saved money rolls over. The currency is defined by parameter 45.17 Tariff currency unit. This parameter is read-only (see parameter 45.21 Energy calculations reset).	-
	04294967295 thousands	Monetary savings in thousands of units.	-
45.06	Saved money	Displays the monetary savings compared to direct-on-line motor connection. This value is a calculated by multiplying the saved energy in kWh by the currently active energy tariff (<i>45.14 Tariff selection</i>). When this parameter rolls over, parameter <i>45.05 Saved</i> <i>money x1000</i> is incremented. The currency is defined by parameter <i>45.17 Tariff currency</i> <i>unit</i> . This parameter is read-only (see parameter <i>45.21 Energy</i> <i>calculations reset</i>).	-
	0.00 999.99 units	Monetary savings.	1 = 1 unit
45.08	CO2 reduction in kilotons	Displays the reduction in CO_2 emissions in metric kilotons compared to direct-on-line motor connection. This value is incremented when parameter 45.09 CO2 reduction in tons rolls over. This parameter is read-only (see parameter 45.21 Energy calculations reset).	-
	0…65535 metric kilotons	Reduction in CO ₂ emissions in metric kilotons.	1 = 1 metric kiloton
45.09	CO2 reduction in tons	Displays the reduction in CO_2 emissions in metric tons compared to direct-on-line motor connection. This value is calculated by multiplying the saved energy in MWh by the value of parameter 45.18 CO2 conversion factor (by default, 0.5 metric tons/MWh). When this parameter rolls over, parameter 45.08 CO2 reduction in kilotons is incremented. This parameter is read-only (see parameter 45.21 Energy calculations reset).	-
	0.0 999.9 metric tons	Reduction in CO ₂ emissions in metric tons.	1 = 1 metric ton

No.	Name/Value	Description	Def/FbEq16
45.11	Energy optimizer	Enables/disables the energy optimization function. The function optimizes the motor flux so that total energy consumption and motor noise level are reduced when the drive operates below the nominal load. The total efficiency (motor and drive) can be improved by 120% depending on load torque and speed. Note: With a permanent magnet motor or a synchronous reluctance motor, energy optimization is always enabled regardless of this parameter.	Disable
	Disable	Energy optimization disabled.	0
	Enable	Energy optimization enabled.	1
45.12	Energy tariff 1	 Defines energy tariff 1 (price of energy per kWh). Depending on the setting of parameter 45.14 Tariff selection, either this value or 45.13 Energy tariff 2 is used for reference when monetary savings are calculated. The currency is defined by parameter 45.17 Tariff currency unit. Note: Tariffs are read only at the instant of selection, and are not applied retroactively. 	1.000 units
	0.000 4294967.295 units	Energy tariff 1.	-
45.13	Energy tariff 2	Defines energy tariff 2 (price of energy per kWh). See parameter <i>45.12 Energy tariff 1</i> .	2.000 units
	0.000 4294967.295 units	Energy tariff 2.	-
45.14	Tariff selection	Selects (or defines a source that selects) which pre-defined energy tariff is used. 0 = 45.12 Energy tariff 1 1 = 45.13 Energy tariff 2	Energy tariff 1
	Energy tariff 1	0.	0
	Energy tariff 2	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
45.17	Tariff currency unit	Specifies the currency used for the savings calculations.	EUR
	Local currency	Local currency. The name of the currency can be edited by choosing Menu - Settings - Edit texts on the control panel.	100
	EUR	Euro.	101
	USD	US dollar.	102
45.18	CO2 conversion factor	Defines a factor for conversion of saved energy into CO_2 emissions (Kg/kWh or tn/MWh).	0.500 tn/MWh
	0.000 65.535 tn/MWh	Factor for conversion of saved energy into CO_2 emissions.	1 = 1 tn/MWh

No.	Name/Value	Description	Def/FbEq16
45.19	Comparison power	Actual power that the motor absorbs when connected direct- on-line and operating the application. The value is used for reference when energy savings are calculated. Note: The accuracy of the energy savings calculation is directly dependent on the accuracy of this value. If nothing is entered here, then the nominal motor power is used by the calculation, but that may inflate the energy savings reported as many motors do not absorb nameplate power.	0.0 kW
	0.0 100000.0 kW	Motor power.	See par. 46.04
45.21	Energy calculations reset	Resets the savings counter parameters 45.0145.09	Done
	Done	Reset not requested (normal operation), or reset complete.	0
	Reset	Reset the savings counter parameters. The value reverts automatically to <i>Done</i> .	1

46 Mo setting	nitoring/scaling gs	Speed supervision settings; actual signal filtering; general scaling settings.	
46.01	Speed scaling	Defines the maximum speed value used to define the acceleration ramp rate and the initial speed value used to define the deceleration ramp rate (see parameter group 23 <i>Speed reference ramp</i>). The speed acceleration and deceleration ramp times are therefore related to this value (not to parameter <i>30.12 Maximum speed</i>). Also defines the 16-bit scaling of speed-related parameters. The value of this parameter corresponds to 20000 in fieldbus, master/follower etc. communication.	1500.00 rpm; 1800.00 rpm (95.20 b0)
	0.1030000.00 rpm	Acceleration/deceleration terminal/initial speed.	1 = 1 rpm
46.02	Frequency scaling	Defines the maximum frequency value used to define the acceleration ramp rate and the initial frequency value used to define deceleration ramp rate. The frequency acceleration and deceleration ramp times are therefore related to this value (not to parameter <i>30.14 Maximum frequency</i>). Also defines the 16-bit scaling of frequency-related parameters. The value of this parameter corresponds to 20000 in fieldbus, master/follower etc. communication.	50.00 Hz; 60.00 Hz (95.20 b0)
	0.10 1000.00 Hz	Acceleration/deceleration terminal/initial frequency.	10 = 1 Hz
46.03	Torque scaling	Defines the 16-bit scaling of torque parameters. The value of this parameter (in percent of nominal motor torque) corresponds to 10000 in fieldbus, master/follower etc. communication. See also parameter <i>46.42 Torque decimals</i> .	100.0%
	0.1 1000.0%	Torque corresponding to 10000 on fieldbus.	10 = 1%
46.04	Power scaling	Defines the output power value that corresponds to 10000 in fieldbus, master/follower etc. communication. The unit is selected by parameter <i>96.16 Unit selection</i> .	1000.00 kW or hp
	0.10 30000.00 kW or 0.10 40214.48 hp	Power corresponding to 10000 on fieldbus.	1 = 1 unit

No.	Name/Value	Description	Def/FbEq16
46.05	Current scaling	Defines the 16-bit scaling of current parameters. The value of this parameter corresponds to 10000 in fieldbus, master/follower etc. communication.	10000 A
	030000 A	Current corresponding to 10000 on fieldbus.	1 = 1 A
46.06	Speed ref zero scaling	Defines a speed corresponding to a zero reference received from fieldbus (either the embedded fieldbus interface, or interface FBA A or FBA B). For example, with a setting of 500, the fieldbus reference range of 020000 would correspond to a speed of 500[46.01] rpm. Note: This parameter is effective only with the ABB Drives communication profile.	0.00 rpm
	0.00 30000.00 rpm	Speed corresponding to minimum fieldbus reference.	1 = 1 rpm
46.07	Frequency ref zero scaling	Defines a frequency corresponding to a zero reference received from fieldbus (either the embedded fieldbus interface, or interface FBAA or FBAB). For example, with a setting of 30, the fieldbus reference range of 020000 would correspond to a speed of 30[46.02] Hz. Note: This parameter is effective only with the ABB Drives communication profile.	0.00 Hz
	0.00 1000.00 Hz	Frequency corresponding to minimum fieldbus reference.	10 = 1 Hz
46.11	Filter time motor speed	Defines a filter time for signals 01.01 Motor speed used, 01.02 Motor speed estimated, 01.04 Encoder 1 speed filtered and 01.05 Encoder 2 speed filtered.	500 ms
	020000 ms	Motor speed signal filter time.	1 = 1 ms
46.12	Filter time output frequency	Defines a filter time for signal 01.06 Output frequency.	500 ms
	020000 ms	Output frequency signal filter time.	1 = 1 ms
46.13	Filter time motor torque	Defines a filter time for signal 01.10 Motor torque.	100 ms
	020000 ms	Motor torque signal filter time.	1 = 1 ms
46.14	Filter time power out	Defines a filter time for signal 01.14 Output power.	100 ms
	020000 ms	Output power signal filter time.	1 = 1 ms

No.	Name/Value	Description	Def/FbEq16
46.21	At speed hysteresis	<i>bed hysteresis</i> Defines the "at setpoint" limits for speed control of the drive. When the absolute difference between reference (22.87 <i>Speed reference act 7</i>) and actual speed (90.01 Motor speed for control) is smaller than 46.21 At speed hysteresis, the drive is considered to be "at setpoint". This is indicated by bit 8 of 06.11 Main status word.	100.00 rpm
		$\begin{array}{c} 90.01 \text{ (rpm)} \\ \hline \\ 22.87 + 46.21 \\ 22.87 \text{ (rpm)} \\ 22.87 \text{ (rpm)} \\ 22.87 - 46.21 \text{ (rpm)} \\ 0 \text{ rpm} \end{array}$	
	0.00 30000.00 rpm	Limit for "at setpoint" indication in speed control.	See par. 46.01
46.22	At frequency hysteresis	Defines the "at setpoint" limits for frequency control of the drive. When the absolute difference between reference and actual frequency (01.06 Output frequency) is smaller than 46.22 At frequency hysteresis, the drive is considered to be "at setpoint". This is indicated by bit 8 of 06.11 Main status word.	10.00 Hz
		$ \begin{array}{c} 01.06 (Hz) \\ \hline 28.96 + 46.22 (Hz) \\ 28.96 (Hz) \\ 28.96 - 46.22 (Hz) \\ \hline 0 Hz \end{array} $	
	0.00 1000.00 Hz	Limit for "at setpoint" indication in frequency control.	See par. 46.02

No.	Name/Value	Description	Def/FbEq16
46.23	At torque hysteresis	Defines the "at setpoint" limits for torque control of the drive. When the absolute difference between reference (26.73 <i>Torque reference act 4</i>) and actual torque (01.10 Motor <i>torque</i>) is smaller than 46.23 At torque hysteresis, the drive is considered to be "at setpoint". This is indicated by bit 8 of 06.11 Main status word.	10.0%
		Drive at setpoint $(06.11 \text{ bit } 8 = 1)$ $\begin{cases} 01.10 (\%) \\ 26.73 + 46.23 (\%) \\ 26.73 - 46.23 (\%) \\ 0 \% \end{cases}$	
	0.0300.0%	Limit for "at setpoint" indication in torque control.	See par. 46.03
46.31	Above speed limit	Defines the trigger level for "above limit" indication in speed control. When actual speed exceeds the limit, bit 10 of <i>06.17 Drive status word 2</i> is set.	1500.00 rpm
	0.00 30000.00 rpm	"Above limit" indication trigger level for speed control.	See par. 46.01
46.32	Above frequency limit	Defines the trigger level for "above limit" indication in frequency control. When actual frequency exceeds the limit, bit 10 of <i>06.17 Drive status word 2</i> is set.	50.00 Hz
	0.00 1000.00 Hz	"Above limit" indication trigger level for frequency control.	See par. 46.02
46.33	Above torque limit	Defines the trigger level for "above limit" indication in torque control. When actual torque exceeds the limit, bit 10 of 06.17 <i>Drive status word 2</i> is set.	300.0%
	0.0 1600.0%	"Above limit" indication trigger level for torque control.	See par. 46.03
46.42	Torque decimals	Defines the number of decimal places of torque-related parameters.	1
	02	Number of decimal places of torque parameters.	1 = 1

No.	Name/Value	Description	Def/FbEq16
47 Dat	ta storage	Data storage parameters that can be written to and read from using other parameters' source and target settings. Note that there are different storage parameters for different data types. Integer-type storage parameters cannot be used as the source of other parameters. See also section <i>Data storage parameters</i> (page 124).	
47.01	Data storage 1 real32	Data storage parameter 1. Parameters 47.0147.08 are real 32-bit numbers that can be used as source values of other parameters. Storage parameters 47.0147.08 can be used as the target of received 16-bit data (parameter group 62 D2D and DDCS receive data) or the source of transmitted 16-bit data (parameter group 61 D2D and DDCS transmit data). The scaling and range are defined by parameters 47.3147.38.	0.000
	See par. 47.31	32-bit real (floating point) number.	See par. 47.31
47.02	Data storage 2 real32	Data storage parameter 2. See also parameter 47.01 Data storage 1 real32.	0.000
	See par. 47.32	32-bit real (floating point) number.	See par. 47.32
47.03	Data storage 3 real32	Data storage parameter 3. See also parameter 47.01 Data storage 1 real32.	0.000
	See par. 47.33	32-bit real (floating point) number.	See par. 47.33
47.04	Data storage 4 real32	Data storage parameter 4. See also parameter 47.01 Data storage 1 real32	0.000
	See par. 47.34	32-bit real (floating point) number.	See par. 47.34
47.05	Data storage 5 real32	Data storage parameter 5. See also parameter 47.01 Data storage 1 real32.	0.000
	See par. 47.35	32-bit real (floating point) number.	See par. 47.35
47.06	Data storage 6 real32	Data storage parameter 6. See also parameter 47.01 Data storage 1 real32.	0.000
	See par. 47.36	32-bit real (floating point) number.	See par. 47.36
47.07	Data storage 7 real32	Data storage parameter 7. See also parameter 47.01 Data storage 1 real32.	0.000
	See par. 47.37	32-bit real (floating point) number.	See par. 47.37
47.08	Data storage 8 real32	Data storage parameter 8. See also parameter 47.01 Data storage 1 real32.	0.000
	See par. 47.38	32-bit real (floating point) number.	See par. 47.38
47.11	Data storage 1 int32	Data storage parameter 9.	0
	-2147483648 2147483647	32-bit integer.	-

No.	Name/Value	Description	Def/FbEq16
47.12	Data storage 2 int32	Data storage parameter 10.	0
	-2147483648 2147483647	32-bit integer.	-
47.13	Data storage 3 int32	Data storage parameter 11.	0
	-2147483648 2147483647	32-bit integer.	-
47.14	Data storage 4 int32	Data storage parameter 12.	0
	-2147483648 2147483647	32-bit integer.	-
47.15	Data storage 5 int32	Data storage parameter 13.	0
	-2147483648 2147483647	32-bit integer.	-
47.16	Data storage 6 int32	Data storage parameter 14.	0
	-2147483648 2147483647	32-bit integer.	-
47.17	Data storage 7 int32	Data storage parameter 15.	0
	-2147483648 2147483647	32-bit integer.	-
47.18	Data storage 8 int32	Data storage parameter 16.	0
	-2147483648 2147483647	32-bit integer.	-
47.21	Data storage 1 int16	Data storage parameter 17.	0
	-32768 32767	16-bit integer.	1 = 1
47.22	Data storage 2 int16	Data storage parameter 18.	0
	-32768 32767	16-bit integer.	1 = 1
47.23	Data storage 3 int16	Data storage parameter 19.	0
	-32768 32767	16-bit integer.	1 = 1
47.24	Data storage 4 int16	Data storage parameter 20.	0
	-32768 32767	16-bit integer.	1 = 1
47.25	Data storage 5 int16	Data storage parameter 21.	0
	-32768 32767	16-bit integer.	1 = 1
47.26	Data storage 6 int16	Data storage parameter 22.	0
	-32768 32767	16-bit integer.	1 = 1

No.	Name/Value	Description	Def/FbEq16
47.27	Data storage 7 int16	Data storage parameter 23.	0
	-32768 32767	16-bit integer.	1 = 1
47.28	Data storage 8 int16	Data storage parameter 24.	0
	-32768 32767	16-bit integer.	1 = 1
47.31	Data storage 1 real32 type	Defines the scaling of parameter 47.01 Data storage 1 real32 to and from 16-bit integer format. This scaling is used when the data storage parameter is the target of received 16-bit data (defined in parameter group 62 D2D and DDCS receive data), or when the data storage parameter is the source of transmitted 16-bit data (defined in parameter group 61 D2D and DDCS transmit data). The setting also defines the visible range of the storage parameter.	Unscaled
	Unscaled	Data storage only. Range: -2147483.264 2147473.264.	0
	Transparent	Scaling: 1 = 1. Range: -32768 32767.	1
	General	Scaling: 1 = 100. Range: -327.68 327.67.	2
	Torque	The scaling is defined by parameter <i>46.03 Torque scaling</i> . Range: -1600.0 1600.0.	3
	Speed	The scaling is defined by parameter <i>46.01 Torque scaling</i> . Range: -1600.0 1600.0.	4
	Frequency	The scaling is defined by parameter <i>46.02 Frequency scaling</i> . Range: -500.00 500.00.	5
47.32	Data storage 2 real32 type	Defines the 16-bit scaling of parameter 47.02 Data storage 2 real32. See parameter 47.31 Data storage 1 real32 type.	Unscaled
47.33	Data storage 3 real32 type	Defines the 16-bit scaling of parameter 47.03 Data storage 3 real32. See parameter 47.31 Data storage 1 real32 type.	Unscaled
47.34	Data storage 4 real32 type	Defines the 16-bit scaling of parameter 47.04 Data storage 4 real32. See parameter 47.31 Data storage 1 real32 type.	Unscaled
47.35	Data storage 5 real32 type	Defines the 16-bit scaling of parameter 47.05 Data storage 5 real32. See parameter 47.31 Data storage 1 real32 type.	Unscaled
47.36	Data storage 6 real32 type	Defines the 16-bit scaling of parameter 47.06 Data storage 6 real32. See parameter 47.31 Data storage 1 real32 type.	Unscaled
47.37	Data storage 7 real32 type	Defines the 16-bit scaling of parameter 47.07 Data storage 7 real32. See parameter 47.31 Data storage 1 real32 type.	Unscaled
47.38	Data storage 8 real32 type	Defines the 16-bit scaling of parameter 47.08 Data storage 8 real32. See parameter 47.31 Data storage 1 real32 type.	Unscaled

No.	Name/Value	Description	Def/FbEq16
	nel port unication	Communication settings for the control panel port on the drive.	
49.01	Node ID number	Defines the node ID of the drive. All devices connected to the network must have a unique node ID. Note: For networked drives, it is advisable to reserve ID 1 for spare/replacement drives.	1
	132	Node ID.	1 = 1
49.03	Baud rate	Defines the transfer rate of the link.	230.4 kbps
	38.4 kbps	38.4 kbit/s.	1
	57.6 kbps	57.6 kbit/s.	2
	86.4 kbps	86.4 kbit/s.	3
	115.2 kbps	115.2 kbit/s.	4
	230.4 kbps	230.4 kbit/s.	5
49.04	Communication loss time	Sets a timeout for control panel (or PC tool) communication. If a communication break lasts longer than the timeout, the action specified by parameter 49.05 Communication loss action is taken.	10.0 s
	0.3 3000.0 s	Panel/PC tool communication timeout.	10 = 1 s
49.05	Communication loss action	Selects how the drive reacts to a control panel (or PC tool) communication break. Changes to this parameter take effect after the control unit is rebooted or the new settings validated by parameter 49.06 <i>Refresh settings</i> . See also parameters 49.07 <i>Panel comm supervision force</i> and 49.08 <i>Secondary comm. loss action</i> .	Fault
	No action	No action taken.	0
	Fault	Drive trips on 7081 Panel port communication. This only occurs if control is expected from the control panel (it is selected as source of start/stop/reference in the currently active control location), or if supervision is forced using parameter 49.07 Panel comm supervision force.	1
	Last speed	Drive generates an A7EE Control panel loss warning and freezes the speed to the level the drive was operating at. This only occurs if control is expected from the control panel, or if supervision is forced using parameter 49.07 Panel comm supervision force. WARNING! Make sure that it is safe to continue operation in case of a communication break.	2
	Speed ref safe	Drive generates an A7EE Control panel loss warning and sets the speed to the speed defined by parameter 22.41 Speed ref safe. This only occurs if control is expected from the control panel, or if supervision is forced using parameter 49.07 Panel comm supervision force. WARNING! Make sure that it is safe to continue operation in case of a communication break.	3
	Fault always	Drive trips on 7081 Panel port communication. This occurs even though no control is expected from the panel (or PC tool).	4

No.	Name/V	alue	Description		
	Warning		Drive generates an A7EE Control panel loss warning. This only occurs if control is expected from the control panel, or if supervision is forced using parameter 49.07 Panel comm supervision force. WARNING! Make sure that it is safe to continue operation in case of a communication break.	5	
49.06	Refresh	settings	Applies the settings of parameters <i>49.0149.05</i> . Note: Refreshing may cause a communication break, so reconnecting the drive may be required.	Done	
	Done		Refresh done or not requested.	0	
	Refresh		Refresh parameters <i>49.0149.05</i> . The value reverts automatically to <i>Done</i> .	1	
49.07	Panel comm supervision force		Activates control panel communication monitoring separately for each control location (see section <i>Local control vs.</i> <i>external control</i> on page 54). The parameter is primarily intended for monitoring the communication with the panel when it is connected to the application program and not selected as a control source by drive parameters.	0000b	
	Bit	Name	Value		
	0	Ext 1	1 = Communication monitoring active when Ext 1 is be	ing used	
	1	Ext 1 Ext 2	1 = Communication monitoring active when Ext 1 is be	·	
	2	Local		1 = Communication monitoring active when local control is being	
	315 Reserved				
	0000b0111b Panel communication monitoring selection.		Panel communication monitoring selection.	1 = 1	
49.08	Secondary comm. loss action		 Selects how the drive reacts to a control panel (or PC tool) communication break. This action is taken when the panel is parametrized as an alternative control or reference source but is not currently the active source, and communication supervision for the active control location is not forced by parameter 49.07 Panel comm supervision force. 	No action	
	No action		No action taken.	0	
	Warning	I	Drive generates an <i>A7EE Control panel loss</i> warning. WARNING! Make sure that it is safe to continue operation in case of a communication break.	5	
49.14	Panel s referenc		Defines the unit for speed reference when given from the control panel.	rpm	
	rpm		rpm.	0	
	%		Percent of parameter 46.01 Speed scaling.	1	
49.15	Minimur ref pane	n ext speed l	Defines a minimum limit for control panel speed reference in external control. In local control, the limits in parameter group <i>30 Limits</i> are in force. See section <i>Local control vs. external control</i> on page <i>54</i>).	-30000.00 rpm	
	-30000. 30000.0		Minimum speed reference.	See par. 46.01	

No.	Name/Value	Description	Def/FbEq16
49.16	Maximum ext speed ref panel	Defines a maximum limit for control panel speed reference in external control. In local control, the limits in parameter group <i>30 Limits</i> are in force. See section <i>Local control vs. external control</i> on page <i>54</i>).	30000.00 rpm
	-30000.00 30000.00 rpm	Maximum speed reference.	See par. 46.01
49.17	Minimum ext frequency ref panel	Defines a minimum limit for control panel frequency reference in external control. In local control, the limits in parameter group <i>30 Limits</i> are in force. See section <i>Local control vs. external control</i> on page <i>54</i>).	-500.00 Hz
	-500.00 500.00 Hz	Minimum frequency reference.	See par. 46.02
49.18	Maximum ext frequency ref panel	Defines a maximum limit for control panel frequency reference in external control. In local control, the limits in parameter group <i>30 Limits</i> are in force. See section <i>Local control vs. external control</i> on page <i>54</i>).	500.00 Hz
	-500.00 500.00 Hz	Maximum frequency reference.	See par. 46.02
49.24	Panel actual source	Selects an actual value to be displayed in the top right corner of the control panel. This parameter is only effective when the control panel is not an active reference source.	Automatic
	Automatic	The active reference is displayed.	0
	Process PID setpoint actual	40.03 Process PID setpoint actual (see page 325).	1
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-

50 Fieldbus adapter (FBA)	Fieldbus communication configuration. See also chapter <i>Fieldbus control through a fieldbus adapter</i> (page 613).	
50.01 FBA A enable	Enables/disables communication between the drive and fieldbus adapter A, and specifies the slot the adapter is installed into.	Disable
Disable	Communication between drive and fieldbus adapter A disabled.	0
Option slot 1	Communication between drive and fieldbus adapter A enabled. The adapter is in slot 1.	1
Option slot 2	Communication between drive and fieldbus adapter A enabled. The adapter is in slot 2.	2
Option slot 3	Communication between drive and fieldbus adapter A enabled. The adapter is in slot 3.	3
50.02 FBA A comm loss func	Selects how the drive reacts upon a fieldbus communication break. A time delay for the action can be defined by parameter 50.03 FBA A comm loss t out. See also parameter 50.26 FBA A comm supervision force.	No action
No action	No action taken.	0

No.	Name/Value	Description	Def/FbEq16
	Fault	The drive trips on 7510 FBA A communication. This only occurs if control is expected from the FBA A interface (FBA A selected as source of start/stop/reference in the currently active control location), or if supervision is forced using parameter 50.26 FBA A comm supervision force.	1
	Last speed	 Drive generates an A7C1 FBA A communication warning and freezes the speed to the level the drive was operating at. This only occurs if control is expected from the FBA A interface, or if supervision is forced using parameter 50.26 FBA A comm supervision force. The speed is determined on the basis of actual speed using 850 ms low-pass filtering. WARNING! Make sure that it is safe to continue operation in case of a communication break. 	2
	Speed ref safe	Drive generates a warning (<i>A7C1 FBA A communication</i>) and sets the speed to the value defined by parameter 22.41 <i>Speed ref safe</i> . This only occurs if control is expected from the FBA A interface, or if supervision is forced using parameter 50.26 FBA A comm supervision force. WARNING! Make sure that it is safe to continue operation in case of a communication break.	3
	Fault always	Drive trips on <i>7510 FBA A communication</i> . This occurs even though no control is expected from the FBA A interface.	4
	Warning	Drive generates an A7C1 FBA A communication warning.This only occurs if control is expected from the FBAA interface, or if supervision is forced using parameter 50.26FBA A comm supervision force.WARNING! Make sure that it is safe to continue operation in case of a communication break.	5
50.03	FBA A comm loss t out	Defines the time delay before the action defined by parameter 50.02 FBA A comm loss func is taken. Time count starts when the communication link fails to update the message. As a rule of thumb, this parameter should be set to at least 3 times the transmit interval of the master. Note: There is a 60-second boot-up delay immediately after power-up. During the delay, the communication break monitoring is disabled (but communication itself can be active).	0.3 s
	0.3 6553.5 s	Time delay.	1 = 1 s
50.04	FBA A ref1 type	Selects the type and scaling of reference 1 received from fieldbus adapter A.	Auto
	Auto	Type and scaling are chosen automatically according to which reference chain (see settings <i>Torque</i> , <i>Speed</i> , <i>Frequency</i>) the incoming reference is connected to. If the reference is not connected to any chain, no scaling is applied (as with setting <i>Transparent</i>).	0
	Transparent	No scaling is applied (the 16-bit scaling is 1 = 1 unit).	1
	General	Generic reference with a scaling of 100 = 1 (ie. integer and two decimals).	2
	Torque	The scaling is defined by parameter 46.03 Torque scaling.	3
	Speed	The scaling is defined by parameter 46.01 Speed scaling.	4
	Frequency	The scaling is defined by parameter 46.02 Frequency scaling.	5

No.	Name/Value	Description	Def/FbEq16
50.05	FBA A ref2 type	Selects the type and scaling of reference 2 received from fieldbus adapter A. For the selections, see parameter <i>50.04 FBA A ref1 type</i>	Auto
50.07	FBA A actual 1 type	Selects the type/source and scaling of actual value 1 transmitted to the fieldbus network through fieldbus adapter A.	Auto
	Auto	Type/source and scaling follow the type of reference 1 selected by parameter <i>50.04 FBA A ref1 type</i> . See the individual settings below for the sources and scalings.	0
	Transparent	The value selected by parameter <i>50.10 FBA A act1</i> <i>transparent source</i> is sent as actual value 1. No scaling is applied (the 16-bit scaling is 1 = 1 unit).	1
	General	The value selected by parameter <i>50.10 FBA A act1</i> <i>transparent source</i> is sent as actual value 1 with a 16-bit scaling of 100 = 1 unit (ie. integer and two decimals).	2
	Torque	<i>01.10 Motor torque</i> is sent as actual value 1. The scaling is defined by parameter <i>46.03 Torque scaling</i> .	3
	Speed	01.01 Motor speed used is sent as actual value 1. The scaling is defined by parameter 46.01 Speed scaling.	4
	Frequency	01.06 Output frequency is sent as actual value 1. The scaling is defined by parameter 46.02 Frequency scaling.	5
	Position	Motor position is sent as actual value 1. See parameter 90.06 Motor position scaled.	6
50.08	FBA A actual 2 type	Selects the type/source and scaling of actual value 2 transmitted to the fieldbus network through fieldbus adapter A.	Auto
	Auto	Type/source and scaling follow the type of reference 2 selected by parameter 50.05 FBA A ref2 type. See the individual settings below for the sources and scalings.	0
	Transparent	The value selected by parameter <i>50.11 FBA A act2</i> <i>transparent source</i> is sent as actual value 2. No scaling is applied (the 16-bit scaling is 1 = 1 unit).	1
	General	The value selected by parameter <i>50.11 FBA A act2</i> <i>transparent source</i> is sent as actual value 2 with a 16-bit scaling of 100 = 1 unit (ie. integer and two decimals).	2
	Torque	<i>01.10 Motor torque</i> is sent as actual value 2. The scaling is defined by parameter <i>46.03 Torque scaling</i> .	3
	Speed	<i>01.01 Motor speed used</i> is sent as actual value 2. The scaling is defined by parameter <i>46.01 Speed scaling</i> .	4
	Frequency	<i>01.06 Output frequency</i> is sent as actual value 2. The scaling is defined by parameter <i>46.02 Frequency scaling</i> .	5
	Position	Motor position is sent as actual value 2. See parameter 90.06 Motor position scaled.	6
50.09	FBA A SW transparent source	Selects the source of the fieldbus status word when fieldbus adapter is set to a transparent communication profile, for example, by its configuration parameters (group <i>51 FBA A settings</i>).	Not selected
	Not selected	No source selected.	-
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-

No.	Name/Value	Description	Def/FbEq16
50.10	FBA A act1 transparent source	When parameter <i>50.07 FBA A actual 1 type</i> is set to <i>Transparent</i> or <i>General</i> , this parameter selects the source of actual value 1 transmitted to the fieldbus network through fieldbus adapter A.	Not selected
	Not selected	No source selected.	-
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
50.11	FBA A act2 transparent source	When parameter <i>50.08 FBA A actual 2 type</i> is set to <i>Transparent</i> or <i>General</i> , this parameter selects the source of actual value 2 transmitted to the fieldbus network through fieldbus adapter A.	Not selected
	Not selected	No source selected.	-
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
50.12	FBA A debug mode	Enables the display of raw (unmodified) data received from and sent to fieldbus adapter A in parameters 50.1350.18. This functionality should only be used for debugging.	Disable
	Disable	Display of raw data from fieldbus adapter A disabled.	0
	Fast	Display of raw data from fieldbus adapter A enabled.	1
50.13	FBA A control word	Displays the raw (unmodified) control word sent by the master (PLC) to fieldbus adapter A if debugging is enabled by parameter <i>50.12 FBA A debug mode</i> . This parameter is read-only.	-
	00000000h FFFFFFFh	Control word sent by master to fieldbus adapter A.	-
50.14	FBA A reference 1	Displays raw (unmodified) reference REF1 sent by the master (PLC) to fieldbus adapter A if debugging is enabled by parameter <i>50.12 FBA A debug mode</i> . This parameter is read-only.	-
	-2147483648 2147483647	Raw REF1 sent by master to fieldbus adapter A.	-
50.15	FBA A reference 2	Displays raw (unmodified) reference REF2 sent by the master (PLC) to fieldbus adapter A if debugging is enabled by parameter <i>50.12 FBA A debug mode</i> . This parameter is read-only.	-
	-2147483648 2147483647	Raw REF2 sent by master to fieldbus adapter A.	-
50.16	FBA A status word	Displays the raw (unmodified) status word sent by fieldbus adapter A to the master (PLC) if debugging is enabled by parameter <i>50.12 FBA A debug mode</i> . This parameter is read-only.	-
	00000000h FFFFFFFh	Status word sent by fieldbus adapter A to master.	-
50.17	FBA A actual value 1	Displays raw (unmodified) actual value ACT1 sent by fieldbus adapter A to the master (PLC) if debugging is enabled by parameter <i>50.12 FBA A debug mode</i> . This parameter is read-only.	-
	-2147483648 2147483647	Raw ACT1 sent by fieldbus adapter A to master.	-
50.18	FBA A actual value 2	Displays raw (unmodified) actual value ACT2 sent by fieldbus adapter A to the master (PLC) if debugging is enabled by parameter <i>50.12 FBA A debug mode</i> . This parameter is read-only.	-

No.	Name/V	alue	Descri	otion			Def/FbEq16
	-214748 2147483		Raw AC	CT2 sent b	oy fieldbus adapter A t	o master.	-
50.21	FBA A ti	melevel sel	In gene CPU loa read/wr	ral, lower ad. The ta	nunication time levels time levels of read/wr ble below shows the es for cyclic high and o setting.	ite services reduce time levels of the	Normal
			Select	ion	Cyclic high *	Cyclic low **	
			Monito	oring	10 ms	10 ms	
			Norma	al	2 ms	10 ms	
			Fast		500 µs	2 ms	
			Very fa	ast	250 µs	2 ms	
	Normal		Act2. ** Cycli parame and acy Control generat	c low data eter groups /clic data. word, Ref ted on rec		ed as interrupts	
			Normal	speed.			0
	Fast		Fast sp				1
	Very fas	t	Very fas	st speed.			2
	Monitori	ng		eed. Optin ing usage	nized for PC tool com	munication and	3
50.26	FBA A c supervis	omm ion force	each co control The par commu applicat	ontrol loca on page 5 rameter is nication w	primarily intended for ith FBAA when it is c am and not selected a	al control vs. external monitoring the	0000b
	Bit	Name		Value			
	0	Ext 1		1 = Comn	nunication monitoring	active when Ext 1 is be	eing used.
	1	Ext 2				active when Ext 2 is be	-
	2	Local		1 = Comn used.	nunication monitoring	active when local conti	rol is being
	315	Reserved					
	0000b	.0111b	FBAAd	communic	ation monitoring selec	ction.	1 = 1
50.31	1			adapter I	communication betwo 3, and specifies the sl		Disable
	Disable		Commu disable		between drive and fiel	dbus adapter B	0
	Option s	lot 1			between drive and fiel apter is in slot 1.	dbus adapter B	1
	Option s	lot 2			between drive and fiel apter is in slot 2.	dbus adapter B	2

No.	Name/Value	Description	Def/FbEq16
	Option slot 3	Communication between drive and fieldbus adapter B enabled. The adapter is in slot 3.	3
50.32	FBA B comm loss func	Selects how the drive reacts upon a fieldbus communication break. A time delay for the action can be defined by parameter 50.33 FBA B comm loss timeout. See also parameter 50.56 FBA B comm supervision force.	No action
	No action	No action taken.	0
	Fault	The drive trips on <i>7520 FBA B communication</i> . This only occurs if control is expected from the FBA B interface (FBA B selected as source of start/stop/reference in the currently active control location), or if supervision is forced using parameter <i>50.56 FBA B comm supervision force</i> .	1
	Last speed	Drive generates an A7C2 FBA B communication warning and freezes the speed to the level the drive was operating at. This only occurs if control is expected from the FBA B interface, or if supervision is forced using parameter 50.56 FBA B comm supervision force. WARNING! Make sure that it is safe to continue operation in case of a communication break.	2
	Speed ref safe	Communication break detection active. Upon a communication break, the drive generates a warning (A7C2 FBA B communication) and sets the speed to the value defined by parameter 22.41 Speed ref safe (or 28.41 Frequency ref safe when frequency reference is being used). This only occurs if control is expected from the FBA B interface, or if supervision is forced using parameter 50.56 FBA B comm supervision force.	3
	Fault always	Drive trips on 7520 FBA B communication. This occurs even though no control is expected from the FBA B interface.	4
	Warning	Drive generates an A7C2 FBA B communication warning. This only occurs if control is expected from the FBA B interface, or if supervision is forced using parameter FBA B comm supervision force. WARNING! Make sure that it is safe to continue operation in case of a communication break.	5
50.33	FBA B comm loss timeout	Defines the time delay before the action defined by parameter 50.32 FBA B comm loss func is taken. Time count starts when the communication link fails to update the message. As a rule of thumb, this parameter should be set to at least 3 times the transmit interval of the master. Note: There is a 60-second boot-up delay immediately after power-up. During the delay, the communication break monitoring is disabled (but communication itself can be active).	0.3 s
	0.3 6553.5 s	Time delay.	1 = 1 s
50.34	FBA B ref1 type	Selects the type and scaling of reference 1 received from fieldbus adapter B. For the selections, see parameter <i>50.04 FBA A ref1 type</i> .	Auto
50.35	FBA B ref2 type	Selects the type and scaling of reference 2 received from fieldbus adapter B. For the selections, see parameter <i>50.04 FBA A ref1 type</i> .	Auto

No.	Name/Value	Description	Def/FbEq16
50.37	FBA B actual 1 type	Selects the type/source and scaling of actual value 1 transmitted to the fieldbus network through fieldbus adapter B. See parameter 50.07 FBA A actual 1 type.	Auto
50.38	FBA B actual 2 type	Selects the type/source and scaling of actual value 2 transmitted to the fieldbus network through fieldbus adapter B. See parameter <i>50.08 FBA A actual 2 type</i> .	Auto
50.39	FBA B SW transparent source	Selects the source of the fieldbus status word when the fieldbus adapter is set to a transparent communication profile, for example, by its configuration parameters (group 54 FBA B settings).	Not selected
	Not selected	No source selected.	-
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
50.40	FBA B act1 transparent source	When parameter 50.37 FBA B actual 1 type is set to Transparent or General, this parameter selects the source of actual value 1 transmitted to the fieldbus network through fieldbus adapter B.	Not selected
	Not selected	No source selected.	-
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
50.41	FBA B act2 transparent source	When parameter 50.38 FBA B actual 2 type is set to Transparent or General, this parameter selects the source of actual value 2 transmitted to the fieldbus network through fieldbus adapter B.	Not selected
	Not selected	No source selected.	-
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
50.42	FBA B debug mode	Enables the display of raw (unmodified) data received from and sent to fieldbus adapter B in parameters 50.4350.48. This functionality should only be used for debugging.	Disable
	Disable	Display of raw data from fieldbus adapter B disabled.	0
	Fast	Display of raw data from fieldbus adapter B enabled.	1
50.43	FBA B control word	Displays the raw (unmodified) control word sent by the master (PLC) to fieldbus adapter B if debugging is enabled by parameter <i>50.42 FBA B debug mode</i> . This parameter is read-only.	-
	00000000h FFFFFFFh	Control word sent by master to fieldbus adapter B.	-
50.44	FBA B reference 1	Displays raw (unmodified) reference REF1 sent by the master (PLC) to fieldbus adapter B if debugging is enabled by parameter <i>50.42 FBA B debug mode</i> . This parameter is read-only.	-
	-2147483648 2147483647	Raw REF1 sent by master to fieldbus adapter B.	-
50.45	FBA B reference 2	Displays raw (unmodified) reference REF2 sent by the master (PLC) to fieldbus adapter B if debugging is enabled by parameter <i>50.42 FBA B debug mode</i> . This parameter is read-only.	-
	-2147483648 2147483647	Raw REF2 sent by master to fieldbus adapter B.	-

No.	Name/Value	Description			Def/FbEq16
50.46	FBA B status word	Displays the raw adapter B to the parameter 50.42 This parameter is	-		
	00000000h FFFFFFFh	Status word sent	by fieldbus adapter B	to master.	-
50.47	FBA B actual value 1	adapter B to the I	master (PLC) if debug FBA B debug mode.	ACT1 sent by fieldbus ging is enabled by	-
	-2147483648 2147483647	Raw ACT1 sent b	by fieldbus adapter B t	o master.	-
50.48	FBA B actual valueDisplays raw (unmodified) actual value ACT2 sent by fieldbus adapter B to the master (PLC) if debugging is enabled by parameter 50.42 FBA B debug mode. This parameter is read-only.				-
	-2147483648 2147483647	Raw ACT2 sent b	oy fieldbus adapter B t	o master.	-
50.51	FBA B timelevel sel	In general, lower CPU load. The ta	nunication time levels. time levels of read/wr ble below shows the t es for cyclic high and o setting.	ite services reduce ime levels of the	Normal
		Selection	Cyclic high *	Cyclic low **	
		Monitoring	10 ms	10 ms	
		Normal	2 ms	10 ms	
		Fast	500 µs	2 ms	
		Very fast	250 µs	2 ms	
		Act2. ** Cyclic low data parameter groups and acyclic data. Control word, Re	a consists of fieldbus S a consists of the paran s 55 FBA B data in an f1 and Ref2 are handl eipt of cyclic high mes	neter data mapped to d <i>56 FBA B data out</i> , ed as interrupts	
	Normal	Normal speed.			0
	Fast	Fast speed.			1
	Very fast	Very fast speed.			2
	Monitoring	Low speed. Optir monitoring usage	nized for PC tool com	munication and	3

No.	Name/V	alue	Descri	ption	Def/FbEq16	
50.56	 FBA B comm supervision force Activates fieldbus communication monitoring separately for each control location (see section <i>Local control vs. external</i> <i>control</i> on page 54). The parameter is primarily intended for monitoring the communication with FBA B when it is connected to the application program and not selected as a control source by drive parameters. 		0000b			
	Bit	Name		Value		
	0	Ext 1		1 = Communication monitoring active when Ext 1 is be	eing used.	
	1	Ext 2		1 = Communication monitoring active when Ext 2 is being used.		
	2	Local		1 = Communication monitoring active when local contr used.	ol is being	
	315	Reserved				
	0000b	.0111b	FBA B	communication monitoring selection.	1 = 1	
51 FB	A A setti	ngs	Fieldbu	is adapter A configuration.		
51.01	FBA A ty	/pe	0 = Mo disable 32 = F0 135 = F	vs the type of the connected fieldbus adapter module. dule is not found or is not properly connected, or is ad by parameter <i>50.01 FBA A enable</i> ; 1 = FPBA; CAN; 37 = FDNA; 101 = FCNA, 128 = FENA-11/21; FECA; 136 = FEPL; 485 = FSCA. arameter is read-only.	-	
51.02	FBA A F	Par2	more ir adapte	eters 51.0251.26 are adapter module-specific. For formation, see the documentation of the fieldbus r module. Note that not all of these parameters are arily in use.	-	
	06553	35	Fieldbu	is adapter configuration parameter.	1 = 1	
51.26	FBA A F	Par26	See pa	rameter 51.02 FBA A Par2.	-	
	06553	35	Fieldbu	is adapter configuration parameter.	1 = 1	

51.20	I DA A Faizo	See parameter 51.021 DA A Parz.	-
	065535	Fieldbus adapter configuration parameter.	1 = 1
51.27	FBA A par refresh	Validates any changed fieldbus adapter module configuration settings. After refreshing, the value reverts automatically to <i>Done</i> . Note: This parameter cannot be changed while the drive is running.	Done
	Done	Refreshing done.	0
	Refresh	Refreshing.	1
51.28	FBA A par table ver	Displays the parameter table revision of the fieldbus adapter module mapping file (stored in the memory of the drive). In format axyz, where ax = major table revision number; yz = minor table revision number. This parameter is read-only.	-
		Parameter table revision of adapter module.	-
51.29	FBA A drive type code	Displays the drive type code in the fieldbus adapter module mapping file (stored in the memory of the drive). This parameter is read-only.	-
	065535	Drive type code stored in the mapping file.	1 = 1

No.	Name/Value	Description	Def/FbEq16
51.30	FBA A mapping file ver	Displays the fieldbus adapter module mapping file revision stored in the memory of the drive in decimal format. This parameter is read-only.	-
	065535	Mapping file revision.	1 = 1
51.31	D2FBA comm status	Displays the status of the fieldbus adapter module communication.	-
	Not configured	Adapter is not configured.	0
	Initializing	Adapter is initializing.	1
	Time out	A timeout has occurred in the communication between the adapter and the drive.	2
	Configuration error	Adapter configuration error: mapping file not found in the file system of the drive, or mapping file upload has failed more than three times.	3
	Off-line	Fieldbus communication is off-line.	4
	On-line	Fieldbus communication is on-line, or fieldbus adapter has been configured not to detect a communication break. For more information, see the documentation of the fieldbus adapter.	5
	Reset	Adapter is performing a hardware reset.	6
51.32	FBA A comm SW ver	Displays the patch and build versions of the adapter module firmware in format xxyy, where xx = patch version number, yy = build version number. Example: C802 = 200.02 (patch version 200, build version 2).	
		Patch and build versions of adapter module firmware.	-
51.33	FBA A appl SW ver	Displays the major and minor versions of the adapter module firmware in format xyz, where x = major revision number, yy = minor revision number. Example: 300 = 3.00 (major version 3, minor version 00).	
		Major and minor versions of adapter module firmware.	-

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None

No.	Name/Value	Description	Def/FbEq16
52 FB/	A A data in	Selection of data to be transferred from drive to fieldbus controller through fieldbus adapter A. Note: 32-bit values require two consecutive parameters. Whenever a 32-bit value is selected in a data parameter, the next parameter is automatically reserved.	
52.01	FBA A data in1	Parameters 52.0152.12 select data to be transferred from the drive to the fieldbus controller through fieldbus adapter A.	None
	None	None.	0
	CW 16bit	Control Word (16 bits)	1
	Ref1 16bit	Reference REF1 (16 bits)	2
	Ref2 16bit	Reference REF2 (16 bits)	3
	SW 16bit	Status Word (16 bits)	4
	Act1 16bit	Actual value ACT1 (16 bits)	5
	Act2 16bit	Actual value ACT2 (16 bits)	6
	CW 32bit	Control Word (32 bits)	11
	Ref1 32bit	Reference REF1 (32 bits)	12
	Ref2 32bit	Reference REF2 (32 bits)	13
	SW 32bit	Status Word (32 bits)	14
	Act1 32bit	Actual value ACT1 (32 bits)	15
	Act2 32bit	Actual value ACT2 (32 bits)	16
	SW2 16bit	Status Word 2 (16 bits)	24
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
52.12	FBA A data in12	See parameter 52.01 FBA A data in1.	None
53 FB/	A A data out	Selection of data to be transferred from fieldbus controller to drive through fieldbus adapter A. Note: 32-bit values require two consecutive parameters. Whenever a 32-bit value is selected in a data parameter, the next parameter is automatically reserved.	
53.01	FBA A data out1	Parameters 53.0153.12 select data to be transferred from the fieldbus controller to the drive through fieldbus adapter A.	None
	None	None.	0
	CW 16bit	Control Word (16 bits)	1
	Ref1 16bit	Reference REF1 (16 bits)	2
	Ref2 16bit	Reference REF2 (16 bits)	3
	CW 32bit	Control Word (32 bits)	11
	Ref1 32bit	Reference REF1 (32 bits)	12
	Ref2 32bit	Reference REF2 (32 bits)	13
	CW2 16bit	Control Word 2 (16 bits)	21
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-

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53.12

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FBA A data out12

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See parameter 53.01 FBA A data out1.

No.	Name/Value	Description	Def/FbEq16
54 FB	A B settings	Fieldbus adapter B configuration.	
54.01	FBA B type	Displays the type of the connected fieldbus adapter module. 0 = Module is not found or is not properly connected, or is disabled by parameter 50.31 FBA B enable; 1 = FPBA; 32 = FCAN; 37 = FDNA; 101 = FCNA, 128 = FENA-11/21; 135 = FECA; 136 = FEPL; 485 = FSCA. This parameter is read-only.	-
54.02	FBA B Par2	Parameters 54.0254.26 are adapter module-specific. For more information, see the documentation of the fieldbus adapter module. Note that not all of these parameters are necessarily in use.	-
	065535	Fieldbus adapter configuration parameter.	1 = 1
54.26	FBA B Par26	See parameter 54.02 FBA A Par2.	-
	065535	Fieldbus adapter configuration parameter.	1 = 1
54.27	FBA B par refresh	Validates any changed fieldbus adapter module configuration settings. After refreshing, the value reverts automatically to <i>Done</i> . Note: This parameter cannot be changed while the drive is running.	Done
	Done	Refreshing done.	0
	Refresh	Refreshing.	1
54.28	FBA B par table ver	Displays the parameter table revision of the fieldbus adapter module mapping file (stored in the memory of the drive). In format axyz, where ax = major table revision number; yz = minor table revision number. This parameter is read-only.	-
	065535	Parameter table revision of adapter module.	-
54.29	FBA B drive type code	Displays the drive type code in the fieldbus adapter module mapping file (stored in the memory of the drive). This parameter is read-only.	-
	065535	Drive type code stored in the mapping file.	1 = 1
54.30	FBA B mapping file ver	Displays the fieldbus adapter module mapping file revision stored in the memory of the drive in decimal format. This parameter is read-only.	-
		Mapping file revision.	1 = 1
54.31	D2FBA B comm status	Displays the status of the fieldbus adapter module communication.	-
	Not configured	Adapter is not configured.	0
	Initializing	Adapter is initializing.	1
	Time out	A timeout has occurred in the communication between the adapter and the drive.	2
	Configuration error	Adapter configuration error: mapping file not found in the file system of the drive, or mapping file upload has failed more than three times.	3
	Off-line	Fieldbus communication is off-line.	4
		1	1

No.	Name/Value	Description	Def/FbEq16
	On-line	Fieldbus communication is on-line, or fieldbus adapter has been configured not to detect a communication break. For more information, see the documentation of the fieldbus adapter.	5
	Reset	Adapter is performing a hardware reset.	6
54.32	FBA B comm SW ver	Displays the patch and build versions of the adapter module firmware in format xxyy, where xx = patch version number, yy = build version number. Example: C802 = 200.02 (patch version 200, build version 2).	
		Patch and build versions of adapter module firmware.	-
54.33	FBA B appl SW ver	Displays the major and minor versions of the adapter module firmware in format xyz, where x = major revision number, yy = minor revision number. Example: 300 = 3.00 (major version 3, minor version 00).	
		Major and minor versions of adapter module firmware.	-

55 FBA B data in	Selection of data to be transferred from drive to fieldbus controller through fieldbus adapter B.	
55.01 FBA B data in1	Parameters 55.0155.12 select data to be transferred from the drive to the fieldbus controller through fieldbus adapter B.	None
None	None.	0
CW 16bit	Control Word (16 bits)	1
Ref1 16bit	Reference REF1 (16 bits)	2
Ref2 16bit	Reference REF2 (16 bits)	3
SW 16bit	Status Word (16 bits)	4
Act1 16bit	Actual value ACT1 (16 bits)	5
Act2 16bit	Actual value ACT2 (16 bits)	6
CW 32bit	Control Word (32 bits)	11
Ref1 32bit	Reference REF1 (32 bits)	12
Ref2 32bit	Reference REF2 (32 bits)	13
SW 32bit	Status Word (32 bits)	14
Act1 32bit	Actual value ACT1 (32 bits)	15
Act2 32bit	Actual value ACT2 (32 bits)	16
SW2 16bit	Status Word 2 (16 bits)	24
Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
55.12 FBA B data in12	See parameter 55.01 FBA B data in1.	None

56 FBA B data out		Selection of data to be transferred from fieldbus controller to drive through fieldbus adapter B.	
56.01	FBA B data out1	Parameters 56.0156.12 select data to be transferred from the fieldbus controller to the drive through fieldbus adapter B.	None
	None	None.	0
	CW 16bit	Control Word (16 bits)	1
	Ref1 16bit	Reference REF1 (16 bits)	2
	Ref2 16bit	Reference REF2 (16 bits)	3

No.	Name/Value	Description	Def/FbEq16
	CW 32bit	Control Word (32 bits)	11
	Ref1 32bit	Reference REF1 (32 bits)	12
	Ref2 32bit	Reference REF2 (32 bits)	13
	CW2 16bit	Control Word 2 (16 bits)	21
	Other	Source selection (see <i>Terms and abbreviations</i> on page <i>131</i>).	-
56.12	FBA B data out12	See parameter 56.01 FBA B data out1.	None
58 Em	bedded fieldbus	Configuration of the embedded fieldbus (EFB) interface. See also chapter <i>Fieldbus control through the embedded fieldbus interface (EFB)</i> (page 589).	
58.01	Protocol enable	Enables/disables the embedded fieldbus interface and selects the protocol to use. Note: When the embedded fieldbus interface is enabled, the drive-to-drive link functionality is automatically disabled.	None
	None	None (communication disabled).	0
	Modbus RTU	Embedded fieldbus interface is enabled and uses the Modbus RTU protocol.	1
58.02	Protocol ID	Displays the protocol ID and revision. This parameter is read-only.	-
		Protocol ID and revision.	1 = 1
58.03	Node address	Defines the node address of the drive on the fieldbus link. Values 1247 are allowable. Two devices with the same address are not allowed on-line. Changes to this parameter take effect after the control unit is rebooted or the new settings validated by parameter 58.06 <i>Communication control</i> .	1
	0255	Node address (values 1247 are allowable).	1 = 1
58.04	Baud rate	Selects the transfer rate of the fieldbus link. Changes to this parameter take effect after the control unit is rebooted or the new settings validated by parameter 58.06 <i>Communication control</i> .	19.2 kbps
	9.6 kbps	9.6 kbit/s.	2
	19.2 kbps	19.2 kbit/s.	3
	38.4 kbps	38.4 kbit/s.	4
	57.6 kbps	57.6 kbit/s.	5
	76.8 kbps	76.8 kbit/s.	6
	115.2 kbps	115.2 kbit/s.	7
58.05	Parity	Selects the type of parity bit, and number of stop bits. Changes to this parameter take effect after the control unit is rebooted or the new settings validated by parameter 58.06 <i>Communication control</i> .	8 EVEN 1
	8 NONE 1	Eight data bits, no parity bit, one stop bit.	0
	8 NONE 2	Eight data bits, no parity bit, two stop bits.	1
	8 EVEN 1	Eight data bits, even parity bit, one stop bit.	2
	8 ODD 1	Eight data bits, odd parity bit, one stop bit.	3

No.	Name/	Value	Descriptio	on	Def/FbEq16
58.06	Communication control		Validates a mode.	any changes in the EFB settings, or activates silent	Enabled
	Enable	ed	Normal op	eration.	0
	Refres	h settings		any changed EFB configuration settings. Reverts ally to <i>Enabled</i> .	1
	Silent	mode	Silent mod	silent mode (no messages are transmitted). e can be terminated by activating the <i>Refresh</i> election of this parameter.	2
58.07	Comm diagno	unication stics		ne status of the EFB communication. neter is read-only.	-
	Bit	Name		Description	
	0	Init failed		1 = EFB initialization failed	
	1	Addr config	err	1 = Node address not allowed by protocol	
	2	Silent mode		1 = Drive not allowed to transmit	
	2 Silent mode		•	0 = Drive allowed to transmit	
	3	Autobaudin	a	1 = Drive attempting to determine transfer rate	
	4	Wiring error	-	1 = Errors detected (A/B wires possibly swapped)	
	5	Parity error		1 = Error detected: check parameters 58.04 and 58	8.05
	6	Baud rate e		1 = Error detected: check parameters 58.05 and 58.04	
	7	No bus acti		1 = 0 bytes received during last 5 seconds	5.04
	8	No packets		1 = 0 packets (addressed to any device) detected during last 5 seconds	
	9	Noise or addressing error		1 = Errors detected (interference, or another device with the same address on line)	
	10	Comm loss		1 = 0 packets addressed to the drive received within timeout (58.16)	
	11	CW/Ref los	S	1 = No control word or references received within timeout (58.16) Reserved	
	12	Not active			
	13	Protocol 1		Reserved	
	14	Protocol 2		Reserved	
	15	Internal erro	or	Reserved	
	0000h	FFFFh	EFB comm	nunication status.	1 = 1
58.08	During nor Can be res		During nor Can be res	count of valid packets addressed to the drive. mal operation, this number increases constantly. set from the control panel by keeping Reset for over 3 seconds.	-
	0429	94967295	Number of	received packets addressed to the drive.	1 = 1
58.09	During no Can be re		During nor Can be res	count of valid packets transmitted by the drive. mal operation, this number increases constantly. set from the control panel by keeping Reset for over 3 seconds.	-
	0429	94967295	Number of	transmitted packets.	1 = 1

No.	Name/Value	Description	Def/FbEq16
58.10	All packets	Displays a count of valid packets addressed to any device on the bus. During normal operation, this number increases constantly. Can be reset from the control panel by keeping Reset depressed for over 3 seconds.	-
	04294967295	Number of all received packets.	1 = 1
58.11	UART errors	Displays a count of character errors received by the drive. An increasing count indicates a configuration problem on the bus.Can be reset from the control panel by keeping Reset depressed for over 3 seconds.	-
	04294967295	Number of UART errors.	1 = 1
58.12	CRC errors	Displays a count of packets with a CRC error received by the drive. An increasing count indicates interference on the bus. Can be reset from the control panel by keeping Reset depressed for over 3 seconds.	-
	04294967295	Number of CRC errors.	1 = 1
58.14	Communication loss action	 Selects how the drive reacts to an EFB communication break. Changes to this parameter take effect after the control unit is rebooted or the new settings validated by parameter 58.06 <i>Communication control</i>. See also parameters 58.15 Communication loss mode and 58.16 Communication loss time. 	Fault
	No	No action taken (monitoring disabled).	0
	Fault	Drive trips on 6681 EFB comm loss. This only occurs if control is expected from the EFB (EFB selected as source of start/stop/reference in the currently active location), or if supervision is forced using parameter 58.36 EFB comm supervision force.	1
	Last speed	Drive generates an A7CE EFB comm loss warning and freezes the speed to the level the drive was operating at. This only occurs if control is expected from the EFB, or if supervision is forced using parameter 58.36 EFB comm supervision force.The speed is determined on the basis of actual speed using 850 ms low-pass filtering.Marning! Make sure that it is safe to continue operation in case of a communication break.	2
	Speed ref safe	Drive generates an A7CE EFB comm loss warning and setsthe speed to the speed defined by parameter 22.41 Speed refsafe. (or 28.41 Frequency ref safe when frequency referenceis being used). This only occurs if control is expected from theEFB, or if supervision is forced using parameter 58.36 EFBcomm supervision force.WARNING! Make sure that it is safe to continueoperation in case of a communication break.	3
	Fault always	Drive trips on 6681 EFB comm loss. This occurs even though no control is expected from the EFB.	4

No.	Name/Value	Description	Def/FbEq16
	Warning	Drive generates an A7CE EFB comm loss warning. This occurs even though no control is expected from the EFB, or if supervision is forced using parameter 58.36 EFB comm supervision force. WARNING! Make sure that it is safe to continue operation in case of a communication break.	5
58.15	Communication loss mode	Defines which message types reset the timeout counter for detecting an EFB communication loss. Changes to this parameter take effect after the control unit is rebooted or the new settings validated by parameter 58.06 <i>Communication control</i> . See also parameters 58.14 <i>Communication loss action</i> and 58.16 <i>Communication loss time</i> .	Cw / Ref1 / Ref2
	None	None (monitoring disabled).	0
	Any message	Any message addressed to the drive resets the timeout.	1
	Cw / Ref1 / Ref2	A write of the control word or a reference resets the timeout.	2
58.16	Communication loss time	Sets a timeout for EFB communication. If a communication break lasts longer than the timeout, the action specified by parameter 58.14 Communication loss action is taken. Changes to this parameter take effect after the control unit is rebooted or the new settings validated by parameter 58.06 Communication control. Note: There is a 30-second boot-up delay immediately after power-up. During the delay, the communication break monitoring is disabled (but communication itself can be active). See also parameter 58.15 Communication loss mode.	3.0 s
	0.0 6000.0 s	EFB communication timeout.	1 = 1
58.17	Transmit delay	Defines a minimum response delay in addition to any fixed delay imposed by the protocol. Changes to this parameter take effect after the control unit is rebooted or the new settings validated by parameter <i>58.06</i> <i>Communication control</i> .	0 ms
	065535 ms	Minimum response delay.	1 = 1
58.18	EFB control word	Displays the raw (unmodified) control word sent by the Modbus controller to the drive. For debugging purposes. This parameter is read-only.	-
	0000hFFFFh	Control word sent by Modbus controller to the drive.	1 = 1
58.19	EFB status word	Displays the raw (unmodified) status word sent by the drive to the Modbus controller. For debugging purposes. This parameter is read-only.	-
	0000hFFFFh	Status word sent by the drive to the Modbus controller.	1 = 1
58.25	Control profile	Defines the control profile used by the protocol.	ABB Drives
	ABB Drives	ABB Drives profile (with a 16-bit control word) with registers in the classic format for backward compatibility.	0
	Transparent	Transparent profile (16-bit or 32-bit control word) with registers in the classic format.	2

No.	Name/Value	Description	Def/FbEq16
58.26	EFB ref1 type	Selects the type and scaling of reference 1 received through the embedded fieldbus interface. The scaled reference is displayed by 03.09 <i>EFB</i> reference 1.	Auto
	Auto	Type and scaling are chosen automatically according to which reference chain (see settings <i>Torque</i> , <i>Speed</i> , <i>Frequency</i>) the incoming reference is connected to. If the reference is not connected to any chain, no scaling is applied (as with setting <i>Transparent</i>).	0
	Transparent	No scaling is applied.	1
	General	Generic reference with a scaling of 100 = 1 (ie. integer and two decimals).	2
	Torque	The scaling is defined by parameter 46.03 Torque scaling.	3
	Speed	The scaling is defined by parameter 46.01 Speed scaling.	4
	Frequency	The scaling is defined by parameter 46.02 Frequency scaling.	5
58.27	EFB ref2 type	 Selects the type and scaling of reference 2 received through the embedded fieldbus interface. The scaled reference is displayed by 03.10 EFB reference 2. For the selections, see parameter 58.26 EFB ref1 type. 	Torque
58.28	EFB act1 type	Selects the type/source and scaling of actual value 1 transmitted to the fieldbus network through the embedded fieldbus interface.	Auto
	Auto	Type/source and scaling follow the type of reference 1 selected by parameter 58.26 <i>EFB</i> ref1 type. See the individual settings below for the sources and scalings.	0
	Transparent	The value selected by parameter 58.31 EFB act1 transparent source is sent as actual value 1. No scaling is applied (the 16-bit scaling is 1 = 1 unit).	1
	General	The value selected by parameter 58.31 EFB act1 transparent source is sent as actual value 1 with a 16-bit scaling of 100 = 1 unit (ie. integer and two decimals).	2
	Torque	<i>01.10 Motor torque</i> is sent as actual value 1. The scaling is defined by parameter <i>46.03 Torque scaling</i> .	3
	Speed	01.01 Motor speed used is sent as actual value 1. The scaling is defined by parameter 46.01 Speed scaling.	4
	Frequency	01.06 Output frequency is sent as actual value 1. The scaling is defined by parameter 46.02 Frequency scaling.	5
	Position	Motor position is sent as actual value 1. See parameter 90.06 Motor position scaled.	6
58.29	EFB act2 type	Selects the type/source and scaling of actual value 2 transmitted to the fieldbus network through the embedded fieldbus interface.	Torque
	Auto	Type/source and scaling follow the type of reference 2 selected by parameter 58.27 <i>EFB ref2 type</i> . See the individual settings below for the sources and scalings.	0
	Transparent	The value selected by parameter 58.32 EFB act2 transparent source is sent as actual value 2. No scaling is applied (the 16-bit scaling is 1 = 1 unit).	1
	General	The value selected by parameter 58.32 EFB act2 transparent source is sent as actual value 2 with a 16-bit scaling of 100 = 1 unit (ie. integer and two decimals).	2

No.	Name/Value	Description	Def/FbEq16
	Torque	<i>01.10 Motor torque</i> is sent as actual value 2. The scaling is defined by parameter <i>46.03 Torque scaling</i> .	3
	Speed	<i>01.01 Motor speed used</i> is sent as actual value 2. The scaling is defined by parameter <i>46.01 Speed scaling</i> .	4
	Frequency	<i>01.06 Output frequency</i> is sent as actual value 2. The scaling is defined by parameter <i>46.02 Frequency scaling</i> .	5
	Position	Motor position is sent as actual value 2. See parameter 90.06 Motor position scaled.	6
58.30	EFB status word transparent source	Selects the source of the status word when 58.25 Control profile is set to Transparent.	Not selected
	Not selected	None.	0
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
58.31	EFB act1 transparent source	Selects the source of actual value 1 when 58.28 EFB act1 type is set to Transparent or General.	Not selected
	Not selected	None.	0
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
58.32	EFB act2 transparent source	Selects the source of actual value 1 when 58.29 EFB act2 type is set to Transparent or General.	Not selected
	Not selected	None.	0
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
58.33	Addressing mode	Defines the mapping between parameters and holding registers in the 400101465535 Modbus register range. Changes to this parameter take effect after the control unit is rebooted or the new settings validated by parameter 58.06 <i>Communication control</i> .	Mode 0
	Mode 0	<u>16-bit values (groups 199, indexes 199)</u> : Register address = 400000 + 100 × parameter group + parameter index. For example, parameter 22.80 would be mapped to register 400000 + 2200 + 80 = 402280. <u>32-bit values (groups 199, indexes 199)</u> : Register address = 420000 + 200 × parameter group + 2 × parameter index. For example, parameter 22.80 would be mapped to register 420000 + 4400 + 160 = 424560.	0
	Mode 1	<u>16-bit values (groups 1255, indexes 1255)</u> : Register address = 400000 + 256 × parameter group + parameter index. For example, parameter 22.80 would be mapped to register 400000 + 5632 + 80 = 405712.	1
	Mode 2	<u>32-bit values (groups 1127, indexes 1255)</u> : Register address = 400000 + 512 × parameter group + 2 × parameter index. For example, parameter 22.80 would be mapped to register 400000 + 11264 + 160 = 411424.	2
58.34	Word order	Selects in which order 16-bit registers of 32-bit parameters are transfered. For each register, the first byte contains the high order byte and the second byte contains the low order byte. Changes to this parameter take effect after the control unit is rebooted or the new settings validated by parameter 58.06 <i>Communication control</i> .	LO-HI
	HI-LO	The first register contains the high order word, the second contains the low order word.	0

No.	Name/\	/alue	Description	Def/FbEq16
	LO-HI		The first register contains the low order word, the second contains the high order word.	1
58.36	EFB co supervi	mm sion force	Activates fieldbus communication monitoring separately for each control location (see section <i>Local control vs. external</i> <i>control</i> on page 54). The parameter is primarily intended for monitoring the communication with EFB when it is connected to the application program and not selected as a control source by drive parameters.	0000b
	Bit	Name	Value	
	0	Ext 1	1 = Communication monitoring active when Ext 1 is be	eing used.
	1	Ext 2	1 = Communication monitoring active when Ext 2 is be	eing used.
	2	Local	 1 = Communication monitoring active when local contr used. 	ol is being
	315	Reserved		
	. <u> </u>	•		
	0000b.	0111b	EFB communication monitoring selection.	1 = 1
58.101	Data I/O 1		Defines the address in the drive which the Modbus master accesses when it reads from or writes to register address 400001. The master defines the type of the data (input or output). The value is transmitted in a Modbus frame consisting of two 16- bit words. If the value is 16-bit, it is transmitted in the LSW (least significant word). If the value is 32-bit, the subsequent parameter is also reserved for it and must be set to <i>None</i> .	CW 16bit
	None		None.	0
	CW 16	oit	Control Word (16 bits).	1
	Ref1 16	Sbit	Reference REF1 (16 bits).	2
	Ref2 16	Sbit	Reference REF2 (16 bits).	3
	SW 16t	oit	Status Word (16 bits).	4
	Act1 16	bit	Actual value ACT1 (16 bits).	5
	Act2 16	bit	Actual value ACT2 (16 bits).	6
	CW 32	oit	Control Word (32 bits).	11
	Ref1 32	2bit	Reference REF1 (32 bits).	12
	Ref2 32	2bit	Reference REF2 (32 bits).	13
	SW 32t	oit	Status Word (32 bits).	14
	Act1 32	bit	Actual value ACT1 (32 bits).	15
	Act2 32	bit	Actual value ACT2 (32 bits).	16
	CW2 16	3bit	Control Word 2 (16 bits). When a 32-bit control word is used, this setting means the most-significant 16 bits.	21
	SW2 16	Sbit	Status Word 2 (16 bits). When a 32-bit control word is used, this setting means the most-significant 16 bits.	24
	RO/DIC word) control	Parameter 10.99 RO/DIO control word.	31
	AO1 da	ita storage	Parameter 13.91 AO1 data storage.	32

No.	Name/Value	Description	Def/FbEq16
	AO2 data storage	Parameter 13.92 AO2 data storage.	33
	Feedback data storage	Parameter 40.91 Feedback data storage.	40
	Setpoint data storage	Parameter 40.92 Setpoint data storage.	41
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
58.102	Data I/O 2	Defines the address in the drive which the Modbus master accesses when it reads from or writes to register address 400002. For the selections, see parameter <i>58.101 Data I/O 1</i> .	Ref1 16bit
58.103	Data I/O 3	Defines the address in the drive which the Modbus master accesses when it reads from or writes to register address 400003. For the selections, see parameter <i>58.101 Data I/O 1</i> .	Ref2 16bit
58.104	Data I/O 4	Defines the address in the drive which the Modbus master accesses when it reads from or writes to register address 400004. For the selections, see parameter 58.101 Data I/O 1.	SW 16bit
58.105	Data I/O 5	Defines the address in the drive which the Modbus master accesses when it reads from or writes to register address 400005. For the selections, see parameter 58.101 Data I/O 1.	Act1 16bit
58.106	Data I/O 6	Defines the address in the drive which the Modbus master accesses when it reads from or writes to register address 400006. For the selections, see parameter <i>58.101 Data I/O 1</i> .	Act2 16bit
58.107	Data I/O 7	Parameter selector for Modbus register address 400007. For the selections, see parameter <i>58.101 Data I/O 1</i> .	None
58.124	Data I/O 24	Parameter selector for Modbus register address 400024. For the selections, see parameter 58.101 Data I/O 1.	None
60 DD comm	CS unication	 DDCS communication configuration. The DDCS protocol is used in the communication between drives in a master/follower configuration (see page 64), the drive and an external controller such as the AC 800M (see page 71), or the drive (or more precisely, an inverter unit) and the supply unit of the drive system (see page 73). All of the above utilize a fiber optic link which also requires an FDCO module (typically with ZCU control units) or an RDCO module (with BCU control units). Master/follower and external controller communication can also be implemented through shielded twisted-pair cable connected to the XD2D connector of the drive. This group also contains parameters for drive-to-drive (D2D) communication supervision. 	
60.01	M/F communication port	Selects the connection used by the master/follower functionality.	Not in use
	Not in use	None (communication disabled).	0
	Slot 1A	Channel A on FDCO module in slot 1 (with ZCU control unit only).	1

No.	Name/Value	Description	Def/FbEq16
	Slot 2A	Channel A on FDCO module in slot 2 (with ZCU control unit only).	2
	Slot 3A	Channel A on FDCO module in slot 3 (with ZCU control unit only).	3
	Slot 1B	Channel B on FDCO module in slot 1 (with ZCU control unit only).	4
	Slot 2B	Channel B on FDCO module in slot 2 (with ZCU control unit only).	5
	Slot 3B	Channel B on FDCO module in slot 3 (with ZCU control unit only).	6
	XD2D	Drive-to-drive link. Note : This connection cannot co-exist, and is not to be confused with, drive-to-drive (D2D) communication implemented by application programming (detailed in Drive application programming manual (IEC 61131-3), 3AUA0000127808 [English]).	7
	RDCO CH 2	Channel 2 on RDCO module (with BCU control unit only).	12
60.02	M/F node address	Selects the node address of the drive for master/follower communication. No two nodes on-line may have the same address. Note: The allowable addresses for the master are 0 and 1. The allowable addresses for followers are 260.	1
	1254	Node address.	
60.03	M/F mode	Defines the role of the drive on the master/follower or drive-to-drive link.	Not in use
	Not in use	Master/follower functionality not active.	0
	DDCS master	The drive is the master on the master/follower (DDCS) link.	1
	DDCS follower	The drive is a follower on the master/follower (DDCS) link.	2
	D2D master	The drive is the master on the drive-to-drive (D2D) link. Note : This setting is only to be used with D2D communication implemented by application programming. If you are using the master/follower functionality (see page 64) through the XD2D connector, select <i>DDCS master</i> instead.	3
	D2D follower	The drive is a follower on the drive-to-drive (D2D) link. Note : This setting is only to be used with D2D communication implemented by application programming. If you are using the master/follower functionality (see page 64) through the XD2D connector, select <i>DDCS follower</i> instead.	4
	DDCS forcing	The role of the drive on the master/follower (DDCS) link is defined by parameters 60.15 Force master and 60.16 Force follower.	5
	D2D forcing	The role of the drive on the drive-to-drive (D2D) link is defined by parameters 60.15 Force master and 60.16 Force follower. Note: This setting is only to be used with D2D communication implemented by application programming. If you are using the master/follower functionality (see page 64) through the XD2D connector, select <i>DDCS forcing</i> instead.	6

No.	Name/Value	Description	Def/FbEq16
60.05	M/F HW connection	Selects the topology of the master/follower link. Note: Use the setting <i>Star</i> if using the master/follower functionality (see page 64) through the XD2D connector (as opposed to a fiber optic link).	Ring
	Ring	The devices are connected in a ring topology. Forwarding of messages is enabled.	0
	Star	The devices are connected in a star topology (for example, through a branching unit). Forwarding of messages is disabled.	1
60.07	M/F link control	Defines the light intensity of the transmission LED of RDCO module channel CH2. (This parameter is effective only when parameter 60.01 <i>M/F communication port</i> is set to <i>RDCO CH</i> 2. FDCO modules have a hardware transmitter current selector.) Master/follower and external controller communication can also be implemented through shielded twisted-pair cable connected to the XD2D connector of the drive.	10
	115	Light intensity.	
60.08	M/F comm loss timeout	Sets a timeout for master/follower (DDCS) communication. If a communication break lasts longer than the timeout, the action specified by parameter <i>60.09 M/F comm loss function</i> is taken. As a rule of thumb, this parameter should be set to at least 3 times the transmit interval of the master.	100 ms
	065535 ms	Master/follower communication timeout.	
60.09	M/F comm loss function	Selects how the drive reacts to a master/follower communication break.	Fault
	No action	No action taken.	0
	Warning	The drive generates an <i>A7CB MF comm loss</i> warning. This only occurs if control is expected from the master/follower link, or if supervision is forced using parameter <i>60.32 M/F comm supervision force</i> . WARNING! Make sure that it is safe to continue operation in case of a communication break.	1
	Fault	Drive trips on 7582 MF comm loss.	2
	Fault always	Drive trips on 7582 <i>MF comm loss</i> . This occurs even though no control is expected from the master/follower link.	3
60.10	M/F ref1 type	Selects the type and scaling of reference 1 received from the master/follower link. The resulting value is shown by 03.13 <i>M/F</i> or D2D ref1.	Auto
	Auto	Type and scaling are chosen automatically according to which reference chain (see settings <i>Torque</i> , <i>Speed</i> , <i>Frequency</i>) the incoming reference is connected to. If the reference is not connected to any chain, no scaling is applied (as with setting <i>Transparent</i>).	0
	Transparent	No scaling is applied.	1
	General	Generic reference with a scaling of 100 = 1 (ie. integer and two decimals).	2
	Torque	The scaling is defined by parameter 46.03 Torque scaling.	3
	Speed	The scaling is defined by parameter 46.01 Speed scaling.	4
	Frequency	The scaling is defined by parameter 46.02 Frequency scaling.	5

No.	Name/Value	Description	Def/FbEq16
60.11	M/F ref2 type	Selects the type and scaling of reference 2 received from the master/follower link. The resulting value is shown by 03.14 <i>M/F or D2D ref2</i> . For the selections, see parameter 60.10 <i>M/F ref1 type</i> .	Torque
60.12	M/F act1 type	Selects the type/source and scaling of actual value ACT1 transmitted to the master/follower link.	Auto
	Auto	Type/source and scaling follow the type of reference 1 selected by parameter <i>60.10 M/F ref1 type</i> . See the individual settings below for the sources and scalings.	0
	Transparent	Reserved.	1
	General	Reserved.	2
	Torque	<i>01.10 Motor torque</i> is sent as actual value 1. The scaling is defined by parameter <i>46.03 Torque scaling</i> .	3
	Speed	<i>01.01 Motor speed used</i> is sent as actual value 1. The scaling is defined by parameter <i>46.01 Speed scaling</i> .	4
	Frequency	<i>01.06 Output frequency</i> is sent as actual value 1. The scaling is defined by parameter <i>46.02 Frequency scaling</i> .	5
60.13	<i>M/F act2 type</i>	Selects the type/source and scaling of actual value ACT2 transmitted to the master/follower link.	Auto
	Auto	Type/source and scaling follow the type of reference 2 selected by parameter 60.11 M/F ref2 type. See the individual settings below for the sources and scalings.	0
	Transparent	Reserved.	1
	General	Reserved.	2
	Torque	<i>01.10 Motor torque</i> is sent as actual value 2. The scaling is defined by parameter <i>46.03 Torque scaling</i> .	3
	Speed	<i>01.01 Motor speed used</i> is sent as actual value 2. The scaling is defined by parameter <i>46.01 Speed scaling</i> .	4
	Frequency	<i>01.06 Output frequency</i> is sent as actual value 2. The scaling is defined by parameter <i>46.02 Frequency scaling</i> .	5
60.14	M/F follower selection	(Effective in the master only.) Defines the followers from which data is read. See also parameters 62.2862.33.	None
	Follower node 2	Data is read from the follower with node address 2.	2
	Follower node 3	Data is read from the follower with node address 3.	4
	Follower node 4	Data is read from the follower with node address 4.	8
	Follower nodes 2+3	Data is read from the followers with node addresses 2 and 3.	6
	Follower nodes 2+4	Data is read from the followers with node addresses 2 and 4.	10
	Follower nodes 3+4	Data is read from the followers with node addresses 3 and 4.	12
	Follower nodes 2+3+4	Data is read from the followers with node addresses 2, 3 and 4.	14
	None	None.	0
60.15	Force master	When parameter 60.03 <i>M/F mode</i> is set to <i>DDCS forcing</i> or <i>D2D forcing</i> , this parameter selects a source that forces the drive to be the master on the master/follower link. 1 = Drive is master on the master/follower link	FALSE
	FALSE	0.	0
	TRUE	1.	1
	Other [bit]	Source selection (see Terms and abbreviations on page 131).	-

No.	Name/Value	Description	Def/FbEq16
60.16	Force follower	When parameter 60.03 <i>M/F mode</i> is set to <i>DDCS forcing</i> or <i>D2D forcing</i> , this parameter selects a source that forces the drive to be a follower on the master/follower link. 1 = Drive is follower on the master/follower link	FALSE
	FALSE	0.	0
	TRUE	1.	1
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
60.17	Follower fault action	(Effective in the master only.) Selects how the drive reacts to a fault in a follower. See also parameter 60.23 <i>M/F status supervision sel 1</i> . Note: Each follower must be configured to transmit its status word as one of the three data words in parameters 61.0161.03. In the master, the corresponding target parameter (62.0462.12) must be set to <i>Follower SW</i> .	Fault
	No action	No action taken. Unaffected drives on the master/follower link will continue running.	0
	Warning	The drive generates a warning (AFE7 Follower).	1
	Fault	Drive trips on <i>FF7E Follower</i> . All followers will be stopped.	2
60.18	Follower enable	Interlocks the starting of the master to the status of the followers. Note: Each follower must be configured to transmit its status word as one of the three data words in parameters $61.0161.03$. In the master, the corresponding target parameter ($62.0462.12$) must be set to Follower SW.	Always
	MSW bit 0	The master can only be started if all followers are ready to switch on (bit 0 of <i>06.11 Main status word</i> in each follower is on).	0
	MSW bit 1	The master can only be started if all followers are ready to operate (bit 1 of <i>06.11 Main status word</i> in each follower is on).	1
	MSW bits 0 + 1	The master can only be started if all followers are ready to switch on and ready to operate (bits 0 and 1 of <i>06.11 Main status word</i> in each follower are on).	2
	Always	The starting of the master is not interlocked to the status of the followers.	3
	MSW bit 12	The master can only be started if user-definable bit 12 of 06.11 Main status word in each follower is on. See parameter 06.31 MSW bit 12 sel.	4
	MSW bits 0 + 12	The master can only be started if both bit 0 and bit 12 of 06.11 Main status word in each follower are on.	5
	MSW bits 1 + 12	The master can only be started if both bit 1 and bit 12 of 06.11 Main status word in each follower are on.	6

No.	Name/Value	Desc	ription		Def/FbEq16
60.19	<i>M/F comm</i> supervision sel 1	the m applie comm (IEC (3AU) In the and 6 that a This p 116 by the 60.09 The s	naster on a D2 cation program <i>nunication por</i> 61131-3) appli A0000127808 e master, parar 60.20 <i>M/F com</i> are monitored f parameter sele 6) are monitore e master. If no 0 <i>M/F comm lo</i> status of comm	.60.28 are only effective when the drive is D (drive-to-drive) link, implemented by ming. See parameters 60.01 <i>M/F</i> t and 60.03 <i>M/F mode</i> , and Drive cation programming manual [English]). meters 60.19 <i>M/F comm supervision sel 1</i> <i>m supervision sel 2</i> specify the followers for loss of communication. ects which followers (out of followers ed. Each of the selected followers is polled reply is received, the action specified in <i>ss function</i> is taken. hunication is shown by 62.37 <i>M/F</i> <i>tus 1</i> and 62.38 <i>M/F communication status</i>	-
		Bit	Name	Description	
		0	Follower 1	1 = Follower 1 is polled by the master.	
		1	Follower 2	1 = Follower 2 is polled by the master.	
		 15	 Follower 16		
		15	Follower To	1 = Follower 16 is polled by the master.	
	0000hFFFFh	1 = 1			
60.20	<i>M/F comm</i> supervision sel 2	monit		vers (out of followers 1732) are of communication. See parameter <i>60.19</i> <i>sion sel 1</i> .	-
		Bit	Name	Description	
		0	Follower 17	1 = Follower 17 is polled by the master.	
		1	Follower 18	1 = Follower 18 is polled by the master.	
		15	Follower 32	1 = Follower 32 is polled by the master.	
	0000hFFFFh	Selec	ction of followe	rs for D2D communication supervision (2).	1 = 1

No.	Name/Value	Description	Def/FbEq16
60.23	<i>M/F status</i> <i>supervision sel 1</i>	 (This parameter is only effective when the drive is the master on a D2D link. See parameters 60.01 <i>M/F communication port</i> and 60.03 <i>M/F mode</i>.) In the master, parameters 60.23 <i>M/F status supervision sel</i> 1 and 60.24 <i>M/F status supervision sel</i> 2 specify the followers whose status word is monitored by the master. This parameter selects the followers (out of followers 116) whose status words are monitored by the master. If a follower reports a fault (bit 3 of the status word is on), the action specified in 60.17 <i>Follower fault action</i> is taken. Bits 0 and 1 of the status word (ready states) are handled as defined by 60.18 <i>Follower enable</i>. Using 60.27 <i>M/F status supv mode sel</i> 1 and 60.28 <i>M/F status supv mode sel</i> 2, it is possible to define whether any given follower is only monitored when it is stopped. Note: Also activate communication supervision for the same followers in parameter 60.19 M/F comm supervision sel 1. The status of communication is shown by 62.37 <i>M/F communication status</i> 1 and 62.38 <i>M/F communication status</i> 2. 	-
		Bit Name Description	
		0Follower 11 = Status of follower 1 is monitored.1Follower 21 = Status of follower 2 is monitored15Follower 161 = Status of follower 16 is monitored.	
	0000hFFFFh	D2D follower status supervision selection (followers 116).	1 = 1
60.24	<i>M/F status</i> supervision sel 2	Selects the followers (out of followers 1732) whose status words are monitored by the D2D master. Note: Also activate communication supervision for the same followers in parameter 60.20 M/F comm supervision sel 2. See parameter 60.23 M/F status supervision sel 1. Bit Name Description 0 Follower 17 1 Status of follower 17 is monitored.	-
		1 Follower 18 1 = Status of follower 18 is monitored. 15 Follower 32 1 = Status of follower 32 is monitored.	
	0000hFFFFh	D2D follower status supervision selection (followers 1732).	1 = 1

	Name	/Value	Description	Def/FbEq16
60.27	M/F status supv mode sel 1		In the D2D master, parameters 60.27 <i>M/F status supv mode</i> <i>sel 1</i> and 60.28 <i>M/F status supv mode sel 2</i> specify the mode of follower status word monitoring. Each follower can individually be set to be monitored continuously, or only when it is in stopped state. This parameter selects the mode of status word monitoring of followers 116.	-
	Bit	Name	Description	
	0	Follower 1	0 = Status of follower 1 is monitored continuously. 1 = Status of follower 1 is monitored only when it is in stopped	state.
	1	Follower 2	0 = Status of follower 2 is monitored continuously.1 = Status of follower 2 is monitored only when it is in stopped	state.
	 15 Follower 16		 0 = Status of follower 16 is monitored continuously. 1 = Status of follower 16 is monitored only when it is in stopped 	l state.
	0000h	FFFFh	D2D status supervision mode selection 1.	1 = 1
60.28	M/F s mode	tatus supv sel 2	Selects the mode of status word monitoring of followers 1732.	-
	Bit	Name	Description	
	Bit 0	Name Follower 17	Description0 = Status of follower 17 is monitored continuously.1 = Status of follower 17 is monitored only when it is in stopped	d state.
	_		0 = Status of follower 17 is monitored continuously.	
	0 1	Follower 17 Follower 18	 0 = Status of follower 17 is monitored continuously. 1 = Status of follower 17 is monitored only when it is in stopped 0 = Status of follower 18 is monitored continuously. 1 = Status of follower 18 is monitored only when it is in stopped 	
	0	Follower 17	 0 = Status of follower 17 is monitored continuously. 1 = Status of follower 17 is monitored only when it is in stopped 0 = Status of follower 18 is monitored continuously. 	d state.
	0 1 15	Follower 17 Follower 18	 0 = Status of follower 17 is monitored continuously. 1 = Status of follower 17 is monitored only when it is in stopped 0 = Status of follower 18 is monitored continuously. 1 = Status of follower 18 is monitored only when it is in stopped 0 = Status of follower 32 is monitored continuously. 	d state.
60.31	0 1 15 0000h	Follower 17 Follower 18 Follower 32	 0 = Status of follower 17 is monitored continuously. 1 = Status of follower 17 is monitored only when it is in stopped 0 = Status of follower 18 is monitored continuously. 1 = Status of follower 18 is monitored only when it is in stopped 0 = Status of follower 32 is monitored continuously. 1 = Status of follower 32 is monitored only when it is in stopped 	d state. d state.

No.	Name/\	/alue	Description	Def/FbEq16
60.32	M/F cor supervi	mm sion force	Activates master/follower communication monitoring separately for each control location (see section <i>Local control</i> <i>vs. external control</i> on page 54). The parameter is primarily intended for monitoring the communication with master or follower when it is connected to the application program and not selected as a control source by drive parameters.	0000b
	Bit	Name	Value	
	0	Ext 1	1 = Communication monitoring active when Ext 1 is be	ing used.
	1	Ext 2	1 = Communication monitoring active when Ext 2 is be	-
	2	Local	1 = Communication monitoring active when local contru- used.	ol is being
	315	Reserved		
	0000b.	.0111b	Master/follower communication monitoring selection.	1 = 1
60.41	Extension adapter com port		Selects the channel used for connecting an optional FEA-xx extension adapter.	No connect
	No connect		None (communication disabled).	0
	Slot 1A		Channel A on FDCO module in slot 1.	1
	Slot 2A		Channel A on FDCO module in slot 2.	2
	Slot 3A		Channel A on FDCO module in slot 3.	3
	Slot 1B		Channel B on FDCO module in slot 1.	4
	Slot 2B		Channel B on FDCO module in slot 2.	5
	Slot 3B		Channel B on FDCO module in slot 3.	6
	RDCO	CH 3	Channel CH 3 on RDCO module (with BCU control unit only).	13
60.50	DDCS o drive ty	controller pe	In ModuleBus communication, defines whether the drive is of the "engineered" or "standard" type.	ABB engineered drive
	ABB en drive	gineered	The drive is an "engineered drive" (data sets 1025 are used).	0
	ABB sta	andard drive	The drive is a "standard drive" (data sets 14 are used).	1
60.51	DDCS o comm p	controller port	Selects the DDCS channel used for connecting an external controller (such as an AC 800M).	Not in use
	Not in u	se	None (communication disabled).	0
	Slot 1A		Channel A on FDCO module in slot 1.	1
	Slot 2A		Channel A on FDCO module in slot 2.	2
	Slot 3A		Channel A on FDCO module in slot 3.	3
	Slot 1B		Channel B on FDCO module in slot 1.	4
	Slot 2B		Channel B on FDCO module in slot 2.	5
	Slot 3B		Channel B on FDCO module in slot 3.	6
	XD2D		Connector XD2D.	7
	RDCO	CH 0	Channel 0 on RDCO module (with BCU control unit only).	10

No.	Name/Value	Description	Def/FbEq16
60.52	DDCS controller node address	 Selects the node address of the drive for communication with the external controller. No two nodes on-line may have the same address. With an AC 800M (CI858) DriveBus connection, drives must be addressed 124. With an AC 80 DriveBus connection, drives must be addressed 112. With optical ModuleBus, the drive address is set according to the position value as follows: 1. Multiply the hundreds of the position value by 16. 2. Add the tens and ones of the position value to the result. For example, if the position value is 101, this parameter must be set to 1×16 + 1 = 17. 	1
	1254	Node address.	
60.55	DDCS controller HW connection	Selects the topology of the fiber optic link with an external controller.	Star
	Ring	The devices are connected in a ring topology. Forwarding of messages is enabled.	0
	Star	The devices are connected in a star topology (for example, through a branching unit). Forwarding of messages is disabled.	1
60.56	DDCS controller baud rate	Selects the communication speed of the channel selected by parameter <i>60.51 DDCS controller comm port</i> .	4 mbps
	1 mbps	1 megabit/second.	1
	2 mbps	2 megabit/second.	2
	4 mbps	4 megabit/second.	4
	8 mbps	8 megabit/second.	8
60.57	DDCS controller link control	 Defines the light intensity of the transmission LED of RDCO module channel CH0. (This parameter is effective only when parameter 60.51 DDCS controller comm port is set to RDCO CH 0. FDCO modules have a hardware transmitter current selector.) In general, use higher values with longer fiber optic cables. The maximum setting is applicable to the maximum length of the fiber optic link. See Specifications of the master/follower link (page 70). 	10
	115	Light intensity.	
			L

No.	Name/Value	Description	Def/FbEq16
60.58	DDCS controller comm loss time	 Sets a timeout for communication with the external controller. If a communication break lasts longer than the timeout, the action specified by parameter 60.59 DDCS controller comm loss function is taken. As a rule of thumb, this parameter should be set to at least 3 times the transmit interval of the controller. Notes: There is a 60-second boot-up delay immediately after power-up. During the delay, the communication break monitoring is disabled (but communication break monitoring is disabled (but communication itself can be active). With an AC 800M controller, the controller detects a communication break immediately but re-establishing the communication is done at 9-second idle intervals. Also note that the sending interval of a data set is not the same as the execution interval of the application task. On ModuleBus, the sending interval is defined by controller parameter <i>Scan Cycle Time</i> (by default, 100 ms). 	100 ms
	060000 ms	Timeout for communication with external controller.	
60.59	DDCS controller comm loss function	Selects how the drive reacts to a communication break between the drive and the external controller.	Fault
	No action	No action taken (monitoring disabled).	0
	Fault	Drive trips on 7581 DDCS controller comm loss. This only occurs if control is expected from the external controller, or if supervision is forced using parameter 60.65 DDCS controller comm supervision force.	1
	Last speed	Drive generates an A7CA DDCS controller comm losswarning and freezes the speed to the level the drive wasoperating at. This only occurs if control is expected from theexternal controller.The speed is determined on the basis of actual speed using850 ms low-pass filtering.WARNING! Make sure that it is safe to continueoperation in case of a communication break.	2
	Speed ref safe	Drive generates an A7CA DDCS controller comm loss warning and sets the speed to the speed defined by parameter 22.41 Speed ref safe (or 28.41 Frequency ref safe when frequency reference is being used). This only occurs if control is expected from the external controller, or if supervision is forced using parameter 60.65 DDCS controller comm supervision force. WARNING! Make sure that it is safe to continue operation in case of a communication break.	3
	Fault always	Drive trips on 7581 DDCS controller comm loss. This occurs even though no control is expected from the external controller.	4
	Warning	Drive generates an A7CA DDCS controller comm loss warning. This occurs even though no control is expected from the external controller, or if supervision is forced using parameter 60.65 DDCS controller comm supervision force. WARNING! Make sure that it is safe to continue operation in case of a communication break.	5

No.	Name/Value	Description	Def/FbEq16
60.60	DDCS controller ref1 type	Selects the type and scaling of reference 1 received from the external controller. The resulting value is shown by 03.11 DDCS controller ref 1.	Auto
	Auto	Type and scaling are chosen automatically according to which reference chain (see settings <i>Torque</i> , <i>Speed</i> , <i>Frequency</i>) the incoming reference is connected to. If the reference is not connected to any chain, no scaling is applied (as with setting <i>Transparent</i>).	0
	Transparent	No scaling is applied.	1
	General	Generic reference with a scaling of 100 = 1 (ie. integer and two decimals).	2
	Torque	The scaling is defined by parameter 46.03 Torque scaling.	3
	Speed	The scaling is defined by parameter 46.01 Speed scaling.	4
	Frequency	The scaling is defined by parameter 46.02 Frequency scaling.	5
60.61	DDCS controller ref2 type	Selects the type and scaling of reference 2 received from the external controller. The resulting value is shown by 03.12 DDCS controller ref 2. For the selections, see parameter 60.60 DDCS controller ref1 type.	Auto
60.62	DDCS controller act1 type	Selects the type/source and scaling of actual value ACT1 transmitted to the external controller.	Auto
	Auto	Type/source and scaling follow the type of reference 1 selected by parameter 60.60 DDCS controller ref1 type. See the individual settings below for the sources and scalings.	0
	Transparent	Reserved.	1
	General	Reserved.	2
	Torque	<i>01.10 Motor torque</i> is sent as actual value 1. The scaling is defined by parameter <i>46.03 Torque scaling</i> .	3
	Speed	01.01 Motor speed used is sent as actual value 1. The scaling is defined by parameter 46.01 Speed scaling.	4
	Frequency	<i>01.06 Output frequency</i> is sent as actual value 1. The scaling is defined by parameter <i>46.02 Frequency scaling</i> .	5
60.63	DDCS controller act2 type	Selects the type/source and scaling of actual value ACT2 transmitted to the external controller.	Auto
	Auto	Type/source and scaling follow the type of reference 2 selected by parameter 60.61 DDCS controller ref2 type. See the individual settings below for the sources and scalings.	0
	Transparent	Reserved.	1
	General	Reserved.	2
	Torque	<i>01.10 Motor torque</i> is sent as actual value 2. The scaling is defined by parameter <i>46.03 Torque scaling</i> .	3
	Speed	01.01 Motor speed used is sent as actual value 2. The scaling is defined by parameter 46.01 Speed scaling.	4
	Frequency	01.06 Output frequency is sent as actual value 2. The scaling is defined by parameter 46.02 Frequency scaling.	5
60.64	Mailbox dataset selection	Selects the pair of data sets used by the mailbox service in the drive/controller communication. See section <i>External controller interface</i> (page 71).	Dataset 32/33
	Dataset 32/33	Data sets 32 and 33.	0

No.	Name/\	/alue	Description	Def/FbEq16
	Dataset	24/25	Data sets 24 and 25.	1
60.65		controller supervision	Activates DDCS controller communication monitoring separately for each control location (see section <i>Local control vs. external control</i> on page <i>54</i>). The parameter is primarily intended for monitoring the communication with the controller when it is connected to the application program and not selected as a control source by drive parameters.	
	Bit	Name	Value	
	0	Ext 1	1 = Communication monitoring active when Ext 1 is b	eing used.
	1	Ext 2	1 = Communication monitoring active when Ext 2 is b	eing used.
	2	Local	1 = Communication monitoring active when local con used.	trol is being
	315	Reserved		
		•		
	0000b		DDCS controller communication monitoring selection.	1 = 1
60.71	INU-LS commu	U nication port	<i>(Only visible when supply unit control activated by 95.20)</i> Selects the DDCS channel used for connecting to another converter (such as a supply unit). The selections available, as well as the default, depend on drive hardware. See also section <i>Control of a supply unit (LSU)</i> (page 73).	See text
	Not in u	se	None (communication disabled).	0
	RDCO (CH 1	Channel 1 on RDCO module.	11
	DDCS v	via BC	Connector X201.	15
60.77	INU-LS control	U link	(Only visible when supply unit control activated by 95.20) Defines the light intensity of the transmission LED of RDCO module channel CH1. (This parameter is effective only when parameter 60.71 INU-LSU communication port is set to RDCO CH 1. FDCO modules have a hardware transmitter current selector.) In general, use higher values with longer fiber optic cables. The maximum setting is applicable to the maximum length of the fiber optic link. See Specifications of the master/follower link (page 70).	
	115		Light intensity.	
60.78	INU-LS loss tim	U comm eout	<i>(Only visible when supply unit control activated by 95.20)</i> Sets a timeout for communication with another converter (such as the supply unit). If a communication break lasts longer than the timeout, the action specified by parameter <i>60.71 INU-LSU comm loss function</i> is taken.	100 ms
	06553	35 ms	Timeout for communication between converters.	
60.79	INU-LS loss fun	U comm ction	 (Only visible when supply unit control activated by 95.20) Selects how the inverter unit reacts to a communication break between the inverter unit and the other converter (typically the supply unit). WARNING! With settings other than <i>Fault</i>, the inverter unit will continue operating based on the status information that was last received from the other converter. Make sure this does not cause danger. 	
	No actio	n	No action taken.	0

No.	Name/Value	Description	Def/FbEq16
	Warning	The drive generates a warning (AF80 INU-LSU comm loss).	1
	Fault	Drive trips on 7580 INU-LSU comm loss.	2
	D and DDCS nit data	Defines the data sent to the DDCS link. See also parameter group 60 DDCS communication.	
61.01	M/F data 1 selection	Preselects the data to be sent as word 1 onto the master/follower link. See also parameter 61.25 M/F data 1 value and section Master/follower functionality (page 64).	Follower CW
	None	None.	0
	CW 16bit	Control Word (16 bits)	1
	SW 16bit	Status Word (16 bits)	4
	Act1 16bit	Actual value ACT1 (16 bits) Note: Using this setting to send a reference to the follower is not recommended as the source signal is filtered. Use the "reference" selections instead.	5
	Act2 16bit	Actual value ACT2 (16 bits) Note: Using this setting to send a reference to the follower is not recommended as the source signal is filtered. Use the "reference" selections instead.	6
	Follower CW	A word consisting of bits 011 of 06.01 Main control word and the bits selected by parameters 06.4506.48. Note: Bit 3 of the follower control word is kept on as long as the master is modulating, and when it switches to 0, the follower coasts to a stop.	27
	ACS800 System ctrl SW	A follower status word compatible with an ACS800 (System Control Program) master. With this setting, status word bit 0 is cleared whenever the run enable signal is missing.	28
	Used speed reference	24.01 Used speed reference (page 248).	6145
	Torque reference used	26.02 Torque reference used (page 264).	6658
	Torque reference act 5	26.75 Torque reference act 5 (page 270).	6731
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
61.02	M/F data 2 selection	Preselects the data to be sent as word 2 onto the master/follower link. See also parameter 61.26 M/F data 2 value. For the selections, see parameter 61.01 M/F data 1 selection.	Used speed reference
61.03	M/F data 3 selection	Preselects the data to be sent as word 3 onto the master/follower link. See also parameter 61.27 M/F data 3 value. For the selections, see parameter 61.01 M/F data 1 selection.	Torque reference act 5
61.25	<i>M/F data 1 value</i> 065535	Displays the data to be sent onto the master/follower link as word 1 as an integer. If no data has been preselected by 61.01 M/F data 1 selection, the value to be sent can be written directly into this parameter. Data to be sent as word 1 in master/follower communication.	0

No.	Name/Value	Description	Def/FbEq16
61.26	M/F data 2 value	Displays the data to be sent onto the master/follower link as word 2 as an integer. If no data has been preselected by 61.02 M/F data 2 selection, the value to be sent can be written directly into this parameter.	0
	065535	Data to be sent as word 2 in master/follower communication.	
61.27	<i>M/F data 3 value</i>	Displays the data to be sent onto the master/follower link as word 3 as an integer. If no data has been preselected by 61.03 M/F data 3 selection, the value to be sent can be written directly into this parameter.	0
	065535	Data to be sent as word 3 in master/follower communication.	
61.45	Data set 2 data 1 selection	Parameters $61.4561.50$ preselect data to be sent in data sets 2 and 4 to the external controller. These data sets are used in ModuleBus communication with a "standard drive" (60.50 DDCS controller drive type = ABB standard drive). Parameters $61.9561.100$ display the data to be sent to the external controller. If no data has been preselected, the value to be sent can be written directly into these parameters. For example, this parameter preselects the data for word 1 of data set 2. Parameter 61.95 Data set 2 data 1 value displays the selected data in integer format. If no data is preselected, the value to be sent can be written directly into parameter 61.95.	None
	None	None.	0
	CW 16bit	Control Word (16 bits)	1
	SW 16bit	Status Word (16 bits)	4
	Act1 16bit	Actual value ACT1 (16 bits)	5
	Act2 16bit	Actual value ACT2 (16 bits)	6
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
61.46	Data set 2 data 2 selection	Preselects the data to be sent as word 2 of data set 2 to the external controller. See also parameter 61.96 Data set 2 data 2 value. For the selections, see parameter 61.45 Data set 2 data 1 selection.	None
61.47	Data set 2 data 3 selection	See parameter 61.45 Data set 2 data 1 selection.	None
61.50	Data set 4 data 3 selection	See parameter 61.45 Data set 2 data 1 selection.	None
61.51	Data set 11 data 1 selection	Parameters 61.5161.74 preselect data to be sent in data sets 11, 13, 15, 17, 19, 21, 23 and 25 to the external controller. Parameters 61.10161.124 display the data to be sent to the external controller. If no data has been preselected, the value to be sent can be written directly into these parameters. For example, this parameter preselects the data for word 1 of data set 11. Parameter 61.101 Data set 11 data 1 value displays the selected data in integer format. If no data is preselected, the value to be sent can be written directly into parameter 61.101.	None
	None	None.	0

No.	Name/Value	Description	Def/FbEq16
	CW 16bit	Control Word (16 bits)	1
	SW 16bit	Status Word (16 bits)	4
	Act1 16bit	Actual value ACT1 (16 bits)	5
	Act2 16bit	Actual value ACT2 (16 bits)	6
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
61.52	Data set 11 data 2 selection	Preselects the data to be sent as word 2 of data set 11 to the external controller. See also parameter 61.102 Data set 11 data 2 value. For the selections, see parameter 61.51 Data set 11 data 1 selection.	None
61.53	Data set 11 data 3 selection	Preselects the data to be sent as word 3 of data set 11 to the external controller. See also parameter 61.103 Data set 11 data 3 value. For the selections, see parameter 61.51 Data set 11 data 1 selection.	None
61.54	Data set 13 data 1 selection	See parameter 61.51 Data set 11 data 1 selection.	None
61.74	Data set 25 data 3 selection	See parameter 61.51 Data set 11 data 1 selection.	None
61.95	Data set 2 data 1 value	Displays (in integer format) the data to be sent to the external controller as word 1 of data set 2. If no data has been preselected by 61.45 Data set 2 data 1 selection, the value to be sent can be written directly into this parameter.	0
	065535	Data to be sent as word 1 of data set 2.	
61.96	Data set 2 data 2 value	Displays (in integer format) the data to be sent to the external controller as word 2 of data set 2. If no data has been preselected by <i>61.46 Data set 2 data 2 selection</i> , the value to be sent can be written directly into this parameter.	0
	065535	Data to be sent as word 2 of data set 2.	
61.97	Data set 2 data 3 value	Displays (in integer format) the data to be sent to the external controller as word 3 of data set 2. If no data has been preselected by 61.47 Data set 2 data 3 selection, the value to be sent can be written directly into this parameter.	0
	065535	Data to be sent as word 3 of data set 2.	
61.100	Data set 4 data 3 value	Displays (in integer format) the data to be sent to the external controller as word 3 of data set 4. If no data has been selected by 61.50 Data set 4 data 3 selection, the value to be sent can be written directly into this parameter.	0
	065535	Data to be sent as word 3 of data set 4.	

No.	Name/Value	Description	Def/FbEq16
61.101	Data set 11 data 1 value	Displays (in integer format) the data to be sent to the external controller as word 1 of dataset 11. If no data has been preselected by <i>61.51 Data set 11 data 1 selection</i> , the value to be sent can be written directly into this parameter.	0
	065535	Data to be sent as word 1 of data set 11.	
61.102	Data set 11 data 2 value	Displays (in integer format) the data to be sent to the external controller as word 2 of data set 11. If no data has been preselected by <i>61.52 Data set 11 data 2 selection</i> , the value to be sent can be written directly into this parameter.	0
	065535	Data to be sent as word 2 of data set 11.	
61.103	Data set 11 data 3 value	Displays (in integer format) the data to be sent to the external controller as word 3 of data set 11. If no data has been selected by 61.53 Data set 11 data 3 selection, the value to be sent can be written directly into this parameter.	0
	065535	Data to be sent as word 3 of data set 11.	
61.104	Data set 13 data 1 value	Displays (in integer format) the data to be sent to the external controller as word 1 of data set 13. If no data has been selected by <i>61.54 Data set 13 data 1 selection</i> , the value to be sent can be written directly into this parameter.	0
	065535	Data to be sent as word 1 of data set 13.	
61.124	Data set 25 data 3 value	Displays (in integer format) the data to be sent to the external controller as word 3 of data set 25. If no data has been selected by <i>61.74 Data set 25 data 3 selection</i> , the value to be sent can be written directly into this parameter.	0
	065535	Data to be sent as word 3 of data set 25.	
61.151	INU-LSU Data set 10 data 1 sel	(Parameters 61.15161.203 only visible when supply unit control activated by 95.20) Parameters 61.15161.153 preselect data to be sent in data sets 10 to another converter. (Data set 32 is typically used by the mailbox function.) Parameters 61.20161.203 display the data to be sent to the other converter. If no data has been preselected, the value to be sent can be written directly into these parameters. For example, this parameter preselects the data for word 1 of data set 10. Parameter 61.201 INU-LSU Data set 10 data 1 value displays the selected data in integer format. If no data is preselected, the value to be sent can be written directly into parameter 61.201.	LSU CW;
	None	None.	0
	LSU CW	Control word for the supply unit.	22
	DC voltage reference	94.20 DC voltage reference (page 451).	24084
	Reactive power reference	94.30 Reactive power reference (page 452).	24094
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-

No.	Name/Value	Description	Def/FbEq16
61.152	INU-LSU Data set 10 data out 2	Preselects the data to be sent as word 2 of data set 10 to the other converter. See also parameter 61.202 INU-LSU Data set 10 data 2 value. For the selections, see parameter 61.151 INU-LSU Data set 10 data 1 sel.	DC voltage reference
61.153	INU-LSU Data set 10 data 2 sel	Preselects the data to be sent as word 3 of data set 10 to the other converter. See also parameter 61.203 INU-LSU Data set 10 data 3 value. For the selections, see parameter 61.151 INU-LSU Data set 10 data 1 sel.	Reactive power reference
61.201	INU-LSU Data set 10 data 1 value	Displays (in integer format) the data to be sent to the other converter as word 1 of data set 10. If no data has been preselected by 61.151 INU-LSU Data set 10 data 1 sel, the value to be sent can be written directly into this parameter.	0
	065535	Data to be sent as word 1 of data set 10.	
61.202	INU-LSU Data set 10 data 2 value	Displays (in integer format) the data to be sent to the other converter as word 2 of data set 10. If no data has been preselected by 61.152 INU-LSU Data set 10 data out 2, the value to be sent can be written directly into this parameter.	0
	065535	Data to be sent as word 2 of data set 10.	
61.203	INU-LSU Data set 10 data 3 value	Displays (in integer format) the data to be sent to the other converter as word 3 of data set 10. If no data has been selected by <i>61.153 INU-LSU Data set 10 data 2 sel</i> , the value to be sent can be written directly into this parameter.	0
	065535	Data to be sent as word 3 of data set 10.	
62 D2D receive	and DDCS data	Mapping of data received through the DDCS link. See also parameter group 60 DDCS communication.	
62.01	M/F data 1 selection	(Follower only) Defines a target for the data received as word 1 from the master through the master/follower link. See also parameter 62.25 <i>MF</i> data 1 value.	None
	None	None.	0
	CW 16bit	Control Word (16 bits)	1
	Ref1 16bit	Reference REF1 (16 bits)	2
	Ref2 16bit	Reference REF2 (16 bits)	3
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
62.02	<i>M/F data 2</i> selection	(Follower only) Defines a target for the data received as word 2 from the master through the master/follower link. See also parameter 62.26 <i>MF data 2 value</i> . For the selections, see parameter 62.01 <i>M/F data 1 selection</i> .	None
62.03	M/F data 3 selection	(Follower only) Defines a target for the data received as word 3 from the master through the master/follower link. See also parameter 62.27 <i>MF data 3 value</i> . For the selections, see parameter 62.01 <i>M/F data 1 selection</i> .	None

No.	Name/Value	Description	Def/FbEq16
62.04	Follower node 2 data 1 sel	Defines a target for the data received as word 1 from the first follower (ie. the follower with node address 2) through the master/follower link. See also parameter 62.28 Follower node 2 data 1 value.	Follower SW
	None	None.	0
	Follower SW	Status word of the follower. See also parameter 60.18 Follower enable.	26
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
62.05	Follower node 2 data 2 sel	Defines a target for the data received as word 2 from the first follower (ie. the follower with node address 2) through the master/follower link. See also parameter 62.29 Follower node 2 data 2 value. For the selections, see parameter 62.04 Follower node 2 data 1 sel.	None
62.06	Follower node 2 data 3 sel	Defines a target for the data received as word 3 from the first follower (ie. the follower with node address 2) through the master/follower link. See also parameter 62.30 Follower node 2 data 3 value. For the selections, see parameter 62.04 Follower node 2 data 1 sel.	None
62.07	Follower node 3 data 1 sel	Defines a target for the data received as word 1 from the second follower (ie. the follower with node address 3) through the master/follower link. See also parameter 62.31 Follower node 3 data 1 value. For the selections, see parameter 62.04 Follower node 2 data 1 sel.	Follower SW
62.08	Follower node 3 data 2 sel	Defines a target for the data received as word 2 from the second follower (ie. the follower with node address 3) through the master/follower link. See also parameter 62.32 Follower node 3 data 2 value. For the selections, see parameter 62.04 Follower node 2 data 1 sel.	None
62.09	Follower node 3 data 3 sel	Defines a target for the data received as word 3 from the second follower (ie. the follower with node address 3) through the master/follower link. See also parameter 62.33 Follower node 3 data 3 value. For the selections, see parameter 62.04 Follower node 2 data 1 sel.	None
62.10	Follower node 4 data 1 sel	Defines a target for the data received as word 1 from the third follower (ie. the follower with node address 4) through the master/follower link. See also parameter 62.34 Follower node 4 data 1 value. For the selections, see parameter 62.04 Follower node 2 data 1 sel.	Follower SW
62.11	Follower node 4 data 2 sel	Defines a target for the data received as word 2 from the third follower (ie. the follower with node address 4) through the master/follower link. See also parameter 62.35 Follower node 4 data 2 value. For the selections, see parameter 62.04 Follower node 2 data 1 sel.	None

No.	Name/Value	Description	Def/FbEq16
62.12	Follower node 4 data 3 sel	Defines a target for the data received as word 3 from the third follower (ie. the follower with node address 4) through the master/follower link.	None
		See also parameter 62.36 Follower node 4 data 3 value. For the selections, see parameter 62.04 Follower node 2 data 1 sel.	
62.25	MF data 1 value	(Follower only) Displays, in integer format, the data received from the master as word 1. Parameter 62.01 <i>M/F data 1 selection</i> can be used to select a target for the received data. This parameter can also be used as a signal source by other parameters.	0
	065535	Data received as word 1 in master/follower communication.	
62.26	MF data 2 value	(Follower only) Displays, in integer format, the data received from the master as word 2. Parameter 62.02 <i>M/F data 2 selection</i> can be used to select a target for the received data. This parameter can also be used as a signal source by other parameters.	0
	065535	Data received as word 2 in master/follower communication.	
62.27	MF data 3 value	(Follower only) Displays, in integer format, the data received from the master as word 3. Parameter 62.03 <i>M/F data 3 selection</i> can be used to select a target for the received data. This parameter can also be used as a signal source by other parameters.	0
	065535	Data received as word 3 in master/follower communication.	
62.28	Follower node 2 data 1 value	Displays, in integer format, the data received from the first follower (ie. follower with node address 2) as word 1. Parameter 62.04 Follower node 2 data 1 sel can be used to select a target for the received data. This parameter can also be used as a signal source by other parameters.	0
	065535	Data received as word 1 from follower with node address 2.	
62.29	Follower node 2 data 2 value	Displays, in integer format, the data received from the first follower (ie. follower with node address 2) as word 2. Parameter 62.05 Follower node 2 data 2 sel can be used to select a target for the received data. This parameter can also be used as a signal source by other parameters.	0
	065535	Data received as word 2 from follower with node address 2.	
62.30	Follower node 2 data 3 value	Displays, in integer format, the data received from the first follower (ie. follower with node address 2) as word 3. Parameter 62.06 Follower node 2 data 3 sel can be used to select a target for the received data. This parameter can also be used as a signal source by other parameters.	0
	065535	Data received as word 3 from follower with node address 2.	
62.31	Follower node 3 data 1 value	Displays, in integer format, the data received from the second follower (ie. follower with node address 3) as word 1. Parameter 62.07 Follower node 3 data 1 sel can be used to select a target for the received data. This parameter can also be used as a signal source by other parameters.	0
	065535	Data received as word 1 from follower with node address 3.	
		1	

No.	Name/Va	alue	Des	scription	Def/FbEq16
62.32	Follower data 2 va		follo Par selo	plays, in integer format, the data received from the second ower (ie. follower with node address 3) as word 2. ameter 62.08 Follower node 3 data 2 sel can be used to ect a target for the received data. This parameter can also used as a signal source by other parameters.	0
	06553	5	Dat	a received as word 2 from follower with node address 3.	
62.33	Follower data 3 va		follo Par selo	plays, in integer format, the data received from the second ower (ie. follower with node address 3) as word 3. rameter 62.09 Follower node 3 data 3 sel can be used to ect a target for the received data. This parameter can also used as a signal source by other parameters.	0
	06553	5	Dat	a received as word 3 from follower with node address 3.	
62.34	Follower data 1 va		folle Par sele	plays, in integer format, the data received from the third ower (ie. follower with node address 4) as word 1. ameter 62.10 Follower node 4 data 1 sel can be used to ect a target for the received data. This parameter can also used as a signal source by other parameters.	0
	06553	5	Dat	a received as word 1 from follower with node address 4.	
62.35	Follower data 2 va		follo Par selo	plays, in integer format, the data received from the third ower (ie. follower with node address 4) as word 2. rameter 62.11 Follower node 4 data 2 sel can be used to ect a target for the received data. This parameter can also used as a signal source by other parameters.	0
	06553	5	Dat	a received as word 2 from follower with node address 4.	
62.36	Follower data 3 va		follo Par selo	plays, in integer format, the data received from the third ower (ie. follower with node address 4) as word 3. rameter 62.12 Follower node 4 data 3 sel can be used to ect a target for the received data. This parameter can also used as a signal source by other parameters.	0
	06553	5	Dat	a received as word 3 from follower with node address 4.	
62.37	M/F com status 1	munication	folle sup In a	the master, displays the status of the communication with owers specified by parameter 60.19 M/F comm pervision sel 1. In follower, bit 0 indicates the status of the communication in the master.	-
	Bit	Name		Description	
	0	Follower 1		1 (in the master) = Communication with follower 1 OK. 1 (in a follower) = Communication with master OK.	
	1	Follower 2		1 = Communication with follower 2 OK.	
	15	Follower 16)	1 = Communication with follower 16 OK.	
	0000h	FFFFh	M/F	communication status (followers 116).	1 = 1

No.	Name/	Value	Description	Def/FbEq16
62.38	M/F communication status 2		In the master, displays the status of the communication with followers specified by parameter 60.20 <i>M/F comm supervision sel 2</i> .	-
	Bit	Name	Description	
	0	Follower 17	1 = Communication with follower 17 OK.	
	1	Follower 18	1 = Communication with follower 18 OK.	
	 15	 Follower 32	 1 = Communication with follower 32 OK.	
	15	Follower 32	T = Communication with follower 32 OK.	
	0000h.	FFFFh	M/F communication status (followers 1732).	1 = 1
62.41	M/F follower ready status 1		In the master, displays the ready status of the communication with followers specified by parameter 60.23 M/F status supervision sel 1.	-
	Bit	Name	Description	
	0	Follower 1	1 = Follower 1 ready.	
	1	Follower 2	1 = Follower 2 ready.	
	15	Follower 16	1 = Follower 16 ready.	
	0000h.	FFFFh	Follower 116 ready status.	1 = 1
62.42	status 2		In the master, displays the ready status of the communication with followers specified by parameter 60.24 M/F status supervision sel 2.	-
	Bit	Name	Description	
	0	Follower 17	-	
	1	F 11 40	1 = Follower 18 ready.	
		Follower 18		
		Follower 18		
	 15	Follower 18	 2 1 = Follower 32 ready.	
	15		 1 = Follower 32 ready. Follower 1732 ready status. 	1 = 1
62.45	15 0000h.	 Follower 32 FFFFh et 1 data 1		1 = 1 None
62.45	15 0000h. <i>Data s</i> e	 Follower 32 FFFFh et 1 data 1	Follower 1732 ready status. Parameters 62.4562.50 define a target for the data received in data sets 1 and 3 from the external controller. These data sets are used in ModuleBus communication with a "standard drive" (60.50 DDCS controller drive type = ABB standard drive). Parameters 62.9562.100 display the data received from the external controller in integer format, and can be used as sources by other parameters. For example, this parameter selects a target for word 1 of data set 1. Parameter 62.95 Data set 1 data 1 value displays the received data in integer format, and can also be used as a	
62.45	15 0000h. Data se selectio	 Follower 32 FFFFh et 1 data 1 on	 Follower 1732 ready status. Parameters 62.4562.50 define a target for the data received in data sets 1 and 3 from the external controller. These data sets are used in ModuleBus communication with a "standard drive" (60.50 DDCS controller drive type = ABB standard drive). Parameters 62.9562.100 display the data received from the external controller in integer format, and can be used as sources by other parameters. For example, this parameter selects a target for word 1 of data set 1. Parameter 62.95 Data set 1 data 1 value displays the received data in integer format, and can also be used as a source by other parameters. 	None
62.45	15 0000h. Data se selection	 Follower 32 FFFFh et 1 data 1 on	 Follower 1732 ready status. Parameters 62.4562.50 define a target for the data received in data sets 1 and 3 from the external controller. These data sets are used in ModuleBus communication with a "standard drive" (60.50 DDCS controller drive type = ABB standard drive). Parameters 62.9562.100 display the data received from the external controller in integer format, and can be used as sources by other parameter selects a target for word 1 of data set 1. Parameter 62.95 Data set 1 data 1 value displays the received data in integer format, and can also be used as a source by other parameters. None. 	None

No.	Name/Value	Description	Def/FbEq16
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
62.46	Data set 1 data 2 selection	Defines a target for the data received as word 2 of data set 1. See also parameter 62.96 Data set 1 data 2 value. For the selections, see parameter 62.45 Data set 1 data 1 selection.	None
62.47	Data set 1 data 3 selection	See parameter 62.45 Data set 1 data 1 selection.	None
62.50	Data set 3 data 3 selection	See parameter 62.45 Data set 1 data 1 selection.	None
62.51	Data set 10 data 1 selection	Parameters 62.5162.74 define a target for the data received in data sets 10, 12, 14, 16, 18, 20, 22 and 24 from the external controller. Parameters 62.10162.124 display the data received from the external controller in integer format, and can be used as sources by other parameters. For example, this parameter selects a target for word 1 of data set 10. Parameter 62.101 Data set 10 data 1 value displays the received data in integer format, and can also be used as a source by other parameters.	None
	None	None.	0
	CW 16bit	Control Word (16 bits)	1
	Ref1 16bit	Reference REF1 (16 bits)	2
	Ref2 16bit	Reference REF2 (16 bits)	3
	Other	Source selection (see Terms and abbreviations on page 131).	-
62.52	Data set 10 data 2 selection	Defines a target for the data received as word 2 of data set 10. See also parameter 62.102 Data set 10 data 2 value. For the selections, see parameter 62.51 Data set 10 data 1 selection.	None
62.53	Data set 10 data 3 selection	Defines a target for the data received as word 3 of data set 10. See also parameter 62.103 Data set 10 data 3 value. For the selections, see parameter 62.51 Data set 10 data 1 selection.	None
62.54	Data set 12 data 1 selection	See parameter 62.51 Data set 10 data 1 selection.	None
62.74	Data set 24 data 3 selection	See parameter 62.51 Data set 10 data 1 selection.	None
62.95	Data set 1 data 1 value	Displays (in integer format) the data received from the external controller as word 1 of data set 1. A target for this data can be selected by parameter 62.45 Data set 1 data 1 selection. The value can also be used as a source by another parameter.	0
	065535	Data received as word 1 of data set 1.	

No.	Name/Value	Description	Def/FbEq16
62.96	Data set 1 data 2 value	Displays (in integer format) the data received from the external controller as word 2 of data set 1. A target for this data can be selected by parameter 62.46 Data set 1 data 2 selection. The value can also be used as a source by another parameter.	0
	065535	Data received as word 2 of data set 1.	
62.97	Data set 1 data 3 value	Displays (in integer format) the data received from the external controller as word 3 of data set 1. A target for this data can be selected by parameter 62.47 Data set 1 data 3 selection. The value can also be used as a source by another parameter.	0
	065535	Data received as word 3 of data set 1.	
62.100	Data set 3 data 3 value	Displays (in integer format) the data received from the external controller as word 3 of data set 3. A target for this data can be selected by parameter 62.50 Data set 3 data 3 selection. The value can also be used as a source by another parameter.	0
	065535	Data received as word 3 of data set 3.	
62.101	Data set 10 data 1 value	Displays (in integer format) the data received from the external controller as word 1 of data set 10. A target for this data can be selected by parameter 62.51 Data set 10 data 1 selection. The value can also be used as a source by another parameter.	0
	065535	Data received as word 1 of data set 10.	
62.102	Data set 10 data 2 value	Displays (in integer format) the data received from the external controller as word 2 of data set 10. A target for this data can be selected by parameter 62.52 Data set 10 data 2 selection. The value can also be used as a source by another parameter.	0
	065535	Data received as word 2 of data set 10.	
62.103	Data set 10 data 3 value	Displays (in integer format) the data received from the external controller as word 3 of data set 10. A target for this data can be selected by parameter 62.53 Data set 10 data 3 selection. The value can also be used as a source by another parameter.	0
	065535	Data received as word 3 of data set 10.	
62.104	Data set 12 data 1 value	Displays (in integer format) the data received from the external controller as word 1 of data set 12. A target for this data can be selected by parameter 62.54 Data set 12 data 1 selection. The value can also be used as a source by another parameter.	0
	065535	Data received as word 1 of data set 12.	
62.124	Data set 24 data 3 value	Displays (in integer format) the data received from the external controller as word 3 of data set 24. A target for this data can be selected by parameter 62.74 Data set 24 data 3 selection. The value can also be used as a source by another parameter.	0
	065535	Data received as word 3 of data set 24.	
		1	1

No.	Name/Value	Description	Def/FbEq16
62.151	INU-LSU Data set 11 data 1 sel	(Parameters 62.15162.203 only visible only visible when supply unit control activated by 95.20) Parameters 62.15162.153 define a target for the data received in data sets 11from another converter (typically the supply unit of the drive). Parameters 62.20162.203 display the data received from the other converter in integer format, and can be used as sources by other parameters. For example, this parameter selects a target for word 1 of data set 11. Parameter 62.201 INU-LSU Data set 11 data 1 value displays the received data in integer format, and can also be used as a source by other parameters.	LSU SW
	None	None.	0
	LSU SW	Status word of the supply unit.	4
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
62.152	INU-LSU Data set 11 data 2 sel	Defines a target for the data received as word 2 of data set 11. See also parameter 62.202 INU-LSU Data set 11 data 2 value. For the selections, see parameter 62.151 INU-LSU Data set 11 data 1 sel.	None
62.153	INU-LSU Data set 11 data 3 sel	Defines a target for the data received as word 3 of data set 11. See also parameter 62.203 INU-LSU Data set 11 data 3 value. For the selections, see parameter 62.151 INU-LSU Data set 11 data 1 sel.	None
62.201	INU-LSU Data set 11 data 1 value	Displays (in integer format) the data received from the other converter as word 1 of data set 11. A target for this data can be selected by parameter 62.151 <i>INU-LSU Data set 11 data 1 sel</i> . The value can also be used as a source by another parameter.	0
	065535	Data received as word 1 of data set 11.	
62.202	INU-LSU Data set 11 data 2 value	Displays (in integer format) the data received from the other converter as word 2 of data set 11. A target for this data can be selected by parameter 62.152 <i>INU-LSU Data set 11 data 2 sel</i> . The value can also be used as a source by another parameter.	0
	065535	Data received as word 2 of data set 11.	
62.203	INU-LSU Data set 11 data 3 value	Displays (in integer format) the data received from the other converter as word 3 of data set 11. A target for this data can be selected by parameter 62.153 <i>INU-LSU Data set 11 data 3 sel</i> . The value can also be used as a source by another parameter.	0
	065535	Data received as word 3 of data set 11.	
			1

No.	Name/Value	Description	Def/FbEq16
74 Spi	nning control	Spinning control functions. See control chain diagram Spinning control function on page 628. Note: The spinning pattern runs only in remote mode. In Local mode drive uses keypad speed reference and spinning pattern will not run.	
74.01	Pattern selection	 Selects the pattern to run. If a pattern is changed when the drive is not running and pattern is not paused, then the selected pattern is updated in parameter 09.05 Current pattern and 09.06 Future pattern. If a pattern is changed while the drive is running or pattern is paused, the changed pattern is updated only in parameter 09.06 Future pattern. The changes are updated in parameter 09.05 Current pattern only when the current pattern is completed or pattern is reset. 	Pattern1
	Pattern1	Pattern 1	1
	Pattern2	Pattern 2	2
	Pattern3	Pattern 3	3
	Pattern4	Pattern 4	4
74.02	Pattern selection mode	Selects the source for pattern-to-be-run selection mode. If the pattern is changed while drive is running or paused, the changes are updated only in parameter <i>09.06 Future pattern</i> . The parameter <i>09.05 Current pattern</i> is updated only when drive is not running and when pattern is reset.	Par 74.01
	Par 74.01	Pattern-to-be-run is selected with parameter 74.01 Pattern selection.	1
	DI3_4	DI3DI4Pattern00Pattern110Pattern201Pattern311Pattern4	2
	DI5_6	DisDifPattern00Pattern110Pattern201Pattern311Pattern4	3
74.03	Shift function sel	Activates the Shift function.	No
	No	Not selected	0
	Yes	When the shift function is selected, the active pattern speed reference is multiplied with the parameter 79.07 Pattern shift <i>multiple</i> . The selection is updated in parameter 09.07 Shift selected.	1
74.04	Reset active pattern	Selects the source to reset the active pattern.	DI6
	False	Reset of active pattern is Off	0
	True	Reset of active pattern is On	1

No.	Name/Value	Description	Def/FbEq16
	DI1	Digital input 1	2
	DI2	Digital input 2	3
	DI3	Digital input 3	4
	DI4	Digital input 4	5
	DI5	Digital input 5	6
	DI6	Digital input 6	7
	DIO1	Digital input/output 1	8
	DIO2	Digital input/output 2	9
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
74.05	Pattern reset with interlock	 Selects the new parameter for pattern reset with additional interlock. Additional interlock as below: In time mode: Pattern reset shall be possible if only the completed pattern time is greater than the completed pattern time set in parameter 74.08-Pattern reset time. In Length (m) and Length (%): Pattern reset shall be possible if only the completed pattern Length is greater than the completed pattern time set in parameter 74.09-Pattern reset length. 	True
	False	Reset of active pattern with additional interlock is Off	0
	True	Reset of active pattern with additional interlock is On	1
	DI1	Digital input 1	2
	DI2	Digital input 2	3
	DI3	Digital input 3	4
	DI4	Digital input 4	5
	DI5	Digital input 5	6
	DI6	Digital input 6	7
	DIO1	Digital input/output 1	8
	DIO2	Digital input/output 2	9
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
74.07	Reverse select	Selects the source for changing the spinning direction.	False
	False	Inactive	0
	True	Active	1
	DI1	Digital input 1	2
	DI2	Digital input 2	3
	DI3	Digital input 3	4
	DI4	Digital input 4	5
	DI5	Digital input 5	6
	DI6	Digital input 6	7
	DIO1	Digital input/output 1	8
	DIO2	Digital input/output 2	9
	Other	Source selection (see Terms and abbreviations on page 131).	-

No.	Name/Value	Description	Def/FbEq16
74.08	Pattern reset time	Defines the minimum completed pattern time to activate pattern reset when Pattern reset with interlock (par. 74.05 <i>Pattern reset with interlock</i>) is selected in Time mode.	400 min
	01500 min	Pattern reset time with interlock in Time mode.	1 = 1 min
74.09	Pattern reset length	Defines the minimum delivered length to activate pattern reset when Pattern reset with interlock is selected in length and % length mode.	2000 m
	030000 m	Pattern reset length is length and % length mode.	1 = 1 m
74.11	Production calculation reset	Resets production and time calculations except the signal 09.11 Pattern completed time. Note: After you reset the production with <i>Reset now</i> , change the value back to <i>No</i> .	No
	No	Reset production calculation is inactive.	0
	Reset now	Reset production calculation is active.	1
74.12	Average speed mode	Defines the spinning average speed used for hank/Kg calculation.	Calculated avg speed
	Calculated avg speed	One of the average spindle speed signals 09.01, 09.02, 09.03 or 09.04 is used for hank/Kg calculation based on the selected pattern.	0
	Calculated sliding speed	Signal <i>09.38 Sliding average speed</i> is used for hank/Kg calculation.	1
75 Pat	ttern1	Defines the preset values for 16 sections in pattern1. ¹⁾ In length mode, the control program converts the set value from length into time.	
75.01	Section No 1.1	Defines the time, length or proportional percentage preset value for section 1 in pattern1 ¹⁾ .	1.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 1 in pattern1.	100 = 1 min/m/% (max. 32767)
75.02	Speed No 1.1	Defines the speed preset value to where the speed ramps, from zero speed during the time specified in parameter 75.01.	10.0%
	0.1200.0%	Speed preset value for section 1 in pattern1.	10 = 1%
75.03	Section No 1.2	Defines the time, length or proportional percentage preset value for section 2 in pattern1 ^{1} .	10.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 2 in pattern1.	100 = 1 min/m/% (max. 32767)
75.04	Speed No 1.2	Defines the speed preset value to where the speed ramps, from speed 75.02 Speed No 1.1 during the time specified in parameter 75.03.	20.0%
	0.1200.0%	Speed preset value for section 2 in pattern1.	10 = 1%
75.05	Section No 1.3	Defines the time, length or proportional percentage preset value for section 3 in pattern1 ^{7}).	15.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 3 in pattern1.	100 = 1 min (max. 32767)
75.06	Speed No 1.3	Defines the speed preset value to where the speed ramps, from speed 75.04 Speed No 1.2 during the time specified in parameter 75.05.	30.0%
	0.1200.0%	Speed preset value for section 3 in pattern1.	10 = 1%

No.	Name/Value	Description	Def/FbEq16
75.07	Section No 1.4	Defines the time, length or proportional percentage preset value for section 4 in pattern1 ¹⁾ .	20.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 4 in pattern1.	100 = 1 min (max. 32767)
75.08	Speed No 1.4	Defines the speed preset value to where the speed ramps, from speed 75.06 Speed No 1.3 during the time specified in parameter 75.07.	40.0%
	0.1200.0%	Speed preset value for section 4 in pattern1.	10 = 1%
75.09	Section No 1.5	Defines the time, length or proportional percentage preset value for section 5 in pattern1 ^{<i>1</i>)} .	25.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 5 in pattern1.	100 = 1 min/m/% (max. 32767)
75.10	Speed No 1.5	Defines the speed preset value to where the speed ramps, from speed 75.08 Speed No 1.4 during the time specified in parameter 75.09.	50.0%
	0.1200.0%	Speed preset value for section 5 in pattern1.	10 = 1%
75.11	Section No 1.6	Defines the time, length or proportional percentage preset value for section 6 in pattern1 ¹⁾ .	30.00 min
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 6 in pattern1.	100 = 1 min/m/% (max. 32767)
75.12	Speed No 1.6	Defines the speed preset value to where the speed ramps, from speed 75.10 Speed No 1.5 during the time specified in parameter 75.11.	60.0%
	0.1200.0%	Speed preset value for section 6 in pattern1.	10 = 1%
75.13	Section No 1.7	Defines the time, length or proportional percentage preset value for section 7 in pattern1 ¹⁾ .	35.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 7 in pattern1.	100 = 1 min/m/% (max. 32767)
75.14	Speed No 1.7	Defines the speed preset value to where the speed ramps, from speed 75.12 Speed No 1.6 during the time specified in parameter 75.13.	70.0%
	0.1200.0%	Speed preset value for section 7 in pattern1.	10 = 1%
75.15	Section No 1.8	Defines the time, length or proportional percentage preset value for section 8 in pattern1 ¹⁾ .	40.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 8 in pattern1.	100 = 1 min/m/% (max. 32767)
75.16	Speed No 1.8	Defines the speed preset value to where the speed ramps, from speed 75.14 Speed No 1.7 during the time specified in parameter 75.15.	80.0%
	0.1200.0%	Speed preset value for section 8 in pattern1.	10 = 1%
75.17	Section No 1.9	Defines the time, length or proportional percentage preset value for section 9 in pattern1 ¹⁾ .	45.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 9 in pattern1.	100 = 1 min/m/% (max. 32767)

No.	Name/Value	Description	Def/FbEq16
75.18	Speed No 1.9	Defines the speed preset value to where the speed ramps, from speed 75.16 Speed No 1.8 during the time specified in parameter 75.17.	75.0%
	0.1200.0%	Speed preset value for section 9 in pattern1.	10 = 1%
75.19	Section No 1.10	Defines the time, length or proportional percentage preset value for section 10 in pattern1 ^{1} .	35.00 min
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 10 in pattern1.	100 = 1 min/m/% (max. 32767)
75.20	Speed No 1.10	Defines the speed preset value to where the speed ramps, from speed 75.18 Speed No 1.9 during the time specified in parameter 75.19.	70.0%
	0.1200.0%	Speed preset value for section 10 in pattern1.	10 = 1%
75.21	Section No 1.11	Defines the time, length or proportional percentage preset value for section 11 in pattern1 ¹⁾ .	30.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 11 in pattern1.	100 = 1 min/m/% (max. 32767)
75.22	Speed No 1.11	Defines the speed preset value to where the speed ramps, from speed 75.20 Speed No 1.10 during the time specified in parameter 75.21.	60.0%
	0.1200.0%	Speed preset value for section 11 in pattern1.	10 = 1%
75.23	Section No 1.12	Defines the time, length or proportional percentage preset value for section 12 in pattern1 ^{1} .	25.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 12 in pattern1.	100 = 1 min/m/% (max. 32767)
75.24	Speed No 1.12	Defines the speed preset value to where the speed ramps, from speed 75.22 Speed No 1.11 during the time specified in parameter 75.23.	50.0%
	0.1200.0%	Speed preset value for section 12 in pattern1.	10 = 1%
75.25	Section No 1.13	Defines the time, length or proportional percentage preset value for section 13 in pattern1 ¹⁾ .	20.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 13 in pattern1.	100 = 1 min/m/% (max. 32767)
75.26	Speed No 1.13	Defines the speed preset value to where the speed ramps, from speed 75.24 Speed No 1.12 during the time specified in parameter 75.25.	40.0%
	0.1200.0%	Speed preset value for section 13 in pattern1.	10 = 1%
75.27	Section No 1.14	Defines the time, length or proportional percentage preset value for section 14 in pattern1 ^{1} .	15.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 14 in pattern1.	100 = 1 min/m/% (max. 32767)
75.28	Speed No 1.14	Defines the speed preset value to where the speed ramps, from speed 75.26 Speed No 1.13 during the time specified in parameter 75.27.	30.0%
	0.1200.0%	Speed preset value for section 14 in pattern1.	10 = 1%

No.	Name/Value	Description	Def/FbEq16
75.29	Section No 1.15	Defines the time, length or proportional percentage preset value for section 15 in pattern 1^{1} .	10.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 15 in pattern1.	100 = 1 min/m/% (max. 32767)
75.30	Speed No 1.15	Defines the speed preset value to where the speed ramps, from speed 75.28 Speed No 1.14 during the time specified in parameter 75.29.	20.0%
	0.1200.0%	Speed preset value for section 15 in pattern1.	10 = 1%
75.31	Section No 1.16	Defines the time, length or proportional percentage preset value for section 16 in pattern $1^{1/2}$.	1.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 16 in pattern1.	100 = 1 min/m/% (max. 32767)
75.32	Speed No 1.16	Defines the speed preset value to where the speed ramps, from speed 75.30 Speed No 1.15 during the time specified in parameter 75.31.	10.0%
	0.1200.0%	Speed preset value for section 16 in pattern1.	10 = 1%
75.33	Pattern1 mode	Selects the mode of pattern1.	Time
	Time	Pattern1 section values are defined in minutes.	0
	Length [m]	Pattern1 section values are defined in meters.	1
	Length [%]	Pattern1 section values are defined in percentage. 100% = Length defined with parameter 75.37 Pattern1 total length.	2
75.34	Pattern1 TPI	Defines the amount of yarn twisting, based on the formula:	30.00 TPI
		Spinning speed 1 [1/min]	
		Front roller surface speed 1 [inch/min]	
	0.00200.00 TPI	Yarn twisting in TPI (Twist per inch)	100 = 1 TPI
75.35	Pattern1 count number	Defines the numerical designation of yarn size in pattern1.	30
	0200	Yarn size in pattern1.	1 = 1
75.36	Pattern1 section total	Shows sections total in pattern1. Section total is sum of sections 1.11.16 in parameter 75.01, 75.03, 75.05,75.29, 75.31. This parameter is read-only.	-
	0.00999999.00 min	Pattern1 sections total in either time, length in m or length in % mode.	100 = 1 min (max. 32767)
75.37	Pattern1 total length	Defines the total length of pattern1 with parameter 75.33 Pattern1 mode in % mode. If the sum of section percentages is not 100%, the warning is displayed. Note: This parameter is effective only when parameter 75.33 Pattern1 mode = Length [%].	100.0 m
	0.099999.0 m	Pattern1 total length in % mode	10 = 1 m (max. 32767)

No.	Name/Value	Description	Def/FbEq16
76 Pat	ttern2	Defines the preset values for 16 sections in pattern2. ²⁾ In length mode, the control program converts the set value from length into time.	
76.01	Section No 2.1	Defines the time, length or proportional percentage preset value for section 1 in pattern2 ²⁾ .	1.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 1 in pattern2.	100 = 1 min/m/% (max. 32767)
76.02	Speed No 2.1	Defines the speed preset value to where the speed ramps, from zero speed during the time specified in parameter 76.01.	10.0%
	0.1200.0%	Speed preset value for section 1 in pattern2.	10 = 1%
76.03	Section No 2.2	Defines the time, length or proportional percentage preset value for section 2 in pattern2 ²⁾ .	10.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 2 in pattern2.	100 = 1 min/m/% (max. 32767)
76.04	Speed No 2.2	Defines the speed preset value to where the speed ramps, from speed 76.02 Speed No 2.1 during the time specified in parameter 76.03.	20.0%
	0.1200.0%	Speed preset value for section 2 in pattern2.	10 = 1%
76.05	Section No 2.3	Defines the time, length or proportional percentage preset value for section 3 in pattern2 ²⁾ .	15.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 3 in pattern2.	100 = 1 min/m/% (max. 32767)
76.06	Speed No 2.3	Defines the speed preset value to where the speed ramps, from speed 76.04 Speed No 2.2 during the time specified in parameter 76.05.	30.0%
	0.1200.0%	Speed preset value for section 3 in pattern2.	10 = 1%
76.07	Section No 2.4	Defines the time, length or proportional percentage preset value for section 4 in pattern2 ²⁾ .	20.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 4 in pattern2.	100 = 1 min/m/% (max. 32767)
76.08	Speed No 2.4	Defines the speed preset value to where the speed ramps, from speed 76.06 Speed No 2.3 during the time specified in parameter 76.07.	40.0%
	0.1200.0%	Speed preset value for section 4 in pattern2.	10 = 1%
76.09	Section No 2.5	Defines the time, length or proportional percentage preset value for section 5 in pattern2 ²⁾ .	25.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 5 in pattern2.	100 = 1 min/m/% (max. 32767)
76.10	Speed No 2.5	Defines the speed preset value to where the speed ramps, from speed 76.08 Speed No 2.4 during the time specified in parameter 76.09.	50.0%
	0.1200.0%	Speed preset value for section 5 in pattern2.	10 = 1%

No.	Name/Value	Description	Def/FbEq16
76.11	Section No 2.6	Defines the time, length or proportional percentage preset value for section 6 in pattern2 ²⁾ .	30.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 6 in pattern2.	100 = 1 min/m/% (max. 32767)
76.12	Speed No 2.6	Defines the speed preset value to where the speed ramps, from speed 76.10 Speed No 2.5 during the time specified in parameter 76.11.	60.0%
	0.1200.0%	Speed preset value for section 6 in pattern2.	10 = 1%
76.13	Section No 2.7	Defines the time, length or proportional percentage preset value for section 7 in pattern 2^{2} .	35.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 7 in pattern2.	100 = 1 min/m/% (max. 32767)
76.14	Speed No 2.7	Defines the speed preset value to where the speed ramps, from speed 76.12 Speed No 2.6 during the time specified in parameter 76.13.	70.0%
	0.1200.0%	Speed preset value for section 7 in pattern2.	10 = 1%
76.15	Section No 2.8	Defines the time, length or proportional percentage preset value for section 8 in pattern 2^{2} .	40.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 8 in pattern2.	100 = 1 min/m/% (max. 32767)
76.16	Speed No 2.8	Defines the speed preset value to where the speed ramps, from speed 76.14 Speed No 2.7 during the time specified in parameter 76.15.	80.0%
	0.1200.0%	Speed preset value for section 8 in pattern2.	10 = 1%
76.17	Section No 2.9	Defines the time, length or proportional percentage preset value for section 9 in pattern 2^{2} .	45.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 9 in pattern2.	100 = 1 min/m/% (max. 32767)
76.18	Speed No 2.9	Defines the speed preset value to where the speed ramps, from speed 76.16 Speed No 2.8 during the time specified in parameter 76.17.	75.0%
	0.1200.0%	Speed preset value for section 9 in pattern2.	10 = 1%
76.19	Section No 2.10	Defines the time, length or proportional percentage preset value for section 10 in pattern2 ²⁾ .	35.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 10 in pattern2.	100 = 1 min/m/% (max. 32767)
76.20	Speed No 2.10	Defines the speed preset value to where the speed ramps, from speed 76.18 Speed No 2.9 during the time specified in parameter 76.19.	70.0%
	0.1200.0%	Speed preset value for section 10 in pattern2.	10 = 1%
76.21	Section No 2.11	Defines the time, length or proportional percentage preset value for section 11 in pattern 2^{2} .	30.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 11 in pattern2.	100 = 1 min/m/% (max. 32767)

No.	Name/Value	Description	Def/FbEq16
76.22	Speed No 2.11	Defines the speed preset value to where the speed ramps, from speed 76.20 Speed No 2.10 during the time specified in parameter 76.21.	60.0%
	0.1200.0%	Speed preset value for section 11 in pattern2.	10 = 1%
76.23	Section No 2.12	Defines the time, length or proportional percentage preset value for section 12 in pattern2 ²⁾ .	25.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 12 in pattern2.	100 = 1 min/m/% (max. 32767)
76.24	Speed No 2.12	Defines the speed preset value to where the speed ramps, from speed 76.22 Speed No 2.11 during the time specified in parameter 76.23.	50.0%
	0.1200.0%	Speed preset value for section 12 in pattern2.	10 = 1%
76.25	Section No 2.13	Defines the time, length or proportional percentage preset value for section 13 in pattern2 ²⁾ .	20.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 13 in pattern2.	100 = 1 min/m/% (max. 32767)
76.26	Speed No 2.13	Defines the speed preset value to where the speed ramps, from speed 76.24 <i>Speed No 2.12</i> during the time specified in parameter 76.25.	40.0%
	0.1200.0%	Speed preset value for section 13 in pattern2.	10 = 1%
76.27	Section No 2.14	Defines the time, length or proportional percentage preset value for section 14 in pattern2 ²⁾ .	15.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 14 in pattern2.	100 = 1 min/m/% (max. 32767)
76.28	Speed No 2.14	Defines the speed preset value to where the speed ramps, from speed 76.26 Speed No 2.13 during the time specified in parameter 76.27.	30.0%
	0.1200.0%	Speed preset value for section 14 in pattern2.	10 = 1%
76.29	Section No 2.15	Defines the time, length or proportional percentage preset value for section 15 in pattern2 ²⁾ .	10.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 15 in pattern2.	100 = 1 min/m/% (max. 32767)
76.30	Speed No 2.15	Defines the speed preset value to where the speed ramps, from speed 76.28 Speed No 2.14 during the time specified in parameter 76.29.	20.0%
	0.1200.0%	Speed preset value for section 15 in pattern2.	10 = 1%
76.31	Section No 2.16	Defines the time, length or proportional percentage preset value for section 16 in pattern2 ²⁾ .	1.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 16 in pattern2.	100 = 1 min/m/% (max. 32767)
76.32	Speed No 2.16	Defines the speed preset value to where the speed ramps, from speed 76.30 Speed No 2.15 during the time specified in parameter 76.31.	10.0%
	0.1200.0%	Speed preset value for section 16 in pattern2.	10 = 1%

No.	Name/Value	Description	Def/FbEq16
76.33	Pattern2 mode	Selects the mode of pattern2.	Time
	Time	Pattern2 section values are defined in minutes.	0
	Length [m]	Pattern2 section values are defined in meters.	1
	Length [%]	Pattern2 section values are defined in percentage. 100% = Length defined with parameter 76.37 Pattern2 total length.	2
76.34	Pattern2 TPI	Defines the amount of yarn twisting, based on the formula:	30.00 TPI
		Spinning speed 2 [1/min]	
		Front roller surface speed 2 [inch/min]	
	0.00200.00 TPI	Yarn twisting in TPI (Twist per inch)	100 = 1 TPI
76.35	Pattern2 count number	Defines the numerical designation of yarn size in pattern2.	30
	1200	Yarn size in pattern2.	1 = 1
76.36	Pattern2 section total	Shows the section total in pattern2. Sections total is the sum of sections 2.12.16 in parameter 76.01, 76.03, 76.05,76.29, 76.31. This parameter is read-only.	-
	0.0099999.00 min	Pattern2 sections total in either time, length m or length % mode.	100 = 1 min (max. 32767)
76.37	Pattern2 total length	Defines the total length of pattern2 with parameter 76.33 <i>Pattern2 mode</i> in % mode. Note : This parameter is effective only when parameter 76.33 <i>Pattern2 mode</i> = Length [%].	100.0 m
	0.099999.0 m	Pattern2 total length in % mode	10 = 1 m (max. 32767)
77 Pat	tern3	Defines the preset values for 16 sections in pattern3. ³⁾ In length mode, the control program converts the set value from length into time.	
77.01	Section No 3.1	Defines the time, length or proportional percentage preset value for section 1 in pattern3 ³⁾ .	1.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 1 in pattern3.	100 = 1 min/m/% (max. 32767)
77.02	Speed No 3.1	Defines the speed preset value to where the speed ramps, from zero speed during the time specified in parameter 77.01.	10.0%
	0.1200.0%	Speed preset value for section 1 in pattern2.	10 = 1%
77.03	Section No 3.2	Defines the time, length or proportional percentage preset value for section 2 in pattern3 ³⁾ .	10.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 2 in pattern3.	100 = 1 min/m/% (max. 32767)
77.04	Speed No 3.2	Defines the speed preset value to where the speed ramps, from speed 77.02 Speed No 3.1 during the time specified in parameter 77.03.	20.0%
	0.1200.0%	Speed preset value for section 2 in pattern2.	10 = 1%

No.	Name/Value	Description	Def/FbEq16
77.05	Section No 3.3	Defines the time, length or proportional percentage preset value for section 3 in pattern3 ³⁾ .	15.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 3 in pattern3.	100 = 1 min/m/% (max. 32767)
77.06	Speed No 3.3	Defines the speed preset value to where the speed ramps, from speed 77.04 Speed No 3.2 during the time specified in parameter 77.05.	30.0%
	0.1200.0%	Speed preset value for section 3 in pattern2.	10 = 1%
77.07	Section No 3.4	Defines the time, length or proportional percentage preset value for section 4 in pattern3 ³⁾ .	20.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 4 in pattern3.	100 = 1 min/m/% (max. 32767)
77.08	Speed No 3.4	Defines the speed preset value to where the speed ramps, from speed 77.06 Speed No 3.3 during the time specified in parameter 77.07.	40.0%
	0.1200.0%	Speed preset value for section 4 in pattern3.	10 = 1%
77.09	Section No 3.5	Defines the time, length or proportional percentage preset value for section 5 in pattern3 ³⁾ .	25.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 5 in pattern3.	100 = 1 min/m/% (max. 32767)
77.10	Speed No 3.5	Defines the speed preset value to where the speed ramps, from speed 77.08 Speed No 3.4 during the time specified in parameter 77.09.	50.0%
	0.1200.0%	Speed preset value for section 5 in pattern2.	10 = 1%
77.11	Section No 3.6	Defines the time, length or proportional percentage preset value for section 6 in pattern3 ³⁾ .	30.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 6 in pattern3.	100 = 1 min/m/% (max. 32767)
77.12	Speed No 3.6	Defines the speed preset value to where the speed ramps, from speed 77.10 Speed No 3.5 during the time specified in parameter 77.11.	60.0%
	0.1200.0%	Speed preset value for section 6 in pattern3.	10 = 1%
77.13	Section No 3.7	Defines the time, length or proportional percentage preset value for section 7 in pattern3 ³⁾ .	35.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 7 in pattern3.	100 = 1 min/m/% (max. 32767)
77.14	Speed No 3.7	Defines the speed preset value to where the speed ramps, from speed 77.12 Speed No 3.6 during the time specified in parameter 77.13.	70.0%
	0.1200.0%	Speed preset value for section 7 in pattern3.	10 = 1%
77.15	Section No 3.8	Defines the time, length or proportional percentage preset value for section 8 in pattern3 ³⁾ .	40.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 8 in pattern3.	100 = 1 min/m/% (max. 32767)

No.	Name/Value	Description	Def/FbEq16
77.16	Speed No 3.8	Defines the speed preset value to where the speed ramps, from speed 77.14 Speed No 3.7 during the time specified in parameter 77.15.	80.0%
	0.1200.0%	Speed preset value for section 8 in pattern3.	10 = 1%
77.17	Section No 3.9	Defines the time, length or proportional percentage preset value for section 9 in pattern3 ³⁾ .	45.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 9 in pattern3.	100 = 1 min/m/% (max. 32767)
77.18	Speed No 3.9	Defines the speed preset value to where the speed ramps, from speed 77.16 Speed No 3.8 during the time specified in parameter 77.17.	75.0%
	0.1200.0%	Speed preset value for section 9 in pattern2.	10 = 1%
77.19	Section No 3.10	Defines the time, length or proportional percentage preset value for section 10 in pattern3 ³⁾ .	35.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 10 in pattern3.	100 = 1 min/m/% (max. 32767)
77.20	Speed No 3.10	Defines the speed preset value to where the speed ramps, from speed 77.18 Speed No 3.9 during the time specified in parameter 77.19.	70.0%
	0.1200.0%	Speed preset value for section 10 in pattern3.	10 = 1%
77.21	Section No 3.11	Defines the time, length or proportional percentage preset value for section 11 in pattern3 ³⁾ .	30.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 11 in pattern3.	100 = 1 min/m/% (max. 32767)
77.22	Speed No 3.11	Defines the speed preset value to where the speed ramps, from speed 77.20 Speed No 3.10 during the time specified in parameter 77.21.	60.0%
	0.1200.0%	Speed preset value for section 11 in pattern3.	10 = 1%
77.23	Section No 3.12	Defines the time, length or proportional percentage preset value for section 12 in pattern3 ³⁾ .	25.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 12 in pattern3.	100 = 1 min/m/% (max. 32767)
77.24	Speed No 3.12	Defines the speed preset value to where the speed ramps, from speed 77.22 Speed No 3.11 during the time specified in parameter 77.23.	50.0%
	0.1200.0%	Speed preset value for section 12 in pattern3.	10 = 1%
77.25	Section No 3.13	Defines the time, length or proportional percentage preset value for section 13 in pattern3 ³⁾ .	20.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 13 in pattern3.	100 = 1 min/m/% (max. 32767)
77.26	Speed No 3.13	Defines the speed preset value to where the speed ramps, from speed 77.24 Speed No 3.12 during the time specified in parameter 77.25.	40.0%
	0.1200.0%	Speed preset value for section 13 in pattern1.	10 = 1%

No.	Name/Value	Description	Def/FbEq16
77.27	Section No 3.14	Defines the time, length or proportional percentage preset value for section 14 in pattern3 ³⁾ .	15.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 14 in pattern3.	100 = 1 min/m/% (max. 32767)
77.28	Speed No 3.14	Defines the speed preset value to where the speed ramps, from speed 77.26 <i>Speed No 3.13</i> during the time specified in parameter 77.27.	30.0%
	0.1200.0%	Speed preset value for section 14 in pattern3.	10 = 1%
77.29	Section No 3.15	Defines the time, length or proportional percentage preset value for section 15 in pattern3 ³⁾ .	10.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 15 in pattern3.	100 = 1 min/m/% (max. 32767)
77.30	Speed No 3.15	Defines the speed preset value to where the speed ramps, from speed 77.28 Speed No 3.14 during the time specified in parameter 77.29.	20.0%
	0.1200.0%	Speed preset value for section 15 in pattern3.	10 = 1%
77.31	Section No 3.16	Defines the time, length or proportional percentage preset value for section 16 in pattern3 ³⁾ .	1.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 16 in pattern3.	100 = 1 min/m/% (max. 32767)
77.32	Speed No 3.16	Defines the speed preset value to where the speed ramps, from speed 77.30 Speed No 3.15 during the time specified in parameter 77.31.	10.0%
	0.1200.0%	Speed preset value for section 16 in pattern3.	10 = 1%
77.33	Pattern3 mode	Selects the mode of pattern3.	Time
	Time	Pattern3 section values are defined in minutes.	0
	Length m	Pattern3 section values are defined in meters.	1
	Length %	Pattern3 section values are defined in percentage. 100% = Length defined with parameter 77.37 Pattern3 total length	2
77.34	Pattern3 TPI	Defines the amount of yarn twisting, based on the formula:	30.00 TPI
		Spinning speed 3 [1/min]	
		Front roller surface speed 3 [inch/min]	
	0.00200.00 TPI	Yarn twisting in TPI (Twist per inch)	100 = 1 TPI
77.35	Pattern3 count number	Defines the numerical designation of yarn size in pattern3.	30
	0200	Yarn size in pattern3.	1 = 1
77.36	Pattern3 section total	Shows the section total in pattern3. Sections total is the sum of sections 2.12.16 in parameter 77.01, 77.03, 77.0577.29, 77.31. This parameter is read-only.	-
	0.0099999.00 min	Pattern3 sections total in either time length m or length % mode.	100 = 1 min (max. 32767)

No.	Name/Value	Description	Def/FbEq16
77.37	Pattern3 total length	Defines the total length of pattern3 with parameter 77.33 <i>Pattern3 mode</i> in % mode. Note : This parameter is effective only when parameter 77.33 <i>Pattern3 mode</i> = Length [%].	100.0 m
	0.0999999.0 m	Pattern3 total length in % mode.	10 = 1 m (max. 32767)
78 Pa	ttern4	Defines the preset values for 16 sections in pattern4. ⁴⁾ In length mode, the control program converts the set value from length into time.	
78.01	Section No 4.1	Defines the time, length or proportional percentage preset value for section 1 in pattern4 ⁴⁾ .	1.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 1 in pattern4.	100 = 1 min/m/% (max. 32767)
78.02	Speed No 4.1	Defines the speed preset value to where the speed ramps, from zero speed during the time specified in parameter 78.01.	10.0%
	0.1200.0%	Speed preset value for section 1 in pattern2.	10 = 1%
78.03	Section No 4.2	Defines the time, length or proportional percentage preset value for section 2 in pattern4.	10.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 2 in pattern4.	100 = 1 min/m/% (max. 32767)
78.04	Speed No 4.2	Defines the speed preset value to where the speed ramps, from speed 78.02 Speed No 4.1 during the time specified in parameter 78.03^{4} .	20.0%
	0.1200.0%	Speed preset value for section 2 in pattern2.	10 = 1%
78.05	Section No 4.3	Defines the time, length or proportional percentage preset value for section 3 in pattern4.	15.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 3 in pattern4.	100 = 1 min/m/% (max. 32767)
78.06	Speed No 4.3	Defines the speed preset value to where the speed ramps, from speed 78.04 during the time specified in parameter 78.05 ⁴).	30.0%
	0.1200.0%	Speed preset value for section 3 in pattern2.	10 = 1%
78.07	Section No 4.4	Defines the time, length or proportional percentage preset value for section 4 in pattern4.	20.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 4 in pattern4.	100 = 1 min/m/% (max. 32767)
78.08	Speed No 4.4	Defines the speed preset value to where the speed ramps, from speed 78.06 during the time specified in parameter 78.07^{4} .	40.0%
	0.1200.0%	Speed preset value for section 4 in pattern4.	10 = 1%
78.09	Section No 4.5	Defines the time, length or proportional percentage preset value for section 5 in pattern4.	25.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 5 in pattern4.	100 = 1 min/m/% (max. 32767)

No.	Name/Value	Description	Def/FbEq16
78.10	Speed No 4.5	Defines the speed preset value to where the speed ramps, from speed 78.08 during the time specified in parameter 78.09 ⁴ .	50.0%
	0.1200.0%	Speed preset value for section 5 in pattern2.	10 = 1%
78.11	Section No 4.6	Defines the time, length or proportional percentage preset value for section 6 in pattern4.	30.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 6 in pattern4.	100 = 1 min/m/% (max. 32767)
78.12	Speed No 4.6	Defines the speed preset value to where the speed ramps, from speed 78.10 during the time specified in parameter 78.11^{4} .	60.0%
	0.1200.0%	Speed preset value for section 6 in pattern4.	10 = 1%
78.13	Section No 4.7	Defines the time, length or proportional percentage preset value for section 7 in pattern4.	35.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 7 in pattern4.	100 = 1 min/m/% (max. 32767)
78.14	Speed No 4.7	Defines the speed preset value to where the speed ramps, from speed 78.12 during the time specified in parameter 78.13^{4} .	70.0%
	0.1200.0%	Speed preset value for section 7 in pattern4.	10 = 1%
78.15	Section No 4.8	Defines the time, length or proportional percentage preset value for section 8 in pattern4.	40.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 8 in pattern4.	100 = 1 min/m/% (max. 32767)
78.16	Speed No 4.8	Defines the speed preset value to where the speed ramps, from speed 78.14 during the time specified in parameter 78.15^{4} .	80.0%
	0.1200.0%	Speed preset value for section 8 in pattern4.	10 = 1%
78.17	Section No 4.9	Defines the time, length or proportional percentage preset value for section 9 in pattern4.	45.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 9 in pattern4.	100 = 1 min/m/% (max. 32767)
78.18	Speed No 4.9	Defines the speed preset value to where the speed ramps, from speed 78.16 during the time specified in parameter 78.17^{4} .	75.0%
	0.1200.0%	Speed preset value for section 9 in pattern2.	10 = 1%
78.19	Section No 4.10	Defines the time, length or proportional percentage preset value for section 10 in pattern4.	35.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 10 in pattern4.	100 = 1 min/m/% (max. 32767)
78.20	Speed No 4.10	Defines the speed preset value to where the speed ramps, from speed 78.18 during the time specified in parameter 78.19 ⁴ .	70.0%
	0.1200.0%	Speed preset value for section 10 in pattern4.	10 = 1%

No.	Name/Value	Description	Def/FbEq16
78.21	Section No 4.11	Defines the time, length or proportional percentage preset value for section 11 in pattern4.	30.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 11 in pattern4.	100 = 1 min/m/% (max. 32767)
78.22	Speed No 4.11	Defines the speed preset value to where the speed ramps, from speed 78.20 during the time specified in parameter 78.21 ⁴⁾ .	60.0%
	0.1200.0%	Speed preset value for section 11 in pattern4.	10 = 1%
78.23	Section No 4.12	Defines the time, length or proportional percentage preset value for section 12 in pattern4.	25.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 12 in pattern4.	100 = 1 min/m/% (max. 32767)
78.24	Speed No 4.12	Defines the speed preset value to where the speed ramps, from speed 78.22 during the time specified in parameter 78.23 ⁴⁾ .	50.0%
	0.1200.0%	Speed preset value for section 12 in pattern4.	10 = 1%
78.25	Section No 4.13	Defines the time, length or proportional percentage preset value for section 13 in pattern4.	20.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 13 in pattern4.	100 = 1 min/m/% (max. 32767)
78.26	Speed No 4.13	Defines the speed preset value to where the speed ramps, from speed 78.24 during the time specified in parameter 78.25 ⁴⁾ .	40.0%
	0.1200.0%	Speed preset value for section 13 in pattern1.	10 = 1%
78.27	Section No 4.14	Defines the time, length or proportional percentage preset value for section 14 in pattern4.	15.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 14 in pattern4.	100 = 1 min/m/% (max. 32767)
78.28	Speed No 4.14	Defines the speed preset value to where the speed ramps, from speed 78.26 during the time specified in parameter 78.27 ⁴⁾ .	30.0%
	0.1200.0%	Speed preset value for section 14 in pattern4.	10 = 1%
78.29	Section No 4.15	Defines the time, length or proportional percentage preset value for section 15 in pattern4.	10.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 15 in pattern4.	100 = 1 min/m/% (max. 32767)
78.30	Speed No 4.15	Defines the speed preset value to where the speed ramps, from speed 78.28 during the time specified in parameter 78.29 ⁴⁾ .	20.0%
	0.1200.0%	Speed preset value for section 15 in pattern4.	10 = 1%
78.31	Section No 4.16	Defines the time, length or proportional percentage preset value for section 16 in pattern4.	1.00 min/m/%
	0.0050000.00 min/m/%	Time, length or proportional percentage for section 16 in pattern4.	100 = 1 min/m/% (max. 32767)

No.	Name/Value	Description	Def/FbEq16
78.32	Speed No 4.16	Defines the speed preset value to where the speed ramps, from speed 78.30 during the time specified in parameter 78.31^{4} .	10.0%
	0.1200.0%	Speed preset value for section 16 in pattern4.	10 = 1%
78.33	Pattern4 mode	Selects the mode of pattern4.	Time
	Time	Pattern4 section values are defined in minutes.	0
	Length [m]	Pattern4 section values are defined in meters.	1
	Length [%]	Pattern4 section values are defined in percentage. 100% = Length defined with parameter 78.37 Pattern4 total length	2
78.34	Pattern4 TPI	Defines the amount of yarn twisting, based on the formula:	30.00 TPI
		Spinning speed 4 [1/min]	
		Front roller surface speed 4 [inch/min]	
	0.00200.00 TPI	Yarn twisting in TPI (Twist per inch)	100 = 1 TPI
78.35	Pattern4 count number	Defines the numerical designation of yarn size in pattern4.	30
	0200	Yarn size in pattern4.	1 = 1
78.36	Pattern4 section total	Shows the section total in pattern4. Sections total is the sum of sections 2.12.16 in parameter 78.01, 78.03, 78.05,78.29, 78.31. This parameter is read-only.	-
	0.0099999.00 min/m/%	Pattern4 sections total in either time, length m or length % mode.	100 = 1 min/m/% (max. 32767)
78.37	Pattern4 total length	Defines the total length of pattern4 with parameter 78.33 Pattern4 mode in % mode. Note: This parameter is effective only when parameter 78.33 Pattern4 mode = Length [%].	100.0 m
	0.099999.0 m	Pattern4 total length in % mode	10 = 1 m (max. 32767)
		Ding frame machine peremeters used for actual value	

79 Ring frame machine		Ring frame machine parameters used for actual value calculation.	
79.01	Gear ratio	Defines the constant value for average speed calculation (spindle speed/motor speed).	10.00
	0.00300.00	Gear ratio	100 = 1
79.07	Pattern shift multiple	Defines the multiplication factor used to multiply the speed reference defined by patterns in groups 7578, if the Shift function is activated with parameter 74.03 Shift function sel.	1.00
	0.002.00	Shift multiplication factor.	100 = 1
79.08	Work shift start time	Defines the start time of shift with respect to real time.	07:00:00
	00.00.0023.59.59	Shift start time.	-
79.11	Work shift time	Defines the shift time for production and run time calculations.	8.00 h
	0.0030.00 h	Work shift time.	100 = 1 h
79.12	Number of spindle	Defines the number of spindles in the ring frame machine.	100
	030000	Spindle number.	1 = 1

No.	Name/Value	Description	Def/FbEq16
79.15	Front roller measurement	Selects the source for front roller speed measurement.	Not selected
	Not selected	Front roller speed measurement is not used. In this case, delivery length of yarn is calculated by parameter 75.34 Pattern1 TPI. The same method applies for groups 7678.	0
	DIO1 (Frequency input)	Proximity switch is used for front roller speed measurement and it is connected to DIO1 of control board.	1
	Encoder 1	Encoder1 is used for front roller speed measurement. See parameter groups 9193 for Encoder module settings.	2
	Encoder 2	Encoder2 is used for front roller speed measurement. See parameter groups 9193 for Encoder module settings.	3
79.16	Front roller diameter	Defines the diameter of front roller for the yarn length and twist per inch calculation. The use of this parameter presumes that speed measurement of front roller is used. See parameter 79.15 <i>Front roller measurement</i> .	50.0 mm
	0.099999.0 mm	Front roller diameter	10 = 1 mm (max. 32767)
79.17	Proximity switch pulse number	Defines the number of pulses per round when proximity switch is used to measure the speed when parameter 79.15 <i>Front roller measurement</i> is set to DIO (frequency input).	1
	0100	Proximity switch pulse number	1 = 1
79.19	TPI Start Speed	Defines the start speed for twist per inch (TPI) calculation.	100 rpm
	030000 rpm	TPI start speed.	1 = 1 rpm
79.20	TPI Filter Time	Defines the filter time constant for TPI calculation.	500 ms
	010000 ms	Filter time constant.	1 = 1 ms
79.21	TPI Deviation	Defines the allowed deviation between set TPI and actual TPI to trigger fault.	2.00 TPI
	0.001000.00 TPI	TPI deviation.	100 = 1 TPI

80 Wobbulation		Wobbulation function. See also description on page 47.	
80.01	Wobbulation up sel	Selects the source for upper Wobbulation.	DI3
	False	Upper Wobbulation is inactive.	0
	True	Upper Wobbulation is active.	1
	DI1	Digital input 1	2
	DI2	Digital input 2	3
	DI3	Digital input 3	4
	DI4	Digital input 4	5
	DI5	Digital input 5	6
	DI6	Digital input 6	7
	DIO1	Digital input/output 1	8
	DIO2	Digital input/output 2	9
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
80.02	Wobbulation down sel	Selects the source for lower Wobbulation.	DI4
	False	Lower Wobbulation is inactive.	0

No.	Name/Value	Description	Def/FbEq16
	True	Lower Wobbulation is active.	1
	DI1	Digital input 1	2
	DI2	Digital input 2	3
	DI3	Digital input 3	4
	DI4	Digital input 4	5
	DI5	Digital input 5	6
	DI6	Digital input 6	7
	DIO1	Digital input/output 1	8
	DIO2	Digital input/output 2	9
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
80.03	Wobbulation up multiple	Defines the multiplication factor used to multiply the speed reference of the running pattern section for upper wobbulation speed.	1.00
	1.002.00	Wobbulation up multiplication factor	100 = 1
80.04	Wobbulation down multiple	Defines the multiplication factor used to multiply the speed reference of the running pattern section for lower wobbulation speed.	1.00
	0.001.00	Wobbulation down multiplication factor.	100 = 1
80.05	Wobbulation acc time	Defines the acceleration time from base pattern speed to the upper wobbulation speed defined with parameter <i>80.03 Wobbulation up multiple</i> .	30.0 s
	0.01000.0 s	Wobbulation acceleration time.	10 = 1 s
80.06	Wobbulation dec time	Defines the deceleration time from base pattern speed to the lower wobbulation speed defined with parameter 80.04 <i>Wobbulation down multiple</i> .	30.0 s
	0.01000.0 s	Wobbulation deceleration time.	10 = 1 s
81 Ma	nual Doff	Manual doff function. See also description on page 50.	
81.01	Manual doff selection mode	Selects the mode to activate the Manual doff function.	Par 81.02
	Par 81.02	Manual doff is activated by parameter 81.02.	0
	Automatic	 Time mode – In this mode, manual doff is activated when % of completed pattern time is greater than % set in parameter 81.08 Manual doff activation percent. Length and Length % – In these modes, manual doff is activated when % of delivery length is greater than % set in parameter 81.08 Manual doff activation percent. 	1
81.02	Manual doff selection	Selects the source to activate the Manual doff function.	DI5
	False	Manual doff function is inactive	0
	True	Manual doff function is active	1
	DI1	Digital input 1	2
	DI2	Digital input 2	3
	DI3	Digital input 3	4
	DI4	Digital input 4	5
	DI5	Digital input 5	6

No.	Name/Value	Description	Def/FbEq16
	DI6	Digital input 6	7
	DIO1	Digital input/output 1	8
	DIO2	Digital input/output 2	9
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
81.03	Manual doff speed	Defines the speed preset value to where the speed decelerates from current actual speed during the time specified in parameter <i>81.04 Manual doff dec time</i> .	80.0%
	0.0200.0%	Manual doff speed	10 = 1%
81.04	Manual doff dec time	Defines the deceleration time from actual speed to manual doff speed defined with parameter <i>81.03 Manual doff speed</i> .	5.0 s
	0.01000.0 s	Deceleration time.	10 = 1 s
81.05	Manual doff time	Defines manual doff time after actual speed reached the manual doff speed (parameter <i>81.03 Manual doff speed</i>). Drive stops after manual doff time is completed and manual doff end status is updated in parameter <i>09.41 Spinning status word</i> , bit 3.	180 s
	030000 s	Manual doff preset time	1 = 1 s
81.06	Doff end alarm time	Defines the time for the warning event <i>D201 Doff end</i> in time mode, before end of active pattern during normal pattern run or if manual doff is activate.	10.0 min
	0.010000.0 min	Doff end alarm time during normal pattern.	10 = 1 min
81.07	Doff End alarm length	Defines the length for the warning event <i>D201 Doff end</i> in length or % length mode, before end of active pattern during normal pattern run or if manual doff is activated.	1000 min
	032000 min	Doff end alarm time during normal pattern.	1 = 1 min
81.08	Manual doff activation percent	Defines the manual doff activation percentage. Time mode – In this mode, manual doff is activated when percentage of completed pattern time is greater than the percentage set in this parameter. Length and length percentage mode – In this mode, manual doff is activated when the percentage of delivery length is greater than the percentage set in this parameter. Note : This parameter is valid only when the parameter <i>81.01</i> <i>Manual doff selection mode</i> is set to Automatic.	70.0 %
	0.0100.0%	Manual doff activation in percent.	10 = 1 %
81.09	Manual doff stop	Selects the type of drive stop after manual doff time is elapsed.	Internal
	Internal	Drive is stopped internally by program after manual doff time has elapsed.	0
	External	Drive is stopped through associated devices after manual doff time has elapsed.	1
82 SIo	w speed function	Slow speed function.	
82.01	Slow Speed	Defines the slow speed reference to start the drive when new pattern is started or pattern is restarted after pause or when pattern is restarted after a power failure and later continues with the pattern speed reference.	100 rpm
	030000 rpm	Slow speed in rpm.	1 = 1 min

No.	Name/Value	Description	Def/FbEq16
82.02	Slow speed run time	Defines the time for which the drive runs with slow speed reference and later switches to pattern speed reference. The time includes accelerating time to reach slow speed.	1.0 min
	0.03000.0 min	Slow speed run time in min.	1 = 1 min
82.03	Slow speed acceleration time1	Defines the acceleration time to reach slow speed.	1 s
	030000 s	Slow speed acceleration time1 in seconds.	1 = 1 s
82.04	Slow speed acceleration time 2	Defines the acceleration time to reach pattern speed from slow speed.	1 s
	030000 s	Slow speed acceleration time2 in seconds.	1 = 1 s
83 Shi	ft Report	Shift report parameters. See description of <i>Production in previous shifts</i> on page <i>43</i> . Note : All parameters in this group are read-only.	
83.01	Shift1 production	Shows the production in Kilograms during previous first shift.	_
00.07	Kg		_
	0.03000.0 Kg	Shift 1 production in Kg.	10 = 1 Kg
83.02	Shift1 production Hank	Shows the production in Hank during previous first shift.	-
	0.00 30000.00 Hank	Shift 1 production in Hank.	100 = 1 Hank (max. 32767)
83.03	Shift1 run time	Shows the total run time of machine during previous first shift.	-
	0.03000.0 min	Shift1 total run time in minutes.	10 = 1 min
83.04	Shift1 stop time	Shows the total stop time of machine during previous first shift.	-
	0.03000.0 min	Shift1 total stop time in minutes.	10 = 1 min
83.05	Shift1 KWh consumption	Shows the total energy (units) consumed during previous first shift.	-
	0.09000.0 KWh	Shift1 total consumption in KWh.	10 = 1 KWh (max. 32767)
83.06	Shift1 KWh per Kg	Shows the energy (units) consumed to produce a kilogram during previous first shift.	-
	0.0 9000.0 KWh/Kg	Shift1 total consumption in KWh.	10 = 1 KWh/Kg (max. 32767)
83.07	Shift1 GPS	Shows the production in grams per active spindle during previous first shift.	-
	03000 g	Shift1 production in grams.	1 = 1 g
83.08	Shift1 pattern count	Shows the total number of completed patterns during previous first shift.	-
	010000	Shift1 total number of completed patterns.	1 = 1
83.09	Shift2 production Kg	Shows the production in kilograms during previous second shift.	-
	0.03000.0 Kg	Shift2 production in Kg.	10 = 1 Kg
83.10	Shift2 production Hank	Shows the production in Hank during previous second shift.	-
	0.00 30000.00 Hank	Shift2 production in Hank.	100 = 1 Hank

No.	Name/Value	Description	Def/FbEq16
83.11	Shift2 run time	Shows the total run time of machine during previous second shift.	-
	0.03000.0 min	Shift2 total run time in minutes.	10 = 1 min
83.12	Shift2 stop time	Shows the total stop time of machine during previous second shift.	-
	0.03000.0 min	Shift2 total stop time in minutes.	10 = 1 min
83.13	Shift2 KWh consumption	Shows the total energy (units) consumed during previous second shift.	-
	0.09000.0 KWh	Shift2 energy consumption in KWh.	10 = 1 KWh (max. 32767)
83.14	Shift2 KWh per Kg	Shows the energy (units) consumed to produce a kilogram during previous second shift.	-
	0.0 9000.0 KWh/Kg	Shift2 energy consumption in KWh per Kg.	10 = 1 KWh/Kg (max. 32767)
83.15	Shift2 GPS	Shows the production in grams per active spindle during previous second shift.	-
	03000 g	Shift2 production in grams.	1 = 1 g
83.16	Shift2 pattern count	Shows the total number of completed patterns during previous second shift.	-
	010000	Shift2 total number of completed patterns.	1 = 1
83.17	Shift3 production Kg	Shows the production in kilograms during previous third shift.	-
	0.03000.0 Kg	Shift3 production in Kg.	10 = 1 Kg
83.18	Shift3 production Hank	Shows the production in Hank during previous third shift.	-
	0.00 30000.00 Hank	Shift3 production in Hank.	100 = 1 Hank (max. 32767)
83.19	Shift3 run time	Shows the total run time of machine during previous third shift.	-
	0.03000.0 min	Shift3 total run time in minutes.	10 = 1 min
83.20	Shift3 stop time	Shows the total stop time of machine during previous third shift.	-
	0.03000.0 min	Shift3 total stop time in minutes.	10 = 1 min
83.21	Shift3 KWh consumption	Shows the total energy (units) consumed during previous third shift.	-
	0.09000.0 KWh	Shift3 energy consumption in KWh.	10 = 1 KWh (max. 32767)
83.22	Shift3 KWh per Kg	Shows the energy (units) consumed to produce a kilogram during previous third shift.	-
	0.0 9000.0 KWh/Kg	Shift3 energy consumption in KWh/Kg.	10 = 1 KWh/Kg (max. 32767)
83.23	Shift3 GPS	Shows the production in grams per active spindle during previous third shift	-
	03000 g	Shift3 production in grams.	1 = 1 g

No.	Name/Value	Description	Def/FbEq16
83.24	Shift3 pattern count	Shows the total number of completed patterns during previous third shift.	-
	010000	Shfit3 total completed patterns.	1 = 1
83.25	Shift4 production Kg	Shows the production in kilograms during previous fourth shift.	-
	03000.0 Kg	Shift4 production in Kg.	10 = 1 Kg
83.26	Shift4 production Hank	Shows the production in Hank during previous fourth shift.	-
	0.00 30000.00 Hank	Shift4 production in hank.	100 = 1 Hank (max. 32767)
83.27	Shift4 run time	Shows the total run time of machine during previous fourth shift.	-
	0.03000.0 min	Shift4 total run time in minutes.	10 = 1 min
83.28	Shift4 stop time	Shows the total stop time of machine during previous fourth shift.	-
	0.03000.0 min	Shift4 total stop time in minutes.	10 = 1 min
83.29	Shift4 KWh consumption	Shows the total energy (units) consumed during previous fourth shift.	-
	0.09000.0 KWh	Shift4 energy consumption in KWh.	10 = 1 KWh (max. 32767)
83.30	Shift4 KWh per Kg	Shows the energy (units) consumed to produce a kilogram during previous fourth shift.	-
	0.0 9000.0 KWh/Kg	Shift4 energy consumption in KWh/Kg.	10 = 1 KWh/Kg (max. 32767)
83.31	Shift4 GPS	Shows the production in grams per active spindle during previous fourth shift.	-
	03000 g	Shift4 production in grams.	1 = 1 g
83.32	Shift4 pattern count	Shows the total number of completed patterns during previous fourth shift.	-
	010000	Shift4 total number of completed patterns.	1 = 1
83.33	Shift5 production Kg	Shows the production in kilograms during previous fifth shift.	-
	0.03000.0 Kg	Shift5 production in Kg.	10 = 1 Kg
83.34	Shift5 production Hank	Shows the production in Hank during previous fifth shift.	-
	0.00 30000.00 Hank	Shift5 production in Hank.	100 = 1 Hank (max. 32767)
83.35	Shift5 run time	Shows the total run time of machine during previous fifth shift.	-
	0.03000.0 min	Shift5 total run time in minutes.	10 = 1 min
83.36	Shift5 stop time	Shows the total stop time of machine during previous fifth shift.	-
	0.03000.0 min	Shift5 total stop time in minutes.	10 = 1 min
83.37	Shift5 KWh consumption	Shows the total energy (units) consumed during previous fifth shift.	-
	0.09000.0 KWh	Shift5 energy consumption in KWh.	10 = 1 KWh (max. 32767)

No.	Name/Value	Description	Def/FbEq16
83.38	Shift5 KWh per Kg	Shows the energy (units) consumed to produce a kilogram during previous fifth shift.	-
	0.0 9000.0 KWh/Kg	Shift5 consumption in KWh/Kg.	10 = 1 KWh/Kg (max. 32767)
83.39	Shift5 GPS	Shows the production in grams per active spindle during previous fifth shift.	-
	03000 g	Shift5 production in grams.	1 = 1 g
83.40	Shift5 pattern count	Shows the total number of completed patterns during previous fifth shift.	-
	010000	Shift5 total number of completed patterns.	1 = 1
84 Doi	ff report	Doff report parameters. See description of <i>Doff production</i> on page <i>49</i> . Note : All parameters in this group are read-only.	
84.01	Doff1 production Kg	Shows the production in kilogram in previous first pattern.	-
	0.03000.0 Kg	Doff1 production in Kg.	10 = 1 Kg
84.02	Doff1 production hank	Shows the production in Hank in previous first pattern.	-
	0.00 30000.00 Hank	Doff 1 production in Hank.	100 = 1 Hank (max. 32767)
84.03	Doff1 total run time	Shows the total doff time of previous first pattern.	-
	0.03000.0 min	Doff1 total run time in minutes.	10 = 1 min
84.04	Doff1 Pattern stop time	Shows the total stop time of previous first pattern.	-
	0.03000.0 min	Doff1 pattern stop time in minutes.	10 = 1 min
84.05	Doff1 KWh	Shows the total energy (units) during previous first pattern.	-
	0.03000.0 KWh	Doff1 energy consumed in KWh.	10 = 1 KWh
84.06	Doff1 KWh/Kg	Shows the total energy (units) consumed to produce a kilogram during previous first pattern.	-
	0.0 3000.0 KWh/Kg	Doff1 consumption in KWh/Kg.	10 = 1 KWh/Kg
84.07	Doff2 production Kg	Shows the production in kilogram in previous second pattern.	-
	0.03000.0 Kg	Doff2 production in Kg.	1 = 10 Kg
84.08	Doff2 production hank	Shows the production in Hank in previous second pattern.	-
	0.00 30000.00 Hank	Doff2 production in Hank.	100 = 1 Hank (max. 32767)
84.09	Doff2 total run time	Shows the total run time of previous second pattern.	-
	0.03000.0 min	Doff2 total run time in minutes.	10 = 1 min
84.10	Doff2 Pattern stop time	Shows the total stop time during previous second pattern.	-
	0.03000.0 min	Doff2 pattern stop time in minutes.	10 = 1 min
84.11	Doff2 KWh	Shows the total energy (units) consumed during previous second pattern.	-
	0.03000.0 KWh	Doff2 energy consumed in KWh.	10 = 1 KWh
L			•

No.	Name/Value	Description	Def/FbEq16
84.12	Doff2 KWh/Kg	Shows the energy (units) consumed to produce a kilogram during previous second pattern.	-
	0.0 3000.0 KWh/Kg	Doff2 energy consumption in KWh/Kg.	10 = 1 KWh/Kg
84.13	Doff3 production Kg	Shows the production in kilogram in previous third pattern.	-
	0.03000.0 kg	Doff3 production in Kg.	10 = 1 kg
84.14	Doff3 production hank	Shows the production in Hank in previous third pattern.	-
	0.00 30000.00 Hank	Doff3 production in Hank.	100 = 1 Hank (max. 32767)
84.15	Doff3 total run time	Shows the total Doff time during previous third pattern.	-
	0.03000.0 min	Doff3 total run time in minutes.	10 = 1 min
84.16	Doff3 Pattern stop time	Shows the total stop time during previous third pattern.	-
	0.03000.0 min	Doff3 pattern stop time in minutes.	10 = 1 min
84.17	Doff3 KWh	Shows the total energy (units) consumed during previous third pattern.	-
	0.03000.0 KWh	Doff3 energy (units) consumed in KWh.	10 = 1 KWh
84.18	Doff3 KWh/Kg	Shows the energy (units) consumed to produce a kilogram during previous third pattern.	-
	0.0 3000.0 KWh/Kg	Doff3 energy (units) consumed in KWh/Kg.	10 = 1 KWh/Kg
84.19	Doff4 production Kg	Shows the production in kilogram during previous fourth pattern.	-
	0.03000.0 Kg	Doff4 production in Kg.	10 = 1 Kg
84.20	Doff4 production hank	Shows the production in Hank during previous fourth pattern.	-
	0.00 30000.00 Hank	Doff4 production in hank.	100 = 1 Hank (max. 32767)
83.21	Doff4 total run time	Shows the total Doff time of previous fourth pattern.	-
	0.03000.0 min	Doff4 total run time in minutes.	10 = 1 min
84.22	Doff4 Pattern stop time	Shows the total stop time of previous fourth pattern.	-
	0.03000.0 min	Doff4 pattern stop time in minutes.	10 = 1 min
84.23	Doff4 KWh	Shows the total energy (units) consumed during previous fourth pattern.	-
	0.03000.0 KWh	Doff4 energy (units) consumed in KWh.	10 = 1 KWh
84.24	Doff4 KWh/Kg	Shows the energy (units) consumed to produce a kilogram during previous fourth pattern.	-
	0.00 3000.0 KWh/Kg	Doff4 energy (units) consumed in KWh/Kg.	10 = 1 KWh/Kg
84.25	Doff5 production Kg	Shows the production in kilogram during previous fifth pattern.	-
	0.03000.0 Kg	Doff5 production in Kg.	10 = 1 Kg

No.	Name/Value	Description	Def/FbEq16
84.26	Doff5 production hank	Shows the production in Hank produced of previous fifth pattern.	-
	0.00 30000.00 hank	Doff5 production in Hank.	100 = 1 Hank (max. 32767)
84.27	Doff5 total run time	Shows the total run time of previous fifth pattern.	-
	0.03000.0 min	Doff5 total run time in minutes.	10 = 1 min
84.28	Doff5 Pattern stop time	Shows the total stop time of previous fifth pattern.	-
	0.03000.0 min	Doff5 pattern stop time in minutes.	10 = 1 min
84.29	Doff5 KWh	Shows the total energy (units) consumed during previous fifth pattern.	-
	0.03000.0 KWh	Doff5 energy (units) consumed in KWh.	10 = 1 KWh
84.30	Doff5 KWh/Kg	Shows the energy (units) consumed to produce a kilogram during previous fifth pattern.	-
	0.0 3000.0 KWh/Kg	Doff5 energy (units) consumed in KWh/Kg.	10 = 1 KWh/Kg
84.31	Doff6 production Kg	Shows the production in kilogram produced during previous sixth pattern.	-
	0.03000.0 Kg	Doff6 production in Kg.	10 = 1 Kg
84.32	Doff6 production hank	Shows the production in Hank produced during previous sixth pattern.	-
	0.00 30000.00 Hank	Doff6 production in Hank.	100 = 1 Hank (max. 32767)
84.33	Doff6 total run time	Shows the total run time during previous sixth pattern.	-
	0.03000.0 min	Doff6 total run time in minutes.	10 = 1 min
84.34	Doff6 Pattern stop time	Shows the total stop time during previous sixth pattern.	-
	0.03000.0 min	Doff6 pattern stop time in minutes.	10 = 1 min
84.35	Doff6 KWh	Shows the total energy (units) consumed during previous sixth pattern.	-
	0.03000.0 KWh	Doff6 energy (units) consumed in KWh.	10 = 1 KWh
84.36	Doff6 KWh/Kg	Shows the energy (units) consumed to produce a kilogram during previous sixth pattern.	-
	0.0 3000.0 KWh/Kg	Doff6 energy (units) consumed in KWh/Kg.	10 = 1 KWh/Kg
84.37	Doff7 production Kg	Shows the production in kilogram produced during previous seventh pattern.	-
	0.03000.0 Kg	Doff7 production in Kg.	10 = 1 Kg
84.38	Doff7 production hank	Shows the production in Hank produced during previous seventh pattern.	-
	0.00 30000.00 Hank	Doff7 production in Hank.	100 = 1 Hank (max. 32767)
84.39	Doff7 total run time	Shows the total run time of previous seventh pattern.	-
	0.03000.0 min	Doff7 total run time in minutes.	10 = 1 min

No.	Name/Value	Description	Def/FbEq16
84.40	Doff7 Pattern stop time	Shows the total stop time during previous seventh pattern.	-
	0.03000.0 min	Doff7 pattern stop time in minutes.	10 = 1 min
84.41	Doff7 KWh	Shows the total energy (units) consumed during previous seventh pattern.	-
	0.03000.0 KWh	Doff7 energy (units) consumed in KWh.	10 = 1 KWh
84.42	Doff7 KWh/Kg	Shows the energy (units) consumed to produce a kilogram during previous seventh pattern.	-
	0.0 3000.0 KWh/Kg	Doff7 energy (units) consumption in KWh/Kg.	10 = 1 KWh/Kg
84.43	Doff8 production Kg	Shows the production in kilogram duirng previous eighth pattern.	-
	0.03000.0 Kg	Doff8 production in Kg.	10 = 1 Kg
84.44	Doff8 production hank	Shows the production in Hank during previous eighth pattern.	-
	0.0 30000.0 Hank	Doff8 production in Hank.	100= 1 Hank (max. 32767)
84.45	Doff8 total run time	Shows the total run time of previous eighth pattern.	-
	0.03000.0 min	Doff8 total run time in minutes.	10 = 1 min
84.46	Doff8 Pattern stop time	Shows the total stop time during previous eighth pattern.	-
	0.03000.0 min	Doff8 pattern stop time in minutes.	10 = 1 min
84.47	Doff8 KWh	Shows the total energy (units) consumed during previous eighth pattern.	-
	0.03000.0 KWh	Doff8 energy (units) consumed in KWh.	10 = 1 KWh
84.48	Doff8 KWh/Kg	Shows the KWh consumed to produce a Kg during previous eighth pattern.	-
	0.0 3000.0 KWh/Kg	Doff8 consumption in KWh/Kg.	10 = 1 KWh/Kg
84.49	Doff9 production Kg	Shows the production in kilogram during previous ninth pattern.	-
	0.03000.0 Kg	Doff9 production in Kg.	10 = 1 Kg
84.50	Doff9 production hank	Shows the production in Hank during previous ninth pattern.	-
	0.00 30000.00 Hank	Doff9 production in Hank.	100 = 1 Hank (max. 32767)
84.51	Doff9 total run time	Shows the total run time of previous ninth pattern.	-
	0.03000.0 min	Doff9 total run time in minutes.	10 = 1 min
84.52	Doff9 Pattern stop time	Shows the total stop time during previous ninth pattern	-
	0.03000.0 min	Doff9 pattern stop time in minutes.	10 = 1 min
84.53	Doff9 KWh	Shows the total energy (units) during previous ninth pattern	-
	0.03000.0 KWh	Doff9 energy (units) consumed in KWh.	10 = 1 KWh

No.	Name/Value	Description	Def/FbEq16
83.54	Doff9 KWh/Kg	Shows the energy (units) consumed to produce a kilogram during previous ninth pattern.	-
	0.0 3000.0 KWh/Kg	Doff9 energy (units) consumed in KWh/Kg.	10 = 1 KWh/Kg
84.55	Doff10 production Kg	Shows the production in Kg during previous tenth pattern.	-
	0.03000.0 Kg	Doff10 production in Kg.	10 = 1 Kg
84.56	Doff10 production hank	Shows the production in Hank during previous tenth pattern.	-
	0.00 30000.00 Hank	Doff10 production in Hank.	100 = 1 Hank (max. 32767)
84.57	Doff10 total run time	Shows the total run time of previous tenth pattern.	-
	0.03000.0 min	Doff10 total run time in minutes.	10 = 1 min
84.58	Doff10 Pattern stop time	Shows the total stop time of previous tenth pattern.	-
	0.03000.0 min	Doff10 pattern stop time in minutes.	10 = 1 min
84.59	Doff10 KWh	Shows the total energy (units) consumed during previous tenth pattern.	-
	0.03000.0 KWh	Doff10 energy (units) consumed in KWh.	10 = 1 KWh
84.60	Doff10 KWh/Kg	Shows the energy (units) consumed to produce a kilogram during previous tenth pattern.	-
	0.0 3000.0 KWh/Kg	Doff10 energy (units) consumption in KWh/Kg.	10 = 1 KWh/Kg
88 Traverse		Traverse control function. Unlike the spinning control function, the Traverse control function works in both Local and Remote control modes. Note : The base speed of traverse is selected by group 22 Speed reference selection. Parameter 22.01 Speed ref	

		Note: The base speed of traverse is selected by group 22Speed reference selection. Parameter 22.01 Speed refunlimited is considered as the base speed for traversecontrol.See control chain diagram Overview of traverse controlprogram on page 51.	
88.01	Traverse control	Enables the traverse control program.	Disable
	Disable	Traverse control is disabled.	0
	Enable	Traverse control is enabled.	1
88.02	Slow acc time	Defines the acceleration time for the traverse control function.	10.00 s
	0.0030000.00 s	Time	100 = 1 s (max. 32767)
88.03	Slow dec time	Defines the deceleration time for the traverse control function.	10.00 s
	0.0030000.00 s	Time	100 = 1 s (max. 32767)

No.	Name/Value	Description	Def/FbEq16
88.04	Slow step up	 Defines the maximum traverse speed. Maximum speed = Value in parameter 22.01 Speed ref unlimited + value in this parameter. Note: The value must not exceed the maximum speed limit of the drive defined in parameter 30.11 Minimum speed. Unit depends on the parameter 88.08 Proportional steps. 	300 rpm
	018000 rpm	Speed	1 = 1 rpm/%
88.05	Slow step down	 Defines the minimum traverse speed. Minimum speed = Value in parameters 22.01 Speed ref unlimited - value in this parameter. Note: The value may not be negative. Unit depends on the parameter 88.08 Proportional steps. 	300 rpm
	018000 rpm	Speed	1 = 1 rpm/%
88.06	Quick step high	Defines the speed step that the traverse function takes downwards after reaching the maximum traverse speed. Note: Unit depends on the parameter <i>88.08 Proportional steps</i> .	50 rpm
	07200 rpm	Speed	1 = 1 rpm/%
88.07	Quick step low	Defines the speed step that the traverse function takes upwards after reaching the minimum traverse speed. Note: Unit depends on the parameter <i>88.08 Proportional steps</i> .	50 rpm
	07200 rpm	Speed	1 = 1 rpm/%
88.08	Proportional steps	 Switches the unit to percent in parameters 88.0488.07. Values of parameters 88.04 Slow step up and 88.05 Slow step down are given in percent of base speed. Values of parameters 88.06 Quick step high and 88.07 Quick step low are given in percent of values in parameters 88.04 and 88.05 respectively. 	Not selected
	Not selected	Inactive	0
	Selected	Active	1

90 Feedback selection		Motor and load feedback configuration. See also section <i>Encoder support</i> (page 82) and <i>Reading/writing position counter values through fieldbus</i> (page 86), and the diagram on page 633.	
90.01	Motor speed for control	Displays the estimated or measured motor speed that is used for motor control, ie. final motor speed feedback selected by parameter 90.41 Motor feedback selection and filtered by parameter 90.42 Motor speed filter time. In case measured feedback is selected, it is also scaled by the motor gear function (90.43 Motor gear numerator and 90.44 Motor gear denominator). This parameter is read-only.	-
	-32768.00 32767.00 rpm	Motor speed used for control.	See par. 46.01

No.	Name/Value	Description	Def/FbEq16
90.02	Motor position	Displays the motor position (within one revolution) received from the source selected by parameter <i>90.41 Motor feedback</i> <i>selection</i> . In case measured feedback is selected, it is also scaled by the motor gear function (<i>90.43 Motor gear numerator</i> and <i>90.44 Motor gear denominator</i>). This parameter is read-only.	-
	0.00000000 1.00000000 rev	Motor position.	32767 = 1 rev
90.03	Load speed	Displays the estimated or measured load speed used for motor control, that is final load speed feedback selected by parameter 90.51 Load feedback selection and filtered by parameter 90.52 Load speed filter time. If measured feedback is selected, it is scaled by the load gear function (90.53 Load gear numerator and 90.54 Load gear denominator). If motor feedback or estimated feedback is used, it is inversely scaled by 90.61 Gear numerator and 90.62 Gear denominator (that is 90.62 divided by 90.61). This parameter is read-only.	-
	-32768.00 32767.00 rpm	Load speed.	See par. 46.01
90.04	Load position	Displays the load position received from the source selected by parameter 90.51 Load feedback selection. The value is multiplied as specified by parameter 90.57 Load position resolution. If measured feedback is selected, it is scaled by the load gear function (90.53 Load gear numerator and 90.54 Load gear denominator). If motor feedback or estimated feedback is used, it is inversely scaled by 90.61 Gear numerator and 90.62 Gear denominator (that is 90.62 divided by 90.61). An offset can be defined by 90.56 Load position offset. This parameter is read-only.	-
	-2147483648 2147483647	Load position.	-
90.05	Load position scaled	Displays the scaled load position in decimal format. The position is relative to the initial position set by parameters 90.6590.69. The number of decimal places is defined by parameter 90.38 <i>Pos counter decimals.</i> Note: This is a floating point parameter, and the accuracy is compromised near the ends of the range. Consider using parameter 90.07 <i>Load position scaled int</i> instead of this parameter. This parameter is read-only.	-
	-2147483.648 2147483.647	Scaled load position in decimal format.	-

No.	Name/Value	Description	Def/FbEq16
90.06	Motor position scaled	Displays the calculated motor position. The axis mode (linear or rollover) and resolution are defined by parameters 90.48 Motor position axis mode and 90.49 Motor position resolution respectively. Note: The position value can be sent on a fast time level to the fieldbus controller by selecting <i>Position</i> in either 50.07 <i>FBA A actual 1 type</i> , 50.08 <i>FBA A actual 2 type</i> , 50.37 <i>FBA B</i> <i>actual 1 type</i> or 50.38 <i>FBA B actual 2 type</i> . This parameter is read-only.	-
	-2147483.648 2147483.647	Motor position.	-
90.07	Load position scaled int	Displays the output of the position counter function as an integer, enabling backwards compatibility with ACS 600 and ACS800 drives. The position is relative to the initial position set by parameters <i>90.58</i> and <i>90.59</i> . See section <i>Reading/writing position counter values through fieldbus</i> (page <i>86</i>), and the block diagram on page <i>634</i> . This parameter is read-only.	-
	-2147483648 2147483647	Scaled load position in integer format.	-
90.10	Encoder 1 speed	Displays encoder 1 speed in rpm. This parameter is read-only.	-
	-32768.00 32767.00 rpm	Encoder 1 speed.	See par. 46.01
90.11	Encoder 1 position	Displays the actual position of encoder 1 within one revolution. This parameter is read-only.	-
	0.00000000 1.00000000 rev	Encoder 1 position within one revolution.	32767 = 1 rev
90.12	Encoder 1 multiturn revolutions	Displays the revolutions of (multiturn) encoder 1 within its value range (see parameter <i>92.14 Revolution data width</i>). This parameter is read-only.	-
	016777215	Encoder 1 revolutions.	-
90.13	Encoder 1 revolution extension	Displays the revolution count extension for encoder 1. With a single-turn encoder, the counter is incremented when encoder position (parameter 90.11) wraps around in the positive direction, and decremented in the negative direction. With a multiturn encoder, the counter is incremented when the revolutions count (parameter 90.12) exceeds the value range in the positive direction, and decremented in the negative direction. This parameter is read-only.	-
	-2147483648 2147483647	Encoder 1 revolution count extension.	-
90.14	Encoder 1 position raw	Displays the raw measurement data of encoder 1 position (within one revolution) as a 24-bit unsigned integer received from the encoder interface. This parameter is read-only.	-
	016777215	Raw encoder 1 position within one revolution.	-

No.	Name/Value	Description	Def/FbEq16
90.15	Encoder 1 revolutions raw	Displays the revolutions of (multiturn) encoder 1 within its value range (see parameter 92.14 Revolution data width) as a raw measurement. This parameter is read-only.	-
	016777215	Raw encoder 1 revolution count.	-
90.20	Encoder 2 speed	Displays encoder 2 speed in rpm. This parameter is read-only.	-
	-32768.00 32767.00 rpm	Encoder 2 speed.	See par. 46.01
90.21	Encoder 2 position	Displays the actual position of encoder 2 within one revolution. This parameter is read-only.	-
	0.00000000 1.00000000 rev	Encoder 2 position within one revolution.	-
90.22	Encoder 2 multiturn revolutions	Displays the revolutions of (multiturn) encoder 2 within its value range (see parameter <i>93.14 Revolution data width</i>). This parameter is read-only.	-
	016777215	Encoder 2 revolutions.	-
90.23	Encoder 2 revolution extension	Displays the revolution count extension for encoder 2. With a single-turn encoder, the counter is incremented when encoder position (parameter 90.21) wraps around in the positive direction, and decremented in the negative direction. With a multiturn encoder, the counter is incremented when the revolutions count (parameter 90.22) exceeds the value range in the positive direction, and decremented in the negative direction. This parameter is read-only.	-
	-2147483648 2147483647	Encoder 2 revolution count extension.	-
90.24	Encoder 2 position raw	Displays the raw measurement data of of encoder 2 position (within one revolution) as a 24-bit unsigned integer received from the encoder interface. This parameter is read-only.	-
	016777215	Raw encoder 2 position within one revolution.	-
90.25	Encoder 2 revolutions raw	Displays the revolutions of (multiturn) encoder 2 within its value range (see parameter 93.14 Revolution data width) as a raw measurement. This parameter is read-only.	-
	016777215	Raw encoder 2 revolution count.	-
90.26	Motor revolution extension	Displays the motor revolution count extension. The counter is incremented when the position selected by 90.41 Motor feedback selection wraps around in the positive direction, and decremented in the negative direction. This parameter is read-only.	-
	-2147483648 2147483647	Motor revolution count extension.	-

No.	Name/	Value	Descri	ption	Def/FbEq16	
90.27	Load revolution extension		The co 90.51 L directio	vs the load revolution count extension. unter is incremented when the position selected by <i>coad feedback selection</i> wraps around in the positive on, and decremented in the negative direction. arameter is read-only.	-	
	-21474 214748	83648 33647	Load re	evolution count extension.	-	
90.35	Pos co	unter status	See se fieldbus	information related to the position counter function. ction <i>Reading/writing position counter values through</i> s (page <i>86</i>). arameter is read-only.	-	
	Bit	Name		Value		
	0	Encoder 1 feedback		1 = Encoder 1 selected as load feedback source		
	1	Encoder 2 feedback		1 = Encoder 2 selected as load feedback source		
	2	Internal pos feedback	sition	1 = Internal load position estimate selected as load fee	dback source	
	3	Motor feed	back	1 = Motor feedback selected as load feedback source		
	4	Pos counte ready	r init	 0 = Position counter not initialized, or encoder feedbac Fresh counter initialization recommended. 1 = Position counter successfully initialized 	k was lost.	
	5	Position co init disable		1 = Position counter initialization is being prevented by	par. 90.68	
	6	Position data inaccurate		1 = Encoder feedback intermittent or lost. (If the drive is running, estimated position is used whenever encoder feedback is unavailable. If the drive is in stopped state, position counting will continue based on encoder data after the connection is restored.)		
	715 Reserved					
	0000 0 0111 11	000b I11b	Positio	n counter status word.	1 = 1	
90.38	Pos counter S decimals fr C F W tt		and 90 from an corresp For exa written the fina	the values of parameters 90.05 Load position scaled .65 Pos counter init value when written from or read to n external source (eg. fieldbus). The setting bonds to the number of decimal places. ample, with the setting of 3, an integer value of 66770 into 90.65 Pos counter init value is divided by 1000, so al value applied will be 66.770. Likewise, the value of Load position scaled is multiplied by 1000 when read.	3	
	09			r of position counter decimal places.	1 = 1	
90.41	Motor f	eedback on	Selects control	the motor speed feedback value used during motor	Estimate	
	Estima	te	A calcu used.	lated speed estimate generated from the DTC core is	0	
	Encode	er 1		speed measured by encoder 1. The encoder is set up parameters in group 92 <i>Encoder 1 configuration</i> .	1	
	Encode	er 2		speed measured by encoder 2. The encoder is set up parameters in group 93 <i>Encoder 2 configuration</i> .	2	

No.	Name/Value	Description	Def/FbEq16
90.42	Motor speed filter time	Defines a filter time for motor speed feedback used for control (90.01 Motor speed for control).	3 ms
	0 10000 ms	Motor speed filter time.	1 = 1 ms
90.43	Motor gear numerator	Parameters 90.43 and 90.44 define a gear function between the motor speed feedback and motor control. The gear is used to correct a difference between the motor and encoder speeds for example if the encoder is not mounted directly on the motor shaft.	1
		90.43 Motor gear numerator Motor speed	
		90.44 Motor gear denominator Encoder speed	
	-2147483648 2147483647	Motor gear numerator.	-
90.44	Motor gear denominator	See parameter 90.43 Motor gear numerator.	1
	-2147483648 2147483647	Motor gear denominator.	-
90.45	Motor feedback fault	Selects how the drive reacts to loss of measured motor feedback.	Fault
	Fault	Drive trips on a 7301 Motor speed feedback or 7381Encoder fault.	0
	Warning	Drive generates a <i>A7B0 Motor speed feedback</i> or <i>A7E1</i> <i>Encoder</i> warning and continues operation using estimated feedbacks. Note: Before using this setting, test the stability of the speed control loop with estimated feedback by running the drive on estimated feedback (see <i>90.41 Motor feedback selection</i>).	1
90.46	Force open loop	Defines the speed feedback used by the DTC motor model.	No
	No	The motor model uses the feedback selected by 90.41 Motor feedback selection.	0
	Yes	The motor model uses the calculated speed estimate (regardless of the setting of <i>90.41 Motor feedback selection</i> , which in this case only selects the source of feedback for the speed controller).	1
90.48	Motor position axis mode	Selects the axis type for motor position measurement.	Rollover
	Linear	Linear.	0
	Rollover	The value is between 0 and 1 revolutions, and rolls over at 360 degrees.	1
90.49	Motor position resolution	Defines how many bits are used for motor position count within one revolution. For example, with the setting of 24, the position value is multiplied by 16777216 for display in parameter <i>90.06 Motor position scaled</i> (or for fieldbus).	24
	031	Motor position resolution.	-
90.51	Load feedback selection	Selects the source of load speed and position feedbacks used in control.	None
	None	No load feedback selected.	0

No.	Name/Value	Description	Def/FbEq16
	Encoder 1	Load feedbacks are updated based on the speed and position values read from encoder 1. The values are scaled by the load gear function (90.53 Load gear numerator and 90.54 Load gear denominator). The encoder is set up by the parameters in group 92 Encoder 1 configuration.	1
	Encoder 2	Load feedbacks are updated based on the speed and position values read from encoder 2. The values are scaled by the load gear function (90.53 Load gear numerator and 90.54 Load gear denominator). The encoder is set up by the parameters in group 93 Encoder 2 configuration.	2
	Estimate	Calculated speed and position estimates are used. The values are scaled from the motor side to the load side using the inverted ratio between 90.61 Gear numerator and 90.62 Gear denominator (that is 90.62 divided by 90.61).	3
	Motor feedback	The source selected by parameter 90.41 Motor feedback selection for motor feedback is also used for load feedback. Any difference between the motor and load speeds (and positions) can be compensated by using the inverted ratio between 90.61 Gear numerator and 90.62 Gear denominator (that is 90.62 divided by 90.61).	4
90.52	Load speed filter time	Defines a filter time for load speed feedback (90.03 Load speed).	4 ms
	0 10000 ms	Load speed filter time.	-
90.53			1
		90.54 Load gear denominator Encoder speed	
	-2147483648 2147483647	Load gear numerator.	-
90.54	Load gear denominator	See parameter 90.53 Load gear numerator.	1
	-2147483648 2147483647	Load gear denominator.	-
90.55	Load feedback fault	Selects how the drive reacts to loss of load feedback.	Fault
	Fault	Drive trips on a 73A1 Load feedback fault.	0
	Warning	Drive generates a <i>A7B1 Load speed feedback</i> warning and continues operation using estimated feedbacks.	1
90.56	Load position offset	Defines a load-side position offset. The resolution is determined by parameter <i>90.57 Load position resolution</i> .	0 rev
	-2147483648 2147483647 rev	Load-side position offset.	-

No.	Name/Value	Description	Def/FbEq16
90.57	Load position resolution	Defines how many bits are used for load position count within one revolution. For example, with the setting of 16, the position value is multiplied by 65536 for display in parameter 90.04 Load position.	16
	031	Load position resolution.	-
90.58	Pos counter init value int	Defines an initial position (or distance) for the position counter (as an integer value) when parameter 90.59 Pos counter init value int source is set to Pos counter init value int. See also section <i>Reading/writing position counter values</i> <i>through fieldbus</i> (page 86).	0
	-2147483648 2147483647	Initial integer value for position counter.	-
90.59	Pos counter init value int source	Selects the source of the initial position integer value. When the source selected by 90.67 Pos counter init cmd source activates, the value selected in this parameter is assumed to be the position of the load.	Pos counter init value int
	Zero	0.	0
	Pos counter init value int	Parameter 90.58 Pos counter init value int.	1
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
90.60	Pos counter error and boot action	Selects how the position counter reacts to loss of load feedback.	Request re- initialization
	Request re- initialization	Bit 4 of <i>90.35 Pos counter status</i> is cleared. Reinitialization of position counter is recommended.	0
	Continue from previous value	Position counting resumes from the previous value over a loss of load feedback or control unit reboot. Bit 4 of 90.35 Pos counter status is not cleared, but bit 6 is set to indicate that an error has occurred.Marking!If load feedback is lost when the drive is in stopped state or not powered, the counter is not updated even if the load moves.	1
90.61	Gear numerator	Parameters 90.61 and 90.62 define a gear function between the motor and load speeds.	1
		90.61 Gear numerator Motor speed	
		90.62 Gear denominator = Load speed	
	-2147483648 2147483647	Gear numerator (motor-side).	-
90.62	Gear denominator	See parameter 90.61 Gear numerator.	1
	-2147483648 2147483647	Gear denominator (load-side).	-

No.	Name/Value	Description	Def/FbEq16
90.63	Feed constant numerator	Parameters 90.63 and 90.64 define the feed constant for the position calculation:	1
		90.63 Feed constant numerator	
		90.64 Feed constant denominator	
		The feed constant converts rotational motion into translatory motion. The feed constant is the distance the load moves during one turn of the motor shaft. The translatory load position is shown by parameter <i>90.05 Load position scaled</i> . Note that the load position is only updated after new position input data is received.	
	-2147483648 2147483647	Feed constant numerator.	-
90.64	Feed constant denominator	See parameter 90.63 Feed constant numerator.	1
	-2147483648 2147483647	Feed constant denominator.	-
90.65	Pos counter init value	Defines an initial position (or distance) for the position counter (as a decimal number) when parameter 90.66 Pos counter init value source is set to Pos counter init value. The number of decimal places is defined by parameter 90.38 Pos counter decimals.	0.000
	-2147483.648 2147483.647	Initial value for position counter.	-
90.66	Pos counter init value source	Selects the source of the initial position value. When the source selected by 90.67 Pos counter init cmd source activates, the value selected in this parameter is assumed to be the position of the load (in decimal format).	Pos counter init value
	Zero	0.	0
	Pos counter init value	Parameter 90.65 Pos counter init value.	1
	Other	Source selection (see <i>Terms and abbreviations</i> on page <i>131</i>).	-
90.67	Pos counter init cmd source	 Selects a digital source (for example, a limit switch connected to a digital input) that initializes the position counter. When the digital source activates, the value selected by 90.66 Pos counter init value source is assumed to be the position of the load. Note: Position counter initialization can be prevented by parameter 90.68 Disable pos counter initialization. 	Not selected
	Not selected	0.	0
	Selected	1.	1
	DI1	Digital input DI1 (10.02 DI delayed status, bit 0).	2
	DI2	Digital input DI2 (10.02 DI delayed status, bit 1).	3
	DI3	Digital input DI3 (10.02 DI delayed status, bit 2).	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).	5
	DI5	Digital input DI5 (10.02 DI delayed status, bit 4).	6
	DI6	Digital input DI6 (10.02 DI delayed status, bit 5).	7
	DIO1	Digital input/output DIO1 (11.02 DIO delayed status, bit 0).	10
	DIO2	Digital input/output DIO2 (11.02 DIO delayed status, bit 1).	11

No.	Name/V	alue	Description		Def/FbEq16
	Other [b	it]	Source selection (see Terms and abbreviations on page 131).	-
90.68	Disable initializa	pos counter tion	Selects a source th counter.	nat prevents the initialization of the position	Not selected
	Not sele	cted	0.		0
	Selected	t	1.		1
	DI1		Digital input DI1 (1	0.02 DI delayed status, bit 0).	2
	DI2		Digital input DI2 (1	0.02 DI delayed status, bit 1).	3
	DI3		Digital input DI3 (1	0.02 DI delayed status, bit 2).	4
	DI4		Digital input DI4 (1	0.02 DI delayed status, bit 3).	5
	DI5		Digital input DI5 (1	0.02 DI delayed status, bit 4).	6
	DI6		Digital input DI6 (1	0.02 DI delayed status, bit 5).	7
	DIO1			DIO1 (<i>11.02 DIO delayed status</i> , bit 0).	10
	DIO2		Digital input/output	DIO2 (11.02 DIO delayed status, bit 1).	11
	Other [b	it]	• • •	see Terms and abbreviations on page 131).	-
90.69		os counter	Selects a source th	hat enables a new initialization of the e. resets bit 4 of 90.35 Pos counter status.	Not selected
	Not sele	cted).		0
	Selected	ţ	1.		1
	DI1		Digital input DI1 (10.02 DI delayed status, bit 0).		2
	DI2		Digital input DI2 (10.02 DI delayed status, bit 1).		3
	DI3		Digital input DI3 (10.02 DI delayed status, bit 2).		4
	DI4		Digital input DI4 (10.02 DI delayed status, bit 3).		5
	DI5		Digital input DI5 (10.02 DI delayed status, bit 4).Digital input DI6 (10.02 DI delayed status, bit 5).Digital input/output DIO1 (11.02 DIO delayed status, bit 0).Digital input/output DIO2 (11.02 DIO delayed status, bit 1).		6
	DI6				7
	DIO1				10
	DIO2				11
	Other [b	it]	Source selection (see Terms and abbreviations on page 131).	-
91 End setting	oder m Is	odule	Configuration of er	ncoder interface modules.	
91.01	FEN DI status		Displays the status nterface modules. This parameter is	s of the digital inputs of FEN-xx encoder read-only.	-
	Bit	Name	Informatio	n	
	0	DI1 /module	1 DI1 of inter	face module 1 (see parameters 91.11 and 9	1.12)
	1	DI2 /module			1.12)
	23	Reserved			
	4 DI1 /modul			face module 2 (see parameters 91.13 and 9	
	5 615	DI2 /module Reserved	le 2 DI2 of interface module 2 (see parameters 91.13 and 9		(1.14)
	010	IVESEIVEN			
	0000 00 0011 00		Status word of digi	tal inputs on FEN-xx modules.	1 = 1

No.	Name/Value	Description	Def/FbEq16
91.02	Module 1 status	Displays the type of the interface module found in the location specified by parameter <i>91.12 Module 1 location</i> . This parameter is read-only.	-
	No option	No module detected in specified slot.	0
	No communication	A module has been detected but cannot be communicated with.	1
	Unknown	The module type is unknown.	2
	FEN-01	An FEN-01 module has been detected and is active.	16
	FEN-11	An FEN-11 module has been detected and is active.	17
	FEN-21	An FEN-21 module has been detected and is active.	18
	FEN-31	An FEN-31 module has been detected and is active.	21
	FSE-31	An FSE-31 module has been detected and is active.	25
91.03	Module 2 status	Displays the type of the interface module found in the location specified by parameter <i>91.14 Module 2 location</i> . For the indications, see parameter <i>91.02 Module 1 status</i> . This parameter is read-only.	-
91.04	Module 1 temperature	Displays the temperature measured through the sensor input of interface module 1. The unit is selected by parameter 96.16 Unit selection. Note: With a PTC sensor, the unit is ohms. This parameter is read-only.	-
	0…1000 °C, °F or ohm	Temperature measured through interface module 1.	-
91.06	Module 2 temperature	Displays the temperature measured through the sensor input of interface module 2. The unit is selected by parameter 96.16 Unit selection. Note: With a PTC sensor, the unit is ohms. This parameter is read-only.	-
	01000 °C, °F or ohm	Temperature measured through interface module 2.	-
91.10	Encoder parameter refresh	Validates any changed encoder interface module parameters. This is needed for any parameter changes in groups 9093 to take effect. After refreshing, the value reverts automatically to <i>Done</i> . Note: The parameter cannot be changed while the drive is running.	Done
	Done	Refreshing done.	0
	Refresh	Refreshing.	1
91.11	Module 1 type	Defines the type of the module used as interface module 1.	None
	None	None (communication disabled).	0
	FEN-01	FEN-01.	1
	FEN-11	FEN-11.	2
	FEN-21	FEN-21.	3
	FEN-31	FEN-31.	4
	FSE-31	FSE-31.	5

No.	Name/Value	Description	Def/FbEq16
91.12	Module 1 location	Specifies the slot (13) on the control unit of the drive into which the interface module is installed. Alternatively, specifies the node ID of the slot on an FEA-0x extension adapter.	Slot 2
	Slot 1	Slot 1.	1
	Slot 2	Slot 2.	2
	Slot 3	Slot 3.	3
	4254	Node ID of the slot on the FEA-0x extension adapter.	1 = 1
91.13	Module 2 type	Defines the type of the module used as interface module 2.	None
	None	None (communication disabled).	0
	FEN-01	FEN-01.	1
	FEN-11	FEN-11.	2
	FEN-21	FEN-21.	3
	FEN-31	FEN-31.	4
	FSE-31	FSE-31.	5
91.14	Module 2 location	Specifies the slot (13) on the control unit of the drive into which the interface module is installed. Alternatively, specifies the node ID of the slot on an FEA-0x extension adapter.	Slot 3
	Slot 1	Slot 1.	1
	Slot 2	Slot 2.	2
	Slot 3	Slot 3.	3
	4254	Node ID of the slot on the FEA-0x extension adapter.	1 = 1
91.21	Module 1 temp sensor type	Specifies the type of temperature sensor connected to interface module 1. Note that the module must also be activated by parameters <i>91.1191.12</i> .	None
	None	None.	0
	PTC	PTC. (The unit is ohms.)	1
	KTY-84	KTY84. (The unit is selected by parameter 96.16 Unit selection.)	2
91.22	Module 1 temp filter time	Defines a filtering time for the temperature measurement through interface module 1.	1500 ms
	010000 ms	Filtering time for temperature measurement.	-
91.24	Module 2 temp sensor type	Specifies the type of temperature sensor connected to interface module 2. Note that the module must also be activated by parameters <i>91.1391.14</i> .	None
	None	None.	0
	PTC	PTC. (The unit is ohms.)	1
	KTY-84	KTY84. (The unit is selected by parameter 96.16 Unit selection.)	2
91.25	Module 2 temp filter time	Defines a filtering time for the temperature measurement through interface 2.	1500 ms
	010000 ms	Filtering time for temperature measurement.	-
91.31	Module 1 TTL output source	Selects the encoder input on interface module 1 whose signal is echoed by or emulated to the TTL output. See also section <i>Encoder support</i> (page <i>82</i>).	Not selected
	Not selected	TTL output not in use.	0

No.	Name/Value	Description	Def/FbEq16
	Module input 1	Input 1 is echoed by or emulated to the TTL output.	1
	Module input 2	Input 2 is echoed by or emulated to the TTL output.	2
91.32	Module 1 emulation pulses/rev	Defines the number of TTL pulses per revolution for encoder emulation output of interface module 1.	0
	065535	Number of TTL pulses for emulation.	1 = 1
91.33	Module 1 emulated Z-pulse offset	 With interface module 1, defines when zero pulses are emulated in relation to zero position received from the encoder. For example, with a value of 0.50000, a zero pulse is emulated whenever the encoder position passes 0.5 revolutions. With a value of 0.00000, a zero pulse is emulated whenever the encoder position passes zero position. 	0.00000
	0.00000 1.00000 rev	Position of emulated zero pulses.	32767 = 1 rev
91.41	Module 2 TTL output source	Selects the encoder input on interface module 2 whose signal is echoed by or emulated to the TTL output. See also section <i>Encoder support</i> (page 82).	Not selected
	Not selected	TTL output not in use.	0
	Module input 1	Input 1 is echoed by or emulated to the TTL output.	1
	Module input 2	Input 2 is echoed by or emulated to the TTL output.	2
91.42	Module 2 emulation pulses/rev	Defines the number of TTL pulses per revolution for encoder emulation output of interface module 2.	0
	065535	Number of TTL pulses for emulation.	1 = 1
91.43	Module 2 emulated Z-pulse offset	With interface module 2, defines when zero pulses are emulated in relation to zero position received from the encoder. For example, with a value of 0.50000, a zero pulse is emulated whenever the encoder position passes 0.5 revolutions. With a value of 0.00000, a zero pulse is emulated whenever the encoder position passes zero position.	0
	0.00000 1.00000 rev	Position of emulated zero pulses.	32767 = 1 rev
02 En	oodor 1	Sattings for anodor 1	•
	coder 1 juration	 Settings for encoder 1. Notes: The contents of the parameter group vary according to the selected encoder type. It is recommended that encoder connection 1 (this group) is used whenever possible since the data received through that interface is fresher than the data received through connection 2 (group 93 Encoder 2 configuration). 	
92.01	Encoder 1 type	Selects the type of encoder/resolver 1.	None configured
	None configured	Inactive.	0
	TTL	TTL. Module type (input): FEN-01 (X31), FEN-11 (X41) or FEN-21 (X51).	1
	TTL+	TTL+ Module type (input): FEN-01 (X32).	2
	Absolute encoder	Absolute encoder. Module type (input): FEN-11 (X42).	3
	Resolver	Resolver. Module type (input): FEN-21 (X52).	4
	HTL	HTL. Module type (input): FEN-31 (X82).	5

No.	Name/Value	Description	Def/FbEq16
	HTL 1	HTL. Module type (input): FSE-31 (X31).	6
	HTL 2	HTL. Module type (input): FSE-31 (X32).	7
	TTL 1	TTL. Module type (input): FSE-31 (X31).	8
	TTL 2	TTL. Module type (input): FSE-31 (X32).	9
92.02	Encoder 1 source	Selects the interface module that the encoder is connected to. (The physical locations and types of encoder interface modules are defined in parameter group <i>91 Encoder module settings</i> .)	Module 1
	Module 1	Interface module 1.	0
	Module 2	Interface module 2.	1
92.10	Pulses/revolution	<i>(Visible when a TTL, TTL+ or HTL encoder is selected)</i> Defines the pulse number per revolution.	2048
	065535	Number of pulses.	-
92.10	Sine/cosine number	 (Visible when an absolute encoder is selected) Defines the number of sine/cosine wave cycles within one revolution. Note: This parameter need not be set when an EnDat or SSI encoder is used in continuous mode. See parameter 92.30 Serial link mode. 	0
	065535	Number of sine/cosine wave cycles within one revolution.	-
92.10	Excitation signal frequency	(Visible when a resolver is selected) Defines the frequency of the excitation signal. Note: With an EnDat or HIPERFACE encoder and FEN-11 FPGA version VIE12200 or later, this parameter is automatically set upon validation of encoder settings (91.10 Encoder parameter refresh).	1 kHz
	120 kHz	Excitation signal frequency.	1 = 1 kHz
92.11	Pulse encoder type	(<i>Visible when a TTL, TTL+ or HTL encoder is selected</i>) Selects the type of encoder.	Quadrature
	Quadrature	Quadrature encoder (with two channels, A and B)	0
	Single track	Single-track encoder (with one channel, A) Note: With this setting, the measured speed value is always positive regardless of direction of rotation.	1
92.11	Absolute position source	(Visible when an absolute encoder is selected) Selects the source of the absolute position information.	None
	None	Not selected.	0
	Commut signals	Commutation signals.	1
	EnDat	Serial interface: EnDat encoder.	2
	Hiperface	Serial interface: HIPERFACE encoder.	3
	SSI	Serial interface: SSI encoder.	4
	Tamagawa	Serial interface: Tamagawa 17/33-bit encoder.	5
92.11	Excitation signal amplitude	<i>(Visible when a resolver is selected)</i> Defines the rms amplitude of the excitation signal.	4.0 V
	4.0 12.0 V	Excitation signal amplitude.	10 = 1 V

No.	Name/Value	Description		Def/FbEq16
92.12	Speed calculation mode	(Visible when a TTL, TTL+ or HT Selects the speed calculation mo *With a single-track encoder (para type is set to Single track), the sp	de. ameter 92.11 Pulse encoder	Auto rising
	A&B all	Channels A and B: Rising and fal speed calculation. *Channel B: Defines the direction Note: With a single-track encode <i>encoder type</i>), this setting acts like	0	
	A all	Channel A: Rising and falling edg calculation. *Channel B: Defines the direction		1
	A rising	Channel A: Rising edges are use *Channel B: Defines the direction	-	2
	A falling	Channel A: Falling edges are use *Channel B: Defines the direction	•	3
	Auto rising	One of the above modes is select on the pulse frequency as follows		4
		Pulse frequency of the channel(s)	Used mode	
		< 2442 Hz	A&B all	
		24424884 Hz	A all	
		> 4884 Hz	A rising	
	Auto falling	One of the above modes is selected automatically depending on the pulse frequency as follows:		5
		Pulse frequency of the channel(s)	Used mode	
		< 2442 Hz	A&B all	
		24424884 Hz	A all	
		> 4884 Hz	A falling	
92.12	Zero pulse enable	(Visible when an absolute encode Enables the encoder zero pulse f input (X42) of the FEN-11 interfac Note: No zero pulse exists with s parameter 92.11 Absolute positio Hiperface, SSI or Tamagawa.	or the absolute encoder ce module. erial interfaces, ie. when	Disable
	Disable	Zero pulse disabled.		0
	Enable	Zero pulse enabled.		1
92.12	Resolver polepairs	(Visible when a resolver is selected Defines the number of pole pairs		1
	132	Number of resolver pole pairs.		1 = 1
92.13	Position estimation enable	(Visible when a TTL, TTL+ or HT, Selects whether position estimation increase position data resolution	on is used with encoder 1 to	Enable
	Disable	Measured position used. (The res revolution for quadrature encoder for single-track encoders.)		0

No.	Name/Value	Description	Def/FbEq16
	Enable	Estimated position used. (Uses position interpolation; extrapolated at the time of data request.)	1
92.13	Position data width	 (Visible when an absolute encoder is selected) Defines the number of bits used to indicate position within one revolution. For example, a setting of 15 bits corresponds to 32768 positions per revolution. The value is used when parameter 92.11 Absolute position source is set to EnDat, Hiperface or SSI. When parameter 92.11 Absolute position source is set to Tamagawa, this parameter is internally set to 17. Note: With an EnDat or HIPERFACE encoder and FEN-11 FPGA version VIE12200 or later, this parameter is automatically set upon validation of encoder settings (91.10 Encoder parameter refresh). 	0
	032	Number of bits used in position indication within one revolution.	1 = 1
92.14	Speed estimation enable	(Visible when a TTL, TTL+ or HTL encoder is selected) Selects whether calculated or estimated speed is used. Estimation increases the speed ripple in steady state operation, but improves the dynamics. Note: This parameter is not effective with FEN-xx modules with FPGA version VIEx 2000 or later.	Disable
	Disable	Last calculated speed used. (The calculation interval is 62.5 microseconds to 4 milliseconds.)	0
	Enable	Estimated speed (estimated at the time of data request) is used.	1
92.14	Revolution data width	 (Visible when an absolute encoder is selected) Defines the number of bits used in revolution counting with a multiturn encoder. For example, a setting of 12 bits would support counting up to 4096 revolutions. The value is used when parameter 92.11 Absolute position source is set to EnDat, Hiperface or SSI. When parameter 92.11 Absolute position source is set to a non-zero value activates multiturn data requesting. Note: With an EnDat or HIPERFACE encoder and FEN-11 FPGA version VIE12200 or later, this parameter is automatically set upon validation of encoder settings (91.10 Encoder parameter refresh). 	0
	032	Number of bits used in revolution count.	1 = 1
92.15	Transient filter	(Visible when a TTL, TTL+ or HTL encoder is selected) Activates transient filtering for the encoder (changes in direction of rotation are ignored above the selected pulse frequency).	4880 Hz
	4880 Hz	Change in direction of rotation allowed below 4880 Hz.	0
	2440 Hz	Change in direction of rotation allowed below 2440 Hz.	1
	1220 Hz	Change in direction of rotation allowed below 1220 Hz.	2
	Disabled	Change in direction of rotation allowed at any pulse frequency.	3
92.16	Encoder 1 supply voltage	(Visible when parameter 92.01 Encoder 1 type = HTL 1, HTL 2, TTL 1 or TTL 2) Selects the power supply voltage for encoder 1.	ον
	0V	Disabled.	0

No.	Name/Value	Description	Def/FbEq16
	5V	5 V.	1
	24V	24 V.	2
92.17 Accepted pulse freq of encoder 1		(Visible when parameter 92.01 Encoder 1 type = HTL 1, HTL 2, TTL 1 or TTL 2) Defines the maximum pulse frequency of encoder 1.	0 kHz
	0300 kHz	Pulse frequency.	1 = 1 kHz
92.21	Encoder cable fault mode	(Visible when a TTL, TTL+ or HTL encoder is selected) Selects which encoder cable channels and wires are monitored for wiring faults.	А, В
	А, В	A and B.	0
	A, B, Z	A, B and Z.	1
	A+, A-, B+, B-	A+, A-, B+ and B	2
	A+, A-, B+, B-, Z+, Z-	A+, A-, B+, B-, Z+ and Z	3
92.23	Maximum pulse waiting time 1200 ms Pulse edge filtering	 (Visible when parameter 92.01 Encoder 1 type = TTL or HTL) Determines a pulse waiting time used in speed calculation for the encoder interface. If no pulse edges are detected within this time, the measured speed is zeroed by the interface. Increasing the setting can improve measuring performance especially at low, near zero speeds. Notes: The parameter is only supported by FEN-xx modules with FPGA version VIEx 2000 or later. On older modules, the pulse waiting time is fixed to 4 ms. The parameter only affects speed measurement. Position is updated whenever a new pulse edge is detected. When the measured speed from the interface is zero, the drive updates its speed data based on position changes. Maximum pulse waiting time. (Visible when parameter 92.01 Encoder 1 type = HTL) Enables pulse edge filtering. Pulse edge filtering can improve the reliability of measurements especially from encoders with a single-ended connection. 	4 ms 1 = 1 ms No filtering
		 Pulse edge filtering is only supported by FEN-31 modules with FPGA version VIE3 2200 or later. Pulse edge filtering decreases the maximum pulse frequency. With 2 µs filtering time, the maximum pulse frequency is 200 kHz. 	
	No filtering	Filtering disabled.	0
	1 µs	Filtering time: 1 microsecond.	1
	2 µs	Filtering time: 2 microseconds.	2
92.25	Pulse overfrequency function	(Visible when parameter 92.01 Encoder 1 type = HTL) Selects how the drive reacts when the encoder interface detects a pulse overfrequency condition. Note: This parameter is effective only with FEN-xx module FPGA version VIEx 2200 or later.	Fault
	Warning	The drive generates a warning, <i>A7E1 Encoder</i> . The FEN-xx module will continue to update speed and position data.	0
	Fault	The drive trips on fault 7381 Encoder.	1

No.	Name/Value	Description	Def/FbEq16
92.30	Serial link mode	(<i>Visible when an absolute encoder is selected</i>) Selects the serial link mode with an EnDat or SSI encoder.	Initial position
	Initial position	Single position transfer mode (initial position).	0
	Continuous	Continuous position data transfer mode.	1
	Continuous speed and position	Continuous speed and position data transfer mode. This setting is intended for EnDat 2.2 encoders without sin/cos signals. Note: This setting requires an FEN-11 interface revision H or later.	2
92.31	EnDat max calculation time	 (Visible when an absolute encoder is selected) Selects the maximum encoder calculation time for an EnDat encoder. Note: This parameter needs to be set only when an EnDat encoder is used in continuous mode, ie. without incremental sin/cos signals (supported only as encoder 1). See also parameter 92.30 Serial link mode. 	50 ms
	10 us	10 microseconds.	0
	100 us	100 microseconds.	1
	1 ms	1 millisecond.	2
	50 ms	50 milliseconds.	3
92.32	SSI cycle time	(Visible when an absolute encoder is selected) Selects the transmission cycle for an SSI encoder. Note: This parameter needs to be set only when an SSI encoder is used in continuous mode, ie. without incremental sin/cos signals (supported only as encoder 1). See also parameter 92.30 Serial link mode.	100 us
	50 us	50 microseconds.	0
	100 us	100 microseconds.	1
	200 us	200 microseconds.	2
	500 us	500 microseconds.	3
	1 ms	1 millisecond.	4
	2 ms	2 milliseconds.	5
92.33	SSI clock cycles	(Visible when an absolute encoder is selected) Defines the length of an SSI message. The length is defined as the number of clock cycles. The number of cycles can be calculated by adding 1 to the number of bits in an SSI message frame.	2
	2127	SSI message length.	-
92.34	SSI position msb	<i>(Visible when an absolute encoder is selected)</i> With an SSI encoder, defines the location of the MSB (most significant bit) of the position data within an SSI message.	1
	1126	Position data MSB location (bit number).	-
92.35	SSI revolution msb	<i>(Visible when an absolute encoder is selected)</i> With an SSI encoder, defines the location of the MSB (most significant bit) of the revolution count within an SSI message.	1
	1126	Revolution count MSB location (bit number).	-

No.	Name/Value	Description			
92.36	SSI data format	(Visible when an absolute encoder is selected) Selects the data format for an SSI encoder.	Binary		
	Binary	Binary code.	0		
	Gray	Gray code.	1		
92.37 SSI baud rate		(Visible when an absolute encoder is selected) Selects the baud rate for an SSI encoder.	100 kBit/s		
	10 kBit/s	10 kbit/s.	0		
	50 kBit/s	50 kbit/s.	1		
	100 kBit/s	100 kbit/s.	2		
	200 kBit/s	200 kbit/s.	3		
	500 kBit/s	500 kbit/s.	4		
	1000 kBit/s	1000 kbit/s.	5		
92.40 SSI zero phase		(Visible when an absolute encoder is selected) Defines the phase angle within one sine/cosine signal period that corresponds to the value of zero on the SSI serial link data. The parameter is used to adjust the synchronization of the SSI position data and the position based on sine/cosine incremental signals. Incorrect synchronization may cause an error of ±1 incremental period. Note: This parameter needs to be set only when an SSI encoder is used in initial position mode (see parameter 92.30 <i>Serial link mode</i>).	315-45 deg		
	315-45 deg	315-45 degrees.	0		
	45-135 deg	45-135 degrees.			
	135-225 deg	135-225 degrees.	2		
	225-315 deg	225-315 degrees.	3		
92.45	Hiperface parity	(Visible when an absolute encoder is selected) Defines the use of parity and stop bits with a HIPERFACE encoder. Typically this parameter need not be set.	Odd		
	Odd	Odd parity indication bit, one stop bit.	0		
	Even	Even parity indication bit, one stop bit.	1		
92.46	Hiperface baud rate	(Visible when an absolute encoder is selected) Defines the transfer rate of the link with a HIPERFACE encoder. Typically this parameter need not be set.	4800 bits/s		
	4800 bits/s	4800 bit/s.	0		
	9600 bits/s	9600 bit/s.	1		
	19200 bits/s	19200 bit/s.	2		
	38400 bits/s	38400 bit/s.	3		
92.47	Hiperface node address	<i>(Visible when an absolute encoder is selected)</i> Defines the node address for a HIPERFACE encoder. Typically this parameter need not be set.	64		
	0255	HIPERFACE encoder node address.	-		

No. Name/Value		Description	Def/FbEq16
	coder 2 Juration	 Settings for encoder 2. Notes: The contents of the parameter group vary according to the selected encoder type. It is recommended that encoder connection 1 (group 92 <i>Encoder 1 configuration</i>) is used whenever possible since the data received through that interface is fresher than the data received through connection 2 (this group). 	
93.01	Encoder 2 type	Selects the type of encoder/resolver 2.	None configured
	None configured	None.	0
	TTL	TTL. Module type (input): FEN-01 (X31), FEN-11 (X41) or FEN-21 (X51).	1
	TTL+	TTL+ Module type (input): FEN-01 (X32).	2
	Absolute encoder	Absolute encoder. Module type (input): FEN-11 (X42).	3
	Resolver	Resolver. Module type (input): FEN-21 (X52).	4
	HTL	HTL. Module type (input): FEN-31 (X82).	5
	HTL 1	HTL. Module type (input): FSE-31 (X31).	6
	HTL 2	HTL. Module type (input): FSE-31 (X32).	7
	TTL 1	TTL. Module type (input): FSE-31 (X31).	8
	TTL 2	TTL. Module type (input): FSE-31 (X32).	9
93.02	Encoder 2 source	Selects the interface module that the encoder is connected to. (The physical locations and types of encoder interface modules are defined in parameter group <i>91 Encoder module settings</i> .)	Module 1
	Module 1	Interface module 1.	1
	Module 2	Interface module 2.	2
93.10	Pulses/rev	(Visible when a TTL, TTL+ or HTL encoder is selected) See parameter 92.10 Pulses/revolution.	2048
93.10	Sine/cosine number	(Visible when an absolute encoder is selected) See parameter 92.10 Sine/cosine number.	0
93.10	Excitation signal frequency	(Visible when a resolver is selected) See parameter 92.10 Excitation signal frequency.	1 kHz
93.11	Pulse encoder type	(Visible when a TTL, TTL+ or HTL encoder is selected) See parameter 92.11 Pulse encoder type.	Quadrature
93.11	Absolute position source	(Visible when an absolute encoder is selected) See parameter 92.11 Absolute position source.	None
93.11	Excitation signal amplitude	(Visible when a resolver is selected) See parameter 92.11 Excitation signal amplitude.	4.0 V
93.12	Speed calculation mode	(<i>Visible when a TTL, TTL+ or HTL encoder is selected</i>) See parameter 92.12 Speed calculation mode.	Auto rising
93.12	Zero pulse enable	(Visible when an absolute encoder is selected) See parameter 92.12 Zero pulse enable.	Disable
93.12	Resolver polepairs	<i>(Visible when a resolver is selected)</i> See parameter <i>92.12 Resolver polepairs.</i>	1
93.13	Position estimation enable	(Visible when a TTL, TTL+ or HTL encoder is selected) See parameter 92.13 Position estimation enable.	Enable

No.	Name/Value	•			
93.13	Position data width	(Visible when an absolute encoder is selected) See parameter 92.13 Position data width.	0		
93.14	Speed estimation enable	(Visible when a TTL, TTL+ or HTL encoder is selected) See parameter 92.14 Speed estimation enable.	Disable		
93.14	Revolution data width	(Visible when an absolute encoder is selected) See parameter 92.14 Revolution data width.	0		
93.15	Transient filter	(<i>Visible when a TTL, TTL+ or HTL encoder is selected</i>) See parameter 92.15 <i>Transient filter</i> .	4880 Hz		
93.16	Encoder 2 supply voltage	(Visible when parameter 93.01 Encoder 2 type = HTL 1, HTL 2, TTL 1 or TTL 2) See parameter 92.16 Encoder 1 supply voltage.	OV		
93.17	Accepted pulse freq of encoder 2	(Visible when parameter 93.01 Encoder 2 type = HTL 1, HTL 2, TTL 1 or TTL 2) See parameter 92.17 Accepted pulse freq of encoder 1.	0 kHz		
93.21	Encoder cable fault mode	(<i>Visible when a TTL, TTL+ or HTL encoder is selected</i>) See parameter 92.21 Encoder cable fault mode.	А, В		
93.23	Maximum pulse waiting time	(Visible when parameter 93.01 Encoder 2 type = TTL or HTL) See parameter 92.23 Maximum pulse waiting time.	4 ms		
93.24	Pulse edge filtering	(Visible when parameter 93.01 Encoder 2 type = HTL) See parameter 92.24 Pulse edge filtering.	No filtering		
93.25	Pulse overfrequency function	(Visible when parameter 93.01 Encoder 2 type = HTL) See parameter 92.25 Pulse overfrequency function.	Fault		
93.30	Serial link mode	(Visible when an absolute encoder is selected) See parameter 92.30 Serial link mode.	Initial position		
93.31	EnDat calc time	(Visible when an absolute encoder is selected) See parameter 92.31 EnDat max calculation time.	50 ms		
93.32	SSI cycle time	(Visible when an absolute encoder is selected) See parameter 92.32 SSI cycle time.	100 us		
93.33	SSI clock cycles	(Visible when an absolute encoder is selected) See parameter 92.33 SSI clock cycles.	2		
93.34	SSI position msb	(Visible when an absolute encoder is selected) See parameter 92.34 SSI position msb.	1		
93.35	SSI revolution msb	(Visible when an absolute encoder is selected) See parameter 92.35 SSI revolution msb.	1		
93.36	SSI data format	(Visible when an absolute encoder is selected) See parameter 92.36 SSI data format.	Binary		
93.37	SSI baud rate	(Visible when an absolute encoder is selected) See parameter 92.37 SSI baud rate.	100 kBit/s		
93.40	SSI zero phase	(Visible when an absolute encoder is selected) See parameter 92.40 SSI zero phase.	315-45 deg		
93.45	Hiperface parity	<i>(Visible when an absolute encoder is selected)</i> See parameter 92.45 <i>Hiperface parity</i> .	Odd		
93.46	Hiperface baud rate	<i>(Visible when an absolute encoder is selected)</i> See parameter 92.46 <i>Hiperface baud rate</i> .	4800 bits/s		
93.47	Hiperface node address	(Visible when an absolute encoder is selected) See parameter 92.47 Hiperface node address.	64		

No.	Name/Value	Description	Def/FbEq16
94 LS	J control	Control of the supply unit of the drive, such as DC voltage and reactive power reference. Note that the references defined here must also be selected as the reference source in the supply control program to be effective. This group is only visible when supply unit control has been activated by parameter <i>95.20 HW options word 1</i> . See also section <i>Control of a supply unit (LSU)</i> (page 73).	
94.01	LSU control	Enables/disables the internal INU-LSU state machine. When the state machine is enabled, the inverter unit (INU) controls the supply unit (LSU) and prevents the inverter unit from starting until the supply unit is ready. When the state machine is disabled, the status of the supply unit (LSU) is ignored by the inverter unit.	On
	Off	INU-LSU state machine disabled.	0
	On	INU-LSU state machine enabled.	1
94.02	LSU panel communication	 Enables/disables control panel and PC tool access to the supply unit (line-side converter) via the inverter unit (motor-side converter). Note: This feature is only supported by the following drives: ACS880-11 ACS880-31 ACS880-17 based on an integrated drive module ACS880-37 based on an integrated drive module. 	Disable
	Disable	Control panel and PC tool access to supply unit via inverter unit disabled.	0
	Enable	Control panel and PC tool access to supply unit via inverter unit enabled.	1
94.10	LSU max charging time	Defines the maximum time the supply unit (LSU) is allowed for charging before a fault (7584 LSU charge failed) is generated.	15 s
	065535 s	Maximum charging time.	1 = 1 s
94.11	LSU stop delay	Defines a stop delay for the supply unit. This parameter can be used to delay the opening of the main breaker/contactor when a restart is expected.	600.0 s
	0.0 3600.0 s	Supply unit stop delay.	10 = 1 s
94.20	DC voltage reference	(Only visible when IGBT supply unit control activated by 95.20) Displays the DC voltage reference sent to the supply unit. This parameter is read-only.	-
	0.0 2000.0 V	DC voltage reference sent to supply unit.	10 = 1 V
94.21	DC voltage ref source	(Only visible when IGBT supply unit control activated by 95.20) Selects the source of the DC voltage reference to be sent to the supply unit.	User ref
	Zero	None.	0
	User ref	94.22 User DC voltage reference.	1
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-

No.	Name/Value	Description	Def/FbEq16
94.22	User DC voltage reference	(Only visible when IGBT supply unit control activated by 95.20) Defines the DC voltage reference for the supply unit when 94.21 DC voltage ref source is set to User ref.	0.0 V
	0.0 2000.0 V	User DC reference.	10 = 1 V
94.30	Reactive power reference	(Only visible when IGBT supply unit control activated by 95.20) Displays the reactive power reference sent to the supply unit. This parameter is read-only.	-
	-3276.8 3276.7 kvar	Reactive power reference sent to the supply unit.	10 = 1 kvar
94.31	Reactive power ref source	(Only visible when IGBT supply unit control activated by 95.20) Selects the source of the reactive power reference to be sent to the supply unit.	User ref
	Zero	None.	0
	User ref	94.32 User reactive power reference.	1
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
	User reactive power reference	(Only visible when IGBT supply unit control activated by 95.20) Defines the reactive power reference for the supply unit when 94.31 Reactive power ref source is set to User ref.	0.0 kvar
	-3276.8 3276.7 kvar	User reactive power reference.	10 = 1 kvar
94.40 Power mot limit on net loss		Defines the maximum shaft power for motoring mode upon a supply network failure when IGBT supply unit control is active (bit 15 of <i>95.20 HW options word 1</i> is on). The value is given in percent of nominal motor power. Note: With a diode supply unit (bit 11 of <i>95.20</i> is on), the motoring shaft power is limited to 2% upon a network failure regardless of this parameter.	600.00%
	0.00 600.00%	Maximum shaft power for motoring mode upon a supply network failure.	1 = 1%
94.41	Power gen limit on net loss	Defines the maximum shaft power for generating upon a supply network failure when supply unit control is active (bit 11 or 15 of 95.20 HW options word 1 is on). The value is given in percent of nominal motor power.	-600.00%
	-600.00 0.00%	Maximum shaft power for generating mode upon a supply network failure.	1 = 1%

No.	Name/Value	Description	Def/FbEq16
95 HN	configuration	Various hardware-related settings.	
95.01	Supply voltage	Selects the supply voltage range. This parameter is used by the drive to determine the nominal voltage of the supply network. The parameter also affects the current ratings and the DC voltage control functions (trip and brake chopper activation limits) of the drive. WARNING! An incorrect setting may cause the motor to rush uncontrollably, or the brake chopper or resistor to overload. Note: The selections shown depend on the hardware of the drive. If only one voltage range is valid for the drive in question, it is selected by default.	-
	Not given	No voltage range selected. The drive will not start modulating before a range is selected.	0
	208240 V	208240 V	1
	380415 V	380415 V	2
	440480 V	440480 V	3
	500 V	500 V	4
	525600 V	525600 V	5
	660690 V	660690 V	6
95.02	Adaptive voltage limits	Enables adaptive voltage limits. Adaptive voltage limits can be used if, for example, an IGBT supply unit is used to raise the DC voltage level. If the communication between the inverter and the IGBT supply unit is active (95.20 HW options word 1), the voltage limits are related to the DC voltage reference transmitted to the supply unit (94.20 DC voltage reference) assuming that the reference is high enough. Otherwise, the limits are calculated based on the measured DC voltage at the end of the pre- charging sequence. This function is also useful if the AC supply voltage to the drive is high, as the warning levels are raised accordingly.	Disable
	Disable	Adaptive voltage limits disabled.	0
	Enable	Adaptive voltage limits enabled.	1
95.04	Control board supply	Specifies how the control unit of the drive is powered. The default value depends on the type of the control unit and the setting of parameter 95.20.	Internal 24V (ZCU); External 24V (BCU;95.20 b4)
	Internal 24V	The drive control unit is powered from the drive power unit it is connected to. Note : If reduced run (see page 90) is required, select <i>External 24V</i> or <i>Redundant external 24V</i> instead.	0
	External 24V	The drive control unit is powered from an external power supply. The drive power unit and power unit link faults are masked when the drive is in stopped state, so the main circuit can be powered down without faults while the control unit is powered.	1

No.	Name/Value	Description	Def/FbEq16
	Redundant external 24V	(Type BCU control units only) The drive control unit is powered from two redundant external power supplies. The loss of one of the supplies generates a warning (<i>AFEC</i> <i>External power signal missing</i>). The drive power unit and power unit link faults are masked when the drive is in stopped state, so the main circuit can be powered down without faults while the control unit is powered.	2
95.08	DC switch monitoring	(Only visible with a ZCU control unit) Enables/disables DC switch monitoring via the DIIL input. This setting is intended for use with inverter modules with an internal charging circuit that are connected to the DC bus through a DC switch. An auxiliary contact of the DC switch must be wired to the DIIL input so that the input switches off when the DC switch is opened. DC bus Image: Charging Charging Charging Charging Charging Contactor Image: Charging Charging Charging Contactor Image: Charging Charging Charging Charging Contactor If the DC switch is opened with the inverter running, the inverter is given a coast-to-stop command, and its charging circuit activated. Starting the inverter is prevented until the DC switch is closed and the DC circuit in the inverter unit recharged. Notes: • By default, DIIL is the input for the Run enable signal. Adjust 20.12 Run enable 1 source if necessary. • An internal charging circuit is standard on some inverter module types but optional on others; check with your local ABB representative.	Disable; Enable (95.20 b7)
	Disable	DC switch monitoring through the DIIL input disabled.	0

No.	Name/Va	alue	Descriptio	n	Def/FbEq16
95.09	 95.09 Switch fuse controller (Only visible with a BCU control unit) Activates communication to a xSFC charging controller. Th setting is intended for use with inverter modules that are connected to a DC bus through a DC switch/charging circu controlled by a charging controller. On units without a DC switch, this parameter should be set to <i>Disable</i>. The charging controller monitors the charging of the inverter unit, and sends an enable command when the charging OK' lar lights, and charging switch opened). For more information, see xSFC documentation. 				
	Disable		Communic	ation with xSFC disabled.	0
	Enable		Communic	ation with xSFC enabled.	1
95.13	Reduced	l run mode	Specifies the This param other than If the contrespecified be generated. See section 0 = Reduce	<i>le with a BCU control unit)</i> he number of inverter modules available. neter must be set if reduced run is required. A value 0 activates the reduced run function. ol program cannot detect the number of modules y this parameter, a fault (<i>5695 Reduced run</i>) is n <i>Reduced run function</i> (page <i>126</i>). ed run disabled umber of modules available	0
	06553	5	Number of inverter modules available		-
95.14	Connected modules		Shows whi	le with a BCU control unit) ch of the parallel-connected inverter modules have cted by the control program.	-
	Bit	Name		Description	
	0	Module 1		1 = Module 1 has been detected.	
	1	Module 2		1 = Module 2 has been detected.	
	11	Module 12		1 = Module 12 has been detected.	
	1215	Reserved			
	0000h	FFFFh	Inverter mo	odules connected.	1 = 1

No.	Name/\	/alue	Descr	iption	Def/FbEq16
95.15	Special HW settingsContains hardware-related settings that can be enabled and disabled by toggling the specific bits.Note: The installation of the hardware specified by this parameter may require derating of drive output, or impose other limitations. Refer to the hardware manual of the drive.		-		
	Bit	Name		Information	
	0	EX motor		1 = The drive is part of a drive/motor package provided potentially explosive atmospheres.	d by ABB for
	1	ABB sine fi	lter	1 = An ABB sine filter is connected to the output of the drive/invert	
	2	High speed	mode	1 = Minimum switching frequency limit adaptation to or frequency active. This setting improves control perforn output frequencies (typically above 120 Hz).	•
	3 Custom sine filter		e filter	1 = A custom sine filter is connected to the output of the drive/inverter. See also parameters 97.01, 97.02, 99.18, 99.19.	
	415	Reserved		,	
0000b0111b Hardw		Hardw	are options configuration word.	1 = 1	

No.	Name/Value	Description	Def/FbEq16
95.20	HW options word 1	Specifies hardware-related options that require differentiated parameter defaults. Activating a bit in this parameter makes the necessary changes in other parameters – for example, activating an emergency stop option reserves a digital input. In many cases, the differentiated parameters will also be write-protected. This parameter, as well as the changes in other parameters	-
		implemented by it, are not affected by a parameter restore.WARNING! After switching any bits in this wordrecheck the values of the affected parameters.	

Bit	Name	Information		
0	Supply frequency 60 Hz	0 = 50 Hz; 1 = 60 Hz. Affects parameters <i>11.45</i> , <i>11.59</i> , 30.11, 30.12, 30.13, 30.14, 31.26, 31.27, 46.01, 46.02.		
1	Emergency stop Cat 0	1 = Emergency stop, Category 0, without FSO module parameters <i>21.04</i> , <i>21.05</i> .	Affects	
2	Emergency stop Cat 1	1 = Emergency stop, Category 1, without FSO module. parameters <i>10.24</i> , <i>21.04</i> , <i>21.05</i> .	Affects	
3	RO2 for -07 cabinet cooling fan	1 = Control of cabinet cooling fan (used only with speci ACS880-07 hardware). Affects parameters <i>10.27</i> , <i>10.2</i>		
4	Externally powered control unit	1 = Control unit powered externally. Affects parameter visible with a ZCU control unit)	95.04. (Only	
5	DC supply switch	1 = DC switch monitoring active. Affects parameters 20 95.08. (Only visible with a ZCU control unit)	0.12, 31.03,	
6	DOL motor switch	1 = Motor fan control active. Affects parameters <i>10.24</i> , <i>35.103</i> , <i>35.104</i> .		
7	xSFC-01 fuse switch controller			
8	Service switch	1 = Service switch connected. Affects parameters 31.0	1, 31.02.	
9	Output contactor	1 = Output contactor present. Affects parameters 10.24	4, 20.12.	
10	Brake resistor, sine filter, IP54 fan	 1 = Status (eg. thermal) switches connected to DIIL inp 20.11, 20.12. 	out. Affects	
11	INU-DSU communication	*1 = Diode supply unit control by inverter unit active. M parameters visible in groups 06, 60, 61, 62 and 94. (On a BCU control unit)		
12	Reserved	•		
13	Du/dt filter activation	1 = Active: An external du/dt filter is connected to the d output. The setting will limit the output switching freque		
		force the fan of the drive/inverter module to full speed.		
		Note: This bit should be set to 0 if the drive/inverter module is equipped with internal du/dt filtering (for example, frame R8i invermodules with option +E205).		
14	DOL fan activation	Reserved		
15	INU-ISU communication	*1 = IGBT supply unit control by inverter unit active. Maparameters visible in groups 01 , 05 , 06 , 07 , 30 , 31 , 60 , and 96 .		
*See s	ection <i>Control of a su</i>	pply unit (LSU) (page 73).		
	FFFFh Hardw	vare options configuration word 1.	1 = 1	

No.	Name/Value		Descri	ption	Def/FbEq16		
95.21	HW options word 2		differer	es more hardware-related options that require ntiated parameter defaults. See parameter 95.20 HW s word 1.	-		
	Bit	Name		Information			
	0	Dual use		1 = Dual use active. For drives with option +N8200. (Allows higher output frequencies and frequency reference limits.)			
	1	SynRM		1 = Synchronous reluctance motor used. Affects paran 25.03, 25.15, 99.03, 99.13.	neters 25.02,		
	2	Salient PM		1 = Salient-pole permanent magnet motor used. Affect 25.02, 25.03, 25.15, 99.03, 99.13.	s parameters		
	315	Reserved		•			
	0000b	.0011b	Hardwa	are options configuration word 2.	1 = 1		
95.30	Parallel	type filter	Filters	<i>visible with a BCU control unit)</i> the list of drive/inverter types listed by parameter 95.31 <i>I connection rating id</i> .	All types		
	All type	S	All type	es listed.	0		
	-3 (380-	-415V)	-3 (380	415 V) types listed.	1		
	-5 (380-	-500V)	-5 (380500 V) types listed.		2		
	-7 (525-	-690V)	-7 (525	690 V) types listed.	3		
95.31	Parallel connection rating id		Defines connec If the d	visible with a BCU control unit) is the drive/inverter type if it consists of parallel- ited modules. rive/inverter consists of a single module, leave the it <i>Not selected</i> .	Not selected		
	Not sele	ected		ve/inverter does not consist of parallel-connected es, or type not selected.	0		
	[Drive/ir	nverter type]	Drive/ir	nverter type consisting of parallel-connected modules.	-		
95.40	Transfo	rmation ratio	Defines	s the ratio of the step-up transformer.	0.000		
	0.000	. 100.000	Step-u	o transformer ratio.			
96 Sys	stem		parame parame	age selection; access levels; macro selection; eter save and restore; control unit reboot; user eter sets; unit selection; data logger triggering; eter checksum calculation; user lock.			
96.01	Langua	ge	display Notes: • Not • This Driv	all languages listed below are necessarily supported. parameter does not affect the languages visible in the e composer PC tool. (Those are specified under View ettings.)	-		
	Not sele	ected	None.		0		
	English		English	l	1033		
	Deutsch	<u></u> ו	Germa	n.	1031		
	Italiano		Italian.		1040		
	Españo		Spanis	h.	3082		
	Portugu	ies	Portug	uese.	2070		

No.	Name/Value	Description	Def/FbEq16
	Nederlands	Dutch.	1043
	Français	French.	1036
	Dansk	Danish.	1030
	Suomi	Finnish.	1035
	Svenska	Swedish.	1053
	Russki	Russian.	1049
	Polski	Polish.	1045
	Czech	Czech.	1029
	Chinese (Simplified, PRC)	Simplified Chinese.	2052
	Türkçe	Turkish.	1055
	Japanese	Japanese	1041
96.02	Pass code	Pass codes can be entered into this parameter to activate further access levels (see parameter 96.03 Access levels active) or to configure the user lock. Entering "358" toggles the parameter lock, which prevents the changing of all other parameters through the control panel or the Drive composer PC tool. Entering the user pass code (by default, "10000000") enables parameters 96.10096.102, which can be used to define a new user pass code and to select the actions that are to be prevented. Entering an invalid pass code will close the user lock if open, ie. hide parameters 96.10096.102. After entering the code, check that the parameters are in fact hidden. If they are not, enter another (random) pass code. Entering several invalid pass codes introduces a delay before a new attempt can be made. Entering further invalid codes will progressively lengthen the delay. Note: You must change the default user pass code to maintain a high level of cybersecurity. Store the code in a safe place – the protection cannot be disabled even by ABB if the code is lost. See also section User lock (page 124).	0
	099999999	Pass code.	-
96.03	Access levels active	Shows which access levels have been activated by pass codes entered into parameter 96.02 Pass code. This parameter is read-only.	0001h
		Bit Name	
		0 End user	
		1 Service 2 Advanced programmer	
		310 Reserved	
		11 OEM access level 1	
		12 OEM access level 2	
		13 OEM access level 3	
		14 Parameter lock	

No.	Name/Value	Description	Def/FbEq16
	0000hFFFFh	Active access levels.	-
96.04	Macro select	Selects the application macro. After a selection is made, the parameter reverts automatically to <i>Done</i> .	Done
	Done	Macro selection complete; normal operation.	0
	Factory	Factory macro used by the control program.	1
	Hand/Auto	Not in use.	2
	PID-CTRL	Not in use.	3
	T-CTRL	Not in use.	4
	Sequence control	Not in use.	5
	FIELDBUS	Not in use.	6
96.05	Macro active Shows which application macro is currently selected. To change the macro, use parameter 96.04 Macro select.		Factory
	Factory	Factory macro.	1
	Hand/Auto	Not in use.	2
	PID-CTRL	Not in use.	3
	T-CTRL	Not in use.	4
	Sequence control Not in use.		5
	FIELDBUS	Not in use.	6
96.06	Parameter restore	Restores the original settings of the control program, ie. parameter default values. Note: This parameter cannot be changed while the drive is running.	Done
	Done	Restoring is completed.	0
	Restore defaults	 All editable parameter values are restored to default values, except motor data and ID run results parameter 31.42 Overcurrent fault limit control panel/PC communication settings I/O extension module settings fieldbus adapter settings encoder configuration data application macro selection and the parameter defaults implemented by it parameter 95.01 Supply voltage parameter 95.09 Switch fuse controller differentiated defaults implemented by parameters 95.20 HW options word 1 and 95.21 HW options word 2 user lock configuration parameters 96.10096.102 	8
	Clear all	 All editable parameter values are restored to default values, except control panel/PC communication settings application macro selection and the parameter defaults implemented by it parameter 95.01 Supply voltage parameter 95.09 Switch fuse controller differentiated defaults implemented by parameters 95.20 HW options word 1 and 95.21 HW options word 2 user lock configuration parameters 96.10096.102. PC tool communication is interrupted during the restoring. 	62

No.	Name/Value	Description	Def/FbEq16	
	Reset all fieldbus settings	Fieldbus adapter and embedded fieldbus interface settings (parameter groups 5058) are restored to default values. This will also restore the default settings of the fieldbus adapter if one is connected.	32	
96.07	Parameter save manually	Saves the valid parameter values to permanent memory. This parameter should be used to store values sent from a fieldbus, or when using an external power supply to the control board as the supply might have a very short hold-up time when powered off. Note: A new parameter value is saved automatically when changed from the PC tool or control panel but not when altered through a fieldbus adapter connection.	Done	
	Done	Save completed.	0	
	Save	Save in progress.	1	
96.08	Control board boot	Changing the value of this parameter to 1 reboots the control unit (without requiring a power off/on cycle of the complete drive module). The value reverts to 0 automatically.	0	
	01	1 = Reboot the control unit.	1 = 1	
96.09	FSO reboot	Changing the value of (or the source selected by) this parameter from 0 to 1 reboots the optional FSO-xx safety functions module. Note: The value does not revert to 0 automatically.	False	
	False	0.	0	
	True	1.	1	
	Other [bit]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-	
96.10	User set status	Shows the status of the user parameter sets. This parameter is read-only. See also section <i>User parameter sets</i> (page <i>123</i>).	-	
	n/a	No user parameter sets have been saved.	0	
	Loading	A user set is being loaded.	1	
	Saving	A user set is being saved.	2	
	Faulted	Invalid or empty parameter set.	3	
	User set 1	User set 1 has been loaded.	4	
	User set 2	User set 2 has been loaded.	5	
	User set 3	User set 3 has been loaded.	6	
	User set 4	User set 4 has been loaded.	7	
96.11	User set save/load	 Enables the saving and restoring of up to four custom sets of parameter settings. See section <i>User parameter sets</i> (page 123). The set that was in use before powering down the drive is in use after the next power-up. Notes: Hardware configuration settings such as I/O extension module, fieldbus and encoder configuration parameters (groups 1416, 5156, 58 and 9293), and parameters 50.01 and 50.31), and forced input/output values (such as 10.03 and 10.04) are not included in user parameter sets. Parameter changes made after loading a set are not automatically stored – they must be saved using this parameter. 	No action	

No.	Name/Value	Description	Def/FbEq16		
	No action	Load or save operati	on complete; normal	operation.	0
	User set I/O mode	Load user parameter mode in1 and 96.13			1
	Load set 1	Load user parameter	r set 1.		2
	Load set 2	Load user parameter	r set 2.		3
	Load set 3	Load user parameter	r set 3.		4
	Load set 4	Load user parameter	r set 4.		5
	Save to set 1	Save user parameter	18		
	Save to set 2	Save user parameter	19		
	Save to set 3	Save user parameter	20		
	Save to set 4 Save user parameter set 4.				21
96.12	User set I/O mode in1	When parameter 96.11 User set save/load is set to User set I/O mode, selects the user parameter set together with parameter 96.13 User set I/O mode in2 as follows:			Not selected
		Status of source defined by par. <u>96.12</u>	Status of source defined by par. 96.13	User parameter set selected	
		0	0	Set 1	
		1	0	Set 2	
		0	1	Set 3	
		1	1	Set 4	
	Not selected	0.	0		
	Selected	1.			1
	DI1	Digital input DI1 (<i>10.02 DI delayed status</i> , bit 0).			2
	DI2	Digital input DI2 (10.	3		
	DI3	Digital input DI3 (10.	-	•	4
	DI4	Digital input DI4 (10.02 DI delayed status, bit 3).			5
	DI5	Digital input DI5 (10.	6		
	DI6	Digital input DI6 (10.	7		
	DIO1	Digital input/output D	0IO1 (<i>11.02 DIO dela</i>	<i>yed status</i> , bit 0).	10
	DIO2	Digital input/output D	0IO2 (<i>11.02 DIO dela</i>	<i>yed status</i> , bit 1).	11
	Other [bit]	Source selection (se	e Terms and abbrevi	ations on page 131).	-
96.13	User set I/O mode in2	See parameter 96.12	2 User set I/O mode	in1.	Not selected

No.	Name/Va	Name/Value Description			Def/FbEq16
96.16	Unit selec	ction	Selects the uni and torque.	t of parameters indicating power, temperature	0000 0000b
	Bit	Name		Information	
	0 Power ur		it	0 = kW	
				1 = hp	
	1	Reserved			
	2	Temperat	ure unit	0 = C (°C) 1 = F (°F)	
	3	Reserved	l		
	4	Torque ur	nit	0 = Nm (N·m)	
				$1 = lbft (lb \cdot ft)$	
	515	Reserved			
	0000 000		Unit selection v	word.	1 = 1
96.20	Time synch primary source		the drive's time The date and ti	t priority external source for synchronization of e and date. ime can also be directly set into <u>96.2496.26</u> his parameter is ignored.	DDCS Controller
	Internal		No external source selected.		0
	DDCS Controller		External contro	oller.	1
	Fieldbus A or B		Fieldbus interfa	ace A or B.	2
	Fieldbus A		Fieldbus interfa	ace A.	3
	Fieldbus B		Fieldbus interface B.		4
	D2D or M/F		The master station on a master/follower or drive-to-drive link.		5
	Embedde	d FB	Reserved. xxxxx Embedded fieldbus interface.		6
	Embedde	d FB	Embedded fieldbus interface.		6
	Embedde	d Ethernet	Ethernet port on type BCU control unit.		7
	Panel link		Control panel, control panel.	or Drive composer PC tool connected to the	8
	Ethernet t	ool link	Drive compose	er PC tool through an FENA module.	9
96.23	M/F and L synchroni		In the master drive, activates clock synchronization for master/follower and drive-to-drive communication.		Inactive
	Inactive		Clock synchronization not active.		0
	Active		Clock synchronization active.		1
96.24	Full days Jan 1980		This parameter h and 96.26 Tin to set the date interface from a	days passed since beginning of the year 1980. r, together with 96.25 Time in minutes within 24 me in ms within one minute makes it possible and time in the drive via the parameter a fieldbus or application program. This may be e fieldbus protocol does not support time n.	-
	159999)	Days since beg	ginning of 1980.	1 = 1
96.25	Time in m within 24		the value 860 c	minutes passed since midnight. For example, corresponds to 2:20 pm.	0 min

No.	Name/Value Description		Def/FbEq16				
	1143	9	Minutes since midnight.	1 = 1			
96.26	<i>Time in ms within one minute</i>		Number of milliseconds passed since last minute.0 msSee parameter 96.24 Full days since 1st Jan 1980.0				
	0599	99	Number of milliseconds since last minute.	1 = 1			
96.29	Time s status		Time source status word. This parameter is read-only.	-			
	Bit	Name	Description				
	0	Time tick received	1 = 1st priority tick received: Tick has been received from 1st source (or from $96.2496.26$).	· · · · ·			
	1	Aux Time tick received	= 2nd priority tick received: Tick has been received from 2nd priority source.				
	2	Tick interval is too long	= Yes: Tick interval too long (accuracy compromised).				
	3	DDCS controller	1 = Tick received: Tick has been received from an external co	= Tick received: Tick has been received from an external controller.			
	4	Master/Follo wer	I = Tick received: Tick has been received through the master/follower link.				
	5	Reserved					
	6	D2D	1 = Tick received: Tick has been received through the drive-to-drive link.				
	7	FbusA	1 = Tick received: Tick has been received through fieldbus interface A.				
	8	FbusB	1 = Tick received: Tick has been received through fieldbus interface B.				
	9	EFB	1 = Tick received: Tick has been received through the embedded fieldbus interface.				
	10	Ethernet	1 = Tick received: Tick has been received through the Ethernet port on type BCU control unit.				
	11	Panel link	1 = Tick received: Tick has been received from the control panel, or Drive composer PC tool connected to the control panel.				
	12	Ethernet tool link	1 = Tick received: Tick has been received from Drive compos through an FENA module.	er PC tool			
	13	Parameter setting	1 = Tick received: Tick has been set by parameters 96.249	6.26.			
	14	RTC	1 = RTC time in use: Time and date have been read from the clock.	real-time			
	15	Drive On- Time	1 = Drive on-time in use: Time and date are displaying drive o	on-time.			
	0000h.	FFFFh	Time source status word 1.	1 = 1			
96.31	Drive II		Specifies an ID number for the drive. The ID can be read by an external controller through DDCS, for example, for comparison with an ID contained by the controller's application.	0			
	0327	67	ID number.	1 = 1			
96.39	Power logging		Enables/disables power-up logging. When enabled, an event (<i>B5A2 Power up</i>) is logged by the drive upon each power-up.	Enable			
	Disable		Power-up event logging disabled.	0			
	Enable		Power-up event logging enabled.	1			

No.	Name/V	alue	Description		Def/FbEq16
96.53	Actual c	hecksum	checksum is ge selected in 96.5	tual parameter configuration checksum. The enerated and updated whenever an action is 54 <i>Checksum action</i> .	Oh
			selected, but th customizer PC		
			See also sectio 123).	n Parameter checksum calculation (page	
	0000000 FFFFFF		Actual checksu	m.	-
96.54	Checks	um action	(96.53 Actual cl approved check	e drive reacts if the parameter checksum hecksum) does not match any of the active (96.5696.59). The active checksums 96.55 Checksum control word.	No action
	No actio	n	No action taken	n. (The checksum feature is not in use.)	0
	Pure eve	ent	The drive gener <i>mismatch</i>).	rates an event log entry (B686 Checksum	1
	Warning		The drive gener	rates a warning (A686 Checksum mismatch).	2
	Warning and prevent start		The drive generates a warning (<i>A686 Checksum mismatch</i>). Starting the drive is prevented.		3
	Fault		The drive trips of	on 6200 Checksum mismatch.	4
			Bits 47 select parameter (96.8	the actual checksum (96.53) is compared. t an approved (reference) checksum 5696.59) into which the actual checksum 96.53 is copied.	
	Bit	Name		Description	-
	0		checksum 1	1 = Enabled: Checksum 1 (96.56) is observed.	
	1		checksum 2	1 = Enabled: Checksum 2 (96.57) is observed.	
	2 3		checksum 3 checksum 4	1 = Enabled: Checksum 3 (96.58) is observed. 1 = Enabled: Checksum 4 (96.59) is observed.	
	3 4	• •	ed checksum 1	1 = Set: Copy value of 96.53 into 96.56.	
	- 5	• •	ed checksum 2	1 = Set. Copy value of 96.53 into 96.57.	
	6		ed checksum 3	1 = Set: Copy value of 96.53 into 96.58.	
	7		ed checksum 4	1 = Set: Copy value of 96.53 into 96.59.	
	815				
<u>-</u>	0000000		Checksum control word.		1 = 1
96.56	Approve checksu		Approved (reference) checksum 1.		Oh
	0000000 FFFFFF		Approved checl	ksum 1.	-
96.57	Approve checksu		Approved (refer	rence) checksum 2.	0h
	0000000)0h	Approved checl	ksum 2.	-

No.	Name/V	Name/Value Description		Def/FbEq16
96.58	Approve checksu		Approved (reference) checksum 3.	Oh
	00000000h FFFFFFFh		Approved checksum 3.	-
96.59	Approve checksu		Approved (reference) checksum 4.	Oh
	0000000 FFFFF		Approved checksum 4.	-
96.61	User da status w	ta logger ⁄ord	Provides status information on the user data logger (see description of <i>User data logger</i> on page <i>551</i>).	0000b
	Bit	Name	Description	
	0 Running		1 = The user data logger is running. The bit is cleared after th time has passed.	e post-trigger
	1	Triggered	1 = The user data logger has been triggered. The bit is cleared when the logger is restarted.	
	2	Data available	1 = The user data logger contains data that can be read. Note not cleared because the data is saved to the memory unit.	that the bit is
	3	Configured	d 1 = The user data logger has been configured. Note that the bit is n cleared because the configuration data is saved to the memory unit	
	415 Reserved		·	
	0000b	.1111b	User data logger status word.	1 = 1
96.63	User da trigger	ta logger	Triggers, or selects a source that triggers, the user data logger.	Off
	Off		0.	0
	On		1.	1
	Other [bit]			I.
96.64	Other [b	it]	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
96.64		it] ta logger	Source selection (see <i>Terms and abbreviations</i> on page <i>131</i>). Starts, or selects a source that starts, the user data logger.	•
96.64	User da	-		-
96.64	User da start	-	Starts, or selects a source that starts, the user data logger.	- Off
96.64	User da start Off	ta logger	Starts, or selects a source that starts, the user data logger.	- Off 0
	User da start Off On Other [b	ta logger it] data logger	Starts, or selects a source that starts, the user data logger. 0. 1.	- Off 0 1
	User da start Off On Other [b Factory	ta logger it] data logger	Starts, or selects a source that starts, the user data logger. 0. 1. Source selection (see <i>Terms and abbreviations</i> on page <i>131</i>). Selects the sampling interval for the factory data logger (see	- Off 0 1 -
	User da start Off On Other [b Factory time leve	ta logger it] data logger	Starts, or selects a source that starts, the user data logger. 0. 1. Source selection (see <i>Terms and abbreviations</i> on page <i>131</i>). Selects the sampling interval for the factory data logger (see description of <i>Factory data logger</i> on page <i>550</i>).	- Off 0 1 - 500us
96.64	User da start Off On Other [b Factory time leve 500us	ta logger it] data logger	Starts, or selects a source that starts, the user data logger. 0. 1. Source selection (see <i>Terms and abbreviations</i> on page <i>131</i>). Selects the sampling interval for the factory data logger (see description of <i>Factory data logger</i> on page <i>550</i>). 500 microseconds.	- Off 0 1 - 500us 500
96.65	User da start Off On Other [b Factory time leve 500us 2ms 10ms	ta logger it] data logger el adaptive	Starts, or selects a source that starts, the user data logger. 0. 1. Source selection (see <i>Terms and abbreviations</i> on page <i>131</i>). Selects the sampling interval for the factory data logger (see description of <i>Factory data logger</i> on page <i>550</i>). 500 microseconds. 2 milliseconds.	- Off 0 1 - 500us 500 2000
	User da start Off On Other [b Factory time lev 500us 2ms 10ms Disable	ta logger it] data logger el adaptive	Starts, or selects a source that starts, the user data logger. 0. 1. Source selection (see <i>Terms and abbreviations</i> on page <i>131</i>). Selects the sampling interval for the factory data logger (see description of <i>Factory data logger</i> on page <i>550</i>). 500 microseconds. 2 milliseconds. 10 milliseconds. Enables/disables the adaptive program (if present).	- Off 0 1 - 500us 500 2000 10000

No.	Name/Value	Description	Def/FbEq16
96.100	Change user pass code	(Visible when user lock is open) To change the current user pass code, enter a new code into this parameter as well as 96.101 Confirm user pass code. A warning will be active until the new pass code is confirmed. To cancel changing the pass code, close the user lock without confirming. To close the lock, enter an invalid pass code in parameter 96.02 Pass code, activate parameter 96.08 Control board boot, or cycle the power. See also section User lock (page 124).	1000000
	10000000 99999999	New user pass code.	-
96.101	Confirm user pass code	(Visible when user lock is open) Confirms the new user pass code entered in 96.100 Change user pass code.	
	10000000 99999999	Confirmation of new user pass code.	-

No.	Name/Value		Description I		Def/FbEq16
96.102	User lock functionality		Selects t user lock the user Note : We	when user lock is open) he actions or functionalities to be prevented by the Note that the changes made take effect only when lock is closed. See parameter 96.02 Pass code. e recommend you select all the actions and lities unless otherwise required by the application.	000b
	Bit	Name		Information	
	0	Disable ABB access levels		1 = ABB access levels (service, advanced programm 96.03) disabled	er, etc.; see
	1	Freeze parameter lock state		1 = Changing the parameter lock state prevented, ie. pass code 358 has no effect	
	2	Disable file download		 1 = Loading of files to drive prevented. This applies to firmware upgrades safety functions module (<i>FSO-xx</i>) configuration parameter restore loading an adaptive program loading and debugging an application program changing home view of control panel editing drive texts editing the favorite parameters list on control panel configuration settings made through control panel such as time/date formats and enabling/disabling clock display. 	
	3	Disable FB write to hidden		1 = Access to parameters on disabled access levels from fieldbus prevented.	
	45	Reserved			
	6 7	Protect AP Disable panel Bluetooth		 1 = Creating a backup and restoring from a backup prevented. 1 = Bluetooth disabled on ACS-AP-W control panel. If the drive is part of a panel bus, Bluetooth is disabled on all panels. 	
	810	Reserved			0.
	11	Disable OEM access level 1		1 = OEM access level 1 disabled	
	12	Disable OEM access level 2		1 = OEM access level 2 disabled	
	13	Disable OEM access level 3		1 = OEM access level 3 disabled	
	1415	15 Reserved			
	0000hFFFFh Selectio		Selection	of actions to be prevented by user lock.	-
6.108	boot 95.20) Changir control u system)		95.20) Changing control u system).	<i>ible when IGBT supply unit control activated by</i> g the value of this parameter to 1 reboots the supply nit (without requiring a power off/on cycle of the drive e reverts to 0 automatically.	0
	01		1 = Rebo	oot the supply control unit.	1 = 1

No.	Name/Value	Description	Def/FbEq16
97 Mo	tor control	Motor model settings.	
97.01	Switching frequency reference	Defines the switching frequency when it is not otherwise being internally limited. Note: This is an expert level parameter and should not be adjusted without appropriate skill.	4.500 kHz
	0.000 24.000 kHz	Switching frequency reference.	1000 = 1 kHz
97.02	Minimum switching frequency	 Defines a minimum switching frequency reference. The actual switching frequency will not fall below this limit under any circumstances. Notes: This is an expert level parameter and should not be adjusted without appropriate skill. The drive has internal switching frequency limits that may override the value entered here. 	1.500 kHz
	0.000 24.000 kHz	Minimum switching frequency.	1000 = 1 kHz
97.03	Slip gain	Defines the slip gain which is used to improve the estimated motor slip. 100% means full slip gain; 0% means no slip gain. The default value is 100%. Other values can be used if a static speed error is detected despite having the setting at full slip gain. Example (with nominal load and nominal slip of 40 rpm): A 1000 rpm constant speed reference is given to the drive. Despite having full slip gain (= 100%), a manual tachometer measurement from the motor axis gives a speed value of 998 rpm. The static speed error is 1000 rpm - 998 rpm = 2 rpm. To compensate the error, the slip gain should be increased to 105% (2 rpm / 40 rpm = 5%).	100%
	0 200%	Slip gain.	1 = 1%
97.04	Voltage reserve	Defines the minimum allowed voltage reserve. When the voltage reserve has decreased to the set value, the drive enters the field weakening area. Note: This is an expert level parameter and should not be adjusted without appropriate skill. If the intermediate circuit DC voltage $U_{dc} = 550$ V and the voltage reserve is 5%, the rms value of the maximum output voltage in steady-state operation is 0.95×550 V / sqrt(2) = 369 V The dynamic performance of the motor control in the field weakening area can be improved by increasing the voltage reserve value, but the drive enters the field weakening area earlier.	-2%
	-4 50%	Voltage reserve.	1 = 1%
97.05	Flux braking	Defines the level of flux braking power. (Other stopping and braking modes can be configured in parameter group 21 <i>Start/stop mode</i>). See section <i>Flux braking</i> (page 95). Note: This is an expert level parameter and should not be adjusted without appropriate skill.	Disabled
	Disabled	Flux braking is disabled.	0
	Moderate	Flux level is limited during the braking. Deceleration time is longer compared to full braking.	1

No.	Name/Value	Description	Def/FbEq16
	Full	Maximum braking power. Almost all available current is used to convert the mechanical braking energy to thermal energy in the motor.	2
97.06	Flux reference select	Defines the source of flux reference. Note: This is an expert level parameter and should not be adjusted without appropriate skill.	User flux reference
	Zero	None.	0
	User flux reference	Parameter 97.07 User flux reference.	1
	Other	Source selection (see <i>Terms and abbreviations</i> on page 131).	-
97.07	User flux reference	Defines the flux reference when parameter 97.06 Flux reference select is set to User flux reference.	100.00%
	0.00 200.00%	User-defined flux reference.	100 = 1%
97.08	Optimizer minimum torque	This parameter can be used to improve the control dynamics of a synchronous reluctance motor or a salient permanent magnet synchronous motor. As a rule of thumb, define a level to which the output torque must rise with minimum delay. This will increase the motor current and improve the torque response at low speeds.	0.0%
	0.0 1600.0%	Optimizer torque limit.	10 = 1%
97.09	Switching freq mode	An optimization setting for balancing between control performance and motor noise level. Note: This is an expert level parameter and should not be adjusted without appropriate skill.	Normal
	Normal	Control performance optimized for long motor cables.	0
	Low noise	Minimizes motor noise. Note: This setting requires derating. Refer to the rating data in the <i>Hardware manual</i> .	1
	Cyclic	Control performance optimized for cyclic load applications. Note: This setting is not suitable for long motor cables.	2
	Custom	This setting is to be used by ABB-authorized service personnel only. Note: This setting may require derating. Refer to the rating data in the <i>Hardware manual</i> .	3
97.10	Signal injection	 Enables signal injection. A high-frequency alternating signal is injected into the motor at low speeds to improve the stability of torque control. Signal injection can be enabled with different amplitude levels. Notes: This is an expert level parameter and should not be adjusted without appropriate skill. Use as low a level as possible that gives satisfactory performance. Signal injection cannot be applied to asynchronous motors. 	Disabled
	Disabled	Signal injection enabled with an amplitude level of 5%.	0
	Enabled (5 %)	Signal injection enabled with an amplitude level of 10%.	1
	Enabled (10 %)	Signal injection enabled with an amplitude level of 15%.	2
	Enabled (15 %)	Signal injection enabled with an amplitude level of 20%.	3
	Enabled (20 %)	Signal injection enabled with an amplitude level of 5%.	4

No.	Name/Value	Description	Def/FbEq16
97.11	TR tuning	Rotor time constant tuning. This parameter can be used to improve torque accuracy in closed-loop control of an induction motor. Normally, the motor identification run provides sufficient torque accuracy, but manual fine-tuning can be applied in exceptionally demanding applications to achieve optimal performance. Note: This is an expert level parameter and should not be adjusted without appropriate skill.	100%
	25400%	Rotor time constant tuning.	1 = 1%
97.12	IR comp step-up frequency	IR compensation (ie. output voltage boost) can be used in step-up applications to compensate for resistive losses in the step-up transformer, cabling and motor. As voltage cannot be fed through a step-up transformer at 0 Hz, a specific type of IR compensation should be used. This parameter adds a frequency breakpoint for parameter 97.13 IR compensation as shown below. U/U_{N} (%) Relative output voltage with IR (%) 100% 97.12 Field weakening point 0.0 Hz = Breakpoint disabled.	0.0 Hz
	0.0 50.0 Hz	IR compensation breakpoint for step-up applications.	1 = 1 Hz

No.	Name/Value	Description	Def/FbEq16
97.13	IR compensation	Defines the relative output voltage boost at zero speed (IR compensation). The function is useful in applications with a high break-away torque where direct torque control (DTC mode) cannot be applied. U/U_N (%) 100% Relative output voltage. IRcompensation $100%IR compensation.IR compensation.Field weakeningf(Hz)See also section IR compensation for scalar motor control onpage 92.$	0.00%
	0.00 50.00%	Voltage boost at zero speed in percent of nominal motor voltage.	1 = 1%
97.15	Motor model temperature adaptation	Selects whether the temperature-dependent parameters (such as stator or rotor resistance) of the motor model adapt to actual (measured or estimated) temperature or not. See parameter group 35 <i>Motor thermal protection</i> for selection of temperature measurement sources.	Disabled
	Disabled	Temperature adaptation of motor model disabled.	0
	Estimated temperature	Estimated temperature (<i>35.01 Motor estimated temperature</i>) used for adaptation of motor model.	1
	Measured temperature 1	Measured temperature 1 (35.02 Measured temperature 1) used for adaptation of motor model.	2
	Measured temperature 2	Measured temperature 2 (35.03 Measured temperature 2) used for adaptation of motor model.	3
97.18	Hexagonal field weakening	 Activates hexagonal motor flux pattern in the field weakening area, ie. above the limit defined by parameter 97.19 Hexagonal field weakening point. Note: This parameter is only effective in scalar motor control mode. See also section Hexagonal motor flux pattern (page 65). 	Off
	Off	The rotating flux vector follows a circular pattern.	0
	On	The flux vector follows a circular pattern below, and a hexagonal pattern above, the hexagonal field weakening point (<i>97.19</i>).	1

No.	Name/Value	Description	Def/FbEq16
97.19	Hexagonal field weakening point	Defines the activation limit for hexagonal field weakening (in percent of the field weakening point, ie. the frequency at which maximum output voltage is reached). See parameter 97.18 Hexagonal field weakening. Note: This parameter is only effective in scalar motor control	120.0%
	0.0 500.0%	mode.	1 - 10/
07.00	0.0 500.0%	Activation limit for hexagonal field weakening.	1 = 1%
97.32	Motor torque unfiltered	Unfiltered motor torque in percent of the nominal motor torque.	-
	-1600.0 1600.0%	Unfiltered motor torque.	See par. 46.03
97.33	Speed estimate filter time	Defines a filtering time for estimated speed. See the diagram on page 633.	5.00 ms
	0.00 100.00 ms	Filtering time for estimated speed.	1 = 1 ms
98 Use parame	r motor eters	Motor values supplied by the user that are used in the motor model. These parameters are useful for non-standard motors, or to just get more accurate motor control of the motor on site. A better motor model always improves the shaft performance.	
98.01	User motor model mode	 Activates the motor model parameters 98.0298.14 and the rotor angle offset parameter 98.15. Notes: Parameter value is automatically set to zero when ID run is selected by parameter 99.13 ID run requested. The values of parameters 98.0298.15 are then updated according to the motor characteristics identified during the ID run. Measurements made directly from the motor terminals during the ID run are likely to produce slightly different values than those on a datasheet from a motor manufacturer. This parameter cannot be changed while the drive is running. 	Not selected
	Not selected	Parameters 98.0298.15 inactive.	0
	Motor parameters	The values of parameters <i>98.0298.14</i> are used as the motor model.	1
	Position offset	The value of parameter 98.15 is used as the rotor angle offset. Parameters 98.0298.14 are inactive.	2
	Motor parameters & position offset	The values of parameters 98.0298.14 are used as the motor model, and the value of parameter 98.15 is used as the rotor angle offset.	3
98.02	Rs user	Defines the stator resistance R_S of the motor model. With a star-connected motor, R_S is the resistance of one winding. With a delta-connected motor, R_S is one-third of the resistance of one winding.	0.00000 p.u.
	0.00000 0.50000 p.u.	Stator resistance in per unit.	-
98.03	Rr user	Defines the rotor resistance R_R of the motor model. Note: This parameter is valid only for asynchronous motors.	0.00000 p.u.
	0.00000 0.50000 p.u.	Rotor resistance in per unit.	-

No.	Name/Value	Description	Def/FbEq16
98.04	Lm user	Defines the main inductance $L_{\rm M}$ of the motor model. Note: This parameter is valid only for asynchronous motors.	0.00000 p.u.
	0.00000 10.00000 p.u.	Main inductance in per unit.	-
98.05	SigmaL user	Defines the leakage inductance $\mathbf{\sigma}_{L_{S}}$. Note: This parameter is valid only for asynchronous motors.	0.00000 p.u.
	0.00000 1.00000 p.u.	Leakage inductance in per unit.	-
98.06	Ld user	Defines the direct axis (synchronous) inductance. Note: This parameter is valid only for permanent magnet motors.	0.00000 p.u.
	0.00000 10.00000 p.u	Direct axis inductance in per unit.	-
98.07	Lq user	Defines the quadrature axis (synchronous) inductance. Note: This parameter is valid only for permanent magnet motors.	0.00000 p.u.
	0.00000 10.00000 p.u	Quadrature axis inductance in per unit.	-
98.08	PM flux user	Defines the permanent magnet flux. Note: This parameter is valid only for permanent magnet motors.	0.00000 p.u.
	0.00000 2.00000 p.u	Permanent magnet flux in per unit.	-
98.09	Rs user SI	Defines the stator resistance R _S of the motor model.	0.00000 ohm
	0.00000 100.00000 ohm	Stator resistance.	-
98.10	Rr user SI	Defines the rotor resistance R_R of the motor model. Note: This parameter is valid only for asynchronous motors.	0.00000 ohm
	0.00000 100.00000 ohm	Rotor resistance.	-
98.11	Lm user SI	Defines the main inductance $L_{\rm M}$ of the motor model. Note: This parameter is valid only for asynchronous motors.	0.00 mH
	0.00100000.00 mH	Main inductance.	1 = 10 mH
98.12	SigmaL user SI	Defines the leakage inductance $\mathbf{\sigma}_{L_{S}}$. Note: This parameter is valid only for asynchronous motors.	0.00 mH
	0.00100000.00 mH	Leakage inductance.	1 = 10 mH
98.13	Ld user SI	Defines the direct axis (synchronous) inductance. Note: This parameter is valid only for permanent magnet motors.	0.00 mH
	0.00100000.00 mH	Direct axis inductance.	1 = 10 mH
98.14	Lq user SI	Defines the quadrature axis (synchronous) inductance. Note: This parameter is valid only for permanent magnet motors.	0.00 mH
	0.00100000.00 mH	Quadrature axis inductance.	1 = 10 mH

No.	Name/Value	Description	Def/FbEq16
98.15	Position offset user	 Defines an angle offset between the zero position of the synchronous motor and the zero position of the position sensor. This value is initially set by the autophasing routine when parameter <i>21.13 Autophasing mode</i> is set to <i>Turning with Z-pulse</i>, and can be fine-tuned later on. Notes: The value is in electrical degrees. The electrical angle equals the mechanical angle multiplied by the number of motor pole pairs. 	0 deg
		This parameter is valid only for permanent magnet motors.	
	0360 deg	Angle offset.	1 = 1 deg

99 Mo	tor data	Motor configuration settings.	
99.03	Motor type	Selects the motor type. Note: This parameter cannot be changed while the drive is running.	Asynchro- nous motor, SynRM (95.21 b1) Permanent magnet motor (95.21 b2)
	Asynchronous motor	Standard squirrel cage AC induction motor (asynchronous induction motor).	0
	Permanent magnet motor	Permanent magnet motor. Three-phase AC synchronous motor with permanent magnet rotor and sinusoidal BackEMF voltage.	1
	SynRM	Synchronous reluctance motor. Three-phase AC synchronous motor with salient pole rotor without permanent magnets.	2
99.04	Motor control mode	Selects the motor control mode.	DTC
	DTC	 Direct torque control. This mode is suitable for most applications. Note: Instead of direct torque control, scalar control is also available, and should be used in the following situations: with multimotor applications 1) if the load is not equally shared between the motors, 2) if the motors are of different sizes, or 3) if the motors are going to be changed after the motor identification (ID run) if the nominal current of the motor is less than 1/6 of the nominal output current of the drive if the drive is used with no motor connected (for example, for test purposes). See also section <i>Operating modes of the drive</i> on page 57. 	0

No.	Name/Value	Description	Def/FbEq16
	Scalar	 Scalar control. The outstanding motor control accuracy of DTC cannot be achieved in scalar control. Refer to the <i>DTC</i> selection above for a list of applications where scalar control should definitely be used. Notes: Correct motor operation requires that the magnetizing current of the motor does not exceed 90% of the nominal current of the inverter. Some standard features are disabled in scalar control mode. See also section <i>Scalar motor control</i> (page <i>91</i>), and section <i>Operating modes of the drive</i> (page <i>57</i>). 	1
99.06	Motor nominal current	 Defines the nominal motor current. This setting must match the value on the rating plate of the motor. If multiple motors are connected to the drive, enter the total current of the motors. Notes: Correct motor operation requires that the magnetizing current of the motor does not exceed 90% of the nominal current of the drive. This parameter cannot be changed while the drive is running. 	0.0 A
	0.0 6400.0 A	Nominal current of the motor. The allowable range is $1/62 \times I_N$ (nominal current) of the drive $(02 \times I_N$ with scalar control mode).	1 = 1 A
99.07	Motor nominal voltage	 Defines the nominal motor voltage supplied to the motor. This setting must match the value on the rating plate of the motor. Notes: With permanent magnet motors, the nominal voltage is the BackEMF voltage at nominal speed of the motor. If the voltage is given as voltage per rpm, e.g. 60 V per 1000 rpm, the voltage for a nominal speed of 3000 rpm is 3 × 60 V = 180 V. The stress on the motor insulation is always dependent on 	0.0 V
		 The stress on the motor insulation is always dependent on the drive supply voltage. This also applies to the case where the motor voltage rating is lower than that of the drive and the supply. This parameter cannot be changed while the drive is running. 	
	0.0 800.0 V	Nominal voltage of the motor. The allowable range is $1/62 \times U_N$ (nominal voltage) of the drive. U_N equals the upper bound of the supply voltage range selected by parameter 95.01 Supply voltage.	10 = 1 V
99.08	Motor nominal frequency	Defines the nominal motor frequency. This setting must match the value on the rating plate of the motor. Note: This parameter cannot be changed while the drive is running.	50.00 Hz
	0.00 1000.00 Hz	Nominal frequency of the motor.	10 = 1 Hz
99.09	Motor nominal speed	Defines the nominal motor speed. The setting must match the value on the rating plate of the motor. Note: This parameter cannot be changed while the drive is running.	0 rpm
	0 30000 rpm	Nominal speed of the motor.	1 = 1 rpm

No.	Name/Value	Description	Def/FbEq16
99.10	Motor nominal power	Defines the nominal motor power. The setting must match the value on the rating plate of the motor. If nominal power is not shown on the rating plate, nominal torque can be entered instead in parameter <i>99.12</i> . If multiple motors are connected to the drive, enter the total power of the motors. The unit is selected by parameter <i>96.16 Unit selection</i> . Note: This parameter cannot be changed while the drive is running.	0.00 kW or hp
	0.0010000.00 kW or 0.0013404.83 hp	Nominal power of the motor.	1 = 1 unit
99.11	Motor nominal cos Φ	 Defines the cosphi of the motor for a more accurate motor model. The value is not obligatory, but is useful with an asynchronous motor, especially when performing a standstill identification run. With a permanent magnet or synchronous reluctance motor, this value is not needed. Notes: Do not enter an estimated value. If you do not know the exact value, leave the parameter at zero. This parameter cannot be changed while the drive is running. 	0.00
	0.00 1.00	Cosphi of the motor.	100 = 1
99.12	Motor nominal torque	 Defines the nominal motor shaft torque for a more accurate motor model. This value can be given instead of nominal power (99.10) if shown on the rating plate of the motor. The unit is selected by parameter 96.16 Unit selection. Note: This setting is an alternative to the nominal power value (99.10). If both are entered, 99.12 takes priority. This parameter cannot be changed while the drive is running. 	0.000 N∙m or lb∙ft
	0.000… 4000000.000 N∙m or Ib∙ft	Nominal motor torque.	1 = 1 unit

No.	Name/Value	Description	Def/FbEq16
99.13	ID run requested	Selects the type of the motor identification routine (ID run) performed at the next start of the drive. During the ID run, the drive will identify the characteristics of the motor for optimum motor control.	None Standstill (95.21 b1b2)
		If no ID run has been performed yet (or if default parameter values have been restored using parameter <i>96.06 Parameter restore</i>), this parameter is automatically set to <i>Standstill</i> , signifying that an ID run must be performed. After the ID run, the drive stops and this parameter is automatically set to <i>None</i> .	
		Notes:	
		• For the <i>Advanced</i> ID run, the machinery must always be de-coupled from the motor.	
		 Before activating the ID run, configure motor temperature measurement (if used) in parameter group 35 Motor thermal protection, and in parameter 97.15. If a sine filter is installed, set the appropriate bit in parameter 95.15 Special HW settings before activating the 	
		ID run. With a non-ABB (custom) filter, set also 99.18 and 99.19.	
		 With scalar control mode (99.04 Motor control mode = Scalar), the ID run is not requested automatically. However, an ID run can be performed for more accurate torque estimation. 	
		 Once the ID run is activated, it can be canceled by stopping the drive. The ID run must be performed every time any of the motor parameters (99.04, 99.0699.12) have been changed. 	
		 Ensure that the Safe torque off and emergency stop circuits (if any) are closed during the ID run. 	
		Mechanical brake (if present) is not opened by the logic for the ID run.	
		This parameter cannot be changed while the drive is running.	
	None	No motor ID run is requested. This mode can be selected only if the ID run (<i>Normal</i> , <i>Reduced</i> , <i>Standstill</i> , <i>Advanced</i> , <i>Advanced Standstill</i>) has already been performed once.	0
	Normal	Normal ID run. Guarantees good control accuracy for all cases. The ID run takes about 90 seconds. This mode should be selected whenever it is possible. Notes:	1
		• If the load torque will be higher than 20% of motor nominal torque, or if the machinery is not able to withstand the nominal torque transient during the ID run, then the driven machinery must be de-coupled from the motor during a Normal ID run.	
		• Check the direction of rotation of the motor before starting the ID run. During the run, the motor will rotate in the forward direction.	
		WARNING! The motor will run at up to approximately 50100% of the nominal speed during the ID run. ENSURE THAT IT IS SAFE TO RUN THE MOTOR BEFORE PERFORMING THE ID RUN!	

No.	Name/Value	Description	Def/FbEq16
	Reduced	 Reduced ID run. This mode should be selected instead of the <i>Normal</i> or <i>Advanced</i> ID Run if mechanical losses are higher than 20% (i.e. the motor cannot be de-coupled from the driven equipment), or if flux reduction is not allowed while the motor is running (i.e. in case of a motor with an integrated brake supplied from the motor terminals). With this ID run mode, the resultant motor control in the field weakening area or at high torques is not necessarily as accurate as motor control following a Normal ID run. Reduced ID run is completed faster than the Normal ID Run (< 90 seconds). Note: Check the direction of rotation of the motor before starting the ID run. During the run, the motor will rotate in the forward direction. WARNING! The motor will run at up to approximately 50100% of the nominal speed during the ID run. ENSURE THAT IT IS SAFE TO RUN THE MOTOR BEFORE PERFORMING THE ID RUN! 	2
	Standstill	 Standstill ID run. The motor is injected with DC current. With an AC induction (asynchronous) motor, the motor shaft is not rotated. With a permanent magnet motor or synchronous reluctance motor, the shaft can rotate up to half a revolution. Note: A standstill ID run should be selected only if the <i>Normal, Reduced</i> or <i>Advanced</i> ID run is not possible due to the restrictions caused by the connected mechanics (eg. with lift or crane applications). See also selection <i>Advanced Standstill</i>. 	3
	Autophasing	 The autophasing routine determines the start angle of a permanent magnet or synchronous reluctance motor (see page 92). Autophasing does not update the other motor model values. Autophasing is automatically performed as part of the <i>Normal, Reduced, Standstill, Advanced</i> or <i>Advanced Standstill</i> ID runs. Using this setting, it is possible to perform autophasing alone. This is useful after changes in the feedback configuration, such as the replacement or addition of an absolute encoder, resolver, or pulse encoder with commutation signals. Notes: This setting can only be used after a <i>Normal, Reduced, Standstill, Advanced</i> or <i>Advanced Standstill</i> ID run has already been performed. Depending on the selected autophasing mode, the shaft can rotate during autophasing. See parameter <i>21.13 Autophasing mode</i>. 	4
	Current measurement calibration	Requests current measurement calibration, that is identification of current measurement offset and gain errors. The calibration will be performed at next start.	5

No.	Name/Value	alue Description I			
Advanced		Advanced ID run. Guarantees the best possible control accuracy. The ID run can take a couple of minutes. This mode should be selected when top performance is needed across the whole operating area. Note: The driven machinery must be de-coupled from the motor because of high torque and speed transients that are applied. WARNING! The motor runs at up to approximately 50100% of the nominal speed during the ID run.	6		
		Several accelerations and decelerations are done. ENSURE THAT IT IS SAFE TO RUN THE MOTOR BEFORE PERFORMING THE ID RUN!			
	Advanced Standstill	 Advanced Standstill ID run. This selection is recommended with AC induction motors up to 75 kW instead of the Standstill ID run if the exact nominal ratings of the motor are not known, or the control performance of the motor is not satisfactory after a Standstill ID run. Note: The time it takes for the Advanced Standstill ID run to complete varies according to motor size. With a small motor, the ID run typically completes within 5 minutes; with a large motor, the ID run may take up to an hour. 	7		
99.14	Last ID run performed	Shows the type of ID run that was performed last. For more information about the different modes, see the selections of parameter <i>99.13 ID run requested</i> .	None		
	None	No ID run has been performed.	0		
	Normal	Normal ID run.	1		
	Reduced	Reduced ID run.	2		
	Standstill	Standstill ID run.	3		
	Advanced	Advanced ID run.	6		
	Advanced Standstill	Advanced Standstill ID run.	7		
99.15	Motor polepairs calculated	Calculated number of pole pairs in the motor.	0		
	01000	Number of pole pairs.	1 = 1		
99.16	Motor phase order	 Switches the rotation direction of motor. This parameter can be used if the motor turns in the wrong direction (for example, because of the wrong phase order in the motor cable), and correcting the cabling is considered impractical. Notes: Changing this parameter does not affect speed reference polarities, so positive speed reference will rotate the motor forward. The phase order selection just ensures that "forward" is in fact the correct direction. After changing this parameter, the sign of encoder feedback (if any) must be checked. This can be done by setting parameter 90.41 Motor feedback selection to Estimate, and comparing the sign of 90.01 Motor speed for control to 90.10 Encoder 1 speed (or 90.20 Encoder 2 speed). If the sign of the measurement is incorrect, the encoder wiring must be corrected or the sign of 90.43 Motor gear numerator reversed. 	UVW		
	UVW	Normal.	0		
	UWV	Reversed rotation direction.	1		

No.	Name/Value	Description	Def/FbEq16
99.18	Sine filter inductance	Defines the inductance of a custom sine filter, ie. when parameter <i>95.15 Special HW settings</i> bit 3 is activated. Note: For an ABB sine filter (<i>95.15 Special HW settings</i> bit 1), this parameter is set automatically and should not be adjusted.	-
	0.000 100000.000 mH	Inductance of custom sine filter.	1000 = 1 mH
99.19	Sine filter capacitance	Defines the capacitance of a custom sine filter, ie. when parameter 95.15 Special HW settings bit 3 is activated. If the capacitors are star/wye-connected, enter the capacitance of <u>one leg</u> into the parameter. $\begin{array}{c} & & \\ & &$	- 100 = 1 µF
	0.00 100000.00 μF	Capacitance of custom sine filter.	100 = 1 μF
99.200	Application select	Activates spinning/traverse control software.	Spinning
	Spinning	Spinning control is activated.	0
	Traverse	Traverse control is activated.	1
	Primary	Primary control program is activated.	2
200 Sa	fetv	FSO-xx settings.	

parameters in this group, refer to the documentation of the FSO-xx safety functions module. For details

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Additional Parameter data

Contents of this chapter

This chapter lists the parameters with some additional data such as their ranges and 32-bit fieldbus scaling. For parameter descriptions, see chapter *Parameters* (page 131).

Terms and abbreviations

Term	Definition
Actual signal	Signal measured or calculated by the drive. Usually can only be monitored but not adjusted; some counter-type signals can however be reset.
Analog src	Analog source: the parameter can be set to the value of another parameter by choosing "Other", and selecting the source parameter from a list.
	Note: The source parameter must be a 32-bit real (floating point) number. To use a 16-bit integer (for example, received in DDCS data sets) as the source, data storage parameters 47.0147.08 (see page 352) can be used.
	In addition to the "Other" selection, the parameter may offer other pre- selected settings.
Binary src	Binary source: the value of the parameter can be taken from a specific bit in another parameter value ("Other"). Sometimes the value can be fixed to 0 (false) or 1 (true). In addition, the parameter may offer other pre-selected settings.
Bit pointer	Bit pointer. A bit pointer can point to a single bit in the value of another parameter, or be fixed to 0 (C.FALSE) or 1 (C.TRUE).
Data	Data parameter.
FbEq32	32-bit fieldbus equivalent: The scaling between the value shown on the panel and the integer used in communication when a 32-bit value is selected for transmission to an external system.
	The corresponding 16-bit scalings are listed in chapter <i>Parameters</i> (page <i>131</i>).
INT16	16-bit integer value (15 bits + sign).
INT32	32-bit integer value (31 bits + sign).
List	Selection list.
No.	Parameter number.
РВ	Packed Boolean (bit list).
Real	Real number.
Туре	Parameter type. See Analog src, Binary src, List, PB, Real.
UDINT	32-bit unsigned integer value.
UINT	32-bit unsigned integer value.

Fieldbus addresses

Refer to the User's manual of the fieldbus adapter.

Parameter groups 1...9

No.	Name	Туре	Range	Unit	FbEq32
01 Actu	al values			1	
01.01	Motor speed used	Real	-30000.00 30000.00	rpm	100 = 1 rpm
01.02	Motor speed estimated	Real	-30000.00 30000.00	rpm	100 = 1 rpm
01.03	Motor speed %	Real	-1000.00 1000.00	%	100 = 1%
01.04	Encoder 1 speed filtered	Real	-30000.00 30000.00	rpm	100 = 1 rpm
01.05	Encoder 2 speed filtered	Real	-30000.00 30000.00	rpm	100 = 1 rpm
01.06	Output frequency	Real	-500.00 500.00	Hz	100 = 1 Hz
01.07	Motor current	Real	0.00 30000.00	А	100 = 1 A
01.08	Motor current % of motor nom	Real	0.0 1000.0	%	10 = 1%
01.10	Motor torque	Real	-1600.0 1600.0	%	10 = 1%
01.11	DC voltage	Real	0.00 2000.00	V	100 = 1 V
01.13	Output voltage	Real	02000	V	1 = 1 V
01.14	Output power	Real	-32768.00 32767.00	kWor hp	100 = 1 unit
01.15	Output power % of motor nom	Real	-300.00 300.00	%	10 = 1%
01.17	Motor shaft power	Real	-32768.00 32767.00	kW or hp	100 = 1 unit
01.18	Inverter GWh motoring	Real	032767	GWh	1 = 1 GWh
01.19	Inverter MWh motoring	Real	0999	MWh	1 = 1 MWh
01.20	Inverter kWh motoring	Real	0999	kWh	1 = 1 kWh
01.21	U-phase current	Real	-30000.00 30000.00	A	100 = 1 A
01.22	V-phase current	Real	-30000.00 30000.00	А	100 = 1 A
01.23	W-phase current	Real	-30000.00 30000.00	А	100 = 1 A
01.24	Flux actual %	Real	0200	%	100 = 1
01.25	INU momentary cos fii	Real	-1.00 1.00	-	1 = 1 rpm/s
01.29	Speed change rate	Real	-15000 15000	rpm/s	1 = 1 rpm/s
01.30	Nominal torque scale	Real	0.000	N•m or Ib∙ft	1000 = 1 unit
01.31	Ambient temperature	Real	-32768 32767	°C or °F	10 = 1°
01.32	Inverter GWh regenerating	Real	032767	GWh	1 = 1 GWh
01.33	Inverter MWh regenerating	Real	0999	MWh	1 = 1 MWh
01.34	Inverter kWh regenerating	Real	0999	kWh	1 = 1 kWh
01.35	Mot - regen energy GWh	Real	-32768 32767	GWh	1 = 1 GWh
01.36	Mot - regen energy MWh	Real	-999999	MWh	1 = 1 MWh
01.37	Mot - regen energy kWh	Real	-999999	kWh	1 = 1 kWh
01.61	Abs motor speed used	Real	0.00 30000.00	rpm	100 = 1 rpm
01.62	Abs motor speed %	Real	0.00 1000.00	%	100 = 1%
01.63	Abs output frequency	Real	0.00 500.00	Hz	100 = 1 Hz
01.64	Abs motor torque	Real	0.0 1600.0	%	10 = 1%
01.65	Abs output power	Real	0.00 32767.00	kW or hp	100 = 1 unit
01.66	Abs output power % motor nom	Real	0.00 300.00	%	10 = 1%

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No.	Name	Туре	Range	Unit	FbEq32
01.68	Abs motor shaft power	Real	0.00 32767.00	kW or hp	100 = 1 unit
01.70	Ambient temperature %	Real	-200.00 200.00	%	100 = 1%
01.71	Step-up motor current	Real	0.00 30000.00	Α	100 = 1 A
01.72	U-phase RMS current	Real	0.00 30000.00	A	100 = 1 A
01.73	V-phase RMS current	Real	0.00 30000.00	A	100 = 1 A
01.74	W-phase RMS current	Real	0.00 30000.00	A	100 = 1 A
1	(Parameters 01.10201.164 on	ly visible w	hen IGBT supply unit control	activated by	(95.20)
01.102	Line current	Real	0.00 30000.00	A	100 = 1 A
01.104	Active current	Real	0.00 30000.00	A	100 = 1 A
01.106	Reactive current	Real	0.00 30000.00	A	100 = 1 A
01.108	Grid frequency	Real	0.00 100.00	Hz	100 = 1 Hz
01.109	Grid voltage	Real	0.00 2000.00	V	100 = 1 V
01.110	Grid apparent power	Real	-30000.00 30000.00	kVA	100 = 1 kVA
01.112	Grid power	Real	-30000.00 30000.00	kW	100 = 1 kW
01.114	Grid reactive power	Real	-30000.00 30000.00	kvar	100 = 1 kvar
01.116	LSU cos Φ	Real	-1.00 1.00	-	100 = 1
01.164	LSU nominal power	Real	030000	kW	1 = 1 kW
03 Input	t references	·			
03.01	Panel reference	Real	-100000.00 100000.00	-	100 = 1
03.02	Panel reference 2	Real	-30000.00 30000.00	-	100 = 1
03.05	FB A reference 1	Real	-100000.00 100000.00	-	100 = 1
03.06	FB A reference 2	Real	-100000.00 100000.00	-	100 = 1
03.07	FB B reference 1	Real	-100000.00 100000.00	-	100 = 1
03.08	FB B reference 2	Real	-100000.00 100000.00	-	100 = 1
03.09	EFB reference 1	Real	-30000.00 30000.00	-	100 = 1
03.10	EFB reference 2	Real	-30000.00 30000.00	-	100 = 1
03.11	DDCS controller ref 1	Real	-30000.00 30000.00	-	100 = 1
03.12	DDCS controller ref 2	Real	-30000.00 30000.00	-	100 = 1
03.13	M/F or D2D ref1	Real	-30000.00 30000.00	-	100 = 1
03.14	M/F or D2D ref2	Real	-30000.00 30000.00	-	100 = 1
04 Warn	nings and faults				
04.01	Tripping fault	Data	0000hFFFFh	-	1 = 1
04.02	Active fault 2	Data	0000hFFFFh	-	1 = 1
04.03	Active fault 3	Data	0000hFFFFh	-	1 = 1
04.04	Active fault 4	Data	0000hFFFFh	-	1 = 1
04.05	Active fault 5	Data	0000hFFFFh	-	1 = 1
04.06	Active warning 1	Data	0000hFFFFh	-	1 = 1
04.07	Active warning 2	Data	0000hFFFFh	-	1 = 1
04.08	Active warning 3	Data	0000hFFFFh	-	1 = 1
04.09	Active warning 4	Data	0000hFFFFh	-	1 = 1
04.10	Active warning 5	Data	0000hFFFFh	-	1 = 1

No.	Name	Туре	Range	Unit	FbEq32
04.11	Latest fault	Data	0000hFFFFh	-	1 = 1
04.12	2nd latest fault	Data	0000hFFFFh	-	1 = 1
04.13	3rd latest fault	Data	0000hFFFFh	-	1 = 1
04.14	4th latest fault	Data	0000hFFFFh	-	1 = 1
04.15	5th latest fault	Data	0000hFFFFh	-	1 = 1
04.16	Latest warning	Data	0000hFFFFh	-	1 = 1
04.17	2nd latest warning	Data	0000hFFFFh	-	1 = 1
04.18	3rd latest warning	Data	0000hFFFFh	-	1 = 1
04.19	4th latest warning	Data	0000hFFFFh	-	1 = 1
04.20	5th latest warning	Data	0000hFFFFh	-	1 = 1
04.21	Fault word 1	PB	0000hFFFFh	-	1 = 1
04.22	Fault word 2	PB	0000hFFFFh	-	1 = 1
04.31	Warning word 1	PB	0000hFFFFh	-	1 = 1
04.32	Warning word 2	PB	0000hFFFFh	-	1 = 1
04.40	Event word 1	PB	0000hFFFFh	-	1 = 1
04.41	Event word 1 bit 0 code	Data	0000hFFFFh	-	1 = 1
04.42	Event word 1 bit 0 aux code	Data	0000 0000h FFFF FFFFh	-	1 = 1
04.43	Event word 1 bit 1 code	Data	0000hFFFFh	-	1 = 1
04.44	Event word 1 bit 1 aux code	Data	0000 0000h FFFF FFFFh	-	1 = 1
04.71	Event word 1 bit 15 code	Data	0000hFFFFh	-	1 = 1
04.72	Event word 1 bit 15 aux code	Data	0000 0000h FFFF FFFFh	-	1 = 1
04.120	Fault/Warning word compatibility	List	01	-	1 = 1
05 Diag	nostics				
05.01	On-time counter	Real	065535	d	1 = 1 d
05.02	Run-time counter	Real	065535	d	1 = 1 d
05.04	Fan on-time counter	Real	065535	d	1 = 1 d
05.11	Inverter temperature	Real	-40.0 160.0	%	10 = 1%
05.22	Diagnostic word 3	PB	0x00000xFFFF	-	-
05.41	Main fan service counter	Real	0150	%	1 = 1%
05.42	Aux. fan service counter	Real	0150	%	1 = 1%
	(Parameters 05.11105.121 on	ly visible w	hen IGBT supply unit control a	activated by	y 95.20)
05.111	Line converter temperature	Real	-40.0 160.0	%	10 = 1%
05.121	MCB closing counter	Real	04294967295	%	1 = 1
06 Cont	rol and status words		•		
06.01	Main control word	PB	0000hFFFFh	-	1 = 1
06.02	Application control word	PB	0000hFFFFh	-	1 = 1
06.03	FBAA transparent control word	PB	00000000hFFFFFFFh	-	1 = 1

No.	Name	Туре	Range	Unit	FbEq32
06.04	FBA B transparent control word	PB	00000000hFFFFFFFh	-	1 = 1
06.05	EFB transparent control word	PB	00000000hFFFFFFFh	-	
06.11	Main status word	PB	0000hFFFFh	-	1 = 1
06.16	Drive status word 1	PB	0000hFFFFh	-	1 = 1
06.17	Drive status word 2	PB	0000hFFFFh	-	1 = 1
06.18	Start inhibit status word	PB	0000hFFFFh	-	1 = 1
06.19	Speed control status word	PB	0000hFFFFh	-	1 = 1
06.20	Constant speed status word	PB	0000hFFFFh	-	1 = 1
06.21	Drive status word 3	PB	0000hFFFFh	-	1 = 1
06.25	Drive inhibit status word 2	PB	0000hFFFFh	-	1 = 1
06.29	MSW bit 10 sel	Binary src	-	-	1 = 1
06.30	MSW bit 11 sel	Binary src	-	-	1 = 1
06.31	MSW bit 12 sel	Binary src	-	-	1 = 1
06.32	MSW bit 13 sel	Binary src	-	-	1 = 1
06.33	MSW bit 14 sel	Binary src	-	-	1 = 1
	(Parameters 06.3606.43 c	only visible	when supply unit control activ	ated by <mark>95</mark>	.20)
06.36	LSU Status Word	PB	0000hFFFFh	-	1 = 1
06.39	Internal state machine LSU CW	PB	0000hFFFFh	-	1 = 1
06.40	LSU CW user bit 0 selection	Binary src	-	-	1 = 1
06.41	LSU CW user bit 1 selection	Binary src	-	-	1 = 1
06.42	LSU CW user bit 2 selection	Binary src	-	-	1 = 1
06.43	LSU CW user bit 3 selection	Binary src	-	-	1 = 1
06.45	Follower CW user bit 0 selection	Binary src	-	-	1 = 1
06.46	Follower CW user bit 1 selection	Binary src	-	-	1 = 1
06.47	Follower CW user bit 2 selection	Binary src	-	-	1 = 1
06.48	Follower CW user bit 3 selection	Binary src	-	-	1 = 1
06.50	User status word 1	PB	0000hFFFFh	-	1 = 1
06.60	User status word 1 bit 0 sel	Binary src	-	-	1 = 1
06.61	User status word 1 bit 1 sel	Binary src	-	-	1 = 1

No.	Name	Туре	Range	Unit	FbEq32
06.62	User status word 1 bit 2 sel	Binary	-	-	1 = 1
		src			
06.63	User status word 1 bit 3 sel	Binary src	-	-	1 = 1
06.64	User status word 1 bit 4 sel	Binary			1 = 1
00.04		src			
06.65	User status word 1 bit 5 sel	Binary	-	-	1 = 1
		src			
06.66	User status word 1 bit 6 sel	Binary src	-	-	1 = 1
06.67	User status word 1 bit 7 sel	Binary			1 = 1
00.07		src			
06.68	User status word 1 bit 8 sel	Binary	-	-	1 = 1
		src			
06.69	User status word 1 bit 9 sel	Binary src	-	-	1 = 1
06.70	User status word 1 bit 10 sel	Binary			1 = 1
00.70		src			
06.71	User status word 1 bit 11 sel	Binary	-	-	1 = 1
		src			
06.72	User status word 1 bit 12 sel	Binary src	-	-	1 = 1
06.73	User status word 1 bit 13 sel	Binary			1 = 1
00.70		src			
06.74	User status word 1 bit 14 sel	Binary	-	-	1 = 1
		src			
06.75	User status word 1 bit 15 sel	Binary src	-	-	1 = 1
06.100	User control word 1	PB	0000hFFFFh	-	1 = 1
06.101		PB	0000hFFFFh	_	1 = 1
	(Parameters 06.11606.118 on			l activated by	/ 95.20)
	LSU drive status word 1	PB	0000hFFFFh	-	1 = 1
06.118		PB	0000hFFFFh	-	1 = 1
07 Syst					
07.03	Drive rating id	List	-		1 = 1
07.04	Firmware name	List	-	-	1 = 1
07.05	Firmware version	Data	-	_	1 = 1
07.06	Loading package name	List	-	_	1 = 1
07.07	Loading package version	Data	-	-	1 = 1
07.08	Boot loader version	Data	-	-	1 = 1
07.11	Cpu usage	Real	0100	%	1 = 1%
07.13	PU logic version number	Data	-	-	1 = 1
	(Parameters 07.1307.24 onl		h option +N8010 lapplication	n proaramma	
07.21	Application environment	PB	0000hFFFFh		1 = 1
UT.21	status 1				

No.	Name	Туре	Range	Unit	FbEq32
07.22	Application environment status 2	PB	0000hFFFFh	-	1 = 1
07.23	Application name	Data	-	-	1 = 1
07.24	Application version	Data	-	-	1 = 1
07.25	Customization package name	Data	-	-	1 = 1
07.26	Customization package version	Data	-	-	1 = 1
07.30	Adaptive program status	PB	0000hFFFFh	-	1 = 1
	(Parameters 07.4007.41 only	visible wit	h option +N8010 [application	programma	ability])
07.40	IEC application Cpu usage peak	Real	0.0 100.0	%	10 = 1%
07.41	IEC application Cpu load average	Real	0.0 100.0	%	10 = 1%
	(Parameters 07.10607.107 on	ly visible w	hen IGBT supply unit control	activated b	y 95.20)
07.106	LSU loading package name	List	-	-	1 = 1
07.107	LSU loading package version	Data	-	-	1 = 1
09 Spin	ning actual				
09.01	Average spindle speed1	Real	099999	rpm	1 = 1 rpm
09.02	Average spindle speed2	Real	099999	rpm	1 = 1 rpm
09.03	Average spindle speed3	Real	099999	rpm	1 = 1 rpm
09.04	Average spindle speed4	Real	099999	rpm	1 = 1 rpm
09.05	Current pattern	UINT	14	-	1 = 1
09.06	Future pattern	UINT	14	-	1 = 1
09.07	Shift selected	UINT	01	-	1 = 1
09.08	Running section	UINT	116	-	1 = 1
09.09	Pattern total run time	Real	0.009999.00	min	100 = 1 min
09.10	Pattern stop time	Real	0.009999.00	min	100 = 1 min
09.11	Pattern completed time	Real	0.009999.00	min	100 = 1 min
09.12	Remaining pattern time	Real	0.009999.00	min	100 = 1 min
09.13	Pattern production Kg	Real	0.03000.0	Kg	10 = 1 Kg
09.14	Pattern production hank	Real	0.0030000.00	Hank	100 = 1 Hank
09.15	Pattern KWH	Real	0.03000.0	KWh	10 = 1 KWh
09.16	Pattern KWh/Kg	Real	0.03000.0	KWh/Kg	10 = 1 KWh/Kg
09.17	Current shift production Kg	Real	0.09000.0	Kg	10 = 1 Kg
09.18	Current shift production Hank	Real	0.0030000.00	Hank	100 = 1 Hank
09.19	Current shift run time	Real	0.03000.0	min	10 = 1 min
09.20	Current shift stop time	Real	0.03000.0	min	10 = 1 min
09.21	Current shift KWh consumption	Real	0.09000.0	KWh	10 = 1 KWh
09.22	Current shift KWh per Kg	Real	0.09000.0	KWh/Kg	10 = 1 KWh/Kg
09.23	Current shift GPS	Real	03000	g	1 = 1 g
09.24	Current shift pattern count	UINT	010000	-	1 = 1
09.35	Spinning speed	Real	099999	rpm	1 = 1 rpm

No.	Name	Туре	Range	Unit	FbEq32
09.36	Delivery length	Real	0.0999999.0	m	10 = 1 m
09.37	Remaining length	Real	0.0999999.0	m	10 = 1 m
09.38	Sliding average speed	Real	099999	rpm	1 = 1 rpm
09.39	Actual TPI	Real	0.0030000.00	TPI	100 = 1 TPI
09.40	Front roller speed	Real	099999	rpm	1 = 1 rpm
09.41	Spinning status word	UINT	0000hFFFFh	-	1 = 1
09.42	Spinning status word1	UINT	0000hFFFFh	-	1 = 1
09.43	Spinning reference	Real	099999	rpm	1 = 1 rpm
09.44	Current shift time	Real	0.00100.00	h	100 = 1 h
09.45	Current shift elapsed time	Real	0.00100.00	h	100 = 1 h

Parameter groups 10...99

No.	Name	Туре	Range	Unit	FbEq32
10 Stan	dard DI, RO			•	
10.01	DI status	PB	0000hFFFFh	-	1 = 1
10.02	DI delayed status	PB	0000hFFFFh	-	1 = 1
10.03	DI force selection	PB	0000hFFFFh	-	1 = 1
10.04	DI force data	PB	0000hFFFFh	-	1 = 1
10.05	DI1 ON delay	Real	0.0 3000.0	s	10 = 1 s
10.06	DI1 OFF delay	Real	0.0 3000.0	s	10 = 1 s
10.07	DI2 ON delay	Real	0.0 3000.0	s	10 = 1 s
10.08	DI2 OFF delay	Real	0.0 3000.0	S	10 = 1 s
10.09	DI3 ON delay	Real	0.0 3000.0	S	10 = 1 s
10.10	DI3 OFF delay	Real	0.0 3000.0	S	10 = 1 s
10.11	DI4 ON delay	Real	0.0 3000.0	S	10 = 1 s
10.12	DI4 OFF delay	Real	0.0 3000.0	S	10 = 1 s
10.13	DI5 ON delay	Real	0.0 3000.0	S	10 = 1 s
10.14	DI5 OFF delay	Real	0.0 3000.0	S	10 = 1 s
10.15	DI6 ON delay	Real	0.0 3000.0	S	10 = 1 s
10.16	DI6 OFF delay	Real	0.0 3000.0	S	10 = 1 s
10.21	RO status	PB	0000hFFFFh	-	1 = 1
10.24	RO1 source	Binary src	-	-	1 = 1
10.25	RO1 ON delay	Real	0.0 3000.0	S	10 = 1 s
10.26	RO1 OFF delay	Real	0.0 3000.0	S	10 = 1 s
10.27	RO2 source	Binary src	-	-	1 = 1
10.28	RO2 ON delay	Real	0.0 3000.0	S	10 = 1 s
10.29	RO2 OFF delay	Real	0.0 3000.0	S	10 = 1 s
10.30	RO3 source	Binary src	-	-	1 = 1
10.31	RO3 ON delay	Real	0.0 3000.0	S	10 = 1 s
10.32	RO3 OFF delay	Real	0.0 3000.0	S	10 = 1 s
10.51	DI filter time	Real	0.3 100.0	ms	10 = 1 ms
10.99	RO/DIO control word	PB	0000hFFFFh	-	1 = 1
11 Stan	dard DIO, FI, FO				
11.01	DIO status	PB	0000hFFFFh	-	1 = 1
11.02	DIO delayed status	PB	0000hFFFFh	-	1 = 1
11.05	DIO1 function	List	02	-	1 = 1
11.06	DIO1 output source	Binary src	-		1 = 1
11.07	DIO1 ON delay	Real	0.0 3000.0	s	10 = 1 s
11.08	DIO1 OFF delay	Real	0.0 3000.0	s	10 = 1 s
11.09	DIO2 function	List	02	-	1 = 1

No.	Name	Туре	Range	Unit	FbEq32
11.10	DIO2 output source	Binary	-		1 = 1
44.44		src	0.0.0000.0		10 1
11.11	DIO2 ON delay	Real	0.0 3000.0	S	10 = 1 s
11.12	DIO2 OFF delay	Real	0.0 3000.0	S	10 = 1 s
11.38	Freq in 1 actual value	Real	016000	Hz	1 = 1 Hz
11.39	Freq in 1 scaled	Real	-32768.000 32767.000	-	1000 = 1
11.42	Freq in 1 min	Real	016000	Hz	1 = 1 Hz
11.43	Freq in 1 max	Real	016000	Hz	1 = 1 Hz
11.44	Freq in 1 at scaled min	Real	-32768.000 32767.000	-	1000 = 1
11.45	Freq in 1 at scaled max	Real	-32768.000 32767.000	-	1000 = 1
11.54	Freq out 1 actual value	Real	016000	Hz	1 = 1 Hz
11.55	Freq out 1 source	Analog src	-	-	1 = 1
11.58	Freq out 1 src min	Real	-32768.000 32767.000	-	1000 = 1
11.59	Freq out 1 src max	Real	-32768.000 32767.000	-	1000 = 1
11.60	Freq out 1 at src min	Real	016000	Hz	1 = 1 Hz
11.61	Freq out 1 at src max	Real	016000	Hz	1 = 1 Hz
11.81	DIO filter time	Real	0.3 100.0	ms	10 = 1 ms
12 Stan	dard Al	•		<u> </u>	
12.01	AI tune	enum	04	-	
12.03	AI supervision function	List	04	-	1 = 1
12.04	AI supervision selection	PB	0000hFFFFh	-	1 = 1
12.05	AI supervision force	PB	0000hFFFFh	-	1 = 1
12.11	AI1 actual value	Real	-22.000 22.000	mA or V	1000 = 1 unit
12.12	AI1 scaled value	Real	-32768.000 32767.000	-	1000 = 1
12.15	AI1 unit selection	List	-	-	1 = 1
12.16	AI1 filter time	Real	0.000 30.000	S	1000 = 1 s
12.17	Al1 min	Real	-22.000 22.000	mA or V	1000 = 1 mA or V
12.18	Al1 max	Real	-22.000 22.000	mA or V	1000 = 1 mA or V
12.19	AI1 scaled at AI1 min	Real	-32768.000 32767.000	-	1000 = 1
12.20	AI1 scaled at AI1 max	Real	-32768.000 32767.000	-	1000 = 1
12.21	Al2 actual value	Real	-22.000 22.000	mA or V	1000 = 1 mA or V
12.22	AI2 scaled value	Real	-32768.000 32767.000	-	1000 = 1
12.25	AI2 unit selection	List	-	-	1 = 1
12.26	AI2 filter time	Real	0.000 30.000	S	1000 = 1 s
12.27	AI2 min	Real	-22.000 22.000	mA or V	1000 = 1 mA or V
12.28	Al2 max	Real	-22.000 22.000	mA or V	1000 = 1 mA or V
12.29	AI2 scaled at AI2 min	Real	-32768.000 32767.000	-	1000 = 1

13.12 AO1 source Analog src - 1 = 1 13.16 AO1 filter time Real 0.00030.000 s 1000 = 1 s 13.17 AO1 source min Real -32768.032767.0 - 10 = 1 13.18 AO1 source max Real -32768.032767.0 - 10 = 1 13.18 AO1 out at AO1 src min Real -32768.032767.0 - 10 = 1 13.19 AO1 out at AO1 src max Real 0.00022.000 mA 1000 = 1 mA 13.20 AO1 out at AO1 src max Real 0.00022.000 mA 1000 = 1 mA 13.21 AO2 actual value Real 0.00022.000 mA 1000 = 1 mA 13.22 AO2 source min Real -32768.032767.0 - 10 = 1 13.28 AO2 source max Real -327.68327.67 - 100 = 1 13.29 AO2 out at AO2 src max Real -327.68327.67 - 100 = 1 13.29 AO2 data storage Real -327.68	No.	Name	Туре	Range	Unit	FbEq32		
13.11 AO1 actual value Real 0.00022.000 mA 1000 = 1 mA 13.12 AO1 source Analog SrC - - 1 = 1 13.16 AO1 filter time Real 0.00030.000 s 1000 = 1 s 13.17 AO1 source max Real -32768.032767.0 - 10 = 1 13.18 AO1 source max Real 0.00022.000 mA 1000 = 1 mA 13.20 AO1 out at AO1 src max Real 0.00022.000 mA 1000 = 1 mA 13.21 AO2 actual value Real 0.00022.000 mA 1000 = 1 mA 13.22 AO2 source Analog SrC - 1 = 1 13.24 AO2 source min Real -32768.032767.0 - 10 = 1 13.28 AO2 source max Real -32768.032767.0 - 10 = 1 13.29 AO2 out at AO2 sor max Real -32768.032767.0 - 10 = 1 13.29 AO2 out at AO2 sor max Real -327.68327.67 - 100 = 1 13.20 AO2 data storage Real <t< td=""><td>12.30</td><td>AI2 scaled at AI2 max</td><td>Real</td><td>-32768.000 32767.000</td><td>-</td><td>1000 = 1</td></t<>	12.30	AI2 scaled at AI2 max	Real	-32768.000 32767.000	-	1000 = 1		
13.12 AO1 source Analog src - 1 = 1 13.16 AO1 filter time Real 0.00030.000 s 1000 = 1 s 13.17 AO1 source max Real -32768.032767.0 - 10 = 1 13.18 AO1 source max Real -32768.032767.0 - 10 = 1 13.19 AO1 out at AO1 src min Real 0.00022.000 mA 1000 = 1 mA 13.20 AO1 out at AO1 src max Real 0.00022.000 mA 1000 = 1 mA 13.21 AO2 actual value Real 0.00022.000 mA 1000 = 1 mA 13.22 AO2 source Analog src - - 1 = 1 13.24 AO2 source max Real -32768.032767.0 - 10 = 1 13.28 AO2 source max Real -327.68327.67 - 100 = 1 13.29 AO2 out at AO2 src min Real -327.68327.67 - 100 = 1 13.29 AO2 data storage Real -327.68	13 Stan	dard AO	I					
src src src 13.16 AO1 filter time $Real$ 0.00030.000 s 1000 = 1 s 13.17 AO1 source min $Real$ -32768.032767.0 - 10 = 1 13.18 AO1 source max $Real$ -32768.032767.0 - 10 = 1 13.19 AO1 out at AO1 src min $Real$ 0.00022.000 mA 1000 = 1 mA 13.20 AO1 out at AO1 src max $Real$ 0.00022.000 mA 1000 = 1 mA 13.21 AO2 actual value $Real$ 0.00022.000 mA 1000 = 1 mA 13.22 AO2 source $Anag$ Src - - 1 = 1 13.22 AO2 source max $Real$ -32768.032767.0 - 10 = 1 13.23 AO2 source max $Real$ -32768.032767.0 - 100 = 1 13.24 AO2 out at AO2 src max $Real$ -327.68327.67 - 100 = 1 13.29 AO2 data storage $Real$ -327.68327.67 -	13.11	AO1 actual value	Real	0.000 22.000	mA	1000 = 1 mA		
13.17 AO1 source min Real -32768.032767.0 - 10 = 1 13.18 AO1 source max Real -32768.032767.0 - 10 = 1 13.19 AO1 out at AO1 src min Real 0.00022.000 mA 1000 = 1 mA 13.20 AO1 out at AO1 src max Real 0.00022.000 mA 1000 = 1 mA 13.21 AO2 actual value Real 0.00022.000 mA 1000 = 1 mA 13.22 AO2 source Analog - - 1 = 1 13.24 AO2 source min Real 32768.032767.0 - 10 = 1 13.28 AO2 source max Real 0.00022.000 mA 1000 = 1 mA 13.29 AO2 out at AO2 src max Real 32768.0327.67. - 10 = 1 13.30 AO2 out at AO2 src max Real 327.68327.67 - 100 = 1 13.30 AO2 data storage Real 327.68327.67 - 100 = 1 13.30 AO2 data storage Real 04 - 1 = 1 14.00 Module 1 type	13.12	AO1 source	-	-	-	1 = 1		
13.16 AO1 source max Real -32766.0	13.16	AO1 filter time	Real	0.000 30.000	S	1000 = 1 s		
13.19 AO1 out at AO1 src min Real 0.00022.000 mA 1000 = 1 mA 13.20 AO1 out at AO1 src max Real 0.00022.000 mA 1000 = 1 mA 13.21 AO2 actual value Real 0.00022.000 mA 1000 = 1 mA 13.22 AO2 source Analog Src - - 1 = 1 13.22 AO2 source min Real 0.32768.032767.0 - 10 = 1 13.28 AO2 source max Real -32768.032767.0 - 10 = 1 13.29 AO2 out at AO2 src max Real 0.00022.000 mA 1000 = 1 mA 13.30 AO2 out at AO2 src max Real 0.00022.000 mA 1000 = 1 13.30 AO2 out at AO2 src max Real -327.68327.67 - 100 = 1 13.91 AO1 data storage Real 4 - 1 = 1 14.02 Module 1 toztion Real 1254 - 1 = 1 14.02 Module 1 toztion Real 0.00	13.17	AO1 source min	Real	-32768.0 32767.0	-	10 = 1		
13.20 AO1 out at AO1 src max Real $0.000 \dots 22.000$ mA $1000 = 1 \text{ mA}$ 13.21 AO2 actual value Real $0.000 \dots 22.000$ mA $1000 = 1 \text{ mA}$ 13.22 AO2 source Analog src - 1 = 1 13.26 AO2 source min Real $0.000 \dots 30.000$ s $1000 = 1 \text{ s}$ 13.27 AO2 source max Real $-32768.0 \dots 32767.0$ - $10 = 1$ 13.28 AO2 source max Real $-32768.0 \dots 32767.0$ - $100 = 1 \text{ mA}$ 13.29 AO2 out at AO2 src max Real $0.000 \dots 22.000$ mA $1000 = 1 \text{ mA}$ 13.91 AO1 data storage Real $-327.68 \dots 327.67$ - $100 = 1$ 13.92 AO2 data storage Real $-327.68 \dots 327.67$ - $100 = 1$ 14.02 Module 1 type List 04 - $1 = 1$ 14.02 Module 1 type List 04 - $1 = 1$ 14.04 Module 1 type List 04 - $1 = 1$ 14.03 Module 1 type	13.18	AO1 source max	Real	-32768.0 32767.0	-	10 = 1		
13.21 AO2 actual value Real $0.000 \dots 22.000$ mA $1000 = 1 \text{ mA}$ 13.22 AO2 source Analog src - - 1 = 1 13.26 AO2 filter time Real $0.000 \dots 30.000$ s $1000 = 1 \text{ s}$ 13.27 AO2 source min Real $-32768.0 \dots 32767.0$ - $10 = 1$ 13.28 AO2 source max Real $-32768.0 \dots 32767.0$ - $100 = 1 \text{ mA}$ 13.29 AO2 out at AO2 src max Real $0.000 \dots 22.000$ mA $1000 = 1 \text{ mA}$ 13.30 AO2 out at AO2 src max Real $-32768.\dots 327.67$ - $100 = 1$ 13.39 AO1 data storage Real $-327.68 \dots 327.67$ - $100 = 1$ 13.31 AO2 data storage Real $-327.68 \dots 327.67$ - $100 = 1$ 14/0 extension module 1 1 04 - $1 = 1$ 14.02 Module 1 type List 04 - $1 = 1$ 14.03 Module 1 status List 04 - $1 = 1$ 14.04 Di statu	13.19	AO1 out at AO1 src min	Real	0.000 22.000	mA	1000 = 1 mA		
13.22 AO2 source Analog src - 1 = 1 13.26 AO2 filter time Real 0.00030.000 s 1000 = 1 s 13.27 AO2 source min Real -32768.032767.0 - 10 = 1 13.28 AO2 source max Real -32768.032767.0 - 100 = 1 13.29 AO2 out at AO2 src min Real 0.00022.000 mA 1000 = 1 mA 13.91 AO1 data storage Real -32768327.67 - 100 = 1 13.92 AO2 data storage Real -327.68327.67 - 100 = 1 13.92 AO2 data storage Real -327.68327.67 - 100 = 1 14.00 Module 1 type List 04 - 1 = 1 14.02 Module 1 type List 04 - 1 = 1 14.03 Module 1 status List 04 - 1 = 1 14.04 Di status PB 00000000FFFFFFFh - 1 = 1 14.04 Di delayed status PB 000000000S 100 = 1 s	13.20	AO1 out at AO1 src max	Real	0.000 22.000	mA	1000 = 1 mA		
src src src 13.26 AO2 filter time Real 0.00030.000 s 1000 = 1 s. 13.27 AO2 source min Real -32768.032767.0 - 10 = 1 13.28 AO2 source max Real -32768.032767.0 - 10 = 1 13.29 AO2 out at AO2 src max Real 0.000 22.000 mA 1000 = 1 mA 13.30 AO2 out at AO2 src max Real 0.000 22.000 mA 1000 = 1 mA 13.91 AO1 data storage Real -327.68 327.67 - 100 = 1 13.92 AO2 data storage Real 1254 - 1 = 1 14.01 Module 1 type List 04 - 1 = 1 14.03 Module 1 status List 04 - 1 = 1 14.03 Module 1 status List 04 - 1 = 1 14.04 DI datayed status PB 00000000FFFFFFFFh - 1 = 1 14.05 DI datayed sta	13.21	AO2 actual value	Real	0.000 22.000	mA	1000 = 1 mA		
13.27 AO2 source min Real -32768.032767.0 - 10 = 1 13.28 AO2 source max Real -32768.032767.0 - 10 = 1 13.29 AO2 out at AO2 src min Real 0.00022.000 mA 1000 = 1 mA 13.30 AO2 out at AO2 src max Real 0.00022.000 mA 1000 = 1 mA 13.91 AO1 data storage Real -327.68327.67 - 100 = 1 13.92 AO2 data storage Real -327.68327.67 - 100 = 1 14.00 extension module 1 - 1 = 1 1 1.00 = 1 14.01 Module 1 type List 04 - 1 = 1 14.02 Module 1 location Real 1254 - 1 = 1 14.03 Module 1 status List 04 - 1 = 1 14.05 DI status PB 00000000hFFFFFFFFh - 1 = 1 14.06 DI delayed status PB 0000000hFFFFFFFFh - 1 = 1 14.08 DI filter time Real 0.00<3000.00	13.22	AO2 source	-	-	-	1 = 1		
13.28 AO2 source max Real -32768.032767.0 - 10 = 1 13.29 AO2 out at AO2 src min Real 0.00022.000 mA 1000 = 1 mA 13.30 AO2 out at AO2 src max Real 0.00022.000 mA 1000 = 1 mA 13.91 AO1 data storage Real -327.68327.67 - 100 = 1 13.92 AO2 data storage Real -327.68327.67 - 100 = 1 14.02 Module 1 type List 04 - 1 = 1 14.02 Module 1 location Real 1254 - 1 = 1 14.03 Module 1 location Real 0.0000000hFFFFFFFFh - 1 = 1 14.04 DI datayed status PB 00000000hFFFFFFFFh - 1 = 1 14.06 DI datayed status PB 00000000hFFFFFFFFh - 1 = 1 14.05 DI status PB 00000000hFFFFFFFFFh - 1 = 1 14.07 Mealay Real 0.003000.00 s 100 = 1 s 14.12 DI O N delay Real	13.26	AO2 filter time	Real	0.000 30.000	S	1000 = 1 s		
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13.92 AO2 data storage Real 327.68 327.67 - 100 = 1 14 I/O extension module 1 100 = 1 14.01 Module 1 type List 04 - 1 = 1 14.02 Module 1 location Real 1254 - 1 = 1 14.03 Module 1 status List 04 - 1 = 1 14.03 Module 1 status List 04 - 1 = 1 14.05 DI status PB 00000000hFFFFFFFFh - 1 = 1 14.05 DI status PB 0000000hFFFFFFFFh - 1 = 1 14.06 DI delayed status PB 0000000hFFFFFFFFh - 1 = 1 14.08 DI filter time Real 0.00 300.00 s 100 = 1 s 14.12 DI O N delay Real 0.00 3000.00 s 100 = 1 s 14.13 DI2 OFF delay Real 0.00	13.30	AO2 out at AO2 src max	Real	0.000 22.000	mA	1000 = 1 mA		
14 I/O extension module 1 14.01 Module 1 type List 04 - 1 = 1 14.02 Module 1 location Real 1254 - 1 = 1 14.03 Module 1 status List 04 - 1 = 1 14.03 Module 1 status List 04 - 1 = 1 14.05 DI status PB 00000000hFFFFFFFh - 1 = 1 14.06 DI delayed status PB 0000000hFFFFFFFFh - 1 = 1 14.08 DI filter time Real 0.8< 100.0	13.91	AO1 data storage	Real	-327.68 327.67	-	100 = 1		
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14.03 Module 1 status List 04 - 1 = 1 DIx (14.01 Module 1 type = FDIO-01) 14.05 DI status PB 0000000hFFFFFFFh - 1 = 1 14.06 DI delayed status PB 0000000hFFFFFFFFh - 1 = 1 14.06 DI delayed status PB 0000000hFFFFFFFFh - 1 = 1 14.08 DI filter time Real 0.8 100.0 ms 10 = 1 ms 14.12 DI 1 ON delay Real 0.00 3000.00 s 100 = 1 s 14.13 DI OFF delay Real 0.00 3000.00 s 100 = 1 s 14.13 DI 2 OFF delay Real 0.00 3000.00 s 100 = 1 s 14.14 DI2 OFF delay Real 0.00 3000.00 s 100 = 1 s 14.22 DI3 ON delay Real 0.00 3000.00 s 100 = 1 s 14.23 DI 3 OFF delay Real 0.00 3000.00 s 100 = 1 s Common parameters for DIOx (14.01 Module 1 type = FIO-01 or FIO-11) I = 1	14.01	Module 1 type	List	04	-	1 = 1		
Dix (14.01 Module 1 type = FDIO-01) 14.05 DI status PB 0000000hFFFFFFFh - 1 = 1 14.06 DI delayed status PB 0000000hFFFFFFFh - 1 = 1 14.06 DI filter time Real 0.8 100.0 ms 10 = 1 ms 14.08 DI filter time Real 0.00 3000.00 s 100 = 1 s 14.12 DI1 ON delay Real 0.00 3000.00 s 100 = 1 s 14.13 DI1 OFF delay Real 0.00 3000.00 s 100 = 1 s 14.17 DI2 ON delay Real 0.00 3000.00 s 100 = 1 s 14.17 DI2 OFF delay Real 0.00 3000.00 s 100 = 1 s 14.18 DI2 OFF delay Real 0.00 3000.00 s 100 = 1 s 14.23 DI3 OFF delay Real 0.00 3000.00 s 100 = 1 s 14.23 DIO status PB 00000000hFFFFFFFFh - 1 = 1 14.05 DI	14.02	Module 1 location	Real	1254	-	1 = 1		
14.05 DI status PB 0000000hFFFFFFFh - 1 = 1 14.06 DI delayed status PB 0000000hFFFFFFFh - 1 = 1 14.06 DI filter time Real 0.8 100.0 ms 10 = 1 ms 14.12 DI1 ON delay Real 0.00 3000.00 s 100 = 1 s 14.13 DI1 OFF delay Real 0.00 3000.00 s 100 = 1 s 14.13 DI2 ON delay Real 0.00 3000.00 s 100 = 1 s 14.14 DI2 ON delay Real 0.00 3000.00 s 100 = 1 s 14.14 DI2 OFF delay Real 0.00 3000.00 s 100 = 1 s 14.22 DI3 ON delay Real 0.00 3000.00 s 100 = 1 s 14.23 DI3 OFF delay Real 0.00 3000.00 s 100 = 1 s Common parameters for DIOx (14.01 Module 1 type = FIO-01 or FIO-11) 14.05 DIO status PB 00000000hFFFFFFFFh - 1 = 1 DIO1/DIO2 (14.01 Module 1 type = FIO-01 or FIO-11) DIO1/DIO2 (14.	14.03	Module 1 status	List	04	-	1 = 1		
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14.12DI1 ON delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.13DI1 OFF delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.14DI2 ON delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.18DI2 OFF delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.18DI2 OFF delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.22DI3 ON delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.23DI3 OFF delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ Common parameters for DIOx (14.01 Module 1 type = FIO-01 or FIO-11)14.05DIO statusPB $00000000hFFFFFFFFh$ $ 1 = 1$ I + 101 DIO1 delayed statusPB $0.00 \dots 0 \text{ or } FIO-01 \text{ or } FIO-11$ I + 100.0ms $100 = 1 \text{ ms}$ I + 101 DIO1 function14.09DIO1 functionList 01 $ 1 = 1$	14.06	DI delayed status	PB	00000000hFFFFFFFh	-	1 = 1		
14.13DI1 OFF delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.17DI2 ON delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.18DI2 OFF delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.22DI3 ON delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.23DI3 OFF delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.23DI3 OFF delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ Common parameters for DIOx (14.01 Module 1 type = FIO-01 or FIO-11)14.05DIO statusPB $0000000h \dots FFFFFFFh$ $ 1 = 1$ 14.06DIO delayed statusPB $0000000h \dots FFFFFFFFh$ $ 1 = 1$ DIO1/DIO2 (14.01 Module 1 type = FIO-01 or FIO-11)14.08DIO filter timeReal $0.8 \dots 100.0$ ms $100 = 1 \text{ ms}$ 14.09DIO1 functionList $0 \dots 1$ $ 1 = 1$ 14.11DIO1 output sourceBinary $ 1 = 1$	14.08	DI filter time	Real	0.8 100.0	ms	10 = 1 ms		
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14.18 DI2 OFF delay Real 0.00 3000.00 s 100 = 1 s 14.22 DI3 ON delay Real 0.00 3000.00 s 100 = 1 s 14.23 DI3 OFF delay Real 0.00 3000.00 s 100 = 1 s 14.23 DI3 OFF delay Real 0.00 3000.00 s 100 = 1 s 14.23 DI3 OFF delay Real 0.00 3000.00 s 100 = 1 s 14.03 DIO status PB 00000000hFFFFFFFFh - 1 = 1 14.06 DIO delayed status PB 0000000hFFFFFFFFh - 1 = 1 14.06 DIO filter time Real 0.8 100.0 ms 10 = 1 ms 14.08 DIO filter time Real 0.8 100.0 ms 10 = 1 ms 14.09 DIO1 function List 01 - 1 = 1	14.13	DI1 OFF delay	Real	0.00 3000.00	S	100 = 1 s		
14.22 DI3 ON delay Real 0.00 3000.00 s 100 = 1 s 14.23 DI3 OFF delay Real 0.00 3000.00 s 100 = 1 s 14.23 DI3 OFF delay Real 0.00 3000.00 s 100 = 1 s Common parameters for DIOx (14.01 Module 1 type = FIO-01 or FIO-11) 14.05 DIO status PB 0000000hFFFFFFFh - 1 = 1 14.06 DIO delayed status PB 0000000hFFFFFFFh - 1 = 1 14.06 DIO delayed status PB 0000000hFFFFFFFh - 1 = 1 III DIO1/DIO2 (14.01 Module 1 type = FIO-01 or FIO-11) III DIO1/DIO2 (14.01 Module 1 type = FIO-01 or FIO-11) 14.08 DIO filter time Real 0.8 100.0 ms 10 = 1 ms 14.09 DIO1 function List 01 - 1 = 1 14.11 DIO1 output source Binary - - 1 = 1	14.17	DI2 ON delay	Real	0.00 3000.00	S	100 = 1 s		
14.23 DI3 OFF delay Real 0.00 3000.00 s 100 = 1 s Common parameters for DIOx (14.01 Module 1 type = FIO-01 or FIO-11) 14.05 DIO status PB 0000000hFFFFFFFh - 1 = 1 14.06 DIO delayed status PB 0000000hFFFFFFFh - 1 = 1 14.06 DIO delayed status PB 0000000hFFFFFFFh - 1 = 1 DIO1/DIO2 (14.01 Module 1 type = FIO-01 or FIO-11) 14.08 DIO filter time Real 0.8 100.0 ms 10 = 1 ms 14.09 DIO1 function List 01 - 1 = 1 14.11 DIO1 output source Binary - - 1 = 1	14.18	DI2 OFF delay	Real	0.00 3000.00	S	100 = 1 s		
Common parameters for DIOx (14.01 Module 1 type = FIO-01 or FIO-11) 14.05 DIO status PB 0000000hFFFFFFFh - 1 = 1 14.06 DIO delayed status PB 0000000hFFFFFFFh - 1 = 1 14.06 DIO delayed status PB 0000000hFFFFFFFh - 1 = 1 DIO1/DIO2 (14.01 Module 1 type = FIO-01 or FIO-11) 14.08 DIO filter time Real 0.8 100.0 ms 10 = 1 ms 14.09 DIO1 function List 01 - 1 = 1 14.11 DIO1 output source Binary - - 1 = 1	14.22	DI3 ON delay	Real	0.00 3000.00	S	100 = 1 s		
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14.09 DIO1 function List 01 - 1 = 1 14.11 DIO1 output source Binary - 1 = 1		DIO1/DIO2 (14.0 <mark>1 Modu</mark>	<i>ile 1 type = FIO-01</i> or <i>FIO-11</i>)				
14.11 DIO1 output source Binary - 1 = 1	14.08	DIO filter time	Real	0.8 100.0	ms	10 = 1 ms		
	14.09	DIO1 function	List	01	-	1 = 1		
SIC	14.11	DIO1 output source	Binary src	-	-	1 = 1		

14.12 DIO1 ON delay Real $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.13 DIO2 function List 01 - $1 = 1$ 14.14 DIO2 function List 01 - $1 = 1$ 14.16 DIO2 output source Binary src - $1 = 1$ 14.17 DIO2 ON delay Real $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.18 DIO2 OFF delay Real $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.18 DIO3 function List 01 - $1 = 1$ 14.21 DIO3 output source Binary src - . $100 = 1 \text{ s}$ 14.22 DIO3 ON delay Real $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.22 DIO3 OFF delay Real $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.24 DIO4 ON delay Real $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.25 DIO4 ON delay Real $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.26 DIO4 ON delay Real <t< th=""><th>No.</th><th>Name</th><th>Туре</th><th>Range</th><th>Unit</th><th>FbEq32</th></t<>	No.	Name	Туре	Range	Unit	FbEq32		
14.14 DIO2 function List 01 - 1 = 1 14.16 DIO2 output source Binary Src - 1 = 1 14.17 DIO2 OUtput source Binary Src - 1 = 1 14.18 DIO2 OFF delay Real 0.00 3000.00 s 100 = 1 s 14.18 DIO3 OVEF delay Real 0.00 3000.00 s 100 = 1 s 14.19 DIO3 output source Binary Src - - 1 = 1 14.21 DIO3 output source Binary Src - - 1 = 1 14.22 DIO3 ONF delay Real 0.00 3000.00 s 100 = 1 s 14.22 DIO4 output source Binary Src - - 1 = 1 14.24 DIO4 output source Binary Src - - 1 = 1 14.25 DIO4 ON delay Real 0.00 3000.00 s 100 = 1 s 14.26 DIO4 ON delay Real 0.00 3000.00 s 100 = 1 s 14.26 DIO4 ON delay Real 0.00 3000.00 s 100 = 1 s <tr< td=""><td>14.12</td><td>DIO1 ON delay</td><td>Real</td><td>0.00 3000.00</td><td>S</td><td>100 = 1 s</td></tr<>	14.12	DIO1 ON delay	Real	0.00 3000.00	S	100 = 1 s		
14.16 DIO2 output source Binary src - 1	14.13	DIO1 OFF delay	Real	0.00 3000.00	S	100 = 1 s		
Interview src src 14.17 DIO2 ON delay Real 0.00 3000.00 s 100 = 1 s 14.18 DIO2 OFF delay Real 0.00 3000.00 s 100 = 1 s DIO3/DIO4 (14.01 Module 1 type = FIO-01) 14.19 DIO3 output source Binary src - 1 = 1 14.21 DIO3 ON delay Real 0.00 3000.00 s 100 = 1 s 14.22 DIO3 ON delay Real 0.00 3000.00 s 100 = 1 s 14.22 DIO3 ON delay Real 0.00 3000.00 s 100 = 1 s 14.24 DIO4 ontput source Binary src - - 1 = 1 14.24 DIO4 ON delay Real 0.00 3000.00 s 100 = 1 s 14.25 DIO4 ON delay Real 0.00 3000.00 s 100 = 1 s 14.26 DIO4 ON delay Real 0.00 3000.00 s 100 = 1 s 14.37 RO status PB 00000hFFFFh - 1 = 1	14.14	DIO2 function	List	01	-	1 = 1		
14.18 DIO2 OFF delay Real 0.00 3000.00 s 100 = 1 s DIO3/DIO4 (14.01 Module 1 type = FIO-01) 14.19 DIO3 function List 01 - 1 = 1 14.21 DIO3 output source Binary src - . 1 = 1 14.22 DIO3 ON delay Real 0.00 3000.00 s 100 = 1 s 14.22 DIO3 ON delay Real 0.00 3000.00 s 100 = 1 s 14.23 DIO4 function List 01 - 1 = 1 14.24 DIO4 output source Binary src - . 1 = 1 14.27 DIO4 ON delay Real 0.00 3000.00 s 100 = 1 s 14.28 DIO4 OFF delay Real 0.00 3000.00 s 100 = 1 s 14.38 RO 1 source Binary src - . 1 = 1 14.35 RO1 ON delay Real 0.00 3000.00 s 100 = 1 s 14.35 RO1 ON delay Real <td< td=""><td>14.16</td><td>DIO2 output source</td><td>-</td><td>-</td><td>-</td><td>1 = 1</td></td<>	14.16	DIO2 output source	-	-	-	1 = 1		
DIO3/DIO4 (14.01 Module 1 type = FIO-01) 14.19 DIO3 function List 01 - 1 = 1 14.21 DIO3 output source Binary src - 1 = 1 14.22 DIO3 ON delay Real 0.00 3000.00 \$ 100 = 1 s 14.22 DIO3 OFF delay Real 0.00 3000.00 \$ 100 = 1 s 14.24 DIO4 function List 01 - 1 = 1 14.26 DIO4 output source Binary src - - 1 = 1 14.27 DIO4 ON delay Real 0.00 3000.00 \$ 100 = 1 s 14.28 DIO4 OFF delay Real 0.00 3000.00 \$ 100 = 1 s 14.38 RO tatus PB 0000hFFFFh - 1 = 1 14.34 RO1 Source Binary src - - 1 = 1 14.35 RO1 ON delay Real 0.00 3000.00 \$ 100 = 1 s 14.35 RO1 ON delay Real 0.00 3000.00 <td< td=""><td>14.17</td><td>DIO2 ON delay</td><td>Real</td><td>0.00 3000.00</td><td>S</td><td>100 = 1 s</td></td<>	14.17	DIO2 ON delay	Real	0.00 3000.00	S	100 = 1 s		
14.19 DIO3 function List 01 - 1 = 1 14.21 DIO3 output source Binary src - - 1 = 1 14.22 DIO3 ON delay Real 0.00 3000.00 s 100 = 1 s 14.23 DIO3 OFF delay Real 0.00 3000.00 s 100 = 1 s 14.24 DIO4 function List 01 - 1 = 1 14.26 DIO4 output source Binary src - - 1 = 1 14.25 DIO4 ON delay Real 0.00 3000.00 s 100 = 1 s 14.27 DIO4 ON delay Real 0.00 3000.00 s 100 = 1 s 14.25 DIO4 OFF delay Real 0.00 3000.00 s 100 = 1 s 14.38 RO status PB 0000hFFFFh - 1 = 1 14.34 RO1 Source Binary src - 1 = 1 14.36 RO1 OF delay Real 0.00 3000.00 s 100 = 1 s 14.36 RO1 OFF delay Real 0.00 3000.00 s 100 = 1 s <	14.18	DIO2 OFF delay	Real	0.00 3000.00	S	100 = 1 s		
14.21 DIO3 output source Binary src - 1		DIO3/DI	104 (<mark>14.01</mark>)	Module 1 type = FIO-01)				
Image: Streen	14.19	DIO3 function	List	01	-	1 = 1		
14.23 DIO3 OFF delay Real 0.00 3000.00 s 100 = 1 s 14.24 DIO4 function List 01 - 1 = 1 14.26 DIO4 output source Binary src - - 1 = 1 14.27 DIO4 ON delay Real 0.00 3000.00 s 100 = 1 s 14.28 DIO4 OFF delay Real 0.00 3000.00 s 100 = 1 s R01/RO2 (14.01 Module 1 type = FIO-01 or FDIO-01) 14.38 R01/RO2 (14.01 Module 1 type = FIO-01 or FDIO-01) 14.31 RO status PB 0000hFFFFh - 1 = 1 14.34 RO1 source Binary src - - 1 = 1 14.35 RO1 OFE delay Real 0.00 3000.00 s 100 = 1 s 14.35 RO2 overce Binary src - - 1 = 1 14.38 RO2 overce Binary src - - 1 = 1 14.39 RO2 overce Binary src - - 1 = 1 14.39 RO2 overce<	14.21	DIO3 output source	-	-	-	1 = 1		
14.24 DIO4 function List 01 - 1 = 1 14.26 DIO4 output source Binary src - 1 = 1 14.27 DIO4 ON delay Real 0.00 3000.00 s 100 = 1 s 14.28 DIO4 OFF delay Real 0.00 3000.00 s 100 = 1 s RO1/RO2 (14.01 Module 1 type = FIO-01 or FDIO-01 THE RO1/RO2 (14.01 Module 1 type = FIO-01 or FDIO-01 14.31 RO status PB 0000hFFFFh - 1 = 1 14.34 RO1 source Binary src - - 1 = 1 14.35 RO1 ON delay Real 0.00 3000.00 s 100 = 1 s 14.35 RO1 ON delay Real 0.00 3000.00 s 100 = 1 s 14.36 RO2 ON delay Real 0.00 3000.00 s 100 = 1 s 14.37 RO2 ON delay Real 0.00 3000.00 s 100 = 1 s 14.37 RO2 ON delay Real 0.00 3000.00 s 100 = 1 s 14.38 RO2 ON delay Real 0.00	14.22	DIO3 ON delay	Real	0.00 3000.00	S	100 = 1 s		
14.26 DIO4 output source Binary src - 1	14.23	DIO3 OFF delay	Real	0.00 3000.00	S	100 = 1 s		
srcsrc14.27DIO4 ON delayReal $0.00 \dots 300.00$ s $100 = 1 \text{ s}$ 14.28DIO4 OFF delayReal $0.00 \dots 300.00$ s $100 = 1 \text{ s}$ RO1/RO2 (14.01 Module 1 type = FIO-01 or FDIO-01)14.31RO statusPB $0000h \dots FFFFh$ $ 1 = 1$ 14.34RO1 sourceBinary src $ 1 = 1$ 14.35RO1 ON delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.36RO1 OFF delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.37RO2 sourceBinary src $ 1 = 1$ 14.38RO2 ON delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.39RO2 ON delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.39RO2 ON delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.39RO2 OFF delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ Common parameters for Alx (14.01 Module 1 type = FIO-11 or FAIO-01)14.19Al supervision functionList $0 \dots 6 (FIO-11)$ $0 \dots 4 (FAIO-01)$ $ 1 = 1$ 14.20Al supervision selectionPB $0000h \dots FFFFh$ $ 1 = 1$ 14.21Al force selectionPB $0000h \dots FFFFh$ $ 1 = 1$ 14.22Al force dataReal $-32768.000 \dots 32767.000$ $ 1000 = 1 \text{ unit}$ 14.23Al1 force dataReal -32768.00	14.24	DIO4 function	List	01	-	1 = 1		
14.28 DIO4 OFF delay Real $0.003000.00$ s $100 = 1 \text{ s}$ R01/R02 (14.01 Module 1 type = FIO-01 or FDIO-01) 14.31 RO status PB $0000hFFFFh$ $ 1 = 1$ 14.34 RO1 source Binary src $ 1 = 1$ 14.35 RO1 N delay Real $0.003000.00$ s $100 = 1 \text{ s}$ 14.35 RO1 OFF delay Real $0.003000.00$ s $100 = 1 \text{ s}$ 14.36 RO1 OFF delay Real $0.003000.00$ s $100 = 1 \text{ s}$ 14.37 RO2 source Binary src $ 1 = 1$ 14.38 RO2 ON delay Real $0.003000.00$ s $100 = 1 \text{ s}$ 14.39 RO2 OFF delay Real $0.003000.00$ s $100 = 1 \text{ s}$ Common parameters for Alx (14.01 Module 1 type = FIO-11 or FAIO-01) 14.19 Al supervision function List $06 (FIO-11)$ $ 1 = 1$ 14.20 Al force selection PB $0000hFFFFh$ $ 1 = 1$	14.26	DIO4 output source	-	-	-	1 = 1		
R01/R02 (14.01 Module 1 type = FIO-01 or FDIO-01) 14.31 RO status PB 0000hFFFFh - 1 = 1 14.34 RO1 source Binary src - 1 - 1 1 14.34 RO1 source Binary src - 1 - 1 1 14.35 RO1 ON delay Real 0.00 3000.00 \$ 100 = 1 \$ 14.36 RO1 OFF delay Real 0.00 3000.00 \$ 100 = 1 \$ 14.37 RO2 source Binary src - - 1 1 14.38 RO2 ON delay Real 0.00 3000.00 \$ 100 = 1 \$ 14.39 RO2 OFF delay Real 0.00 3000.00 \$ 100 = 1 \$ Common parameters for Alx (14.01 Module 1 type = FIO-11 or FAIO-01) 14.19 Al supervision function List 06 (FIO-11) - 1 = 1 14.20 Al supervision selection PB 0000hFFFFh - 1 = 1 14.21 Al tune </td <td>14.27</td> <td>DIO4 ON delay</td> <td>Real</td> <td>0.00 3000.00</td> <td>S</td> <td>100 = 1 s</td>	14.27	DIO4 ON delay	Real	0.00 3000.00	S	100 = 1 s		
14.31RO statusPB0000hFFFFh-1 = 114.34RO1 sourceBinary src-1114.35RO1 ON delayReal0.00 3000.00s100 = 1 s14.36RO1 OFF delayReal0.00 3000.00s100 = 1 s14.37RO2 sourceBinary src1 = 114.38RO2 ON delayReal0.00 3000.00s100 = 1 s14.38RO2 ON delayReal0.00 3000.00s100 = 1 s14.39RO2 OFF delayReal0.00 3000.00s100 = 1 s14.39RO2 OFF delayReal0.00 3000.00s100 = 1 sCommon parameters for Alx (14.01 Module 1 type = FIO-11 or FAIO-01)14.19Al supervision functionList04-1 = 114.20Al supervision selectionPB0000hFFFFh-1 = 114.21Al tuneList06 (FIO-11) 04 (FAIO-01)-1 = 114.22Al force selectionPB0000hFFFFh-1 = 1Al1/Al2 (14.01 Module 1 type = FIO-11 or FAIO-01)14.26Al1 actual valueReal-22.000 22.000mA or V1000 = 1 unit14.27Al1 scaled valueReal-22.000 22.000mA or V1000 = 1 unit14.28Al1 force dataReal-22.000 22.000mA or V1000 = 1 unit14.29Al1 HW switch positionList <td< td=""><td>14.28</td><td>DIO4 OFF delay</td><td>Real</td><td>0.00 3000.00</td><td>S</td><td>100 = 1 s</td></td<>	14.28	DIO4 OFF delay	Real	0.00 3000.00	S	100 = 1 s		
14.34RO1 sourceBinary src-1 = 114.35RO1 ON delayReal $0.00 \dots 3000.00$ s $100 = 1$ s14.36RO1 OFF delayReal $0.00 \dots 3000.00$ s $100 = 1$ s14.37RO2 sourceBinary src $1 = 1$ 14.38RO2 ON delayReal $0.00 \dots 3000.00$ s $100 = 1$ s14.39RO2 OFF delayReal $0.00 \dots 3000.00$ s $100 = 1$ s14.39RO2 OFF delayReal $0.00 \dots 3000.00$ s $100 = 1$ sCommon parameters for Alx (14.01 Module 1 type = FIO-11 or FAIO-01)14.19Al supervision functionList 04 - $1 = 1$ 14.20Al supervision selectionPB $0000hFFFFh$ - $1 = 1$ 14.21Al tuneList 06 (FIO-11) 04 (FAIO-01)- $1 = 1$ 14.22Al force selectionPB $0000hFFFFh$ - $1 = 1$ Al1/Al2 (14.01 Module 1 type = FIO-11 or FAIO-01)14.22Al force selectionPB $0000hFFFFh$ - $1 = 1$ Al1/Al2 (14.01 Module 1 type = FIO-11 or FAIO-01)14.24Al1 actual valueReal $-22.000 \dots 22.000$ mA or V $1000 = 1$ unit14.25Al1 force dataReal $-22.000 \dots 22.000$ mA or V $1000 = 1$ unit14.29Al1 HW switch positionList $1 = 1$ 14.30Al1 unit selectionList $1 = 1$ <td colspan="8">RO1/RO2 (14.01 Module 1 type = FIO-01 or FDIO-01)</td>	RO1/RO2 (14.01 Module 1 type = FIO-01 or FDIO-01)							
srcsrc14.35RO1 ON delayReal $0.00300.00$ s $100 = 1 \text{ s}$ 14.36RO1 OFF delayReal $0.00300.00$ s $100 = 1 \text{ s}$ 14.37RO2 sourceBinary src $1 = 1$ 14.38RO2 ON delayReal $0.00300.00$ s $100 = 1 \text{ s}$ 14.39RO2 OFF delayReal $0.00300.00$ s $100 = 1 \text{ s}$ 14.39RO2 OFF delayReal $0.00300.00$ s $100 = 1 \text{ s}$ Common parameters for Alx (14.01 Module 1 type = FIO-11 or FAIO-01)14.19Al supervision functionList 04 - $1 = 1$ 14.20Al supervision selectionPB $0000hFFFFh$ - $1 = 1$ 14.21Al tuneList $06 (FIO-11)$ $04 (FAIO-01)$ - $1 = 1$ 14.22Al force selectionPB $0000hFFFFh$ - $1 = 1$ All/Al2 (14.01 Module 1 type = FIO-11 or FAIO-01)14.22Al force selectionPB $0000hFFFFh$ - $1 = 1$ All/Al2 (14.01 Module 1 type = FIO-11 or FAIO-01)14.24Al1 actual valueReal-22.000 22.000mA or V $1000 = 1 \text{ unit}$ 14.25Al1 actual valueReal-22.000 22.000mA or V $1000 = 1 \text{ unit}$ 14.29Al1 HW switch positionList $1 = 1$ 14.30Al1 unit selectionList $1 = 1$ 14.31 <td< td=""><td>14.31</td><td>RO status</td><td>PB</td><td>0000hFFFFh</td><td>-</td><td>1 = 1</td></td<>	14.31	RO status	PB	0000hFFFFh	-	1 = 1		
14.36RO1 OFF delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.37RO2 sourceBinary src-1114.38RO2 ON delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.39RO2 OFF delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ Common parameters for Alx (14.01 Module 1 type = FIO-11 or FAIO-01)14.19Al supervision functionList 04 - $1 = 1$ 14.20Al supervision selectionPB $0000hFFFFh$ - $1 = 1$ 14.21Al tuneList 06 (FIO-11) 04 (FAIO-01)- $1 = 1$ 14.22Al force selectionPB $0000hFFFFh$ - $1 = 1$ All/Al2 (14.01 Module 1 type = FIO-11 or FAIO-01)14.22Al force selectionPB $0000hFFFFh$ - $1 = 1$ All/Al2 (14.01 Module 1 type = FIO-11 or FAIO-01)14.22Al force selectionPB $0000hFFFFh$ - $1 = 1$ All/Al2 (14.01 Module 1 type = FIO-11 or FAIO-01)14.26Al1 actual valueReal-22.000 22.000mA or V $1000 = 1 unit$ 14.23Al1 actual valueReal-22.000 22.000mA or V $1000 = 1 unit$ 14.24Al1 force dataReal-22.000 22.000mA or V $1000 = 1 unit$ 14.29Al1 HW switch positionList $1 = 1$ 14.30Al1 unit selectionList <td>14.34</td> <td>RO1 source</td> <td>-</td> <td>-</td> <td>-</td> <td>1 = 1</td>	14.34	RO1 source	-	-	-	1 = 1		
14.37RO2 sourceBinary src-1 = 114.38RO2 ON delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ 14.39RO2 OFF delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ Common parameters for Alx (14.01 Module 1 type = FIO-11 or FAIO-01)14.19Al supervision functionList 04 - $1 = 1$ 14.20Al supervision selectionPB $0000hFFFFh$ - $1 = 1$ 14.21Al tuneList 06 (FIO-11) 04 (FAIO-01)- $1 = 1$ 14.22Al force selectionPB $0000hFFFFh$ - $1 = 1$ 14.23Al force selectionPB $0000hFFFFh$ - $1 = 1$ All/Al2 (14.01 Module 1 type = FIO-11 or FAIO-01)14.24Al force selectionPB $0000hFFFFh$ - $1 = 1$ All/Al2 (14.01 Module 1 type = FIO-11 or FAIO-01)14.25Al1 actual valueReal-22.000 22.000mA or V $1000 = 1$ unit14.25Al1 actual valueReal-22.000 22.000mA or V $1000 = 1$ unit14.26Al1 scaled valueReal-22.000 22.000mA or V $1000 = 1$ unit14.29Al1 HW switch positionList $1 = 1$ 14.30Al1 unit selectionList $1 = 1$ 14.31Al1 filter gainList07- $1 = 1$	14.35	RO1 ON delay	Real	0.00 3000.00	S	100 = 1 s		
srcsrcImage: src14.38RO2 ON delayReal $0.00 \dots 3000.00$ s $100 = 1$ s14.39RO2 OFF delayReal $0.00 \dots 3000.00$ s $100 = 1$ sCommon parameters for Alx (14.01 Module 1 type = FIO-11 or FAIO-01)14.19Al supervision functionList 04 - $1 = 1$ 14.20Al supervision selectionPB $0000hFFFFh$ - $1 = 1$ 14.21Al tuneList 06 (FIO-11)- $1 = 1$ 14.22Al force selectionPB $0000hFFFFh$ - $1 = 1$ All/Al2 (14.01 Module 1 type = FIO-11 or FAIO-01)14.22Al force selectionPB $0000hFFFFh$ - $1 = 1$ All/Al2 (14.01 Module 1 type = FIO-11 or FAIO-01)14.26Al1 actual valueReal $-22.00022.000$ mA or V $1000 = 1$ unit14.26Al1 actual valueReal $-32768.00032767.000$ - $1000 = 1$ unit14.28Al1 force dataReal $-22.00022.000$ mA or V $1000 = 1$ unit14.29Al1 HW switch positionList $1 = 1$ 14.30Al1 unit selectionList $1 = 1$ 14.31Al1 filter gainList07- $1 = 1$	14.36	RO1 OFF delay	Real	0.00 3000.00	S	100 = 1 s		
14.39RO2 OFF delayReal $0.00 \dots 3000.00$ s $100 = 1 \text{ s}$ Common parameters for Alx (14.01 Module 1 type = FIO-11 or FAIO-01)14.19Al supervision functionList 04 - $1 = 1$ 14.20Al supervision selectionPB $0000hFFFFh$ - $1 = 1$ 14.21Al tuneList $06 (FIO-11)$ $04 (FAIO-01)$ - $1 = 1$ 14.22Al force selectionPB $0000hFFFFh$ - $1 = 1$ All/Al2 (14.01 Module 1 type = FIO-11 or FAIO-01)14.22Al force selectionPB $0000hFFFFh$ - $1 = 1$ All/Al2 (14.01 Module 1 type = FIO-11 or FAIO-01)14.22Al force selectionReal-22.000 22.000mA or V $1000 = 1$ unit14.27Al1 scaled valueReal-32768.000 32767.000- $1000 = 1$ 14.28Al1 force dataReal-22.000 22.000mA or V $1000 = 1$ unit14.29Al1 HW switch positionList $1 = 1$ 14.30Al1 unit selectionList $1 = 1$ 14.31Al1 filter gainList 07 - $1 = 1$	14.37	RO2 source	-	-	-	1 = 1		
Common parameters for Alx (14.01 Module 1 type = FIO-11 or FAIO-01) 14.19 Al supervision function List 04 - 1 = 1 14.20 Al supervision selection PB 0000hFFFFh - 1 = 1 14.21 Al tune List 06 (FIO-11) - 1 = 1 14.21 Al tore PB 0000hFFFFh - 1 = 1 14.22 Al force selection PB 0000hFFFFh - 1 = 1 14.22 Al force selection PB 0000hFFFFh - 1 = 1 14.22 Al force data Real -22.000 2000 MA or V 1000 = 1 unit 14.26 Al1 actual value Real -32768.000 2767.000 - 1000 = 1 14.27 Al1 scaled value Real -22.000 22.000 mA or V 1000 = 1 unit 14.28 Al1 force data Real -22.000 22.000 mA or V 1000 = 1 unit 14.29 Al1 HW switch position List <t< td=""><td>14.38</td><td>RO2 ON delay</td><td>Real</td><td>0.00 3000.00</td><td>S</td><td>100 = 1 s</td></t<>	14.38	RO2 ON delay	Real	0.00 3000.00	S	100 = 1 s		
14.19Al supervision functionList 04 $ 1 = 1$ 14.20Al supervision selectionPB $0000hFFFFh$ $ 1 = 1$ 14.21Al tuneList 06 (FIO-11) 04 (FAIO-01) $ 1 = 1$ 14.22Al force selectionPB $0000hFFFFh$ $ 1 = 1$ All/Al2 (14.01 Module 1 type = FIO-11 or FAIO-01)14.26Al1 actual valueReal $-22.00022.000$ mA or V $1000 = 1$ unit14.27Al1 scaled valueReal $-32768.00032767.000$ $ 1000 = 1$ 14.28Al1 force dataReal $-22.00022.000$ mA or V $1000 = 1$ unit14.29Al1 HW switch positionList $ 1 = 1$ 14.30Al1 unit selectionList $ 1 = 1$ 14.31Al1 filter gainList 07 $ 1 = 1$	14.39	RO2 OFF delay	Real	0.00 3000.00	S	100 = 1 s		
14.20AI supervision selectionPB0000hFFFFh-1 = 114.21AI tuneList $06 (FIO-11)$ $04 (FAIO-01)$ -1 = 114.22AI force selectionPB $0000hFFFFh$ -1 = 1AI1/AI2 (14.01 Module 1 type = FIO-11 or FAIO-01)14.26AI1 actual valueReal-22.000 22.000mA or V1000 = 1 unit14.27AI1 scaled valueReal-32768.000 32767.000-1000 = 1 unit14.28AI1 force dataReal-22.000 22.000mA or V1000 = 1 unit14.29AI1 HW switch positionList1 = 114.30AI1 unit selectionList1 = 114.31AI1 filter gainList07-1 = 1		Common parameters	for Alx (<mark>14.</mark>	01 Module 1 type = FIO-11 or	FAIO-01)			
14.21Al tuneList $06 (FlO-11)$ $04 (FAIO-01)$ - $1 = 1$ 14.22Al force selectionPB $0000hFFFh$ - $1 = 1$ Al1/Al2 (14.01 Module 1 type = FlO-11 or FAIO-01)14.26Al1 actual valueReal-22.000 22.000mA or V $1000 = 1$ unit14.27Al1 scaled valueReal-32768.000 32767.000- $1000 = 1$ 14.28Al1 force dataReal-22.000 22.000mA or V $1000 = 1$ unit14.29Al1 HW switch positionList $1 = 1$ 14.30Al1 unit selectionList $1 = 1$ 14.31Al1 filter gainList 07 - $1 = 1$	14.19	AI supervision function	List	04	-	1 = 1		
Image: Market	14.20	AI supervision selection	PB	0000hFFFFh	-	1 = 1		
All/Al2 (14.01 Module 1 type = FIO-11 or FAIO-01) 14.26 Al1 actual value Real -22.000 22.000 mA or V 1000 = 1 unit 14.27 Al1 scaled value Real -32768.000 32767.000 - 1000 = 1 14.28 Al1 force data Real -22.000 22.000 mA or V 1000 = 1 14.28 Al1 force data Real -22.000 22.000 mA or V 1000 = 1 unit 14.29 Al1 HW switch position List - - 1 = 1 14.30 Al1 unit selection List - - 1 = 1 14.31 Al1 filter gain List 07 - 1 = 1	14.21	Al tune	List		-	1 = 1		
14.26 Al1 actual value Real -22.000 22.000 mA or V 1000 = 1 unit 14.27 Al1 scaled value Real -32768.000 32767.000 - 1000 = 1 14.28 Al1 force data Real -22.000 22.000 mA or V 1000 = 1 unit 14.29 Al1 force data Real -22.000 22.000 mA or V 1000 = 1 unit 14.29 Al1 HW switch position List - - 1 = 1 14.30 Al1 unit selection List - - 1 = 1 14.31 Al1 filter gain List 07 - 1 = 1	14.22	Al force selection	PB	0000hFFFFh	-	1 = 1		
14.27 Al1 scaled value Real -32768.000 32767.000 - 1000 = 1 14.28 Al1 force data Real -22.000 22.000 mA or V 1000 = 1 unit 14.29 Al1 HW switch position List - - 1 = 1 14.30 Al1 unit selection List - - 1 = 1 14.31 Al1 filter gain List 07 - 1 = 1	AI1/AI2 (14.01 Module 1 type = FIO-11 or FAIO-01)							
14.28 Al1 force data <i>Real</i> -22.000 22.000 mA or V 1000 = 1 unit 14.29 Al1 HW switch position <i>List</i> - - 1 = 1 14.30 Al1 unit selection <i>List</i> - - 1 = 1 14.31 Al1 filter gain <i>List</i> 07 - 1 = 1	14.26	AI1 actual value	Real	-22.000 22.000	mA or V	1000 = 1 unit		
14.29 Al1 HW switch position List - 1 = 1 14.30 Al1 unit selection List - 1 = 1 14.31 Al1 filter gain List 07 - 1 = 1	14.27	AI1 scaled value	Real	-32768.000 32767.000	-	1000 = 1		
14.30 Al1 unit selection List - 1 = 1 14.31 Al1 filter gain List 07 - 1 = 1	14.28	AI1 force data	Real	-22.000 22.000	mA or V	1000 = 1 unit		
14.31 Al1 filter gain List 07 - 1 = 1	14.29	AI1 HW switch position	List	-	-	1 = 1		
	14.30	AI1 unit selection	List	-	-	1 = 1		
14.32 Al1 filter time Real 0.000 30.000 s 1000 = 1 s	14.31	AI1 filter gain	List	07	-	1 = 1		
	14.32	AI1 filter time	Real	0.000 30.000	S	1000 = 1 s		

No.	Name	Туре	Range	Unit	FbEq32
14.33	Al1 min	Real	-22.000 22.000	mA or V	1000 = 1 mA or V
14.34	Al1 max	Real	-22.000 22.000	mA or V	1000 = 1 mA or V
14.35	AI1 scaled at AI1 min	Real	-32768.000 32767.000	-	1000 = 1
14.36	AI1 scaled at AI1 max	Real	-32768.000 32767.000	-	1000 = 1
14.41	Al2 actual value	Real	-22.000 22.000	mA or V	1000 = 1 unit
14.42	Al2 scaled value	Real	-32768.000 32767.000	-	1000 = 1
14.43	Al2 force data	Real	-22.000 22.000	mA or V	1000 = 1 unit
14.44	AI2 HW switch position	List	-	-	1 = 1
14.45	AI2 unit selection	List	-	-	1 = 1
14.46	Al2 filter gain	List	07	-	1 = 1
14.47	AI2 filter time	Real	0.000 30.000	S	1000 = 1 s
14.48	Al2 min	Real	-22.000 22.000	mA or V	1000 = 1 mA or V
14.49	Al2 max	Real	-22.000 22.000	mA or V	1000 = 1 mA or V
14.50	AI2 scaled at AI2 min	Real	-32768.000 32767.000	-	1000 = 1
14.51	AI2 scaled at AI2 max	Real	-32768.000 32767.000	-	1000 = 1
	A/3	(14.01 Mod	dule 1 type = FIO-11)		
14.56	Al3 actual value	Real	-22.000 22.000	mA or V	1000 = 1 unit
14.57	Al3 scaled value	Real	-32768.000 32767.000	-	1000 = 1
14.58	AI3 force data	Real	-22.000 22.000	mA or V	1000 = 1 unit
14.59	AI3 HW switch position	List	-	-	1 = 1
14.60	AI3 unit selection	List	-	-	1 = 1
14.61	Al3 filter gain	List	07	-	1 = 1
14.62	AI3 filter time	Real	0.000 30.000	s	1000 = 1 s
14.63	AI3 min	Real	-22.000 22.000	mA or V	1000 = 1 mA or V
14.64	Al3 max	Real	-22.000 22.000	mA or V	1000 = 1 mA or V
14.65	AI3 scaled at AI3 min	Real	-32768.000 32767.000	-	1000 = 1
14.66	AI3 scaled at AI3 max	Real	-32768.000 32767.000	-	1000 = 1
	Common parameters fo	or AOx (14.	01 Module 1 type = FIO-11 o	FAIO-01)	
14.71	AO force selection	PB	00000000hFFFFFFFh	-	1 = 1
	AO1 (14.0	1 Module 1	type = FIO-11 or FAIO-01)		
14.76	AO1 actual value	Real	0.000 22.000	mA	1000 = 1 mA
14.77	AO1 source	Analog src	-	-	1 = 1
14.78	AO1 force data	Real	0.000 22.000	mA	1000 = 1 mA
14.79	AO1 filter time	Real	0.000 30.000	S	1000 = 1 s
14.80	AO1 source min	Real	-32768.0 32767.0	-	10 = 1
14.81	AO1 source max	Real	-32768.0 32767.0	-	10 = 1

No.	Name	Туре	Range	Unit	FbEq32				
14.82	AO1 out at AO1 src min	Real	0.000 22.000	mA	1000 = 1 mA				
14.83	AO1 out at AO1 src max	Real	0.000 22.000	mA	1000 = 1 mA				
	AO2 (14.01 Module 1 type = FAIO-01)								
14.86	AO2 actual value	Real	0.000 22.000	mA	1000 = 1 mA				
14.87	AO2 source	Analog src	-	-	1 = 1				
14.88	AO2 force data	Real	0.000 22.000	mA	1000 = 1 mA				
14.89	AO2 filter time	Real	0.000 30.000	S	1000 = 1 s				
14.90	AO2 source min	Real	-32768.0 32767.0	-	10 = 1				
14.91	AO2 source max	Real	-32768.0 32767.0	-	10 = 1				
14.92	AO2 out at AO2 src min	Real	0.000 22.000	mA	1000 = 1 mA				
14.93	AO2 out at AO2 src max	Real	0.000 22.000	mA	1000 = 1 mA				
15 I/O e	xtension module 2								
15.01	Module 2 type	List	04	-	1 = 1				
15.02	Module 2 location	Real	1254	-	1 = 1				
15.03	Module 2 status	List	02	-	1 = 1				
	DIx (15.01 Mod	ule 2 type = FDIO-01)						
15.05	DI status	PB	00000000hFFFFFFFh	-	1 = 1				
15.06	DI delayed status	PB	00000000hFFF FFFFFh	-	1 = 1				
15.08	DI filter time	Real	0.8 100.0	ms	10 = 1 ms				
15.12	DI1 ON delay	Real	0.00 3000.00	S	100 = 1 s				
15.13	DI1 OFF delay	Real	0.00 3000.00	S	100 = 1 s				
15.17	DI2 ON delay	Real	0.00 3000.00	S	100 = 1 s				
15.18	DI2 OFF delay	Real	0.00 3000.00	S	100 = 1 s				
15.22	DI3 ON delay	Real	0.00 3000.00	S	100 = 1 s				
15.23	DI3 OFF delay	Real	0.00 3000.00	S	100 = 1 s				
	Common parameters	for DIOx (1	5.01 Module 2 type = FIO-01 (or <i>FIO-11</i>)					
15.05	DIO status	PB	00000000hFFFFFFFh	-	1 = 1				
15.06	DIO delayed status	PB	00000000hFFFFFFFh	-	1 = 1				
	DIO1/DIO2 (15.01 Modu	Ile 2 type = FIO-01 or FIO-11)					
15.08	DIO filter time	Real	0.8 100.0	ms	10 = 1 ms				
15.09	DIO1 function	List	01	-	1 = 1				
15.11	DIO1 output source	Binary src	-	-	1 = 1				
15.12	DIO1 ON delay	Real	0.00 3000.00	S	100 = 1 s				
15.13	DIO1 OFF delay	Real	0.00 3000.00	S	100 = 1 s				
15.14	DIO2 function	List	01	-	1 = 1				
15.16	DIO2 output source	Binary src	-	-	1 = 1				
15.17	DIO2 ON delay	Real	0.00 3000.00	S	100 = 1 s				
15.18	DIO2 OFF delay	Real	0.00 3000.00	S	100 = 1 s				

No.	Name	Туре	Range	Unit	FbEq32
	DIO3/E	0104 (15.01	Module 2 type = FIO-01)		
15.19	DIO3 function	List	01	-	1 = 1
15.21	DIO3 output source	Binary src	-	-	1 = 1
15.22	DIO3 ON delay	Real	0.00 3000.00	s	100 = 1 s
15.23	DIO3 OFF delay	Real	0.00 3000.00	s	100 = 1 s
15.24	DIO4 function	List	01	-	1 = 1
15.26	DIO4 output source	Binary src	-	-	1 = 1
15.27	DIO4 ON delay	Real	0.00 3000.00	s	100 = 1 s
15.28	DIO4 OFF delay	Real	0.00 3000.00	S	100 = 1 s
	R01/R02 (1	5.01 Module	e 2 type = FIO-01 or FDIO-01)	
15.31	RO status	PB	0000hFFFFh	-	1 = 1
15.34	RO1 source	Binary src	-	-	1 = 1
15.35	RO1 ON delay	Real	0.00 3000.00	S	100 = 1 s
15.36	RO1 OFF delay	Real	0.00 3000.00	S	100 = 1 s
15.37	RO2 source	Binary src	-	-	1 = 1
15.38	RO2 ON delay	Real	0.00 3000.00	s	100 = 1 s
15.39	RO2 OFF delay	Real	0.00 3000.00	s	100 = 1 s
	Common parameters	for Alx (15.	01 Module 2 type = FIO-11 or	FAIO-01)	•
15.19	AI supervision function	List	04	-	1 = 1
15.20	Al supervision selection	PB	0000hFFFFh	-	1 = 1
15.21	Al tune	List	06 (FIO-11) 04 (FAIO-01)	-	1 = 1
15.22	Al force selection	PB	00000000hFFFFFFFh	-	1 = 1
	AI1/AI2 (15	5.01 Module	2 type = FIO-11 or FAIO-01)		
15.26	Al1 actual value	Real	-22.000 22.000	mA or V	1000 = 1 unit
15.27	Al1 scaled value	Real	-32768.000 32767.000	-	1000 = 1
15.28	AI1 force data	Real	-22.000 22.000	mA or V	1000 = 1 unit
15.29	AI1 HW switch position	List	-	-	1 = 1
15.30	AI1 unit selection	List	-	-	1 = 1
15.31	AI1 filter gain	List	07	-	1 = 1
15.32	AI1 filter time	Real	0.000 30.000	s	1000 = 1 s
15.33	Al1 min	Real	-22.000 22.000	mA or V	1000 = 1 mA or V
15.34	Al1 max	Real	-22.000 22.000	mA or V	1000 = 1 mA or V
15.35	AI1 scaled at AI1 min	Real	-32768.000 32767.000	-	1000 = 1
15.36	AI1 scaled at AI1 max	Real	-32768.000 32767.000	-	1000 = 1
15.41	AI2 actual value	Real	-22.000 22.000	mA or V	1000 = 1 unit
15.42	Al2 scaled value	Real	-32768.000 32767.000	-	1000 = 1

15.44 Al2 HW switch position List - - 1 = 1 15.45 Al2 unit selection List - - 1 = 1 15.46 Al2 filter gain List 07 - 1 = 1 15.47 Al2 filter gain List 07 - 1 = 1 15.48 Al2 filter gain Real 0.00030.000 s 1000 = 1 15.48 Al2 max Real -22.00022.000 mA or V 1000 = 1 15.50 Al2 scaled at Al2 min Real -32768.00032767.000 - 1000 = 1 15.51 Al2 scaled value Real -32768.00032767.000 - 1000 = 1 15.57 Al3 actual value Real -22.00022.000 mA or V 1000 = 1 15.56 Al3 actual value Real -32768.00032767.000 - 1000 = 1 15.58 Al3 filter gain List - - 1 = 1 15.60 Al3 mit selection List 07 - 1 = 1 15.61 Al3 filter gain List 07 - <th>No.</th> <th>Name</th> <th>Туре</th> <th>Range</th> <th>Unit</th> <th>FbEq32</th>	No.	Name	Туре	Range	Unit	FbEq32	
15.45 Al2 unit selection List - 1 = 1 15.46 Al2 filter gain List 07 - 1 = 1 15.47 Al2 filter gain List 07 - 1 = 1 15.48 Al2 min Real 0.000 30.000 s 1000 = 1 15.49 Al2 max Real -22.000 22.000 mA or V 1000 = 1 15.50 Al2 scaled at Al2 min Real -32768.000 32767.000 - 1000 = 1 15.51 Al2 scaled at Al2 max Real -32768.000 32767.000 - 1000 = 1 15.57 Al3 actual value Real -32768.000 32767.000 - 1000 = 1 15.57 Al3 scaled value Real -32768.000 32767.000 - 1000 = 1 15.58 Al3 force data Real -32768.000 32767.000 - 1000 = 1 15.59 Al3 HW switch position List - - 1 = 1 15.60 Al3 filter gain List 07 1 = 1 15.61 Al3 filter gain List 07 1 = 1	15.43	AI2 force data	Real	-22.000 22.000	mA or V	1000 = 1 unit	
15.46 Al2 filter gain List 07 - 1 = 1 15.47 Al2 filter time Real 0.000 30.000 s 1000 = 1 15.48 Al2 min Real -22.000 22.000 mA or V 1000 = 1 15.49 Al2 max Real -22.000 22.000 mA or V 1000 = 1 15.50 Al2 scaled at Al2 min Real -32768.000 32767.000 - 1000 = 1 15.51 Al2 scaled at Al2 max Real -32768.000 32767.000 - 1000 = 1 15.57 Al3 actual value Real -32768.000 32767.000 - 1000 = 1 15.57 Al3 scaled value Real -32768.000 32767.000 - 1000 = 1 15.58 Al3 force data Real -22.000 22.000 mA or V 1000 = 1 15.59 Al HW switch position List - - 1 = 1 1 15.60 Al3 min Real -0.200 2000 mA or V 1000 = 1 15.64 Al3 mix	15.44	AI2 HW switch position	List	-	-	1 = 1	
15.47 Al2 filter time Real 0.000	15.45	AI2 unit selection	List	-	-	1 = 1	
15.48 Al2 min Real -22.000 mA or V 1000 = 1 or V 15.49 Al2 max Real -22.000	15.46	AI2 filter gain	List	07	-	1 = 1	
Image: space of the system or V 15.49 Al2 max Real -22.000 mA or V 1000 = 1 15.50 Al2 scaled at Al2 min Real -32768.000 .32767.000 - 1000 = 1 15.51 Al2 scaled at Al2 max Real -32768.000 .32767.000 - 1000 = 1 15.57 Al3 scaled value Real -22.000	15.47	AI2 filter time	Real	0.000 30.000	s	1000 = 1 s	
Image: space of the system or V 15.50 Al2 scaled at Al2 min Real -32768.000 32767.000 - 1000 = 15.51 Al2 scaled at Al2 max Real -32768.000 32767.000 - 1000 = Al3 (15.01 Module 2 type = FIO-11) 15.56 Al3 actual value Real -22.000 22.000 mA or V 1000 = 15.57 Al3 scaled value Real -22.000 2000 mA or V 1000 = 15.58 Al3 force data Real -22.000 2000 mA or V 1000 = 15.59 Al3 thW switch position List - - 1 = 1 15.60 Al3 unit selection List 07 - 1 = 1 15.61 Al3 filter time Real 0.000 30.000 s 1000 = 1 15.62 Al3 min Real -22.000 2000 mA or V 1000 = 1 15.64 Al3 max Real -32768.000 32767.000 - 1000 =	15.48	AI2 min	Real	-22.000 22.000	mA or V	1000 = 1 mA or V	
15.51 Al2 scaled at Al2 max Real -32768.000 32767.000 - 1000 = Al3 (15.01 Module 2 type = FIO-11) 15.56 Al3 actual value Real -22.000 mA or V 1000 = 1 15.57 Al3 scaled value Real -32768.000 32767.000 - 1000 = 1 15.57 Al3 scaled value Real -32768.000 32767.000 - 1000 = 1 15.59 Al3 filter data Real -22.000 2000 mA or V 1000 = 1 15.60 Al3 unit selection List - - 1 = 1 15.61 Al3 filter gain List 07 - 1 = 1 15.62 Al3 filter time Real 0.000 30.000 s 1000 = 1 15.63 Al3 max Real -22.000 22.000 mA or V 1000 = 1 15.64 Al3 scaled at Al3 max Real -32768.000 32767.000 - 1000 = 1 15.65 Al3 scaled at Al3 max Real 0.32767.000 - 1000 = 1 <td col<="" td=""><td>15.49</td><td>AI2 max</td><td>Real</td><td>-22.000 22.000</td><td>mA or V</td><td>1000 = 1 mA or V</td></td>	<td>15.49</td> <td>AI2 max</td> <td>Real</td> <td>-22.000 22.000</td> <td>mA or V</td> <td>1000 = 1 mA or V</td>	15.49	AI2 max	Real	-22.000 22.000	mA or V	1000 = 1 mA or V
Al3 (15.01 Module 2 type = FIO-11) 15.56 Al3 actual value Real -22.000 mA or V 1000 = 1 15.57 Al3 scaled value Real -32768.000 32767.000 - 1000 = 1 15.58 Al3 force data Real -22.000 2000 mA or V 1000 = 1 15.59 Al3 HW switch position List - - 1 = 1 15.60 Al3 unit selection List - - 1 = 1 15.61 Al3 filter gain List 07 - 1 = 1 15.62 Al3 filter time Real 0.000< 30.000	15.50	AI2 scaled at AI2 min	Real	-32768.000 32767.000	-	1000 = 1	
15.56 Al3 actual value Real -22.000	15.51	AI2 scaled at AI2 max	Real	-32768.000 32767.000	-	1000 = 1	
15.57 Al3 scaled value Real -32768.000 32767.000 - 1000 = 15.58 Al3 force data Real -22.000 mA or V 1000 = 1 15.59 Al3 HW switch position List - - 1 = 1 15.60 Al3 unit selection List - - 1 = 1 15.61 Al3 filter gain List 07 - 1 = 1 15.62 Al3 filter time Real 0.000 30.000 s 1000 = 1 15.63 Al3 min Real -22.000 22.000 mA or V 1000 = 1 15.64 Al3 max Real -22.000 22.000 mA or V 1000 = 1 15.65 Al3 scaled at Al3 min Real -32768.00 32767.000 - 1000 = 1 15.66 Al3 scaled at Al3 max Real -32768.00 32767.000 - 1000 = 1 15.67 AO force selection PB 00000000hFFFFFFFh - 1 = 1 AO1 (15.01 Module 2 type = FIO-11 or FAIO-01) 15.76 AO1 ac		AI3	(15.01 Mod	lule 2 type = FIO-11)			
15.58 Al3 force data Real -22.000 mA or V 1000 = 1 15.59 Al3 HW switch position List - - 1 = 1 15.60 Al3 unit selection List - - 1 = 1 15.61 Al3 filter gain List 07 - 1 = 1 15.62 Al3 filter time Real 0.00030.000 s 1000 = 1 15.63 Al3 min Real -22.000 22.000 mA or V 1000 = 1 15.64 Al3 max Real -22.000 22.000 mA or V 1000 = 1 15.65 Al3 scaled at Al3 min Real -32768.00 32767.000 - 1000 = 15.66 Al3 scaled at Al3 max Real -32768.00 32767.000 - 1000 = 15.66 Al3 scaled at Al3 max Real -32768.00 32767.000 - 1000 = 15.77 AO force selection PB 00000000hFFFFFFFh - 1 = 1 AO1 actual value Real 0.000 2000 mA 1000 = 1	15.56	AI3 actual value	Real	-22.000 22.000	mA or V	1000 = 1 unit	
15.59 Al3 HW switch position List - 1 = 1 15.60 Al3 unit selection List - 1 = 1 15.61 Al3 filter gain List 07 - 1 = 1 15.62 Al3 filter time Real 0.000 30.000 s 1000 = 1 15.63 Al3 min Real -22.000 22.000 mA or V 1000 = 1 15.64 Al3 max Real -22.000 22.000 mA or V 1000 = 1 15.65 Al3 scaled at Al3 min Real -32768.000 32767.000 - 1000 = 15.66 Al3 scaled at Al3 max Real -32768.000 32767.000 - 1000 = 15.71 AO force selection PB 00000000hFFFFFFFh - 1 = 1 AO1 (15.01 Module 2 type = FIO-11 or FAIO-01) 15.76 AO1 actual value Real 0.000 22.000 mA 1000 = 1 15.76 AO1 force data Real 0.000 22.000 mA 1000 = 1 15.77 AO1 force data Real 0.000 22.000 mA 1000 = 1 1	15.57	AI3 scaled value	Real	-32768.000 32767.000	-	1000 = 1	
15.60 Al3 unit selection List - 1 = 1 15.61 Al3 filter gain List 07 - 1 = 1 15.62 Al3 filter time Real 0.000 30.000 s 1000 = 1 15.63 Al3 min Real -22.000 22.000 mA or V 1000 = 1 15.64 Al3 max Real -22.000 22.000 mA or V 1000 = 1 15.65 Al3 scaled at Al3 min Real -32768.000 32767.000 - 1000 = 15.66 Al3 scaled at Al3 max Real -32768.000 32767.000 - 1000 = 15.66 Al3 scaled at Al3 max Real -32768.000 32767.000 - 1000 = Common parameters for AOx (15.01 Module 2 type = FIO-11 or FAIO-01) 15.71 AO force selection PB 00000000hFFFFFFFFh - 1 = 1 AO1 (15.01 Module 2 type = FIO-11 or FAIO-01) 15.76 AO1 actual value Real 0.000 22.000 mA 1000 = 1 15.77 AO1 force data Real 0.000 22.000 mA 1000 = 1 15.79 <td>15.58</td> <td>AI3 force data</td> <td>Real</td> <td>-22.000 22.000</td> <td>mA or V</td> <td>1000 = 1 unit</td>	15.58	AI3 force data	Real	-22.000 22.000	mA or V	1000 = 1 unit	
15.61 Al3 filter gain List 07 - $1 = 1$ 15.62 Al3 filter time Real $0.000 \dots 30.000$ s $1000 = 1$ 15.63 Al3 min Real -22.000 \dots 22.000 mA or V $1000 = 1$ 15.64 Al3 max Real -22.000 \dots 22.000 mA or V $1000 = 1$ 15.64 Al3 scaled at Al3 min Real -32768.000 \dots 32767.000 - $1000 = 1$ 15.65 Al3 scaled at Al3 max Real -32768.000 \dots 32767.000 - $1000 = 1$ 15.66 Al3 scaled at Al3 max Real -32768.000 \dots 32767.000 - $1000 = 1$ 15.66 Al3 scaled at Al3 max Real -32768.000 \dots 32767.000 - $1000 = 1$ 15.71 AO force selection PB 00000000hFFFFFFFh - $1 = 1$ AO1 (15.01 Module 2 type = FIO-11 or FAIO-01) 15.76 AO1 actual value Real $0.000 \dots 22.000$ mA $1000 = 1$ 15.77 AO1 force data Real $0.000 \dots 30.000$ s $1000 = 1$ 15.78 AO1 force data Real	15.59	AI3 HW switch position	List	-	-	1 = 1	
15.62 Al3 filter time Real 0.000 30.000 s 1000 = 1 15.63 Al3 min Real -22.000 mA or V 1000 = 1 15.64 Al3 max Real -22.000 mA or V 1000 = 1 15.64 Al3 max Real -22.000 mA or V 1000 = 1 15.65 Al3 scaled at Al3 min Real -32768.000 32767.000 - 1000 = 15.66 Al3 scaled at Al3 max Real -32768.000 32767.000 - 1000 = 15.66 Al3 scaled at Al3 max Real -32768.000 32767.000 - 1000 = 15.71 AO force selection PB 000000000 FFFFFFFh - 1 = 1 AO1 actual value Real 0.000 22.000 mA 1000 = 1 15.76 AO1 actual value Real 0.000 22.000 mA 1000 = 1 15.77 AO1 source Analog - - 1 = 1 1	15.60	AI3 unit selection	List	-	-	1 = 1	
15.63 Al3 min Real -22.000 mA or V 1000 = 1 or V 15.64 Al3 max Real -22.000 mA or V 1000 = 1 or V 15.64 Al3 max Real -22.000 mA or V 1000 = 1 or V 15.65 Al3 scaled at Al3 min Real -32768.000 32767.000 - 1000 = 15.66 Al3 scaled at Al3 max Real -32768.000 32767.000 - 1000 = Common parameters for AOx (15.01 Module 2 type = FIO-11 or FAIO-01) 15.71 AO force selection PB 00000000hFFFFFFFFh - 1 = 1 AO1 (15.01 Module 2 type = FIO-11 or FAIO-01) 15.76 AO1 actual value Real 0.000 22.000 mA 1000 = 1 15.77 AO1 source Analog src - - 1 = 1 15.78 AO1 force data Real 0.000 22.000 mA 1000 = 1 15.79 AO1 filter time Real -32768.0 32767.0 - 10 = 1 15.80 AO1 source max Real -32768.0	15.61	AI3 filter gain	List	07	-	1 = 1	
Image: search of the	15.62	AI3 filter time	Real	0.000 30.000	s	1000 = 1 s	
Image: second	15.63	AI3 min	Real	-22.000 22.000	mA or V	1000 = 1 mA or V	
15.66 AI3 scaled at AI3 max Real -32768.000 32767.000 - 1000 = Common parameters for AOx (15.01 Module 2 type = FIO-11 or FAIO-01) 15.71 AO force selection PB 00000000hFFFFFFFh - 1 = 1 AO1 (15.01 Module 2 type = FIO-11 or FAIO-01) 15.76 AO1 actual value Real 0.000 22.000 mA 1000 = 1 15.77 AO1 source Analog src - - 1 = 1 15.78 AO1 force data Real 0.000 22.000 mA 1000 = 1 15.79 AO1 force data Real 0.000 30.000 s 1000 = 1 15.80 AO1 source min Real -32768.0 32767.0 - 10 = 1 15.81 AO1 source max Real -32768.0 32767.0 - 10 = 1 15.82 AO1 out at AO1 src min Real 0.000 22.000 mA 1000 = 1 15.83 AO1 out at AO1 src max Real 0.000 22.000 mA 1000 = 1 AO2 (15.01 Module 2 type = FAIO-01) AO2 actual value Real 0.000	15.64	AI3 max	Real	-22.000 22.000	mA or V	1000 = 1 mA or V	
Common parameters for AOx (15.01 Module 2 type = FIO-11 or FAIO-01) 15.71 AO force selection PB 00000000hFFFFFFFh - 1 = 1 AO1 (15.01 Module 2 type = FIO-11 or FAIO-01) 15.76 AO1 actual value Real 0.000 22.000 mA 1000 = 1 15.77 AO1 source Analog src - - 1 = 1 15.78 AO1 force data Real 0.000 22.000 mA 1000 = 1 15.79 AO1 filter time Real 0.000 22.000 mA 1000 = 1 15.79 AO1 filter time Real 0.000 30.000 s 1000 = 1 15.80 AO1 source min Real -32768.0 32767.0 - 10 = 1 15.81 AO1 source max Real -32768.0 32767.0 - 10 = 1 15.82 AO1 out at AO1 src min Real 0.000 22.000 mA 1000 = 1 15.83 AO1 out at AO1 src max Real 0.000 22.000 mA 1000 = 1 15.86 AO2 actual value Real <td< td=""><td>15.65</td><td>AI3 scaled at AI3 min</td><td>Real</td><td>-32768.000 32767.000</td><td>-</td><td>1000 = 1</td></td<>	15.65	AI3 scaled at AI3 min	Real	-32768.000 32767.000	-	1000 = 1	
15.71 AO force selection PB 0000000hFFFFFFh - 1 = 1 AO1 (15.01 Module 2 type = FIO-11 or FAIO-01) 15.76 AO1 actual value Real 0.000 22.000 mA 1000 = 1 15.77 AO1 source Analog src - 1 = 1 15.78 AO1 force data Real 0.000 22.000 mA 1000 = 1 15.79 AO1 filter time Real 0.000 30.000 s 1000 = 1 15.80 AO1 source min Real	15.66	AI3 scaled at AI3 max	Real	-32768.000 32767.000	-	1000 = 1	
AO1 (15.01 Module 2 type = FIO-11 or FAIO-01) 15.76 AO1 actual value Real $0.000 \dots 22.000$ mA $1000 = 1$ 15.77 AO1 source Analog src - 1 = 1 15.78 AO1 force data Real $0.000 \dots 22.000$ mA $1000 = 1$ 15.79 AO1 force data Real $0.000 \dots 22.000$ mA $1000 = 1$ 15.79 AO1 filter time Real $0.000 \dots 30.000$ s $1000 = 1$ 15.80 AO1 source min Real $-32768.0 \dots 32767.0$ - $10 = 1$ 15.81 AO1 source max Real $-32768.0 \dots 32767.0$ - $10 = 1$ 15.82 AO1 out at AO1 src min Real $0.000 \dots 22.000$ mA $1000 = 1$ 15.83 AO1 out at AO1 src max Real $0.000 \dots 22.000$ mA $1000 = 1$ $AO2 (15.01 Module 2 type = FAIO-01)$ 15.86 AO2 actual value Real $0.000 \dots 22.000$ mA $1000 = 1$ 15.87 AO2 source Analog - -		Common parameters fo	or AOx (<mark>15</mark> .	01 Module 2 type = FIO-11 o	r <i>FAIO-01</i>)		
15.76 AO1 actual value Real 0.000 22.000 mA 1000 = 1 15.77 AO1 source Analog src - 1 = 1 15.78 AO1 force data Real 0.000 22.000 mA 1000 = 1 15.78 AO1 force data Real 0.000 22.000 mA 1000 = 1 15.79 AO1 filter time Real 0.000 30.000 s 1000 = 1 15.80 AO1 source min Real -32768.0 32767.0 - 10 = 1 15.81 AO1 source max Real -32768.0 32767.0 - 10 = 1 15.82 AO1 out at AO1 src min Real 0.000 22.000 mA 1000 = 1 15.83 AO1 out at AO1 src max Real 0.000 22.000 mA 1000 = 1 15.83 AO1 out at AO1 src max Real 0.000 22.000 mA 1000 = 1 15.86 AO2 actual value Real 0.000 22.000 mA 1000 = 1 15.86 AO2 actual value Real 0.000 22.000 mA 1000 = 1 15.87 AO2 source An	15.71	AO force selection	PB	00000000hFFFFFFFFh	-	1 = 1	
15.77AO1 sourceAnalog src-1 = 115.78AO1 force dataReal $0.000 \dots 22.000$ mA $1000 = 1$ 15.79AO1 filter timeReal $0.000 \dots 30.000$ s $1000 = 1$ 15.80AO1 source minReal $-32768.0 \dots 32767.0$ - $10 = 1$ 15.81AO1 source maxReal $-32768.0 \dots 32767.0$ - $10 = 1$ 15.82AO1 out at AO1 src minReal $0.000 \dots 22.000$ mA $1000 = 1$ 15.83AO1 out at AO1 src maxReal $0.000 \dots 22.000$ mA $1000 = 1$ AO2 (15.01 Module 2 type = FAIO-01)15.86AO2 actual valueReal $0.000 \dots 22.000$ mA $1000 = 1$ 15.87AO2 sourceAnalog $1 = 1$		AO1 (15.0	1 Module 2	<i>type</i> = <i>FIO-11</i> or <i>FAIO-01</i>)			
src src 15.78 AO1 force data Real 0.000 22.000 mA 1000 = 1 15.79 AO1 filter time Real 0.000 30.000 s 1000 = 1 15.79 AO1 source min Real -32768.0 32767.0 - 10 = 1 15.81 AO1 source max Real -32768.0 32767.0 - 10 = 1 15.82 AO1 out at AO1 src min Real 0.000 22.000 mA 1000 = 1 15.83 AO1 out at AO1 src max Real 0.000 22.000 mA 1000 = 1 15.84 AO1 out at AO1 src max Real 0.000 22.000 mA 1000 = 1 15.85 AO1 out at AO1 src max Real 0.000 22.000 mA 1000 = 1 15.86 AO2 actual value Real 0.000 22.000 mA 1000 = 1 15.87 AO2 source Analog - - 1 = 1	15.76	AO1 actual value	Real	0.000 22.000	mA	1000 = 1 mA	
15.79 AO1 filter time Real $0.000 \dots 30.000$ s $1000 = 1$ 15.80 AO1 source min Real $-32768.0 \dots 32767.0$ - $10 = 1$ 15.81 AO1 source max Real $-32768.0 \dots 32767.0$ - $10 = 1$ 15.82 AO1 out at AO1 src min Real $0.000 \dots 22.000$ mA $1000 = 1$ 15.83 AO1 out at AO1 src max Real $0.000 \dots 22.000$ mA $1000 = 1$ 15.83 AO1 out at AO1 src max Real $0.000 \dots 22.000$ mA $1000 = 1$ 15.86 AO2 actual value Real $0.000 \dots 22.000$ mA $1000 = 1$ 15.87 AO2 source Analog - - $1 = 1$	15.77	AO1 source	-	-	-	1 = 1	
15.80 AO1 source min Real -32768.0 32767.0 - 10 = 1 15.81 AO1 source max Real -32768.0 32767.0 - 10 = 1 15.82 AO1 out at AO1 src min Real 0.000 22.000 mA 1000 = 1 15.83 AO1 out at AO1 src max Real 0.000 22.000 mA 1000 = 1 15.86 AO2 actual value Real 0.000 22.000 mA 1000 = 1 15.87 AO2 source Analog - 1 = 1	15.78	AO1 force data	Real	0.000 22.000	mA	1000 = 1 mA	
15.81 AO1 source max Real -32768.0 32767.0 - 10 = 1 15.82 AO1 out at AO1 src min Real 0.000 22.000 mA 1000 = 1 15.83 AO1 out at AO1 src max Real 0.000 22.000 mA 1000 = 1 15.83 AO1 out at AO1 src max Real 0.000 22.000 mA 1000 = 1 AO2 (15.01 Module 2 type = FAIO-01) 15.86 AO2 actual value Real 0.000 22.000 mA 1000 = 1 15.87 AO2 source Analog - - 1 = 1	15.79	AO1 filter time	Real	0.000 30.000	S	1000 = 1 s	
15.82 AO1 out at AO1 src min Real 0.000 22.000 mA 1000 = 1 15.83 AO1 out at AO1 src max Real 0.000 22.000 mA 1000 = 1 AO2 (15.01 Module 2 type = FAIO-01) 15.86 AO2 actual value Real 0.000 22.000 mA 1000 = 1 15.87 AO2 source Analog - 1 = 1	15.80	AO1 source min	Real	-32768.0 32767.0	-	10 = 1	
15.83 AO1 out at AO1 src max Real 0.000 22.000 mA 1000 = 1 AO2 (15.01 Module 2 type = FAIO-01) 15.86 AO2 actual value Real 0.000 22.000 mA 1000 = 1 15.87 AO2 source Analog - 1 = 1	15.81	AO1 source max	Real	-32768.0 32767.0	-	10 = 1	
AO2 (15.01 Module 2 type = FAIO-01) 15.86 AO2 actual value Real 0.000 22.000 mA 1000 = 1 15.87 AO2 source Analog - 1 = 1	15.82	AO1 out at AO1 src min	Real	0.000 22.000	mA	1000 = 1 mA	
15.86 AO2 actual value Real 0.000 22.000 mA 1000 = 1 15.87 AO2 source Analog - 1 = 1	15.83	AO1 out at AO1 src max	Real	0.000 22.000	mA	1000 = 1 mA	
15.87 AO2 source Analog - 1 = 1		AO2	(15.01 Mod	lule 2 type = FAIO-01)			
	15.86	AO2 actual value	Real	0.000 22.000	mA	1000 = 1 mA	
STC	15.87	AO2 source	Analog src	-	-	1 = 1	
15.88 AO2 force data Real 0.000 22.000 mA 1000 = 1	15.88	AO2 force data	Real	0.000 22.000	mA	1000 = 1 mA	
15.89 AO2 filter time Real 0.000 30.000 s 1000 = 1	15.89	AO2 filter time	Real	0.000 30.000	S	1000 = 1 s	

No.	Name	Туре	Range	Unit	FbEq32		
15.90	AO2 source min	Real	-32768.0 32767.0	-	10 = 1		
15.91	AO2 source max	Real	-32768.0 32767.0	-	10 = 1		
15.92	AO2 out at AO2 src min	Real	0.000 22.000	mA	1000 = 1 mA		
15.93	AO2 out at AO2 src max	Real	0.000 22.000	mA	1000 = 1 mA		
16 I/O e	ctension module 3						
16.01	Module 3 type	List	04	-	1 = 1		
16.02	Module 3 location	Real	1254	-	1 = 1		
16.03	Module 3 status	List	02	-	1 = 1		
	DIx (16.01 Mod	ule 3 type = FDIO-01)		•		
16.05	DI status	PB	00000000hFFFFFFFh	-	1 = 1		
16.06	DI delayed status	PB	00000000hFFFFFFFh	-	1 = 1		
16.08	DI filter time	Real	0.8 100.0	ms	10 = 1 ms		
16.12	DI1 ON delay	Real	0.00 3000.00	S	100 = 1 s		
16.13	DI1 OFF delay	Real	0.00 3000.00	S	100 = 1 s		
16.17	DI2 ON delay	Real	0.00 3000.00	s	100 = 1 s		
16.18	DI2 OFF delay	Real	0.00 3000.00	S	100 = 1 s		
16.22	DI3 ON delay	Real	0.00 3000.00	S	100 = 1 s		
16.23	DI3 OFF delay	Real	0.00 3000.00	S	100 = 1 s		
Common parameters for DIOx (16.01 Module 3 type = FIO-01 or FIO-11)							
16.05	DIO status	PB	00000000hFFFFFFFh	-	1 = 1		
16.06	DIO delayed status	PB	00000000hFFFFFFFFh	-	1 = 1		
	DIO1/DIO2 (16.01 Modu	<i>Ile 3 type = FIO-01</i> or <i>FIO-11</i>)				
16.08	DIO filter time	Real	0.8 100.0	ms	10 = 1 ms		
16.09	DIO1 function	List	01	-	1 = 1		
16.11	DIO1 output source	Binary src	-	-	1 = 1		
16.12	DIO1 ON delay	Real	0.00 3000.00	S	100 = 1 s		
16.13	DIO1 OFF delay	Real	0.00 3000.00	S	100 = 1 s		
16.14	DIO2 function	List	01	-	1 = 1		
16.16	DIO2 output source	Binary src	-	-	1 = 1		
16.17	DIO2 ON delay	Real	0.00 3000.00	S	100 = 1 s		
16.18	DIO2 OFF delay	Real	0.00 3000.00	S	100 = 1 s		
DIO3/DIO4 (16.01 Module 3 type = FIO-01)							
16.19	DIO3 function	List	01	-	1 = 1		
16.21	DIO3 output source	Binary src	-	-	1 = 1		
16.22	DIO3 ON delay	Real	0.00 3000.00	S	100 = 1 s		
16.23	DIO3 OFF delay	Real	0.00 3000.00	S	100 = 1 s		
16.24	DIO4 function	List	01	-	1 = 1		
16.26	DIO4 output source	Binary src	-	-	1 = 1		

No.	Name	Туре	Range	Unit	FbEq32			
16.27	DIO4 ON delay	Real	0.0 3000.0	S	10 = 1 s			
16.28	DIO4 OFF delay	Real	0.0 3000.0	S	10 = 1 s			
RO1/RO2 (16.01 Module 3 type = FIO-01 or FDIO-01)								
16.31	RO status	PB	0000hFFFFh	-	1 = 1			
16.34	RO1 source	Binary src	-	-	1 = 1			
16.35	RO1 ON delay	Real	0.00 3000.00	S	100 = 1 s			
16.36	RO1 OFF delay	Real	0.00 3000.00	S	100 = 1 s			
16.37	RO2 source	Binary src	-	-	1 = 1			
16.38	RO2 ON delay	Real	0.00 3000.00	S	100 = 1 s			
16.39	RO2 OFF delay	Real	0.00 3000.00	S	100 = 1 s			
	Common parameters	for Alx (<mark>16</mark> .	01 Module 3 type = FIO-11 or	FAIO-01)				
16.19	AI supervision function	List	04	-	1 = 1			
16.20	AI supervision selection	PB	0000hFFFFh	-	1 = 1			
16.21	AI tune	List	06 (FIO-11) 04 (FAIO-01)	-	1 = 1			
16.22	Al force selection	PB	00000000hFFFFFFFh	-	1 = 1			
AI1/AI2 (16.01 Module 3 type = FIO-11 or FAIO-01)								
16.26	AI1 actual value	Real	-22.000 22.000	mA or V	1000 = 1 unit			
16.27	AI1 scaled value	Real	-32768.000 32767.000	-	1000 = 1			
16.28	AI1 force data	Real	-22.000 22.000	mA or V	1000 = 1 unit			
16.29	AI1 HW switch position	List	-	-	1 = 1			
16.30	AI1 unit selection	List	-	-	1 = 1			
16.31	AI1 filter gain	List	07	-	1 = 1			
16.32	AI1 filter time	Real	0.000 30.000	S	1000 = 1 s			
16.33	AI1 min	Real	-22.000 22.000	mA or V	1000 = 1 mA or V			
16.34	AI1 max	Real	-22.000 22.000	mA or V	1000 = 1 mA or V			
16.35	AI1 scaled at AI1 min	Real	-32768.000 32767.000	-	1000 = 1			
16.36	AI1 scaled at AI1 max	Real	-32768.000 32767.000	-	1000 = 1			
16.41	AI2 actual value	Real	-22.000 22.000	mA or V	1000 = 1 unit			
16.42	AI2 scaled value	Real	-32768.000 32767.000	-	1000 = 1			
16.43	AI2 force data	Real	-22.000 22.000	mA or V	1000 = 1 unit			
16.44	AI2 HW switch position	List	-	-	1 = 1			
16.45	AI2 unit selection	List	-	-	1 = 1			
16.46	AI2 filter gain	List	07	-	1 = 1			
16.47	AI2 filter time	Real	0.000 30.000	S	1000 = 1 s			
16.48	Al2 min	Real	-22.000 22.000	mA or V	1000 = 1 mA or V			
16.49	Al2 max	Real	-22.000 22.000	mA or V	1000 = 1 mA or V			

No.	Name	Туре	Range	Unit	FbEq32
16.50	AI2 scaled at AI2 min	Real	-32768.000 32767.000	-	1000 = 1
16.51	AI2 scaled at AI2 max	Real	-32768.000 32767.000	-	1000 = 1
	AI3	(16.01 Mod	lule 3 type = FIO-11)		I
16.56	AI3 actual value	Real	-22.000 22.000	mA or V	1000 = 1 unit
16.57	AI3 scaled value	Real	-32768.000 32767.000	-	1000 = 1
16.58	AI3 force data	Real	-22.000 22.000	mA or V	1000 = 1 unit
16.59	AI3 HW switch position	List	-	-	1 = 1
16.60	AI3 unit selection	List	-	-	1 = 1
16.61	AI3 filter gain	List	07	-	1 = 1
16.62	AI3 filter time	Real	0.000 30.000	S	1000 = 1 s
16.63	AI3 min	Real	-22.000 22.000	mA or V	1000 = 1 mA or V
16.64	Al3 max	Real	-22.000 22.000	mA or V	1000 = 1 mA or V
16.65	AI3 scaled at AI3 min	Real	-32768.000 32767.000	-	1000 = 1
16.66	AI3 scaled at AI3 max	Real	-32768.000 32767.000	-	1000 = 1
	Common parameters for	or AOx (<mark>16</mark> .	01 Module 3 type = FIO-11 o	FAIO-01)	
16.71	AO force selection	PB	00000000hFFFFFFFh	-	1 = 1
	AO1 (16.0	1 Module 3	type = FIO-11 or FAIO-01)		
16.76	AO1 actual value	Real	0.000 22.000	mA	1000 = 1 mA
16.77	AO1 source	Analog src	-	-	1 = 1
16.78	AO1 force data	Real	0.000 22.000	mA	1000 = 1 mA
16.79	AO1 filter time	Real	0.000 30.000	S	1000 = 1 s
16.80	AO1 source min	Real	-32768.0 32767.0	-	10 = 1
16.81	AO1 source max	Real	-32768.0 32767.0	-	10 = 1
16.82	AO1 out at AO1 src min	Real	0.000 22.000	mA	1000 = 1 mA
16.83	AO1 out at AO1 src max	Real	0.000 22.000	mA	1000 = 1 mA
	AO2	(16.01 Moa	lule 3 type = FAIO-01)		
16.86	AO2 actual value	Real	0.000 22.000	mA	1000 = 1 mA
16.87	AO2 source	Analog src	-	-	1 = 1
16.88	AO2 force data	Real	0.000 22.000	mA	1000 = 1 mA
16.89	AO2 filter time	Real	0.000 30.000	S	1000 = 1 s
16.90	AO2 source min	Real	-32768.0 32767.0	-	10 = 1
16.91	AO2 source max	Real	-32768.0 32767.0	-	10 = 1
16.92	AO2 out at AO2 src min	Real	0.000 22.000	mA	1000 = 1 mA
16.93	AO2 out at AO2 src max	Real	0.000 22.000	mA	1000 = 1 mA
19 Oper	ation mode				
19.01	Actual operation mode	List	-	-	1 = 1
19.11	Ext1/Ext2 selection	Binary src	-	-	1 = 1
19.12	Ext1 control mode	List	16		1 = 1

No.	Name	Туре	Range	Unit	FbEq32
19.14	Ext2 control mode	List	16	-	1 = 1
19.16	Local control mode	List	01	-	1 = 1
19.17	Local control disable	List	01	-	1 = 1
19.20	Scalar control reference unit	List	01	-	1 = 1
20 Start	/stop/direction	1 1			•
20.01	Ext1 commands	List	-	-	1 = 1
20.02	Ext1 start trigger type	List	01	-	1 = 1
20.03	Ext1 in1 source	Binary src	-	-	1 = 1
20.04	Ext1 in2 source	Binary src	-	-	1 = 1
20.05	Ext1 in3 source	Binary src	-	-	1 = 1
20.06	Ext2 commands	List	-	-	1 = 1
20.07	Ext2 start trigger type	List	01	-	1 = 1
20.08	Ext2 in1 source	Binary src	-	-	1 = 1
20.09	Ext2 in2 source	Binary src	-	-	1 = 1
20.10	Ext2 in3 source	Binary src	-	-	1 = 1
20.11	Run enable stop mode	List	02	-	1 = 1
20.12	Run enable 1 source	Binary src	-	-	1 = 1
20.19	Enable start command	Binary src	-	-	1 = 1
20.23	Positive speed enable	Binary src	-	-	1 = 1
20.24	Negative speed enable	Binary src	-	-	1 = 1
20.25	Jogging enable	Binary src	-	-	1 = 1
20.26	Jogging 1 start source	Binary src	-	-	1 = 1
20.27	Jogging 2 start source	Binary src	-	-	1 = 1
20.29	Local start trigger type	List	01	-	1 = 1
20.30	Enable signals warning function	PB	00b11b	-	1 = 1
21 Start	/stop mode				
21.01	Start mode	List	03	-	1 = 1
21.02	Magnetization time	Real	010000	ms	1 = 1 ms
21.03	Stop mode	List	02	-	1 = 1
21.04	Emergency stop mode	List	02	-	1 = 1
21.05	Emergency stop source	Binary src	-	-	1 = 1

No.	Name	Туре	Range	Unit	FbEq32
21.06	Zero speed limit	Real	0.00 30000.00	rpm	100 = 1 rpm
21.07	Zero speed delay	Real	030000	ms	1 = 1 ms
21.08	DC current control	PB	00b11b	-	1 = 1
21.09	DC hold speed	Real	0.00 1000.00	rpm	100 = 1 rpm
21.10	DC current reference	Real	0.0 100.0	%	10 = 1%
21.11	Post magnetization time	Real	030000	s	1 = 1 s
21.12	Continuous magnetization command	Binary src	-	-	1 = 1
21.13	Autophasing mode	List	03	-	1 = 1
21.14	Pre-heating input source	Binary src	-	-	1 = 1
21.16	Pre-heating current	Real	0.0 30.0	%	10 = 1%
21.18	Auto restart time	Real	0.0, 0.1 5.0	S	10 = 1 s
21.19	Scalar control mode	List	02	-	1 = 1
21.20	Follower force ramp stop	Binary src	-	-	1 = 1
22 Spee	ed reference selection				
22.01	Speed ref unlimited	Real	-30000.00 30000.00	rpm	100 = 1 rpm
22.11	Speed ref1 source	Analog src	-	-	1 = 1
22.12	Speed ref2 source	Analog src	-	-	1 = 1
22.13	Speed ref1 function	List	05	-	1 = 1
22.14	Speed ref1/2 selection	Binary src	-	-	1 = 1
22.15	Speed additive 1 source	Analog src	-	-	1 = 1
22.16	Speed share	Real	-8.000 8.000	-	1000 = 1
22.17	Speed additive 2 source	Analog src	-	-	1 = 1
22.21	Constant speed function	PB	00b11b	-	1 = 1
22.22	Constant speed sel1	Binary src	-	-	1 = 1
22.23	Constant speed sel2	Binary src	-	-	1 = 1
22.24	Constant speed sel3	Binary src	-	-	1 = 1
22.26	Constant speed 1	Real	-30000.00 30000.00	rpm	100 = 1 rpm
22.27	Constant speed 2	Real	-30000.00 30000.00	rpm	100 = 1 rpm
22.28	Constant speed 3	Real	-30000.00 30000.00	rpm	100 = 1 rpm
22.29	Constant speed 4	Real	-30000.00 30000.00	rpm	100 = 1 rpm
22.30	Constant speed 5	Real	-30000.00 30000.00	rpm	100 = 1 rpm
22.31	Constant speed 6	Real	-30000.00 30000.00	rpm	100 = 1 rpm
22.32	Constant speed 7	Real	-30000.00 30000.00	rpm	100 = 1 rpm
22.41	Speed ref safe	Real	-30000.00 30000.00	rpm	100 = 1 rpm

No.	Name	Туре	Range	Unit	FbEq32
22.42	Jogging 1 ref	Real	-30000.00 30000.00	rpm	100 = 1 rpm
22.43	Jogging 2 ref	Real	-30000.00 30000.00	rpm	100 = 1 rpm
22.51	Critical speed function	PB	00b11b	-	1 = 1
22.52	Critical speed 1 low	Real	-30000.00 30000.00	rpm	100 = 1 rpm
22.53	Critical speed 1 high	Real	-30000.00 30000.00	rpm	100 = 1 rpm
22.54	Critical speed 2 low	Real	-30000.00 30000.00	rpm	100 = 1 rpm
22.55	Critical speed 2 high	Real	-30000.00 30000.00	rpm	100 = 1 rpm
22.56	Critical speed 3 low	Real	-30000.00 30000.00	rpm	100 = 1 rpm
22.57	Critical speed 3 high	Real	-30000.00 30000.00	rpm	100 = 1 rpm
22.71	Motor potentiometer function	List	02	-	1 = 1
22.72	Motor potentiometer initial value	Real	-32768.00 32767.00	-	100 = 1
22.73	Motor potentiometer up source	Binary src	-	-	1 = 1
22.74	Motor potentiometer down source	Binary src	-	-	1 = 1
22.75	Motor potentiometer ramp time	Real	0.0 3600.0	S	10 = 1 s
22.76	Motor potentiometer min value	Real	-32768.00 32767.00	-	100 = 1
22.77	Motor potentiometer max value	Real	-32768.00 32767.00	-	100 = 1
22.80	Motor potentiometer ref act	Real	-32768.00 32767.00	-	100 = 1
22.81	Speed reference act 1	Real	-30000.00 30000.00	rpm	100 = 1 rpm
22.82	Speed reference act 2	Real	-30000.00 30000.00	rpm	100 = 1 rpm
22.83	Speed reference act 3	Real	-30000.00 30000.00	rpm	100 = 1 rpm
22.84	Speed reference act 4	Real	-30000.00 30000.00	rpm	100 = 1 rpm
22.85	Speed reference act 5	Real	-30000.00 30000.00	rpm	100 = 1 rpm
22.86	Speed reference act 6	Real	-30000.00 30000.00	rpm	100 = 1 rpm
22.87	Speed reference act 7	Real	-30000.00 30000.00	rpm	100 = 1 rpm
23 Spee	d reference ramp				
23.01	Speed ref ramp input	Real	-30000.00 30000.00	rpm	100 = 1 rpm
23.02	Speed ref ramp output	Real	-30000.00 30000.00	rpm	100 = 1 rpm
23.11	Ramp set selection	Binary src	-	-	1 = 1
23.12	Acceleration time 1	Real	0.0001800.000	S	1000 = 1 s
23.13	Deceleration time 1	Real	0.0001800.000	S	1000 = 1 s
23.14	Acceleration time 2	Real	0.0001800.000	S	1000 = 1 s
23.15	Deceleration time 2	Real	0.0001800.000	S	1000 = 1 s
23.16	Shape time acc 1	Real	0.0001800.000	S	1000 = 1 s
23.17	Shape time acc 2	Real	0.0001800.000	S	1000 = 1 s
23.18	Shape time dec 1	Real	0.0001800.000	S	1000 = 1 s
23.19	Shape time dec 2	Real	0.0001800.000	S	1000 = 1 s
23.20	Acc time jogging	Real	0.0001800.000	S	1000 = 1 s
23.21	Dec time jogging	Real	0.000 1800.000	S	1000 = 1 s

No.	Name	Туре	Range	Unit	FbEq32
23.23	Emergency stop time	Real	0.000 1800.000	S	1000 = 1 s
23.24	Speed ramp in zero source	Binary src	-	-	1 = 1
23.26	Ramp out balancing enable	Binary src	-	-	1 = 1
23.27	Ramp out balancing ref	Real	-30000.00 30000.00	rpm	100 = 1 rpm
23.28	Variable slope enable	List	01	-	1 = 1
23.29	Variable slope rate	Real	230000	ms	1 = 1 ms
23.39	Follower speed correction out	Real	-30000.00 30000.00	rpm	100 = 1 rpm
23.40	Follower speed correction enable	Binary src	-	-	1 = 1
23.41	Follower speed correction gain	Real	0.00 100.00	%	100 = 1%
23.42	Follower speed corr torq source	Analog src	-	-	1 = 1
23.200	Ramp set selection	Binary src	-	-	1 = 1
23.201	Acceleration time 1	Real	0.000 1800.000	S	1000 = 1 s
23.202	Deceleration time 1	Real	0.000 1800.000	S	1000 = 1 s
23.203	Acceleration time 2	Real	0.000 1800.000	S	1000 = 1 s
23.204	Deceleration time 2	Real	0.000 1800.000	S	1000 = 1 s
24 Spee	d reference conditioning				•
24.01	Used speed reference	Real	-30000.00 30000.00	rpm	100 = 1 rpm
24.02	Used speed feedback	Real	-30000.00 30000.00	rpm	100 = 1 rpm
24.03	Speed error filtered	Real	-30000.0 30000.0	rpm	100 = 1 rpm
24.04	Speed error inverted	Real	-30000.0 30000.0	rpm	100 = 1 rpm
24.11	Speed correction	Real	-10000.0010000.00	-	100 = 1
24.12	Speed error filter time	Real	010000	ms	1 = 1 ms
24.13	RFE speed filter	List	01	-	1 = 1
24.14	Frequency of zero	Real	0.50 500.00	Hz	10 = 1 Hz
24.15	Damping of zero	Real	-1.000 1.000	-	100 = 1
24.16	Frequency of pole	Real	0.50 500.00	Hz	10 = 1 Hz
24.17	Damping of pole	Real	-1.000 1.000	-	100 = 1
24.41	Speed error window control enable	Binary src	-	-	1 = 1
24.42	Speed window control mode	List	01	-	1 = 1
24.43	Speed error window high	Real	0.00 3000.00	rpm	100 = 1 rpm
24.44	Speed error window low	Real	0.00 3000.00	rpm	100 = 1 rpm
24.46	Speed error step	Real	-3000.00 3000.00	rpm	100 = 1 rpm
25 Spee	d control				
25.01	Torque reference speed control	Real	-1600.0 1600.0	%	10 = 1%
25.02	Speed proportional gain	Real	0.00 250.00	-	100 = 1
25.03	Speed integration time	Real	0.00 1000.00	S	100 = 1 s

No.	Name	Туре	Range	Unit	FbEq32
25.04	Speed derivation time	Real	0.000 10.000	s	1000 = 1 s
25.05	Derivation filter time	Real	010000	ms	1 = 1 ms
25.06	Acc comp derivation time	Real	0.00 1000.00	S	100 = 1 s
25.07	Acc comp filter time	Real	0.0 1000.0	ms	10 = 1 ms
25.08	Drooping rate	Real	0.00 100.00	%	100 = 1%
25.09	Speed ctrl balancing enable	Binary src	-	-	1 = 1
25.10	Speed ctrl balancing ref	Real	-300.0 300.0	%	10 = 1%
25.11	Speed control min torque	Real	-1600.0 0.0	%	10 = 1%
25.12	Speed control max torque	Real	0.0 1600.0	%	10 = 1%
25.13	Min torq sp ctrl em stop	Real	-1600.0 0.0	%	10 = 1%
25.14	Max torq sp ctrl em stop	Real	0.0 1600.0	%	10 = 1%
25.15	Proportional gain em stop	Real	1.00 250.00	-	100 = 1
25.18	Speed adapt min limit	Real	030000	rpm	1 = 1 rpm
25.19	Speed adapt max limit	Real	030000	rpm	1 = 1 rpm
25.21	Kp adapt coef at min speed	Real	0.000 10.000	-	1000 = 1
25.22	Ti adapt coef at min speed	Real	0.000 10.000	-	1000 = 1
25.25	Torque adapt max limit	Real	0.0 1600.0	%	10 = 1%
25.26	Torque adapt filt time	Real	0.000 100.000	s	1000 = 1 s
25.27	Kp adapt coef at min torque	Real	0.000 10.000	-	1000 = 1
25.30	Flux adaption enable	List	01	-	1 = 1
25.33	Speed controller autotune	Binary src	-	-	1 = 1
25.34	Speed controller autotune mode	List	02	-	1 = 1
25.37	Mechanical time constant	Real	0.00 1000.00	s	100 = 1 s
25.38	Autotune torque step	Real	0.00 100.00	%	100 = 1%
25.39	Autotune speed step	Real	0.00 100.00	%	100 = 1%
25.40	Autotune repeat times	Real	110	-	1 = 1
25.53	Torque prop reference	Real	-30000.0 30000.0	%	10 = 1%
25.54	Torque integral reference	Real	-30000.0 30000.0	%	10 = 1%
25.55	Torque deriv reference	Real	-30000.0 30000.0	%	10 = 1%
25.56	Torque acc compensation	Real	-30000.0 30000.0	%	10 = 1%
25.57	Torque reference unbalanced	Real	-30000.0 30000.0	%	10 = 1%
26 Torq	ue reference chain	· · · ·		1	•
26.01	Torque reference to TC	Real	-1600.0 1600.0	%	10 = 1%
26.02	Torque reference used	Real	-1600.0 1600.0	%	10 = 1%
26.08	Minimum torque ref	Real	-1000.0 0.0	%	10 = 1%
26.09	Maximum torque ref	Real	0.0 1000.0	%	10 = 1%
26.11	Torque ref1 source	Analog src	-	-	1 = 1
26.12	Torque ref2 source	Analog src	-	-	1 = 1

No.	Name	Туре	Range	Unit	FbEq32
26.13	Torque ref1 function	List	05	-	1 = 1
26.14	Torque ref1/2 selection	Binary src	-	-	1 = 1
26.15	Load share	Real	-8.000 8.000	-	1000 = 1
26.16	Torque additive 1 source	Analog src	-	-	1 = 1
26.17	Torque ref filter time	Real	0.000 30.000	s	1000 = 1 s
26.18	Torque ramp up time	Real	0.000 60.000	S	1000 = 1 s
26.19	Torque ramp down time	Real	0.000 60.000	s	1000 = 1 s
26.25	Torque additive 2 source	Analog src	-	-	1 = 1
26.26	Force torque ref add 2 zero	Binary src	-	-	1 = 1
26.41	Torque step	Real	-300.0 300.0	%	10 = 1%
26.42	Torque step enable	List	01	-	1 = 1
26.51	Oscillation damping	Binary src	-	-	1 = 1
26.52	Oscillation damping out enable	Binary src	-	-	1 = 1
26.53	Oscillation compensation input	List	01	-	1 = 1
26.55	Oscillation damping frequency	Real	0.1 60.0	Hz	10 = 1 Hz
26.56	Oscillation damping phase	Real	0360	deg	1 = 1 deg
26.57	Oscillation damping gain	Real	0.0 100.0	%	10 = 1%
26.58	Oscillation damping output	Real	-1600.000 1600.000	%	1000 = 1%
26.70	Torque reference act 1	Real	-1600.0 1600.0	%	10 = 1%
26.71	Torque reference act 2	Real	-1600.0 1600.0	%	10 = 1%
26.72	Torque reference act 3	Real	-1600.0 1600.0	%	10 = 1%
26.73	Torque reference act 4	Real	-1600.0 1600.0	%	10 = 1%
26.74	Torque ref ramp out	Real	-1600.0 1600.0	%	10 = 1%
26.75	Torque reference act 5	Real	-1600.0 1600.0	%	10 = 1%
26.76	Torque reference act 6	Real	-1600.0 1600.0	%	10 = 1%
26.77	Torque ref add A actual	Real	-1600.0 1600.0	%	10 = 1%
26.78	Torque ref add B actual	Real	-1600.0 1600.0	%	10 = 1%
26.81	Rush control gain	Real	0.0 10000.0	-	10 = 1
26.82	Rush control integration time	Real	0.0 10.0	S	10 = 1 s
28 Freq	uency reference chain				
28.01	Frequency ref ramp input	Real	-500.00 500.00	Hz	100 = 1 Hz
28.02	Frequency ref ramp output	Real	-500.00 500.00	Hz	100 = 1 Hz
28.11	Frequency ref1 source	Analog src	-	-	1 = 1
28.12	Frequency ref2 source	Analog src	-	-	1 = 1
28.13	Frequency ref1 function	List	05	-	1 = 1

No.	Name	Туре	Range	Unit	FbEq32
28.14	Frequency ref1/2 selection	Binary src	-	-	1 = 1
28.21	Constant frequency function	PB	00b11b	-	1 = 1
28.22	Constant frequency sel1	Binary src	-	-	1 = 1
28.23	Constant frequency sel2	Binary src	-	-	1 = 1
28.24	Constant frequency sel3	Binary src	-	-	1 = 1
28.26	Constant frequency 1	Real	-500.00 500.00	Hz	100 = 1 Hz
28.27	Constant frequency 2	Real	-500.00 500.00	Hz	100 = 1 Hz
28.28	Constant frequency 3	Real	-500.00 500.00	Hz	100 = 1 Hz
28.29	Constant frequency 4	Real	-500.00 500.00	Hz	100 = 1 Hz
28.30	Constant frequency 5	Real	-500.00 500.00	Hz	100 = 1 Hz
28.31	Constant frequency 6	Real	-500.00 500.00	Hz	100 = 1 Hz
28.32	Constant frequency 7	Real	-500.00 500.00	Hz	100 = 1 Hz
28.41	Frequency ref safe	Real	-500.00 500.00	Hz	100 = 1 Hz
28.51	Critical frequency function	PB	00b11b	-	1 = 1
28.52	Critical frequency 1 low	Real	-500.00 500.00	Hz	100 = 1 Hz
28.53	Critical frequency 1 high	Real	-500.00 500.00	Hz	100 = 1 Hz
28.54	Critical frequency 2 low	Real	-500.00 500.00	Hz	100 = 1 Hz
28.55	Critical frequency 2 high	Real	-500.00 500.00	Hz	100 = 1 Hz
28.56	Critical frequency 3 low	Real	-500.00 500.00	Hz	100 = 1 Hz
28.57	Critical frequency 3 high	Real	-500.00 500.00	Hz	100 = 1 Hz
28.71	Freq ramp set selection	Binary src	-	-	1 = 1
28.72	Freq acceleration time 1	Real	0.0001800.000	S	1000 = 1 s
28.73	Freq deceleration time 1	Real	0.0001800.000	S	1000 = 1 s
28.74	Freq acceleration time 2	Real	0.0001800.000	S	1000 = 1 s
28.75	Freq deceleration time 2	Real	0.0001800.000	S	1000 = 1 s
28.76	Freq ramp in zero source	Binary src	-	-	1 = 1
28.77	Freq ramp hold	Binary src	-	-	1 = 1
28.78	Freq ramp output balancing	Real	-500.00 500.00	Hz	100 = 1 Hz
28.79	Freq ramp out balancing enable	Binary src	-	-	1 = 1
28.90	Frequency ref act 1	Real	-500.00 500.00	Hz	100 = 1 Hz
28.91	Frequency ref act 2	Real	-500.00 500.00	Hz	100 = 1 Hz
28.92	Frequency ref act 3	Real	-500.00 500.00	Hz	100 = 1 Hz
28.96	Frequency ref act 7	Real	-500.00 500.00	Hz	100 = 1 Hz
28.97	Frequency ref unlimited	Real	-500.00 500.00	Hz	100 = 1 Hz
30 Limit	S				
30.01	Limit word 1	PB	0000hFFFFh	-	1 = 1
	1				<u> </u>

No.	Name	Туре	Range	Unit	FbEq32
30.02	Torque limit status	PB	0000hFFFFh	-	1 = 1
30.11	Minimum speed	Real	-30000.00 30000.00	rpm	100 = 1 rpm
30.12	Maximum speed	Real	-30000.00 30000.00	rpm	100 = 1 rpm
30.13	Minimum frequency	Real	-500.00 500.00	Hz	100 = 1 Hz
30.14	Maximum frequency	Real	-500.00 500.00	Hz	100 = 1 Hz
30.15	Maximum start current enable	List	01	-	1 = 1
30.16	Maximum start current	Real	0.00 30000.00	Α	100 = 1 A
30.17	Maximum current	Real	0.00 30000.00	А	100 = 1 A
30.18	Minimum torque sel	Binary src	-	-	1 = 1
30.19	Minimum torque 1	Real	-1600.0 1600.0	%	10 = 1%
30.20	Maximum torque 1	Real	-1600.0 1600.0	%	10 = 1%
30.21	Minimum torque 2 source	Analog src	-	-	1 = 1
30.22	Maximum torque 2 source	Analog src	-	-	1 = 1
30.23	Minimum torque 2	Real	-1600.0 0.0	%	10 = 1%
30.24	Maximum torque 2	Real	0.0 1600.0	%	10 = 1%
30.25	Maximum torque sel	Binary src	-	-	1 = 1
30.26	Power motoring limit	Real	0.00 600.00	%	100 = 1%
30.27	Power generating limit	Real	-600.00 0.00	%	100 = 1%
30.30	Overvoltage control	List	01	-	1 = 1
30.31	Undervoltage control	List	01	-	1 = 1
	(Parameters 30.10130.149 or	nly visible w	hen IGBT supply unit control	activated b	y 95.20)
30.101	LSU limit word 1	PB	0000hFFFFh	-	1 = 1
30.102	LSU limit word 2	PB	0000hFFFFh	-	1 = 1
30.103	LSU limit word 3	PB	0000hFFFFh	-	1 = 1
30.104	LSU limit word 4	PB	0000hFFFFh	-	1 = 1
30.148	LSU minimum power limit	Real	-200.0 0.0	%	10 = 1%
30.149	LSU maximum power limit	Real	0.0 200.0	%	10 = 1%
31 Fault	functions				
31.01	External event 1 source	Binary src	-	-	1 = 1
31.02	External event 1 type	List	03	-	1 = 1
31.03	External event 2 source	Binary src	-	-	1 = 1
31.04	External event 2 type	List	03	-	1 = 1
31.05	External event 3 source	Binary src	-	-	1 = 1
31.06	External event 3 type	List	03	-	1 = 1
31.07	External event 4 source	Binary src	-	-	1 = 1
31.08	External event 4 type	List	03	-	1 = 1

No.	Name	Туре	Range	Unit	FbEq32
31.09	External event 5 source	Binary src	-	-	1 = 1
31.10	External event 5 type	List	03	-	1 = 1
31.11	Fault reset selection	Binary src	-	-	1 = 1
31.12	Autoreset selection	PB	0000hFFFFh	-	1 = 1
31.13	User selectable fault	Real	0000hFFFFh	-	1 = 1
31.14	Number of trials	Real	05	-	1 = 1
31.15	Total trials time	Real	1.0 600.0	S	10 = 1 s
31.16	Delay time	Real	0.0 120.0	S	10 = 1 s
31.19	Motor phase loss	List	01	-	1 = 1
31.20	Earth fault	List	02	-	1 = 1
31.21	Supply phase loss	List	01	-	1 = 1
31.22	STO indication run/stop	List	05	-	1 = 1
31.23	Wiring or earth fault	List	01	-	1 = 1
31.24	Stall function	List	02	-	1 = 1
31.25	Stall current limit	Real	0.0 1600.0	%	10 = 1%
31.26	Stall speed limit	Real	0.0 10000.0	rpm	100 = 1 rpm
31.27	Stall frequency limit	Real	0.00 500.00	Hz	100 = 1 Hz
31.28	Stall time	Real	03600	S	1 = 1 s
31.30	Overpeed trip margin	Real	010000	rpm	100 = 1 rpm
31.32	Emergency ramp supervision	Real	0300	%	1 = 1%
31.33	Emergency ramp supervision delay	Real	032767	s	1 = 1 s
31.35	Main fan fault function	List	02	-	1 = 1
31.36	Aux fan fault bypass	List	01	-	1 = 1
31.37	Ramp stop supervision	Real	0300	%	1 = 1%
31.38	Ramp stop supervision delay	Real	032767	S	1 = 1 s
31.40	Disable warning messages	PB	0000hFFFFh	-	1 = 1
31.42	Overcurrent fault limit	Real	0.00 30000.00	A	100 = 1 A
	(Parameters 31.12031.121 or	nly visible w	hen IGBT supply unit control	activated b	y 95.20)
31.120	LSU earth fault	List	01	-	1 = 1
31.121	LSU supply phase loss	List	01	-	1 = 1
32 Supe	ervision				
32.01	Supervision status	PB	000b111b	-	1 = 1
32.05	Supervision 1 function	List	06	-	1 = 1
32.06	Supervision 1 action	List	03	-	1 = 1
32.07	Supervision 1 signal	Analog src	-	-	1 = 1
32.08	Supervision 1 filter time	Real	0.000 30.000	S	1000 = 1 s
32.09	Supervision 1 low	Real	-21474830.00 21474830.00	-	100 = 1

No.	Name	Туре	Range	Unit	FbEq32
32.10	Supervision 1 high	Real	-21474830.00 21474830.00	-	100 = 1
32.15	Supervision 2 function	List	06	-	1 = 1
32.16	Supervision 2 action	List	03	-	1 = 1
32.17	Supervision 2 signal	Analog src	-	-	1 = 1
32.18	Supervision 2 filter time	Real	0.000 30.000	s	1000 = 1 s
32.19	Supervision 2 low	Real	-21474830.00 21474830.00	-	100 = 1
32.20	Supervision 2 high	Real	-21474830.00 21474830.00	-	100 = 1
32.25	Supervision 3 function	List	06	-	1 = 1
32.26	Supervision 3 action	List	03	-	1 = 1
32.27	Supervision 3 signal	Analog src	-	-	1 = 1
32.28	Supervision 3 filter time	Real	0.000 30.000	s	1000 = 1 s
32.29	Supervision 3 low	Real	-21474830.00 21474830.00	-	100 = 1
32.30	Supervision 3 high	Real	21474830.00 21474830.00	-	100 = 1
33 Gene	eric timer & counter	<u>.</u>			
33.01	Counter status	PB	000000b111111b	-	1 = 1
33.10	On-time 1 actual	Real	04294967295	S	1 = 1 s
33.11	On-time 1 warn limit	Real	04294967295	s	1 = 1 s
33.12	On-time 1 function	PB	00b11b	-	1 = 1
33.13	On-time 1 source	Binary src	-	-	1 = 1
33.14	On-time 1 warn message	List	-	-	1 = 1
33.20	On-time 2 actual	Real	04294967295	S	1 = 1 s
33.21	On-time 2 warn limit	Real	04294967295	S	1 = 1 s
33.22	On-time 2 function	PB	00b11b	-	1 = 1
33.23	On-time 2 source	Binary src	-	-	1 = 1
33.24	On-time 2 warn message	List	-	-	1 = 1
33.30	Edge counter 1 actual	Real	04294967295	-	1 = 1
33.31	Edge counter 1 warn limit	Real	04294967295	-	1 = 1
33.32	Edge counter 1 function	PB	0000b1111b	-	1 = 1
33.33	Edge counter 1 source	Binary src	-	-	1 = 1
33.34	Edge counter 1 divider	Real	14294967295	-	1 = 1
33.35	Edge counter 1 warn message	List	-	-	1 = 1
33.40	Edge counter 2 actual	Real	04294967295	-	1 = 1
33.41	Edge counter 2 warn limit	Real	04294967295	-	1 = 1
	Edge counter 2 function	PB	0000b1111b	1	1 = 1

No.	Name	Туре	Range	Unit	FbEq32
33.43	Edge counter 2 source	Binary src	-	-	1 = 1
33.44	Edge counter 2 divider	Real	14294967295	-	1 = 1
33.45	Edge counter 2 warn message	List	-	-	1 = 1
33.50	Value counter 1 actual	Real	-2147483008 2147483008	-	1 = 1
33.51	Value counter 1 warn limit	Real	-2147483008 2147483008	-	1 = 1
33.52	Value counter 1 function	PB	00b11b	-	1 = 1
33.53	Value counter 1 source	Analog src	-	-	1 = 1
33.54	Value counter 1 divider	Real	0.001 2147483.000	-	1000 = 1
33.55	Value counter 1 warn message	List	-	-	1 = 1
33.60	Value counter 2 actual	Real	-2147483008 2147483008	-	1 = 1
33.61	Value counter 2 warn limit	Real	-2147483008 2147483008	-	1 = 1
33.62	Value counter 2 function	PB	00b11b	-	1 = 1
33.63	Value counter 2 source	Analog src	-	-	1 = 1
33.64	Value counter 2 divider	Real	0.001 2147483.000	-	1000 = 1
33.65	Value counter 2 warn message	List	-	-	1 = 1
35 Moto	r thermal protection				
35.01	Motor estimated temperature	Real	-60 1000	°C or °F	1 = 1 °
35.02	Measured temperature 1	Real	-60 … 1000 °C, -76 … 1832 °F, 0…5000 ohm	°C, °F or ohm	1 = 1 unit
35.03	Measured temperature 2	Real	-60 … 1000 °C, -76 … 1832 °F, 0…5000 ohm	°C, °F or ohm	1 = 1 unit
35.04	FPTC status word	PB	0000hFFFFh	-	1 = 1
35.11	Temperature 1 source	List	011	-	1 = 1
35.12	Temperature 1 fault limit	Real	-60 … 1000 °C, -76 … 1832 °F or 0…5000 ohm	°C, °F or ohm	1 = 1 unit
35.13	Temperature 1 warning limit	Real	-60 … 1000 °C, -76 … 1832 °F or 0…5000 ohm	°C, °F or ohm	1 = 1 unit
35.14	Temperature 1 AI source	Analog src	-	-	1 = 1
35.21	Temperature 2 source	List	011	-	1 = 1
35.22	Temperature 2 fault limit	Real	-60 … 1000 °C, -76 … 1832 °F or 0…5000 ohm	°C, °F or ohm	1 = 1 unit

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No.	Name	Туре	Range	Unit	FbEq32
35.23	Temperature 2 warning limit	Real	-60 … 1000 °C,	°C, °F or	1 = 1 unit
			-76 … 1832 °F or	ohm	
			05000 ohm		
35.24	Temperature 2 AI source	Analog src	-	-	1 = 1
35.30	FPTC configuration word	PB	0000hFFFFh	-	1 = 1
35.50	Motor ambient temperature	Real	-60 … 100 °C or -76 … 212 °F	°C or °F	1 = 1 °C
35.51	Motor load curve	Real	50150	%	1 = 1%
35.52	Zero speed load	Real	50150	%	1 = 1%
35.53	Break point	Real	1.00 500.00	Hz	100 = 1 Hz
35.54	Motor nominal temperature rise	Real	0300 °C or 32572 °F	°C or °F	1 = 1°
35.55	Motor thermal time constant	Real	10010000	S	1 = 1 s
35.60	Cable temperature	Real	0.0 200.0	%	10 = 1%
35.61	Cable nominal current	Real	0.00 10000.0	Α	100 = 1 A
35.62	Cable thermal rise time	Real	050000	S	1 = 1 s
35.100	DOL starter control source	Binary src	-	-	1 = 1
35.101	DOL starter on delay	Real	042949673	S	1 = 1 s
35.102	DOL starter off delay	Real	0715828	min	1 = 1 min
35.103	DOL starter feedback source	Binary src	-	-	1 = 1
35.104	DOL starter feedback delay	Real	042949673	s	1 = 1 s
35.105	DOL starter status word	PB	0000b1111b	-	1 = 1
35.106	DOL starter event type	List	02	-	1 = 1
36 Load	l analyzer	1			
36.01	PVL signal source	Analog src	-	-	1 = 1
36.02	PVL filter time	Real	0.00 120.00	S	100 = 1 s
36.06	AL2 signal source	Analog src	-	-	1 = 1
36.07	AL2 signal scaling	Real	0.00 32767.00	-	100 = 1
36.09	Reset loggers	List	03	-	1 = 1
36.10	PVL peak value	Real	-32768.00 32767.00	-	100 = 1
36.11	PVL peak date	Data	-	-	1 = 1
36.12	PVL peak time	Data	-	-	1 = 1
36.13	PVL current at peak	Real	-32768.00 32767.00	A	100 = 1 A
36.14	PVL DC voltage at peak	Real	0.00 2000.00	V	100 = 1 V
36.15	PVL speed at peak	Real	-32768.00 32767.00	rpm	100 = 1 rpm
36.16	PVL reset date	Data	-	-	1 = 1
36.17	PVL reset time	Data	-	-	1 = 1
36.20	AL1 below 10%	Real	0.00 100.00	%	100 = 1%

No.	Name	Туре	Range	Unit	FbEq32
36.21	AL1 10 to 20%	Real	0.00 100.00	%	100 = 1%
36.22	AL1 20 to 30%	Real	0.00 100.00	%	100 = 1%
36.23	AL1 30 to 40%	Real	0.00 100.00	%	100 = 1%
36.24	AL1 40 to 50%	Real	0.00 100.00	%	100 = 1%
36.25	AL1 50 to 60%	Real	0.00 100.00	%	100 = 1%
36.26	AL1 60 to 70%	Real	0.00 100.00	%	100 = 1%
36.27	AL1 70 to 80%	Real	0.00 100.00	%	100 = 1%
36.28	AL1 80 to 90%	Real	0.00 100.00	%	100 = 1%
36.29	AL1 over 90%	Real	0.00 100.00	%	100 = 1%
36.40	AL2 below 10%	Real	0.00 100.00	%	100 = 1%
36.41	AL2 10 to 20%	Real	0.00 100.00	%	100 = 1%
36.42	AL2 20 to 30%	Real	0.00 100.00	%	100 = 1%
36.43	AL2 30 to 40%	Real	0.00 100.00	%	100 = 1%
36.44	AL2 40 to 50%	Real	0.00 100.00	%	100 = 1%
36.45	AL2 50 to 60%	Real	0.00 100.00	%	100 = 1%
36.46	AL2 60 to 70%	Real	0.00 100.00	%	100 = 1%
36.47	AL2 70 to 80%	Real	0.00 100.00	%	100 = 1%
36.48	AL2 80 to 90%	Real	0.00 100.00	%	100 = 1%
36.49	AL2 over 90%	Real	0.00 100.00	%	100 = 1%
36.50	AL2 reset date	Data	-	-	1 = 1
36.51	AL2 reset time	Data	-	-	1 = 1
37 User	load curve				•
37.01	ULC output status word	PB	0000hFFFFh	-	1 = 1
37.02	ULC supervision signal	List	-	-	1 = 1
37.03	ULC overload actions	List	03	-	1 = 1
37.04	ULC underload actions	List	03	-	1 = 1
37.11	ULC speed table point 1	Real	0.0 30000.0	rpm	10 = 1 rpm
37.12	ULC speed table point 2	Real	0.0 30000.0	rpm	10 = 1 rpm
37.13	ULC speed table point 3	Real	0.0 30000.0	rpm	10 = 1 rpm
37.14	ULC speed table point 4	Real	0.0 30000.0	rpm	10 = 1 rpm
37.15	ULC speed table point 5	Real	0.0 30000.0	rpm	10 = 1 rpm
37.16	ULC frequency table point 1	Real	0.0 500.0	Hz	10 = 1 Hz
37.17	ULC frequency table point 2	Real	0.0 500.0	Hz	10 = 1 Hz
37.18	ULC frequency table point 3	Real	0.0 500.0	Hz	10 = 1 Hz
37.19	ULC frequency table point 4	Real	0.0 500.0	Hz	10 = 1 Hz
37.20	ULC frequency table point 5	Real	0.0 500.0	Hz	10 = 1 Hz
37.21	ULC underload point 1	Real	0.0 1600.0	%	10 = 1%
37.22	ULC underload point 2	Real	0.0 1600.0	%	10 = 1%
37.23	ULC underload point 3	Real	0.0 1600.0	%	10 = 1%
37.24	ULC underload point 4	Real	0.0 1600.0	%	10 = 1%
37.25	ULC underload point 5	Real	0.0 1600.0	%	10 = 1%

No.	Name	Туре	Range	Unit	FbEq32
37.31	ULC overload point 1	Real	0.0 1600.0	%	10 = 1%
37.32	ULC overload point 2	Real	0.0 1600.0	%	10 = 1%
37.33	ULC overload point 3	Real	0.0 1600.0	%	10 = 1%
37.34	ULC overload point 4	Real	0.0 1600.0	%	10 = 1%
37.35	ULC overload point 5	Real	0.0 1600.0	%	10 = 1%
37.41	ULC overload timer	Real	0.0 10000.0	S	10 = 1 s
37.42	ULC underload timer	Real	0.0 10000.0	s	10 = 1 s
40 Proc	ess PID set 1			1	
40.01	Process PID output actual	Real	-32768.00 32767.00	rpm, % or Hz	100 = 1 rpm, % or Hz
40.02	Process PID feedback actual	Real	-32768.00 32767.00	rpm, % or Hz	100 = 1 rpm, % or Hz
40.03	Process PID setpoint actual	Real	-32768.00 32767.00	rpm, % or Hz	100 = 1 rpm, % or Hz
40.04	Process PID deviation actual	Real	-32768.00 32767.00	rpm, % or Hz	100 = 1 rpm, % or Hz
40.05	Process PID trim output act	Real	-32768.00 32767.00	rpm, % or Hz	100 = 1 rpm, % or Hz
40.06	Process PID status word	PB	0000hFFFFh	-	1 = 1
40.07	Set 1 PID operation mode	List	02	-	1 = 1
40.08	Set 1 feedback 1 source	Analog src	-	-	1 = 1
40.09	Set 1 feedback 2 source	Analog src	-	-	1 = 1
40.10	Set 1 feedback function	List	011	-	1 = 1
40.11	Set 1 feedback filter time	Real	0.000 30.000	s	1000 = 1 s
40.12	Set 1 unit selection	List	02	-	1 = 1
40.14	Set 1 setpoint scaling	Real	-32768.00 32767.00	-	100 = 1
40.15	Set 1 output scaling	Real	-32768.00 32767.00	-	100 = 1
40.16	Set 1 setpoint 1 source	Analog src	-	-	1 = 1
40.17	Set 1 setpoint 2 source	Analog src	-	-	1 = 1
40.18	Set 1 setpoint function	List	011	-	1 = 1
40.19	Set 1 internal setpoint sel1	Binary src	-	-	1 = 1
40.20	Set 1 internal setpoint sel2	Binary src	-	-	1 = 1
40.21	Set 1 internal setpoint 1	Real	-32768.00 32767.00	rpm, % or Hz	100 = 1 rpm, % or Hz
40.22	Set 1 internal setpoint 2	Real	-32768.00 32767.00	rpm, % or Hz	100 = 1 rpm, % or Hz
40.23	Set 1 internal setpoint 3	Real	-32768.00 32767.00	rpm, % or Hz	100 = 1 rpm, % or Hz
40.24	Set 1 internal setpoint 4	Real	-32768.00 32767.00	rpm, % or Hz	100 = 1 rpm, % or Hz

No.	Name	Туре	Range	Unit	FbEq32
40.25	Set 1 setpoint selection	Binary src	-	-	1 = 1
40.26	Set 1 setpoint min	Real	-32768.00 32767.00	-	100 = 1
40.27	Set 1 setpoint max	Real	-32768.00 32767.00	-	100 = 1
40.28	Set 1 setpoint increase time	Real	0.0 1800.0	s	10 = 1 s
40.29	Set 1 setpoint decrease time	Real	0.0 1800.0	s	10 = 1 s
40.30	Set 1 setpoint freeze enable	Binary src	-	-	1 = 1
40.31	Set 1 deviation inversion	Binary src	-	-	1 = 1
40.32	Set 1 gain	Real	0.10 100.00	-	100 = 1
40.33	Set 1 integration time	Real	0.0 32767.0	S	10 = 1 s
40.34	Set 1 derivation time	Real	0.000 10.000	S	1000 = 1 s
40.35	Set 1 derivation filter time	Real	0.0 10.0	s	10 = 1 s
40.36	Set 1 output min	Real	-32768.0 32767.0	-	10 = 1
40.37	Set 1 output max	Real	-32768.0 32767.0	-	10 = 1
40.38	Set 1 output freeze enable	Binary src	-	-	1 = 1
40.39	Set 1 deadband range	Real	0.0 32767.0	-	10 = 1
40.40	Set 1 deadband delay	Real	0.0 3600.0	S	10 = 1 s
40.41	Set 1 sleep mode	List	02	-	1 = 1
40.42	Set 1 sleep enable	Binary src	-	-	1 = 1
40.43	Set 1 sleep level	Real	0.0 32767.0	-	10 = 1
40.44	Set 1 sleep delay	Real	0.0 3600.0	s	10 = 1 s
40.45	Set 1 sleep boost time	Real	0.0 3600.0	S	10 = 1 s
40.46	Set 1 sleep boost step	Real	0.0 32767.0	-	10 = 1
40.47	Set 1 wake-up deviation	Real	-32768.00 32767.00	rpm, % or Hz	100 = 1 rpm, % or Hz
40.48	Set 1 wake-up delay	Real	0.00 60.00	s	100 = 1 s
40.49	Set 1 tracking mode	Binary src	-	-	1 = 1
40.50	Set 1 tracking ref selection	Analog src	-	-	1 = 1
40.51	Set 1 trim mode	List	03	-	1 = 1
40.52	Set 1 trim selection	List	13	-	1 = 1
40.53	Set 1 trimmed ref pointer	Analog src	-	-	1 = 1
40.54	Set 1 trim mix	Real	0.000 1.000	-	1000 = 1
40.55	Set 1 trim adjust	Real	-100.000 100.000	-	1000 = 1
40.56	Set 1 trim source	List	12	-	1 = 1
40.57	PID set1/set2 selection	Binary src	-	-	1 = 1
40.60	Set 1 PID activation source	Binary src	-	-	1 = 1

No.	Name	Туре	Range	Unit	FbEq32			
40.91	Feedback data storage	Real	-327.68 327.67	-	100 = 1			
40.92	Setpoint data storage	Real	-327.68 327.67	-	100 = 1			
41 Proc	41 Process PID set 2							
41.07	Set 2 PID operation mode	List	02	-	1 = 1			
41.08	Set 2 feedback 1 source	Analog src	-	-	1 = 1			
41.09	Set 2 feedback 2 source	Analog src	-	-	1 = 1			
41.10	Set 2 feedback function	List	011	-	1 = 1			
41.11	Set 2 feedback filter time	Real	0.000 30.000	S	1000 = 1 s			
41.12	Set 2 unit selection	List	02	-	1 = 1			
41.14	Set 2 setpoint scaling	Real	-32768 32767	-	100 = 1			
41.15	Set 2 output scaling	Real	-32768 32767	-	100 = 1			
41.16	Set 2 setpoint 1 source	Analog src	-	-	1 = 1			
41.17	Set 2 setpoint 2 source	Analog src	-	-	1 = 1			
41.18	Set 2 setpoint function	List	011	-	1 = 1			
41.19	Set 2 internal setpoint sel1	Binary src	-	-	1 = 1			
41.20	Set 2 internal setpoint sel2	Binary src	-	-	1 = 1			
41.21	Set 2 internal setpoint 1	Real	-32768.0 32767.0	rpm, % or Hz	100 = 1 rpm, % or Hz			
41.22	Set 2 internal setpoint 2	Real	-32768.0 32767.0	rpm, % or Hz	100 = 1 rpm, % or Hz			
41.23	Set 2 internal setpoint 3	Real	-32768.0 32767.0	rpm, % or Hz	100 = 1 rpm, % or Hz			
41.24	Set 2 internal setpoint 4	Real	-32768.0 32767.0	rpm, % or Hz	100 = 1 rpm, % or Hz			
41.25	Set 2 setpoint selection	Binary src	-	-	1 = 1			
41.26	Set 2 setpoint min	Real	-32768.0 32767.0	-	100 = 1			
41.27	Set 2 setpoint max	Real	-32768.0 32767.0	-	100 = 1			
41.28	Set 2 setpoint increase time	Real	0.0 1800.0	S	10 = 1 s			
41.29	Set 2 setpoint decrease time	Real	0.0 1800.0	S	10 = 1 s			
41.30	Set 2 setpoint freeze enable	Binary src	-	-	1 = 1			
41.31	Set 2 deviation inversion	Binary src	-	-	1 = 1			
41.32	Set 2 gain	Real	0.1 100.0	-	100 = 1			
41.33	Set 2 integration time	Real	0.0 3600.0	S	10 = 1 s			
41.34	Set 2 derivation time	Real	0.0 10.0	S	1000 = 1 s			
41.35	Set 2 derivation filter time	Real	0.0 10.0	S	10 = 1 s			
41.36	Set 2 output min	Real	-32768.0 32767.0	-	10 = 1			

No.	Name	Туре	Range	Unit	FbEq32
41.37	Set 2 output max	Real	-32768.0 32767.0	-	10 = 1
41.38	Set 2 output freeze enable	Binary src	-	-	1 = 1
41.39	Set 2 deadband range	Real	0.0 32767.0	-	10 = 1
41.40	Set 2 deadband delay	Real	0.0 3600.0	S	10 = 1 s
41.41	Set 2 sleep mode	List	02	-	1 = 1
41.42	Set 2 sleep enable	Binary src	-	-	1 = 1
41.43	Set 2 sleep level	Real	0.0 32767.0	-	10 = 1
41.44	Set 2 sleep delay	Real	0.0 3600.0	S	10 = 1 s
41.45	Set 2 sleep boost time	Real	0.0 3600.0	s	10 = 1 s
41.46	Set 2 sleep boost step	Real	0.0 32767.0	-	10 = 1
41.47	Set 2 wake-up deviation	Real	-32768.00 32767.00	rpm, % or Hz	100 = 1 rpm, % or Hz
41.48	Set 2 wake-up delay	Real	0.00 60.00	S	100 = 1 s
41.49	Set 2 tracking mode	Binary src	-	-	1 = 1
41.50	Set 2 tracking ref selection	Analog src	-	-	1 = 1
41.51	Set 2 trim mode	List	03	-	1 = 1
41.52	Set 2 trim selection	List	13	-	1 = 1
41.53	Set 2 trimmed ref pointer	Analog src	-	-	1 = 1
41.54	Set 2 trim mix	Real	0.000 1.000	-	1000 = 1
41.55	Set 2 trim adjust	Real	-100.000 100.000	-	1000 = 1
41.56	Set 2 trim source	List	12	-	1 = 1
41.60	Set 2 PID activation source	Binary src	-	-	1 = 1
43 Brak	e chopper				
43.01	Braking resistor temperature	Real	0.0 120.0	%	10 = 1%
43.06	Brake chopper function	List	03	-	1 = 1
43.07	Brake chopper run enable	Binary src	-	-	1 = 1
43.08	Brake resistor thermal tc	Real	010000	S	1 = 1 s
43.09	Brake resistor Pmax cont	Real	0.10 10000.00	kW	100 = 1 kW
43.10	Brake resistance	Real	0.01000.0	ohm	10 = 1 ohm
43.11	Brake resistor fault limit	Real	0150	%	1 = 1%
43.12	Brake resistor warning limit	Real	0150	%	1 = 1%
44 Mech	nanical brake control				
44.01	Brake control status	PB	00000000b11111111b	-	1 = 1
44.02	Brake torque memory	Real	-1600.0 1600.0	%	10 = 1%
44.03	Brake open torque reference	Real	-1600.0 1600.0	%	10 = 1%
44.06	Brake control enable	Binary src	-	-	1 = 1

No.	Name	Туре	Range	Unit	FbEq32
44.07	Brake acknowledge selection	Binary src	-	-	1 = 1
44.08	Brake open delay	Real	0.00 5.00	S	100 = 1 s
44.09	Brake open torque source	Analog src	-	-	1 = 1
44.10	Brake open torque	Real	-10001000	%	10 = 1%
44.11	Keep brake closed	Binary src	-	-	1 = 1
44.12	Brake close request	Binary src	-	-	1 = 1
44.13	Brake close delay	Real	0.00 60.00	S	100 = 1 s
44.14	Brake close level	Real	0.0 1000.0	rpm	100 = 1 rpm
44.15	Brake close level delay	Real	0.00 10.00	S	100 = 1 s
44.16	Brake reopen delay	Real	0.00 10.00	S	100 = 1 s
44.17	Brake fault function	List	02	-	1 = 1
44.18	Brake fault delay	Real	0.00 60.00	S	100 = 1 s
45 Ener	gy efficiency				
45.01	Saved GW hours	Real	065535	GWh	1 = 1 GWh
45.02	Saved MW hours	Real	0999	MWh	1 = 1 MWh
45.03	Saved kW hours	Real	0.0 999.0	kWh	10 = 1 kWh
45.05	Saved money x1000	Real	04294967295	thousand	1 = 1 thousand
45.06	Saved money	Real	0.00 999.99	(selecta- ble)	100 = 1 unit
45.08	CO2 reduction in kilotons	Real	065535	metric kiloton	1 = 1 metric kiloton
45.09	CO2 reduction in tons	Real	0.0 999.9	metric ton	10 = 1 metric ton
45.11	Energy optimizer	List	01	-	1 = 1
45.12	Energy tariff 1	Real	0.000 4294967.295	(selecta- ble)	1000 = 1 unit
45.13	Energy tariff 2	Real	0.000 4294967.295	(selecta- ble)	1000 = 1 unit
45.14	Tariff selection	Binary src	-	-	1 = 1
45.17	Tariff currency unit	List	100102	-	1 = 1
45.18	CO2 conversion factor	Real	0.000 65.535	metric ton/ MWh	1000 = 1 metric ton/MWh
45.19	Comparison power	Real	0.0 100000.0	kW	10 = 1 kW
45.21	Energy calculations reset	List	01	-	1 = 1
46 Mon	itoring/scaling settings				·
46.01	Speed scaling	Real	0.10 30000.00	rpm	100 = 1 rpm
46.02	Frequency scaling	Real	0.10 1000.00	Hz	100 = 1 Hz
46.03	Torque scaling	Real	0.1 1000.0	%	10 = 1%

No.	Name	Туре	Range	Unit	FbEq32
46.04	Power scaling	Real	0.10 30000.00 kW or 0.10 40214.48 hp	kW or hp	100 = 1 unit
46.05	Current scaling	Real	030000	А	1 = 1 A
46.06	Speed ref zero scaling	Real	0.00 30000.00	rpm	100 = 1 rpm
46.07	Frequency ref zero scaling	Real	0.00 1000.00	Hz	100 = 1 Hz
46.11	Filter time motor speed	Real	020000	ms	1 = 1 ms
46.12	Filter time output frequency	Real	020000	ms	1 = 1 ms
46.13	Filter time motor torque	Real	020000	ms	1 = 1 ms
46.14	Filter time power out	Real	020000	ms	1 = 1 ms
46.21	At speed hysteresis	Real	0.00 30000.00	rpm	100 = 1 rpm
46.22	At frequency hysteresis	Real	0.00 1000.00	Hz	100 = 1 Hz
46.23	At torque hysteresis	Real	0.0 300.0	%	1 = 1%
46.31	Above speed limit	Real	0.00 30000.00	rpm	100 = 1 rpm
46.32	Above frequency limit	Real	0.00 1000.00	Hz	100 = 1 Hz
46.33	Above torque limit	Real	0.00 3000.00	%	1 = 1%
46.42	Torque decimals	List	02	-	1 = 1
47 Data	storage				
47.01	Data storage 1 real32	Real	Defined by 47.31	-	1000 = 1
47.02	Data storage 2 real32	Real	Defined by 47.32	-	1000 = 1
47.03	Data storage 3 real32	Real	Defined by 47.33	-	1000 = 1
47.04	Data storage 4 real32	Real	Defined by 47.34	-	1000 = 1
47.05	Data storage 5 real32	Real	Defined by 47.35	-	1000 = 1
47.06	Data storage 6 real32	Real	Defined by 47.36	-	1000 = 1
47.07	Data storage 7 real32	Real	Defined by 47.37	-	1000 = 1
47.08	Data storage 8 real32	Real	Defined by 47.38	-	1000 = 1
47.11	Data storage 1 int32	Real	-2147483648 2147483647	-	1 = 1
47.12	Data storage 2 int32	Real	-2147483648 2147483647	-	1 = 1
47.13	Data storage 3 int32	Real	-2147483648 2147483647	-	1 = 1
47.14	Data storage 4 int32	Real	-2147483648 2147483647	-	1 = 1
47.15	Data storage 5 int32	Real	-2147483648 2147483647	-	1 = 1
47.16	Data storage 6 int32	Real	-2147483648 2147483647	-	1 = 1
47.17	Data storage 7 int32	Real	-2147483648 2147483647	-	1 = 1
47.18	Data storage 8 int32	Real	-2147483648 2147483647	-	1 = 1
47.21	Data storage 1 int16	Real	-32768 32767	-	1 = 1
47.22	Data storage 2 int16	Real	-32768 32767	-	1 = 1
47.23	Data storage 3 int16	Real	-32768 32767	-	1 = 1

No.	Name	Туре	Range	Unit	FbEq32
47.24	Data storage 4 int16	Real	-32768 32767	-	1 = 1
47.25	Data storage 5 int16	Real	-32768 32767	-	1 = 1
47.26	Data storage 6 int16	Real	-32768 32767	-	1 = 1
47.27	Data storage 7 int16	Real	-32768 32767	-	1 = 1
47.28	Data storage 8 int16	Real	-32768 32767	-	1 = 1
47.31	Data storage 1 real32 type	List	05	-	1 = 1
47.32	Data storage 2 real32 type	List	05	-	1 = 1
47.33	Data storage 3 real32 type	List	05	-	1 = 1
47.34	Data storage 4 real32 type	List	05	-	1 = 1
47.35	Data storage 5 real32 type	List	05	-	1 = 1
47.36	Data storage 6 real32 type	List	05	-	1 = 1
47.37	Data storage 7 real32 type	List	05	-	1 = 1
47.38	Data storage 8 real32 type	List	05	-	1 = 1
49 Pane	I port communication				1
49.01	Node ID number	Real	132	-	1 = 1
49.03	Baud rate	List	15	-	1 = 1
49.04	Communication loss time	Real	0.3 3000.0	S	10 = 1 s
49.05	Communication loss action	List	05	-	1 = 1
49.06	Refresh settings	List	01	-	1 = 1
49.07	Panel comm supervision force	PB	0000hFFFFh	-	1 = 1
49.08	Secondary comm. loss action	List	05	-	1 = 1
49.14	Panel speed reference unit	List	01	-	1 = 1
49.15	Minimum ext speed ref panel	Real	-30000.00 30000.00	-	100 = 1
49.16	Maximum ext speed ref panel	Real	-30000.00 30000.00	-	100 = 1
49.17	Minimum ext frequency ref panel	Real	-500.00 500.00	Hz	100 = 1 Hz
49.18	Maximum ext frequency ref panel	Real	-500.00 500.00	Hz	100 = 1 Hz
49.24	Panel actual source	Analog src	-	-	1 = 1
50 Field	bus adapter (FBA)				
50.01	FBA A enable	List	03	-	1 = 1
50.02	FBAA comm loss func	List	05	-	1 = 1
50.03	FBAA comm loss t out	Real	0.3 6553.5	S	10 = 1 s
50.04	FBAA ref1 type	List	05	-	1 = 1
50.05	FBAA ref2 type	List	05	-	1 = 1
50.07	FBAA actual 1 type	List	06	-	1 = 1
50.08	FBAA actual 2 type	List	06	-	1 = 1
50.09	FBAA SW transparent source	Analog src	-	-	1 = 1
50.10	FBAA act1 transparent source	Analog src	-	-	1 = 1

50.11 FBA A act2 transparent source src Analog src - 1 = 1 50.12 FBA A debug mode List 01 - 1 = 1 50.13 FBA A control word Data 0000000h FFFFFFFh - 1 = 1 50.14 FBA A reference 1 Real -2147483648 2147483647 - 1 = 1 50.15 FBA A status word Data 0000000h FFFFFFFh - 1 = 1 50.16 FBA A status word Data 0000000h FFFFFFFh - 1 = 1 50.16 FBA A actual value 1 Real -2147483648 2147483647 - 1 = 1 50.17 FBA A actual value 2 Real -2147483648 2147483647 - 1 = 1 50.21 FBA A coulal value 2 Real 0.2147483648 2147483647 - 1 = 1 50.21 FBA A itmelevel sel List 01 - 1 = 1 50.23 FBA B corm loss timeout List 05 - 1 = 1 50.34 FBA B actual 1 type List 06 - 1 = 1 50.35 FBA B actual 2 ty	No.	Name	Туре	Range	Unit	FbEq32
50.12 FBAA debug mode List 01 - 1 = 1 50.13 FBAA control word Data 00000000h FFFFFFFh - 1 = 1 50.14 FBAA reference 1 Real -2147483647 - 1 = 1 50.15 FBAA reference 2 Real -2147483647 - 1 = 1 50.16 FBAA status word Data 00000000h FFFFFFFFh - 1 = 1 50.16 FBAA actual value 1 Real -2147483647 - 1 = 1 50.17 FBAA actual value 2 Real -2147483648 - 1 = 1 50.18 FBAA actual value 2 Real -2147483647 - 1 = 1 50.21 FBAA timelevel sel List 03 - 1 = 1 50.23 FBAA comm supervision force PB 0000hFFFFh - 1 = 1 50.34 FBA B comm loss func Real 05 - 1 = 1 50.35 FBA B actual 1 type List 05 - 1 = 1	50.11	FBAA act2 transparent source	-	-	-	1 = 1
50.13 FBAA control word Data 00000000hFFFFFFFh - 1 = 1 50.14 FBAA reference 1 Real -2147483648 2147483647 - 1 = 1 50.15 FBAA reference 2 Real -2147483648 2147483647 - 1 = 1 50.16 FBAA status word Data 00000000hFFFFFFF - 1 = 1 50.17 FBAA actual value 1 Real -2147483647 - 1 = 1 50.18 FBAA actual value 2 Real -2147483647 - 1 = 1 50.21 FBAA timelevel sel List 03 - 1 = 1 50.24 FBAA comm supervision force PB 0000hFFFFh - 1 = 1 50.25 FBA B comm loss func Real 05 - 1 = 1 50.33 FBA B ref1 type List 05 - 1 = 1 50.34 FBA B actual 1 type List 06 - 1 = 1 50.36 FBA B actual ransparent source Src - 1 = 1						
50.14 FBA reference 1 Real -2147483648 2147483647 - 1 = 1 50.15 FBA reference 2 Real -2147483647 - 1 = 1 50.16 FBA status word Data 00000000h FFFFFFFh - 1 = 1 50.16 FBA actual value 1 Real -2147483647 - 1 = 1 50.17 FBA actual value 2 Real -2147483647 - 1 = 1 50.18 FBA actual value 2 Real -2147483647 - 1 = 1 50.21 FBA actual value 2 Real -2147483647 - 1 = 1 50.21 FBA actual value 2 Real 05 - 1 = 1 50.23 FBA benable List 01 - 1 = 1 50.33 FBA B comm loss timeout List 05 - 1 = 1 50.34 FBA B comm loss timeout List 05 - 1 = 1 50.35 FBA B comm loss timeout List 06 - 1 = 1	-	-			-	
Image: Second			Data		-	1 = 1
2147483647 50.16 FBA A status word Data 00000000h FFFFFFFFh - 1 = 1 50.17 FBA A actual value 1 Real -2147483648 - 1 = 1 50.18 FBA A actual value 2 Real -2147483647 - 1 = 1 50.21 FBA A actual value 2 Real -2147483647 - 1 = 1 50.21 FBA A comm supervision force PB 0000h FFFFh - 1 = 1 50.26 FBA B comm loss func Real 05 - 1 = 1 50.33 FBA B comm loss timeout List 05 - 1 = 1 50.34 FBA B statual 1 type List 05 - 1 = 1 50.35 FBA B actual 1 type List 06 - 1 = 1 50.37 FBA B actual 2 type Analog - - 1 = 1 50.36 FBA B actual 2 type Analog - 1 = 1 50.37 FBA B actual ransparent source Analog <td>50.14</td> <td>FBAA reference 1</td> <td>Real</td> <td></td> <td>-</td> <td>1 = 1</td>	50.14	FBAA reference 1	Real		-	1 = 1
50.17 FBAA actual value 1 Real -2147483648 2147483647 - 1 = 1 50.18 FBAA actual value 2 Real -2147483647 - 1 = 1 50.21 FBAA timelevel sel List 03 - 1 = 1 50.26 FBAA comm supervision force PB 0000hFFFFh - 1 = 1 50.31 FBA B enable List 01 - 1 = 1 50.32 FBA B comm loss timeout List 05 - 1 = 1 50.33 FBA B comm loss timeout List 05 - 1 = 1 50.34 FBA B ref1 type List 05 - 1 = 1 50.35 FBA B ref2 type List 05 - 1 = 1 50.36 FBA B actual 1 type List 06 - 1 = 1 50.37 FBA B actual 2 type Analog - 1 = 1 50.38 FBA B actual 2 type Analog - 1 = 1 50.40 FBA B actual ransparent source Analog - 1 = 1 50.41 F	50.15	FBA A reference 2	Real		-	1 = 1
Image: Section of the sectio	50.16	FBAA status word	Data	00000000h FFFFFFFh	-	1 = 1
2147483647 2147483647 50.21 FBA A timelevel sel List 03 - 1 = 1 50.26 FBA A comm supervision force PB 0000hFFFFh - 1 = 1 50.31 FBA B enable List 01 - 1 = 1 50.32 FBA B comm loss func Real 05 - 1 = 1 50.33 FBA B comm loss func List 05 - 1 = 1 50.34 FBA B reft type List 05 - 1 = 1 50.35 FBA B reft type List 05 - 1 = 1 50.35 FBA B actual 1 type List 06 - 1 = 1 50.38 FBA B actual 2 type Analog src - - 1 = 1 50.40 FBA B act1 transparent source Analog src - - 1 = 1 50.41 FBA B bact2 transparent source List - - 1 = 1 50.42 FBA B control word Real 00000000h FFFF	50.17	FBAA actual value 1	Real		-	1 = 1
50.26 FBAA comm supervision force PB 0000hFFFFh - 1 = 1 50.31 FBA B enable List 01 - 1 = 1 50.32 FBA B comm loss func Real 05 - 1 = 1 50.33 FBA B comm loss timeout List 0.36553.5 S 10 = 1 s 50.34 FBA B ref1 type List 05 - 1 = 1 50.35 FBA B ref2 type List 06 - 1 = 1 50.37 FBA B actual 1 type List 06 - 1 = 1 50.38 FBA B actual 2 type Analog src - - 1 = 1 50.39 FBA B sct1 transparent source Analog src - - 1 = 1 50.40 FBA B act2 transparent source List - - 1 = 1 50.41 FBA B control word Real 00000000h FFFFFFFh - 1 = 1 50.42 FBA B treference 1 Real 00000000h FFFFFFFFh - 1 = 1 </td <td>50.18</td> <td>FBAA actual value 2</td> <td>Real</td> <td></td> <td>-</td> <td>1 = 1</td>	50.18	FBAA actual value 2	Real		-	1 = 1
50.31 FBA B enable List 01 - 1 = 1 50.32 FBA B comm loss func Real 05 - 1 = 1 50.33 FBA B comm loss timeout List 0.36553.5 s 10 = 1 s 50.34 FBA B ref1 type List 05 - 1 = 1 50.35 FBA B ref2 type List 06 - 1 = 1 50.37 FBA B actual 1 type List 06 - 1 = 1 50.38 FBA B actual 2 type Analog src - 1 = 1 50.39 FBA B actual 2 type Analog src - 1 = 1 50.40 FBA B act1 transparent source Analog src - 1 = 1 50.41 FBA B act2 transparent source List - 1 = 1 50.42 FBA B debug mode Data 01 - 1 = 1 50.43 FBA B reference 1 Real 00000000h FFFFFFFFh - 1 = 1 50.44 FBA B reference 2 Data -2147483647 - 1 = 1 50.45 FBA B actual value 1<	50.21	FBA A timelevel sel	List	03	-	1 = 1
50.32 FBA B comm loss func Real 05 - $1 = 1$ 50.33 FBA B comm loss timeout List $0.36553.5$ s $10 = 1$ s 50.34 FBA B ref1 type List 05 - $1 = 1$ 50.35 FBA B ref2 type List 05 - $1 = 1$ 50.37 FBA B actual 1 type List 06 - $1 = 1$ 50.38 FBA B actual 2 type Analog src 06 - $1 = 1$ 50.39 FBA B actual 2 type Analog src - $1 = 1$ $1 = 1$ 50.40 FBA B act1 transparent source Analog src - $1 = 1$ $1 = 1$ 50.41 FBA B act2 transparent source List - - $1 = 1$ $1 = 1$ 50.42 FBA B control word Real $00000000h FFFFFFFh$ - $1 = 1$ $1 = 1$ 50.43 FBA B reference 1 Real -2147483647 - $1 = 1$ 50.44 FBA B status word Real -2147483648 $ 1 = 1$ 50	50.26	FBAA comm supervision force	PB	0000hFFFFh	-	1 = 1
50.33 FBA B comm loss timeout List $0.3 \dots 6553.5$ s $10 = 1$ s 50.34 FBA B ref1 type List 05 - $1 = 1$ 50.35 FBA B ref2 type List 05 - $1 = 1$ 50.37 FBA B actual 1 type List 06 - $1 = 1$ 50.38 FBA B actual 2 type Analog src 06 - $1 = 1$ 50.39 FBA B actual 2 type Analog src - - $1 = 1$ 50.40 FBA B act1 transparent source Analog src - - $1 = 1$ 50.41 FBA B act2 transparent source List - - $1 = 1$ 50.42 FBA B debug mode Data 01 - $1 = 1$ 50.43 FBA B control word Real 00000000h FFFFFFFh - $1 = 1$ 50.44 FBA B reference 1 Real -2147483648 2147483647 - $1 = 1$ 50.45 FBA B setue word Real 00000000h FFFFFFFh - $1 = 1$ 50.45 FBA B actual value 1	50.31	FBA B enable	List	01	-	1 = 1
50.34 FBA B ref1 type List 05 - $1 = 1$ 50.35 FBA B ref2 type List 06 - $1 = 1$ 50.37 FBA B actual 1 type List 06 - $1 = 1$ 50.38 FBA B actual 2 type Analog src 06 - $1 = 1$ 50.39 FBA B SW transparent source Analog src - . $1 = 1$ 50.40 FBA B act1 transparent source Analog src - . $1 = 1$ 50.41 FBA B act2 transparent source List - - $1 = 1$ 50.42 FBA B debug mode Data 01 - $1 = 1$ 50.42 FBA B control word Real 00000000h FFFFFFFh - $1 = 1$ 50.43 FBA B reference 1 Real -2147483648 2147483647 - $1 = 1$ 50.44 FBA B reference 2 Data -2147483648 2147483647 - $1 = 1$ 50.45 FBA B actual value 1 Real 00000000h FFFFFFFFh - $1 = 1$ 50.46 FBA B actual va	50.32	FBA B comm loss func	Real	05	-	1 = 1
50.35 FBA B ref2 type List 05 - 1 = 1 50.37 FBA B actual 1 type List 06 - 1 = 1 50.38 FBA B actual 2 type Analog src 06 - 1 = 1 50.39 FBA B actual 2 type Analog src - 1 = 1 50.39 FBA B actual 2 type Analog src - 1 = 1 50.40 FBA B act1 transparent source Analog src - 1 = 1 50.41 FBA B act2 transparent source List - - 1 = 1 50.42 FBA B debug mode Data 01 - 1 = 1 50.43 FBA B control word Real 00000000h FFFFFFFh - 1 = 1 50.43 FBA B reference 1 Real -2147483648 2147483647 - 1 = 1 50.44 FBA B status word Real 00000000h FFFFFFFh - 1 = 1 50.45 FBA B actual value 1 Real -2147483648 2147483647 - 1 = 1 50.46 FBA B actual value 2 -2147483648 2147483647 1 = 1 1 = 1	50.33	FBA B comm loss timeout	List	0.3 6553.5	S	10 = 1 s
50.37 FBA B actual 1 type List 06 - 1 = 1 50.38 FBA B actual 2 type Analog src 06 - 1 = 1 50.39 FBA B SW transparent source Analog src - - 1 = 1 50.39 FBA B act1 transparent source Analog src - - 1 = 1 50.40 FBA B act2 transparent source Analog src - - 1 = 1 50.41 FBA B act2 transparent source List - - 1 = 1 50.42 FBA B debug mode Data 01 - 1 = 1 50.43 FBA B control word Real 00000000h FFFFFFFh - 1 = 1 50.44 FBA B reference 1 Real -2147483648 2147483647 - 1 = 1 50.45 FBA B status word Real 00000000h FFFFFFFFh - 1 = 1 50.46 FBA B actual value 1 Real -2147483648 2147483647 - 1 = 1 50.47 FBA B actual value 2 -2147483648 2147	50.34	FBA B ref1 type	List	05	-	1 = 1
50.38 FBA B actual 2 type Analog src 06 - 1 = 1 50.39 FBA B SW transparent source Analog src 06 - 1 = 1 50.39 FBA B SW transparent source Analog src - 1 = 1 50.40 FBA B act1 transparent source Analog src - 1 = 1 50.41 FBA B act2 transparent source List - 1 = 1 50.42 FBA B debug mode Data 01 - 1 = 1 50.43 FBA B control word Real 00000000h FFFFFFFh - 1 = 1 50.44 FBA B reference 1 Real -2147483648 2147483647 - 1 = 1 50.45 FBA B reference 2 Data -2147483648 2147483647 - 1 = 1 50.46 FBA B actual value 1 Real 00000000h FFFFFFFh - 1 = 1 50.47 FBA B actual value 2 -2147483648 2147483647 - 1 = 1 50.48 FBA B actual value 2 -2147483648 2147483647 1 = 1 1 = 1 <td>50.35</td> <td>FBA B ref2 type</td> <td>List</td> <td>05</td> <td>-</td> <td>1 = 1</td>	50.35	FBA B ref2 type	List	05	-	1 = 1
src src 50.39 FBA B SW transparent source Analog src - 1 = 1 50.40 FBA B act1 transparent source Analog src - 1 = 1 50.40 FBA B act1 transparent source List - 1 = 1 50.41 FBA B act2 transparent source List - 1 = 1 50.42 FBA B debug mode Data 01 - 1 = 1 50.43 FBA B control word Real 00000000h FFFFFFFh - 1 = 1 50.43 FBA B reference 1 Real -2147483648 - 1 = 1 50.44 FBA B reference 2 Data -2147483648 - 1 = 1 50.45 FBA B status word Real 00000000h FFFFFFFh - 1 = 1 50.46 FBA B actual value 1 Real -2147483648 - 1 = 1 50.47 FBA B actual value 2 -2147483648 - 1 = 1 1 = 1 50.48 FBA B actual value 2 -2147483648 1 = 1	50.37	FBA B actual 1 type	List	06	-	1 = 1
Src Src 50.40 FBA B act1 transparent source Analog Src - 1 = 1 50.41 FBA B act2 transparent source List - 1 = 1 50.42 FBA B debug mode Data 01 - 1 = 1 50.42 FBA B debug mode Data 01 - 1 = 1 50.43 FBA B control word Real 00000000h FFFFFFFh - 1 = 1 50.44 FBA B reference 1 Real -2147483648 - 1 = 1 50.45 FBA B reference 2 Data -2147483648 - 1 = 1 50.45 FBA B status word Real 00000000h FFFFFFFh - 1 = 1 50.46 FBA B status word Real 0000000h FFFFFFFF - 1 = 1 50.47 FBA B actual value 1 Real -2147483648 - 1 = 1 50.48 FBA B actual value 2 -2147483648 - 1 = 1 1 50.51 FBA B timelevel sel List	50.38	FBA B actual 2 type	-	06	-	1 = 1
src - 1 1 50.41 FBA B act2 transparent source List - 1 = 1 50.42 FBA B debug mode Data 01 - 1 = 1 50.43 FBA B control word Real 00000000h FFFFFFFh - 1 = 1 50.43 FBA B control word Real 0000000h FFFFFFFh - 1 = 1 50.44 FBA B reference 1 Real -2147483648 - 1 = 1 50.45 FBA B reference 2 Data -2147483647 - 1 = 1 50.46 FBA B status word Real 00000000h FFFFFFFh - 1 = 1 50.46 FBA B actual value 1 Real -2147483648 - 1 = 1 50.47 FBA B actual value 2 -2147483648 - 1 = 1 50.48 FBA B actual value 2 -2147483648 - 1 = 1 50.51 FBA B timelevel sel List 03 - 1 = 1 50.56 FBA B comm supervision force	50.39	FBA B SW transparent source	-	-	-	1 = 1
50.42 FBA B debug mode Data 01 - 1 = 1 50.43 FBA B control word Real 00000000h FFFFFFFh - 1 = 1 50.43 FBA B control word Real 0000000h FFFFFFFh - 1 = 1 50.44 FBA B reference 1 Real -2147483648 2147483647 - 1 = 1 50.45 FBA B reference 2 Data -2147483648 2147483647 - 1 = 1 50.46 FBA B status word Real 00000000h FFFFFFFh - 1 = 1 50.46 FBA B actual value 1 Real 0000000h FFFFFFFh - 1 = 1 50.47 FBA B actual value 2 -2147483648 2147483647 - 1 = 1 50.48 FBA B actual value 2 -2147483648 2147483647 - 1 = 1 50.51 FBA B timelevel sel List 03 - 1 = 1 50.56 FBA B comm supervision force PB 00000hFFFFh - 1 = 1 51 FBA A settings - 1 = 1 - 1 = 1 1	50.40	FBA B act1 transparent source	-	-	-	1 = 1
50.43 FBA B control word Real 0000000h FFFFFFFh - 1 = 1 50.43 FBA B control word Real -2147483648 - 1 = 1 50.44 FBA B reference 1 Real -2147483648 - 1 = 1 50.45 FBA B reference 2 Data -2147483648 - 1 = 1 50.45 FBA B reference 2 Data -2147483648 - 1 = 1 50.46 FBA B status word Real 00000000h FFFFFFFh - 1 = 1 50.47 FBA B actual value 1 Real -2147483648 - 1 = 1 50.47 FBA B actual value 2 -2147483648 - 1 = 1 50.48 FBA B actual value 2 -2147483647 - 1 = 1 50.51 FBA B timelevel sel List 03 - 1 = 1 50.56 FBA B comm supervision force PB 0000hFFFFh - 1 = 1 51 FBA A settings - 1 = 1 - 1 = 1 -	50.41	FBA B act2 transparent source	List	-	-	1 = 1
50.44 FBA B reference 1 Real -2147483648 - 1 = 1 50.45 FBA B reference 2 Data -2147483647 - 1 = 1 50.45 FBA B reference 2 Data -2147483648 - 1 = 1 50.46 FBA B status word Real 00000000h FFFFFFh - 1 = 1 50.47 FBA B actual value 1 Real -2147483648 - 1 = 1 50.48 FBA B actual value 2 -2147483648 - 1 = 1 50.48 FBA B actual value 2 -2147483647 - 1 = 1 50.51 FBA B timelevel sel List 03 - 1 = 1 50.56 FBA B comm supervision force PB 0000hFFFFh - 1 = 1 51 FBA A settings - 1 = 1 - 1 = 1 -	50.42	FBA B debug mode	Data	01	-	1 = 1
50.45 FBA B reference 2 Data -2147483647 - 1 = 1 50.45 FBA B reference 2 Data -2147483648 - 1 = 1 50.46 FBA B status word Real 00000000h FFFFFFFh - 1 = 1 50.47 FBA B actual value 1 Real -2147483648 - 1 = 1 50.47 FBA B actual value 2 -2147483648 - 1 = 1 50.48 FBA B actual value 2 -2147483648 - 1 = 1 50.51 FBA B timelevel sel List 03 - 1 = 1 50.56 FBA B comm supervision force PB 0000hFFFFh - 1 = 1 51 FBA A settings - 1 = 1 - 1 = 1 -	50.43	FBA B control word	Real	00000000h FFFFFFFh	-	1 = 1
1 2147483647 1 50.46 FBA B status word Real 0000000h FFFFFFFh - 1 = 1 50.47 FBA B actual value 1 Real -2147483648 - 1 = 1 50.48 FBA B actual value 2 -2147483648 - 1 = 1 50.48 FBA B actual value 2 -2147483648 - 1 = 1 50.51 FBA B timelevel sel List 03 - 1 = 1 50.56 FBA B comm supervision force PB 0000hFFFFh - 1 = 1 51 FBA A settings - 1 = 1 - 1 = 1 -	50.44	FBA B reference 1	Real		-	1 = 1
50.47 FBA B actual value 1 Real -2147483648 - 1 = 1 50.48 FBA B actual value 2 -2147483647 - 1 = 1 50.48 FBA B actual value 2 -2147483648 - 1 = 1 50.51 FBA B timelevel sel List 03 - 1 = 1 50.56 FBA B comm supervision force PB 0000hFFFFh - 1 = 1 51 FBA A settings - - 1 = 1 - 1 = 1	50.45	FBA B reference 2	Data		-	1 = 1
50.47 FBA B actual value 1 Real -2147483648 - 1 = 1 50.48 FBA B actual value 2 -2147483648 - 1 = 1 50.48 FBA B actual value 2 -2147483648 - 1 = 1 50.51 FBA B timelevel sel List 03 - 1 = 1 50.56 FBA B comm supervision force PB 0000hFFFFh - 1 = 1 51 FBA A settings - - 1 = 1 - 1 = 1	50.46	FBA B status word	Real		-	1 = 1
50.48 FBA B actual value 2 -2147483648 - 1 = 1 50.51 FBA B timelevel sel List 03 - 1 = 1 50.56 FBA B comm supervision force PB 0000hFFFFh - 1 = 1 51 FBA A settings - - 1 = 1	50.47	FBA B actual value 1	Real		-	1 = 1
50.56 FBA B comm supervision force PB 0000hFFFFh - 1 = 1 51 FBA A settings	50.48	FBA B actual value 2		-2147483648	-	1 = 1
51 FBA A settings	50.51	FBA B timelevel sel	List	03	-	1 = 1
	50.56	FBA B comm supervision force	PB	0000hFFFFh	-	1 = 1
	51 FBA	A settings		· · · · · · · · · · · · · · · · · · ·		•
		-	List	-	-	1 = 1
51.02 FBA A Par2 Real 065535 - 1 = 1				065535	-	1 = 1

No.	Name	Туре	Range	Unit	FbEq32
51.26	FBA A Par26	Real	065535	-	1 = 1
51.27	FBA A par refresh	List	01	-	1 = 1
51.28	FBA A par table ver	Data	-	-	1 = 1
51.29	FBA A drive type code	Real	065535	-	1 = 1
51.30	FBA A mapping file ver	Real	065535	-	1 = 1
51.31	D2FBA comm status	List	06	-	1 = 1
51.32	FBAA comm SW ver	Data	-	-	1 = 1
51.33	FBA A appl SW ver	Data	-	-	1 = 1
52 FBA	A data in				
52.01	FBA A data in1	List	-	-	1 = 1
52.12	FBA A data in 12	List	-	-	1 = 1
53 FBA	A data out				I
53.01	FBA A data out1	List	-	-	1 = 1
53.12	FBA A data out 12	List	-	-	1 = 1
54 FBA	B settings				
54.01	FBA B type				
54.02	FBA B Par2	UINT16	065535	-	
54.26	FBA B Par26	UINT16	065535	-	
54.27	FBA B par refresh	List	01	-	
54.28	FBA B par table ver	UINT16	065535	-	
54.29	FBA B drive type code	UINT16	065535	-	
54.30	FBA B mapping file ver	UINT16	065535	-	
54.31	D2FBA B comm status	List	06	-	
54.32	FBA B comm SW ver	UINT16	065535	-	
54.33	FBA B appl SW ver	UINT16	065535	-	
55 FBA	B data in				
55.01	FBA B data in1	List	-	-	1 = 1
55.12	FBA B data in12	List	-	-	1 = 1
56 FBA	B data out				
56.01	FBA B data out1	List	-	-	1 = 1
56.12	FBA B data out12	List	-	-	1 = 1
58 Emb	edded fieldbus				l
58.01	Protocol enable	List	01	-	1 = 1
58.02	Protocol ID	Real	0000hFFFFh	-	1 = 1
58.03	Node address	Real	0255	-	1 = 1

No.	Name	Туре	Range	Unit	FbEq32
58.04	Baud rate	List	27	-	1 = 1
58.05	Parity	List	03	-	1 = 1
58.06	Communication control	List	02	-	1 = 1
58.07	Communication diagnostics	PB	0000hFFFFh	-	1 = 1
58.08	Received packets	Real	04294967295	-	1 = 1
58.09	Transmitted packets	Real	04294967295	-	1 = 1
58.10	All packets	Real	04294967295	-	1 = 1
58.11	UART errors	Real	04294967295	-	1 = 1
58.12	CRC errors	Real	04294967295	-	1 = 1
58.14	Communication loss action	List	03	-	1 = 1
58.15	Communication loss mode	List	02	-	1 = 1
58.16	Communication loss time	Real	0.0 6000.0	s	10 = 1 s
58.17	Transmit delay	Real	065535	ms	1 = 1 ms
58.18	EFB control word	PB	0000hFFFFh	-	1 = 1
58.19	EFB status word	PB	0000hFFFFh	-	1 = 1
58.25	Control profile	List	0, 2	-	1 = 1
58.26	EFB ref1 type	List	05	-	1 = 1
58.27	EFB ref2 type	List	05	-	1 = 1
58.28	EFB act1 type	List	06	-	1 = 1
58.29	EFB act2 type	List	06	-	1 = 1
58.30	EFB status word transparent source	Analog src	-	-	1 = 1
58.31	EFB act1 transparent source	Analog src	-	-	1 = 1
58.32	EFB act2 transparent source	Analog src	-	-	1 = 1
58.33	Addressing mode	List	03	-	1 = 1
58.34	Word order	List	01	-	1 = 1
58.36	EFB comm supervision force	PB	0000hFFFFh	-	1 = 1
58.101	Data I/O 1	Analog src	-	-	1 = 1
58.102	Data I/O 2	Analog src	-	-	1 = 1
58.103	Data I/O 3	Analog src	-	-	1 = 1
58.104	Data I/O 4	Analog src	-	-	1 = 1
58.105	Data I/O 5	Analog src	-	-	1 = 1
58.106	Data I/O 6	Analog src	-	-	1 = 1
58.107	Data I/O 7	Analog src	-	-	1 = 1

No.	Name	Туре	Range	Unit	FbEq32
58.124	Data I/O 24	Analog src	-	-	1 = 1
60 DDC	S communication				
60.01	M/F communication port	List	-	-	-
60.02	M/F node address	Real	1254	-	-
60.03	M/F mode	List	06	-	-
60.05	M/F HW connection	List	01	-	-
60.07	M/F link control	Real	115	-	-
60.08	M/F comm loss timeout	Real	065535	ms	-
60.09	M/F comm loss function	List	03	-	-
60.10	M/F ref1 type	List	05	-	-
60.11	M/F ref2 type	List	05	-	-
60.12	M/F act1 type	List	05	-	-
60.13	M/F act2 type	List	05	-	-
60.14	M/F follower selection	Real	016	-	-
60.15	Force master	Binary src	-	-	1 = 1
60.16	Force follower	Binary src	-	-	1 = 1
60.17	Follower fault action	List	02	-	1 = 1
60.18	Follower enable	List	03	-	1 = 1
60.19	M/F comm supervision sel 1	PB	0000hFFFFh	-	1 = 1
60.20	M/F comm supervision sel 2	PB	0000hFFFFh	-	1 = 1
60.23	M/F status supervision sel 1	PB	0000hFFFFh	-	1 = 1
60.24	M/F status supervision sel 2	PB	0000hFFFFh	-	1 = 1
60.27	M/F status supv mode sel 1	PB	0000hFFFFh	-	1 = 1
60.28	M/F status supv mode sel 2	PB	0000hFFFFh	-	1 = 1
60.31	M/F wake up delay	Real	0.0 180.0	S	10 = 1 s
60.32	M/F comm supervision force	PB	0000hFFFFh	-	1 = 1
60.41	Extension adapter com port	List	-	-	-
60.50	DDCS controller drive type	List	01	-	-
60.51	DDCS controller comm port	List	-	-	-
60.52	DDCS controller node address	Real	1254	-	-
60.55	DDCS controller HW connection	List	01	-	-
60.56	DDCS controller baud rate	List	1, 2, 4, 8	-	-
60.57	DDCS controller link control	Real	115	-	-
60.58	DDCS controller comm loss time	Real	060000	ms	-
60.59	DDCS controller comm loss function	List	05	-	-
60.60	DDCS controller ref1 type	List	05	-	-

No.	Name	Туре	Range	Unit	FbEq32
60.61	DDCS controller ref2 type	List	05	-	-
60.62	DDCS controller act1 type	List	05	-	-
60.63	DDCS controller act2 type	List	05	-	-
60.64	Mailbox dataset selection	List	01	-	-
60.65	DDCS controller comm supervision force	PB	0000hFFFFh	-	1 = 1
	(Parameters 60.7160.79 (only visible	when supply unit control ac	tivated by <mark>95</mark> .	20)
60.71	INU-LSU communication port	List	-	-	1 = 1
60.77	INU-LSU link control	Real	115	-	-
60.78	INU-LSU comm loss timeout	Real	065535	ms	-
60.79	INU-LSU comm loss function	Binary src	-	-	1 = 1
61 D2D	and DDCS transmit data				<u> </u>
61.01	M/F data 1 selection	List	-	-	-
61.02	M/F data 2 selection	List	-	-	-
61.03	M/F data 3 selection	List	-	-	-
61.25	M/F data 1 value	Real	065535	-	-
61.26	M/F data 2 value	Real	065535	-	-
61.27	M/F data 3 value	Real	065535	-	-
61.45	Data set 2 data 1 selection	List	-	-	-
61.46	Data set 2 data 2 selection	List	-	-	-
61.47	Data set 2 data 3 selection	List	-	-	-
61.48	Data set 4 data 1 selection	List	-	-	-
61.49	Data set 4 data 2 selection	List	-	-	-
61.50	Data set 4 data 3 selection	List	-	-	-
61.51	Data set 11 data 1 selection	List	-	-	-
61.52	Data set 11 data 2 selection	List	-	-	-
61.53	Data set 11 data 3 selection	List	_	-	-
61.54	Data set 13 data 1 selection	List	-	-	-
61.55	Data set 13 data 2 selection	List	-	-	-
61.56	Data set 13 data 3 selection	List	-	-	-
61.57	Data set 15 data 1 selection	List	-	-	-
61.58	Data set 15 data 2 selection	List	_	-	-
61.59	Data set 15 data 3 selection	List	_	-	-
61.60	Data set 17 data 1 selection	List	-	-	-
61.61	Data set 17 data 2 selection	List	-	-	-
61.62	Data set 17 data 3 selection	List	-	-	-
61.63	Data set 19 data 1 selection	List	-	-	-
61.64	Data set 19 data 2 selection	List	-	-	-
61.65	Data set 19 data 3 selection	List	-	-	-
61.66	Data set 21 data 1 selection	List	-	-	-
61.67	Data set 21 data 2 selection	List		_	_
01.07		2.00			

No.	Name	Туре	Range	Unit	FbEq32
61.68	Data set 21 data 3 selection	List	-	-	-
61.69	Data set 23 data 1 selection	List	-	-	-
61.70	Data set 23 data 2 selection	List	-	-	-
61.71	Data set 23 data 3 selection	List	-	-	-
61.72	Data set 25 data 1 selection	List	-	-	-
61.73	Data set 25 data 2 selection	List	-	-	-
61.74	Data set 25 data 3 selection	List	-	-	-
61.95	Data set 2 data 1 value	Real	065535	-	-
61.96	Data set 2 data 2 value	Real	065535	-	-
61.97	Data set 2 data 3 value	Real	065535	-	-
61.98	Data set 4 data 1 value	Real	065535	-	-
61.99	Data set 4 data 2 value	Real	065535	-	-
61.100	Data set 4 data 3 value	Real	065535	-	-
61.101	Data set 11 data 1 value	Real	065535	-	-
61.102	Data set 11 data 2 value	Real	065535	-	-
61.103	Data set 11 data 3 value	Real	065535	-	-
61.104	Data set 13 data 1 value	Real	065535	-	-
61.105	Data set 13 data 2 value	Real	065535	-	-
61.106	Data set 13 data 3 value	Real	065535	-	-
61.107	Data set 15 data 1 value	Real	065535	-	-
61.108	Data set 15 data 2 value	Real	065535	-	-
61.109	Data set 15 data 3 value	Real	065535	-	-
61.110	Data set 17 data 1 value	Real	065535	-	-
61.111	Data set 17 data 2 value	Real	065535	-	-
61.112	Data set 17 data 3 value	Real	065535	-	-
61.113	Data set 19 data 1 value	Real	065535	-	-
61.114	Data set 19 data 2 value	Real	065535	-	-
61.115	Data set 19 data 3 value	Real	065535	-	-
61.116	Data set 21 data 1 value	Real	065535	-	-
61.117	Data set 21 data 2 value	Real	065535	-	-
61.118	Data set 21 data 3 value	Real	065535	-	-
61.119	Data set 23 data 1 value	Real	065535	-	-
61.120	Data set 23 data 2 value	Real	065535	-	-
61.121	Data set 23 data 3 value	Real	065535	-	-
61.122	Data set 25 data 1 value	Real	065535	-	-
61.123	Data set 25 data 2 value	Real	065535	-	-
61.124	Data set 25 data 3 value	Real	065535	-	-
	(Parameters 61.15161.203	only visible	when supply unit control ac	tivated by <mark>98</mark>	5.20)
61.151	INU-LSU Data set 10 data 1 sel	List	-	-	-
61.152	INU-LSU Data set 10 data out 2	List	-	-	-

No.	Name	Туре	Range	Unit	FbEq32
61.153	INU-LSU Data set 10 data 2 sel	List	-	-	-
61.201	INU-LSU Data set 10 data 1 value	Real	065535	-	-
61.202	INU-LSU Data set 10 data 2 value	Real	065535	-	-
61.203	INU-LSU Data set 10 data 3 value	Real	065535	-	-
62 D2D	and DDCS receive data				
62.01	M/F data 1 selection	List	-	-	-
62.02	M/F data 2 selection	List	-	-	-
62.03	M/F data 3 selection	List	-	-	-
62.04	Follower node 2 data 1 sel	List	-	-	-
62.05	Follower node 2 data 2 sel	List	-	-	-
62.06	Follower node 2 data 3 sel	List	-	-	-
62.07	Follower node 3 data 1 sel	List	-	-	-
62.08	Follower node 3 data 2 sel	List	-	-	-
62.09	Follower node 3 data 3 sel	List	-	-	-
62.10	Follower node 4 data 1 sel	List	-	-	-
62.11	Follower node 4 data 2 sel	List	-	-	-
62.12	Follower node 4 data 3 sel	List	-	-	-
62.25	MF data 1 value	Real	065535	-	-
62.26	MF data 2 value	Real	065535	-	-
62.27	MF data 3 value	Real	065535	-	-
62.28	Follower node 2 data 1 value	Real	065535	-	-
62.29	Follower node 2 data 2 value	Real	065535	-	-
62.30	Follower node 2 data 3 value	Real	065535	-	-
62.31	Follower node 3 data 1 value	Real	065535	-	-
62.32	Follower node 3 data 2 value	Real	065535	-	-
62.33	Follower node 3 data 3 value	Real	065535	-	-
62.34	Follower node 4 data 1 value	Real	065535	-	-
62.35	Follower node 4 data 2 value	Real	065535	-	-
62.36	Follower node 4 data 3 value	Real	065535	-	-
62.37	M/F communication status 1	PB	0000hFFFFh	-	1 = 1
62.38	M/F communication status 2	PB	0000hFFFFh	-	1 = 1
62.41	M/F follower ready status 1	PB	0000hFFFFh	-	1 = 1
62.42	M/F follower ready status 2	PB	0000hFFFFh	-	1 = 1
62.45	Data set 1 data 1 selection	List	-	-	-
62.46	Data set 1 data 2 selection	List	-	-	-
62.47	Data set 1 data 3 selection	List	-	-	-
62.48	Data set 3 data 1 selection	List	-	-	-
62.49	Data set 3 data 2 selection	List	-	-	-

No.	Name	Туре	Range	Unit	FbEq32
62.50	Data set 3 data 3 selection	List	-	-	-
62.51	Data set 10 data 1 selection	List	-	-	-
62.52	Data set 10 data 2 selection	List	-	-	-
62.53	Data set 10 data 3 selection	List	-	-	-
62.54	Data set 12 data 1 selection	List	-	-	-
62.55	Data set 12 data 2 selection	List	-	-	-
62.56	Data set 12 data 3 selection	List	-	-	-
62.57	Data set 14 data 1 selection	List	-	-	-
62.58	Data set 14 data 2 selection	List	-	-	-
62.59	Data set 14 data 3 selection	List	-	-	-
62.60	Data set 16 data 1 selection	List	-	-	-
62.61	Data set 16 data 2 selection	List	-	-	-
62.62	Data set 16 data 3 selection	List	-	-	-
62.63	Data set 18 data 1 selection	List	-	-	-
62.64	Data set 18 data 2 selection	List	-	-	-
62.65	Data set 18 data 3 selection	List	-	-	-
62.66	Data set 20 data 1 selection	List	-	-	-
62.67	Data set 20 data 2 selection	List	-	-	-
62.68	Data set 20 data 3 selection	List	-	-	-
62.69	Data set 22 data 1 selection	List	-	-	-
62.70	Data set 22 data 2 selection	List	-	-	-
62.71	Data set 22 data 3 selection	List	-	-	-
62.72	Data set 24 data 1 selection	List	-	-	-
62.73	Data set 24 data 2 selection	List	-	-	-
62.74	Data set 24 data 3 selection	List	-	-	-
62.95	Data set 1 data 1 value	Real	065535	-	-
62.96	Data set 1 data 2 value	Real	065535	-	-
62.97	Data set 1 data 3 value	Real	065535	-	-
62.98	Data set 3 data 1 value	Real	065535	-	-
62.99	Data set 3 data 2 value	Real	065535	-	-
62.100	Data set 3 data 3 value	Real	065535	-	-
62.101	Data set 10 data 1 value	Real	065535	-	-
62.102	Data set 10 data 2 value	Real	065535	-	-
62.103	Data set 10 data 3 value	Real	065535	-	-
62.104	Data set 12 data 1 value	Real	065535	-	-
62.105	Data set 12 data 2 value	Real	065535	-	-
62.106	Data set 12 data 3 value	Real	065535	-	-
62.107	Data set 14 data 1 value	Real	065535	-	-
62.108	Data set 14 data 2 value	Real	065535	-	-
62.109	Data set 14 data 3 value	Real	065535	-	-
62.110	Data set 16 data 1 value	Real	065535	-	-

No.	Name	Туре	Range	Unit	FbEq32
62.111	Data set 16 data 2 value	Real	065535	-	-
62.112	Data set 16 data 3 value	Real	065535	-	-
62.113	Data set 18 data 1 value	Real	065535	-	-
62.114	Data set 18 data 2 value	Real	065535	-	-
62.115	Data set 18 data 3 value	Real	065535	-	-
62.116	Data set 20 data 1 value	Real	065535	-	-
62.117	Data set 20 data 2 value	Real	065535	-	-
62.118	Data set 20 data 3 value	Real	065535	-	-
62.119	Data set 22 data 1 value	Real	065535	-	-
62.120	Data set 22 data 2 value	Real	065535	-	-
62.121	Data set 22 data 3 value	Real	065535	-	-
62.122	Data set 24 data 1 value	Real	065535	-	-
62.123	Data set 24 data 2 value	Real	065535	-	-
62.124	Data set 24 data 3 value	Real	065535	-	-
	(Parameters 62.15162.203	only visible	e when supply unit control ac	tivated by <mark>95</mark>	5.20)
62.151	INU-LSU Data set 11 data 1 sel	Real	List	-	-
62.152	INU-LSU Data set 11 data 2 sel	Real	List	-	-
62.153	INU-LSU Data set 11 data 3 sel	Real	List	-	-
62.201	INU-LSU Data set 11 data 1 value	Real	065535	-	-
62.202	INU-LSU Data set 11 data 2 value	Real	065535	-	-
62.203	INU-LSU Data set 11 data 3 value	Real	065535	-	-
74 Spin	ning control	•		<u> </u>	
74.01	Pattern selection	UINT	14	-	1 = 1
74.02	Pattern selection mode	UINT	13	-	1 = 1
74.03	Shift function sel	UINT	01	-	1 = 1
74.04	Reset active pattern	Bit pointer	010	-	-
74.05	Pattern reset with interlock	Bit pointer	010	-	-
74.07	Reverse select	UINT	010	-	-
74.08	Pattern reset time	Real	01500	min	1 = 1 min
74.09	Pattern reset length	Real	030000	m	1 = 1 m
74.11	Production calculation reset	UINT	01	-	1 = 1
74.12	Average speed mode	UINT	01	-	1 = 1
75 Patte	rn1				
75.01	Section No 1.1	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
75.02	Speed No 1.1	Real	0.1200.0	%	10 = 1%

No.	Name	Туре	Range	Unit	FbEq32
75.03	Section No 1.2	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
75.04	Speed No 1.2	Real	0.1200.0	%	10 = 1%
75.05	Section No 1.3	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
75.06	Speed No 1.3	Real	0.1200.0	%	10 = 1%
75.07	Section No 1.4	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
75.08	Speed No 1.4	Real	0.1200.0	%	10 = 1%
75.09	Section No 1.5	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
75.10	Speed No 1.5	Real	0.1200.0	%	10 = 1%
75.11	Section No 1.6	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
75.12	Speed No 1.6	Real	0.1200.0	%	10 = 1%
75.13	Section No 1.7	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
75.14	Speed No 1.7	Real	0.1200.0	%	10 = 1%
75.15	Section No 1.8	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
75.16	Speed No 1.8	Real	0.1200.0	%	10 = 1%
75.17	Section No 1.9	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
75.18	Speed No 1.9	Real	0.1200.0	%	10 = 1%
75.19	Section No 1.10	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
75.20	Speed No 1.10	Real	0.1200.0	%	10 = 1%
75.21	Section No 1.11	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
75.22	Speed No 1.11	Real	0.1200.0	%	10 = 1%
75.23	Section No 1.12	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
75.24	Speed No 1.12	Real	0.1200.0	%	10 = 1%
75.25	Section No 1.13	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
75.26	Speed No 1.13	Real	0.1200.0	%	10 = 1%
75.27	Section No 1.14	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
75.28	Speed No 1.14	Real	0.1200.0	%	10 = 1%
75.29	Section No 1.15	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
75.30	Speed No 1.15	Real	0.1200.0	%	10 = 1%
75.31	Section No 1.16	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
75.32	Speed No 1.16	Real	0.1200.0	%	10 = 1%
75.33	Pattern1 mode	Real	02	-	1 = 1

No.	Name	Туре	Range	Unit	FbEq32
75.34	Pattern1 TPI	Real	0.00200.00	TPI	100 = 1 TPI
75.35	Pattern1 count number	Real	0200	-	1 = 1
75.36	Pattern1 section total	Real	0.00999999.00	min/m/%	100 = 1 min/m/%
75.37	Pattern1 total length	Real	0.0999999.0	m	10 = 1 m
76 Patte	ern2				
76.01	Section No 2.1	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
76.02	Speed No 2.1	Real	0.1200.0	%	10 = 1%
76.03	Section No 2.2	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
76.04	Speed No 2.2	Real	0.1200.0	%	10 = 1%
76.05	Section No 2.3	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
76.06	Speed No 2.3	Real	0.1200.0	%	10 = 1%
76.07	Section No 2.4	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
76.08	Speed No 2.4	Real	0.1200.0	%	10 = 1%
76.09	Section No 2.5	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
76.10	Speed No 2.5	Real	0.1200.0	%	10 = 1%
76.11	Section No 2.6	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
76.12	Speed No 2.6	Real	0.1200.0	%	10 = 1%
76.13	Section No 2.7	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
76.14	Speed No 2.7	Real	0.1200.0	%	10 = 1%
76.15	Section No 2.8	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
76.16	Speed No 2.8	Real	0.1200.0	%	10 = 1%
76.17	Section No 2.9	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
76.18	Speed No 2.9	Real	0.1200.0	%	10 = 1%
76.19	Section No 2.10	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
76.20	Speed No 2.10	Real	0.1200.0	%	10 = 1%
76.21	Section No 2.11	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
76.22	Speed No 2.11	Real	0.1200.0	%	10 = 1%
76.23	Section No 2.12	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
76.24	Speed No 2.12	Real	0.1200.0	%	10 = 1%
76.25	Section No 2.13	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
76.26	Speed No 2.13	Real	0.1200.0	%	10 = 1%

No.	Name	Туре	Range	Unit	FbEq32
76.27	Section No 2.14	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
76.28	Speed No 2.14	Real	0.1200.0	%	10 = 1%
76.29	Section No 2.15	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
76.30	Speed No 2.15	Real	0.1200.0	%	10 = 1%
76.31	Section No 2.16	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
76.32	Speed No 2.16	Real	0.1200.0	%	10 = 1%
76.33	Pattern2 mode	Real	02	-	1 = 1
76.34	Pattern2 TPI	Real	0.00200.00	TPI	100 = 1 TPI
76.35	Pattern2 count number	Real	0200	-	1 = 1
76.36	Pattern2 section total	Real	0.00999999.00	min/m/%	100 = 1 min/m/%
76.37	Pattern2 total length	Real	0.0999999.0	m	10 = 1 m
77 Patte	ern3	<u>.</u>			
77.01	Section No 3.1	Real	00.050000.00	min/m/%	100 = 1 min/m/%
77.02	Speed No 3.1	Real	0.1200.0	%	10 = 1%
77.03	Section No 3.2	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
77.04	Speed No 3.2	Real	0.1200.0	%	10 = 1%
77.05	Section No 3.3	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
77.06	Speed No 3.3	Real	0.1200.0	%	10 = 1%
77.07	Section No 3.4	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
77.08	Speed No 3.4	Real	0.1200.0	%	10 = 1%
77.09	Section No 3.5	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
77.10	Speed No 3.5	Real	0.1200.0	%	10 = 1%
77.11	Section No 3.6	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
77.12	Speed No 3.6	Real	0.1200.0	%	10 = 1%
77.13	Section No 3.7	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
77.14	Speed No 3.7	Real	0.1200.0	%	10 = 1%
77.15	Section No 3.8	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
77.16	Speed No 3.8	Real	0.1200.0	%	10 = 1%
77.17	Section No 3.9	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
77.18	Speed No 3.9	Real	0.1200.0	%	10 = 1%
77.19	Section No 3.10	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
77.20	Speed No 3.10	Real	0.1200.0	%	10 = 1%

No.	Name	Туре	Range	Unit	FbEq32
77.21	Section No 3.11	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
77.22	Speed No 3.11	Real	0.1200.0	%	10 = 1%
77.23	Section No 3.12	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
77.24	Speed No 3.12	Real	0.1200.0	%	10 = 1%
77.25	Section No 3.13	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
77.26	Speed No 3.13	Real	0.1200.0	%	10 = 1%
77.27	Section No 3.14	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
77.28	Speed No 3.14	Real	0.1200.0	%	10 = 1%
77.29	Section No 3.15	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
77.30	Speed No 3.15	Real	0.1200.0	%	10 = 1%
77.31	Section No 3.16	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
77.32	Speed No 3.16	Real	0.1200.0	%	10 = 1%
77.33	Pattern3 mode	Real	02	-	1 = 1
77.34	Pattern3 TPI	Real	0.00200.00	TPI	100 = 1 TPI
77.35	Pattern3 count number	Real	0200	-	1 = 1
77.36	Pattern3 section total	Real	0.00999999.00	min/m/%	100 = 1 min/m/%
77.37	Pattern3 total length	Real	0.099999.0	m	10 = 1 m
78 Patte	ern4				
78.01	Section No 4.1	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
78.02	Speed No 4.1	Real	0.1200.0	%	10 = 1%
78.03	Section No 4.2	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
78.04	Speed No 4.2	Real	0.1200.0	%	10 = 1%
78.05	Section No 4.3	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
78.06	Speed No 4.3	Real	0.1200.0	%	10 = 1%
78.07	Section No 4.4	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
78.08	Speed No 4.4	Real	0.1200.0	%	10 = 1%
78.09	Section No 4.5	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
78.10	Speed No 4.5	Real	0.1200.0	%	10 = 1%
78.11	Section No 4.6	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
78.12	Speed No 4.6	Real	0.1200.0	%	10 = 1%
78.13	Section No 4.7	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
78.14	Speed No 4.7	Real	0.1200.0	%	10 = 1%

No.	Name	Туре	Range	Unit	FbEq32
78.15	Section No 4.8	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
78.16	Speed No 4.8	Real	0.1200.0	%	10 = 1%
78.17	Section No 4.9	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
78.18	Speed No 4.9	Real	0.1200.0	%	10 = 1%
78.19	Section No 4.10	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
78.20	Speed No 4.10	Real	0.1200.0	%	10 = 1%
78.21	Section No 4.11	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
78.22	Speed No 4.11	Real	0.1200.0	%	10 = 1%
78.23	Section No 4.12	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
78.24	Speed No 4.12	Real	0.1200.0	%	10 = 1%
78.25	Section No 4.13	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
78.26	Speed No 4.13	Real	0.1200.0	%	10 = 1%
78.27	Section No 4.14	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
78.28	Speed No 4.14	Real	0.1200.0	%	10 = 1%
78.29	Section No 4.15	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
78.30	Speed No 4.15	Real	0.1200.0	%	10 = 1%
78.31	Section No 4.16	Real	0.0050000.00	min/m/%	100 = 1 min/m/%
78.32	Speed No 4.16	Real	0.1200.0	%	10 = 1%
78.33	Pattern4 mode	Real	02	-	1 = 1
78.34	Pattern4 TPI	Real	0.00200.00	TPI	100 = 1 TPI
78.35	Pattern4 count number	Real	0200	-	1 = 1
78.36	Pattern4 section total	Real	0.0099999.00	min/m/%	100 = 1 min/m/%
78.37	Pattern4 total length	Real	0.0999999.0	m	10 = 1 m
79 Ring	frame machine				
79.01	Gear ratio	Real	0.00300.00	-	100 = 1
79.07	Pattern shift multiple	Real	0.002.00	-	100 = 1
79.08	Work shift start time	Real	00.00.0024.00.00	hh:mm:ss	-
79.11	Work shift time	Real	0.0030.00	h	100 = 1 h
79.12	Number of spindle	Real	030000	-	1 = 1
79.15	Front roller measurement	UINT	03	-	1 = 1
79.16	Front roller diameter	Real	0.0999999.0	mm	10 = 1 mm
79.17	Proximity switch pulse number	Real	0100	-	1 = 1
79.19	TPI Start Speed	Real	030000	rpm	1 = 1 rpm
79.20	TPI Filter Time	Real	010000	ms	1 = 1 ms

No.	Name	Туре	Range	Unit	FbEq32
79.21	TPI Deviation	Real	0.001000.00	TPI	100 = 1 TPI
80 Wob	bulation				•
80.01	Wobbulation up sel	Bit pointer	010	-	-
80.02	Wobbulation down sel	Bit pointer	010	-	-
80.03	Wobbulation up multiple	Real	1.002.00	-	100 = 1
80.04	Wobbulation down multiple	Real	0.001.00	-	100 = 1
80.05	Wobbulation acc time	Real	0.01000.0	S	10 = 1 s
80.06	Wobbulation dec time	Real	0.01000.0	S	10 = 1 s
81 Manu	ual Doff				
81.01	Manual doff selection mode	UINT	01	-	1 = 1
81.02	Manual doff selection	Bit pointer	010	-	-
81.03	Manual doff speed	Real	0.0200.0	%	10 = 1 %
81.04	Manual doff dec time	Real	0.01000.0	S	10 = 1 s
81.05	Manual doff time	Real	030000	S	1 = 1 s
81.06	Doff end alarm time	Real	0.010000.0	min	10 = 1 min
81.07	Doff End alarm length	Real	032000	m	1 = 1 m
81.08	Manual doff activation percent	Real	0.0100.0	%	10 = 1 %
81.09	Manual doff stop	UINT	02	-	1 = 1
82 Slow	speed function				•
82.01	Slow Speed	Real	030000	rpm	1 = 1 rpm
82.02	Slow speed run time	Real	0.03000.0	min	10 = 1 min
82.03	Slow speed acceleration time1	Real	030000	s	1 = 1 s
82.04	Slow speed acceleration time 2	Real	030000	S	1 = 1 s
83 Shift	Report				
83.01	Shift1 production Kg	Real	0.03000.0	Kg	10 = Kg
83.02	Shift1 production Hank	Real	0.003000.00	Hank	100 = 1 Hank
83.03	Shift1 run time	Real	0.03000.0	min	10 = 1 min
83.04	Shift1 stop time	Real	0.03000.0	min	10 = 1 min
83.05	Shift1 KWh consumption	Real	0.09000.0	KWh	10 = 1 KWh
83.06	Shift1 KWh per Kg	Real	0.09000.0	KWh	10 = 1 KWh
83.07	Shift1 GPS	Real	03000	g	1 = 1 g
83.08	Shift1 pattern count	UINT	010000	-	1 = 1
83.09	Shift2 production Kg	Real	0.03000.0	Kg	10 = 1 Kg
83.10	Shift2 production Hank	Real	0.0030000.00	Hank	100 = 1 Hank
83.11	Shift2 run time	Real	0.03000.0	min	10 = 1 min
83.12	Shift2 stop time	Real	0.03000.0	min	10 = min
83.13	Shift2 KWh consumption	Real	0.09000.0	KWh	10 = 1 KWh
83.14	Shift2 KWh per Kg	Real	0.09000.0	KWh	10 = 1 KWh

No.	Name	Туре	Range	Unit	FbEq32
83.15	Shift2 GPS	Real	03000	g	1 = 1 g
83.16	Shift2 pattern count	Real	010000	-	1 = 1
83.17	Shift3 production Kg	Real	0.03000.0	Kg	10 = 1 Kg
83.18	Shift3 production Hank	Real	0.0030000.00	Hank	100 = 1 Hank
83.19	Shift3 run time	Real	0.03000.0	min	10 = 1 min
83.20	Shift3 stop time	Real	0.03000.0	min	10 = 1 min
83.21	Shift3 KWh consumption	Real	0.09000.0	KWh	10 = 1 KWh
83.22	Shift3 KWh per Kg	Real	0.09000.0	KWh	10 = 1 KWh
83.23	Shift3 GPS	Real	03000	g	1 = 1 g
83.24	Shift3 pattern count	UINT	010000	-	1 = 1
83.25	Shift4 production Kg	Real	0.03000.0	Kg	10 = 1 Kg
83.26	Shift4 production Hank	Real	0.0030000.00	Hank	100 = 1 Hank
83.27	Shift4 run time	Real	0.03000.0	min	10 = 1 min
83.28	Shift4 stop time	Real	0.03000.0	min	10 = 1 min
83.29	Shift4 KWh consumption	Real	0.09000.0	KWh	10 = 1 KWh
83.30	Shift4 KWh per Kg	Real	0.09000.0	KWh	10 = 1 KWh
83.31	Shift4 GPS	Real	03000	g	1 = 1 g
83.32	Shift4 pattern count	UINT	010000	-	1 = 1
83.33	Shift5 production Kg	Real	0.03000.0	Kg	10 = 1 Kg
83.34	Shift5 production Hank	Real	0.0030000.00	Hank	100 = 1 Hank
83.35	Shift5 run time	Real	0.03000.0	min	10 = 1 min
83.36	Shift5 stop time	Real	0.03000.0	min	10 = 1 min
83.37	Shift5 KWh consumption	Real	0.09000.0	KWh	10 = 1 KWh
83.38	Shift5 KWh per Kg	Real	0.09000.0	KWh	10 = 1 KWh
83.39	Shift5 GPS	Real	03000	g	1 = 1 g
83.40	Shift5 pattern count	UINT	010000	-	1 = 1
84 Doff	report				·
84.01	Doff1 production Kg	Real	0.03000.0	Kg	10 = 1 Kg
84.02	Doff1 production hank	Real	0.0030000.00	Hank	100 = 1 Hank
84.03	Doff1 total run time	Real	0.03000.0	min	10 = 1 min
84.04	Doff1 Pattern stop time	Real	0.03000.0	min	10 = 1 min
84.05	Doff1 KWh	Real	0.03000.0	KWh	10 = 1 KWh
84.06	Doff1 KWh/Kg	Real	0.03000.0	KWh/Kg	10 = 1 KWh/Kg
84.07	Doff2 production Kg	Real	0.03000.0	Kg	10 = 1 Kg
84.08	Doff2 production hank	Real	0.0030000.00	Hank	100 = 1 Hank
84.09	Doff2 total run time	Real	0.03000.0	min	10 = 1 min
84.10	Doff2 Pattern stop time	Real	0.03000.0	min	10 = 1 min
84.11	Doff2 KWh	Real	0.03000.0	KWh	10 = 1 KWh
84.12	Doff2 KWh/Kg	Real	0.03000.0	KWh/Kg	10 = 1 KWh/Kg
84.13	Doff3 production Kg	Real	0.03000.0	Kg	10 = 1 Kg
84.14	Doff3 production hank	Real	0.0030000.00	Hank	100 = 1 Hank

No.	Name	Туре	Range	Unit	FbEq32
84.15	Doff3 total run time	Real	0.03000.0	min	10 = 1 min
84.16	Doff3 Pattern stop time	Real	0.03000.0	min	10 = 1 min
84.17	Doff3 KWh	Real	0.03000.0	KWh	10 = 1 KWh
84.18	Doff3 KWh/Kg	Real	0.03000.0	KWh/Kg	10 = 1 KWh/Kg
84.19	Doff4 production Kg	Real	0.03000.0	Kg	10 = 1 Kg
84.20	Doff4 production hank	Real	0.0030000.00	Hank	100 = 1 Hank
83.21	Doff4 total run time	Real	0.03000.0	min	10 = 1 min
84.22	Doff4 Pattern stop time	Real	0.03000.0	min	10 = 1 min
84.23	Doff4 KWh	Real	0.03000.0	KWh	10 = 1 KWh
84.24	Doff4 KWh/Kg	Real	0.03000.0	KWh/Kg	10 = 1 KWh/Kg
84.25	Doff5 production Kg	Real	0.03000.0	Kg	10 = 1 Kg
84.26	Doff5 production hank	Real	0.0030000.00	Hank	100 = 1 Hank
84.27	Doff5 total run time	Real	0.03000.0	min	10 = 1 min
84.28	Doff5 Pattern stop time	Real	0.03000.0	min	10 = 1 min
84.29	Doff5 KWh	Real	0.03000.0	KWh	10 = 1 KWh
84.30	Doff5 KWh/Kg	Real	0.03000.0	KWh/Kg	10 = 1 KWh/Kg
84.31	Doff6 production Kg	Real	0.03000.0	Kg	10 = 1 Kg
84.32	Doff6 production hank	Real	0.0030000.00	Hank	100 = 1 Hank
84.33	Doff6 total run time	Real	0.03000.0	min	10 = 1 min
84.34	Doff6 Pattern stop time	Real	0.03000.0	min	10 = 1 min
84.35	Doff6 KWh	Real	0.03000.0	KWh	10 = 1 KWh
84.36	Doff6 KWh/Kg	Real	0.03000.0	KWh/Kg	10 = 1 KWh/Kg
84.37	Doff7 production Kg	Real	0.03000.0	Kg	10 = 1 Kg
84.38	Doff7 production hank	Real	0.0030000.00	Hank	100 = 1 Hank
84.39	Doff7 total run time	Real	0.03000.0	min	10 = 1 min
84.40	Doff7 Pattern stop time	Real	0.03000.0	min	10 = 1 min
84.41	Doff7 KWh	Real	0.03000.0	KWh	10 = 1 KWh
84.42	Doff7 KWh/Kg	Real	0.03000.0	KWh/Kg	10 = 1 KWh/Kg
84.43	Doff8 production Kg	Real	0.03000.0	Kg	10 = 1 Kg
84.44	Doff8 production hank	Real	0.030000.0	Hank	100 = 1 Hank
84.45	Doff8 total run time	Real	0.03000.0	min	10 = 1 min
84.46	Doff8 Pattern stop time	Real	0.03000.0	min	10 = 1 min
84.47	Doff8 KWh	Real	0.03000.0	KWh	10 = 1 KWh
84.48	Doff8 KWh/Kg	Real	0.03000.0	KWh/Kg	10 = 1 KWhKg
84.49	Doff9 production Kg	Real	0.03000.0	Kg	10 = 1 Kg
84.50	Doff9 production hank	Real	0.0030000.00	Hank	100 = 1 Hank
84.51	Doff9 total run time	Real	0.03000.0	min	10 = 1 min
84.52	Doff9 Pattern stop time	Real	0.03000.0	min	10 = 1 min
84.53	Doff9 KWh	Real	0.03000.0	KWh	10 = 1 KWh
83.54	Doff9 KWh/Kg	Real	0.03000.0	KWh/Kg	10 = 1 KWh/Kg
84.55	Doff10 production Kg	Real	0.03000.0	Kg	10 = 1 Kg

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No.	Name	Туре	Range	Unit	FbEq32
84.56	Doff10 production hank	Real	0.0030000.00	Hank	100 = 1 Hank
84.57	Doff10 total run time	Real	0.03000.0	min	10 = 1 min
84.58	Doff10 Pattern stop time	Real	0.03000.0	min	10 = 1 min
84.59	Doff10 KWh	Real	0.03000.0	KWh	10 = 1 KWh
84.60	Doff10 KWh/Kg	Real	0.03000.0	KWh/Kg	10 = 1 KWh/Kg
88 Trav	erse				
88.01	Traverse control	UINT	01	S	1 = 1 s
88.02	Slow acc time	Real	0.0030000.00	s	100 = 1 s
88.03	Slow dec time	Real	0.0030000.00	S	100 = 1 s
88.04	Slow step up	Real	018000	rpm/%	1 = 1 rpm/%
88.05	Slow step down	Real	018000	rpm/%	1 = 1 rpm/%
88.06	Quick step high	Real	07200	rpm/%	1 = 1 rpm/%
88.07	Quick step low	Real	07200	rpm/%	1 = 1 rpm/%
88.08	Proportional steps	UINT	01	-	1 = 1
90 Feed	back selection	<u>.</u>			
90.01	Motor speed for control	Real	-32768.00 32767.00	rpm	100 = 1 rpm
90.02	Motor position	Real	0.0000000 1.00000000	rev	10000000 = 1 rev
90.03	Load speed	Real	-32768.00 32767.00	rpm	100 = 1 rpm
90.04	Load position	Real	-2147483648 2147483647	-	1 = 1
90.05	Load position scaled	Real	-2147483.648 2147483.647	-	100000 = 1
90.06	Motor position scaled	Real	-2147483.648 2147483.647	-	1000 = 1
90.07	Load position scaled int	Real	-2147483648 2147483647	-	1 = 1
90.10	Encoder 1 speed	Real	-32768.00 32767.00	rpm	100 = 1 rpm
90.11	Encoder 1 position	Real	0.0000000 1.00000000	rev	10000000 = 1 rev
90.12	Encoder 1 multiturn revolutions	Real	016777215	-	1 = 1
90.13	Encoder 1 revolution extension	Real	-2147483648 2147483647	-	1 = 1
90.14	Encoder 1 position raw	Real	016777215	-	1 = 1
90.15	Encoder 1 revolutions raw	Real	016777215	-	1 = 1
90.20	Encoder 2 speed	Real	-32768.00 32767.00	rpm	100 = 1 rpm
90.21	Encoder 2 position	Real	0.00000000 1.00000000	rev	10000000 = 1 rev
90.22	Encoder 2 multiturn revolutions	Real	016777215	-	1 = 1
90.23	Encoder 2 revolution extension	Real	-2147483648 2147483647	-	1 = 1
90.24	Encoder 2 position raw	Real	016777215	-	1 = 1
90.25	Encoder 2 revolutions raw	Real	016777215	-	1 = 1

No.	Name	Туре	Range	Unit	FbEq32
90.26	Motor revolution extension	Real	-2147483648 2147483647	-	1 = 1
90.27	Load revolution extension	Real	-2147483648 2147483647	-	1 = 1
90.35	Pos counter status	PB	000000b111111b	-	1 = 1
90.38	Pos counter decimals	List	09	-	1 = 1
90.41	Motor feedback selection	List	02	-	1 = 1
90.42	Motor speed filter time	Real	010000	ms	1 = 1 ms
90.43	Motor gear numerator	Real	-3276832767	-	1 = 1
90.44	Motor gear denominator	Real	-3276832767	-	1 = 1
90.45	Motor feedback fault	List	01	-	1 = 1
90.46	Force open loop	List	01	-	1 = 1
90.48	Motor position axis mode	List	01	-	1 = 1
90.49	Motor position resolution	Real	031	-	1 = 1
90.51	Load feedback selection	List	04	-	1 = 1
90.52	Load speed filter time	Real	010000	ms	1 = 1 ms
90.53	Load gear numerator	Real	-2147483648 2147483647	-	1 = 1
90.54	Load gear denominator	Real	-2147483648 2147483647	-	1 = 1
90.55	Load feedback fault	List	01	-	1 = 1
90.56	Load position offset	Real	-2147483648 2147483647	rev	1 = 1 rev
90.57	Load position resolution	Real	031	-	1 = 1
90.58	Pos counter init value int	Real	-2147483648 2147483647	-	1 = 1
90.59	Pos counter init value int source	Binary src	-	-	1 = 1
90.60	Pos counter error and boot action	List	01	-	1 = 1
90.61	Gear numerator	Real	-2147483648 2147483647	-	1 = 1
90.62	Gear denominator	Real	-2147483648 2147483647	-	1 = 1
90.63	Feed constant numerator	Real	-2147483648 2147483647	-	1 = 1
90.64	Feed constant denominator	Real	-2147483648 2147483647	-	1 = 1
90.65	Pos counter init value	Real	-2147483.648 2147483.647	-	1 = 1
90.66	Pos counter init value source	Binary src	-	-	1 = 1
90.67	Pos counter init cmd source	Binary src	-	-	1 = 1
90.68	Disable pos counter initialization	Binary src	-	-	1 = 1

No.	Name	Туре	Range	Unit	FbEq32
90.69	Reset pos counter init ready	Binary src	-	-	1 = 1
91 Enco	oder module settings				·
91.01	FEN DI status	PB	000000b111111b	-	1 = 1
91.02	Module 1 status	List	-	-	1 = 1
91.03	Module 2 status	List	-	-	1 = 1
91.04	Module 1 temperature	Real	01000	°C, °F or ohm	1 = 1 unit
91.06	Module 2 temperature	Real	01000	°C, °F or ohm	1 = 1 unit
91.10	Encoder parameter refresh	List	01	-	1 = 1
91.11	Module 1 type	List	04	-	1 = 1
91.12	Module 1 location	Real	1254	-	1 = 1
91.13	Module 2 type	List	04	-	1 = 1
91.14	Module 2 location	Real	1254	-	1 = 1
91.21	Module 1 temp sensor type	List	02	-	1 = 1
91.22	Module 1 temp filter time	Real	010000	ms	1 = 1 ms
91.24	Module 2 temp sensor type	List	02	-	1 = 1
91.25	Module 2 temp filter time	Real	010000	ms	1 = 1 ms
91.31	Module 1 TTL output source	List	02	-	1 = 1
91.32	Module 1 emulation pulses/rev	Real	065535	-	1 = 1
91.33	Module 1 emulated Z-pulse offset	Real	0.00000 1.00000	rev	100000 = 1 rev
91.41	Module 2 TTL output source	List	02	-	1 = 1
91.42	Module 2 emulation pulses/rev	Real	065535	-	1 = 1
91.43	Module 2 emulated Z-pulse offset	Real	0.00000 1.00000	rev	100000 = 1 rev
92 Enco	oder 1 configuration				·
92.01	Encoder 1 type	List	09	-	1 = 1
92.02	Encoder 1 source	List	12	-	1 = 1
			a TTL, TTL+ and HTL encod ble depending on encoder typ		
92.10	Pulses/revolution	Real	065535	-	1 = 1
92.11	Pulse encoder type	List	01	-	1 = 1
92.12	Speed calculation mode	List	05	-	1 = 1
92.13	Position estimation enable	List	01	-	1 = 1
92.14	Speed estimation enable	List	01	-	1 = 1
92.15	Transient filter	List	03	-	1 = 1
92.16	Encoder 1 supply voltage	List	02	-	1 = 1
92.17	Accepted pulse freq of encoder 1	Real	0300	kHz	1 = 1 kHz
92.21	Encoder cable fault mode	List	03	-	1 = 1

No.	Name	Туре	Range	Unit	FbEq32
92.23	Maximum pulse waiting time	Real	1200	ms	1 = 1 ms
92.24	Pulse edge filtering	List	02	-	1 = 1
92.25	Pulse overfrequency function	List	01	-	1 = 1
	Other parameters in	this group w	hen an absolute encoder is	selected	!
92.10	Sine/cosine number	Real	065535	-	1 = 1
92.11	Absolute position source	List	05	-	1 = 1
92.12	Zero pulse enable	List	01	-	1 = 1
92.13	Position data width	Real	032	-	1 = 1
92.14	Revolution data width	Real	032	-	1 = 1
92.30	Serial link mode	List	02	-	1 = 1
92.31	EnDat max calculation time	List	03	-	1 = 1
92.32	SSI cycle time	List	05	-	1 = 1
92.33	SSI clock cycles	Real	2127	-	1 = 1
92.34	SSI position msb	Real	1126	-	1 = 1
92.35	SSI revolution msb	Real	1126	-	1 = 1
92.36	SSI data format	List	01	-	1 = 1
92.37	SSI baud rate	List	05	-	1 = 1
92.40	SSI zero phase	List	03	-	1 = 1
92.45	Hiperface parity	List	01	-	1 = 1
92.46	Hiperface baud rate	List	03	-	1 = 1
92.47	Hiperface node address	Real	0255	-	1 = 1
	Other paramete	ers in this gro	oup when a resolver is sele	cted	
92.10	Excitation signal frequency	Real	120	kHz	1 = 1 kHz
92.11	Excitation signal amplitude	Real	4.0 12.0	V	10 = 1 V
92.12	Resolver polepairs	List	132	-	1 = 1
93 Enco	oder 2 configuration				·
93.01	Encoder 2 type	List	09	-	1 = 1
93.02	Encoder 2 source	List	12	-	1 = 1
			a TTL, TTL+ and HTL enco depending on encoder typ		ed
93.10	Pulses/rev	Real	065535	-	1 = 1
93.11	Pulse encoder type	List	01	-	1 = 1
93.12	Speed calculation mode	List	05	-	1 = 1
93.13	Position estimation enable	List	01	-	1 = 1
93.14	Speed estimation enable	List	01	-	1 = 1
93.15	Transient filter	List	03	-	1 = 1
	Encoder 2 supply voltage	List	02	-	1 = 1
93.16		1	0 200	kHz	1 = 1 kHz
93.16 93.17	Accepted pulse freq of encoder 2	Real	0300	KI IZ	
	Accepted pulse freq of	Real List	03	-	1 = 1
93.17	Accepted pulse freq of encoder 2				

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No.	Name	Туре	Range	Unit	FbEq32
93.25	Pulse overfrequency function	List	01	-	1 = 1
	Other parameters in a	this group v	when an absolute encoder is	selected	
93.10	Sine/cosine number	Real	065535	-	1 = 1
93.11	Absolute position source	List	05	-	1 = 1
93.12	Zero pulse enable	List	01	-	1 = 1
93.13	Position data width	Real	032	-	1 = 1
93.14	Revolution data width	Real	032	-	1 = 1
93.30	Serial link mode	List	02	-	1 = 1
93.31	EnDat calc time	List	03	-	1 = 1
93.32	SSI cycle time	List	05	-	1 = 1
93.33	SSI clock cycles	Real	2127	-	1 = 1
93.34	SSI position msb	Real	1126	-	1 = 1
93.35	SSI revolution msb	Real	1126	-	1 = 1
93.36	SSI data format	List	01	-	1 = 1
93.37	SSI baud rate	List	05	-	1 = 1
93.40	SSI zero phase	List	03	-	1 = 1
93.45	Hiperface parity	List	01	-	1 = 1
93.46	Hiperface baud rate	List	03	-	1 = 1
93.47	Hiperface node address	Real	0255	-	1 = 1
	Other paramete	rs in this gi	roup when a resolver is seled	ted	L.
93.10	Excitation signal frequency	Real	120	kHz	1 = 1 kHz
93.11	Excitation signal amplitude	Real	4.0 12.0	V	10 = 1 V
93.12	Resolver polepairs	List	132	-	1 = 1
94 LSU	control			I	
	(Group only visible	e when sup	ply unit control activated by §	95.20)	
94.01	LSU control	List	01	-	1 = 1
94.02	LSU panel communication	List	01	-	1 = 1
	(Parameters 94.2094.32 only	visible wh	en IGBT supply unit control a	activated by	95.20)
94.10	LSU max charging time	Real	065535	S	1 = 1 s
94.11	LSU stop delay	Real	0.0 3600.0	s	10 = 1 s
94.20	DC voltage reference	Real	0.0 2000.0	V	10 = 1 V
94.21	DC voltage ref source	List	-	-	1 = 1
94.22	User DC voltage reference	Real	0.0 2000.0	V	10 = 1 V
94.30	Reactive power reference	Real	-3276.8 3276.7	kvar	10 = 1 kvar
94.31	Reactive power ref source	List	-	-	1 = 1
94.32	User reactive power reference	Real	-3276.8 3276.7	kvar	10 = 1 kvar
	(Parameters 94.40 and 94.41	only visible	e when supply unit control ac	tivated by 9	5.20)
94.40	Power mot limit on net loss	Real	0.00 600.00	%	100 = 1%
94.41	Power gen limit on net loss	Real	-600.00 0.00	%	100 = 1%
95 HW d	configuration		<u> </u>	ļ	<u> </u>
95.01	Supply voltage	List	06	-	1 = 1
95.01	Supply voltage	List	06	-	1 = 1

No.	Name	Туре	Range	Unit	FbEq32
95.02	Adaptive voltage limits	List	01	-	1 = 1
95.04	Control board supply	List	02	-	1 = 1
	(Parameters	95.08 only	visible with a ZCU control un	nit)	
95.08	DC switch monitoring	List	01	-	1 = 1
	(Parameters 95.0	995.14 o	nly visible with a BCU contro	ol unit)	
95.09	Switch fuse controller	List	01	-	1 = 1
95.13	Reduced run mode	List	065535	-	1 = 1
95.14	Connected modules	PB	0000hFFFFh	-	1 = 1
95.15	Special HW settings	PB	0000hFFFFh	-	1 = 1
95.20	HW options word 1	PB	0000hFFFFh	-	1 = 1
95.21	HW options word 2	PB	0000hFFFFh	-	1 = 1
	(Parameters 95.3	095.31 o	nly visible with a BCU contro	ol unit)	
95.30	Parallel type filter	List	04	-	1 = 1
95.31	Parallel connection rating id	List	-	-	1 = 1
95.40	Transformation ratio	Real	0.000 100.000	-	1000 = 1
96 Syst	em				
96.01	Language	List	-	-	1 = 1
96.02	Pass code	Data	099999999	-	1 = 1
96.03	Access levels active	PB	0000hFFFFh	-	1 = 1
96.04	Macro select	List	06	-	1 = 1
96.05	Macro active	List	16	-	1 = 1
96.06	Parameter restore	List	-	-	1 = 1
96.07	Parameter save manually	List	01	-	1 = 1
96.08	Control board boot	Real	01	-	1 = 1
96.09	FSO reboot	Binary src	-	-	-
96.10	User set status	List	-	-	-
96.11	User set save/load	List	-	-	-
96.12	User set I/O mode in1	Binary src	-	-	-
96.13	User set I/O mode in2	Binary src	-	-	-
96.16	Unit selection	PB	0000hFFFFh	-	1 = 1
96.20	Time synch primary source	List	09	-	1 = 1
96.23	M/F and D2D clock synchronization	List	01	-	1 = 1
96.24	Full days since 1st Jan 1980	Real	159999	-	1 = 1
96.25	Time in minutes within 24 h	Real	01439	-	1 = 1
96.26	Time in ms within one minute	Real	059999	-	1 = 1
96.29	Time sync source status	PB	0000hFFFFh	-	1 = 1
96.31	Drive ID number	Real	032767	-	1 = 1
96.39	Power up event logging	List	01	-	1 = 1

No.	Name	Туре	Range	Unit	FbEq32
96.53	Actual checksum	Real	00000000hFFFFFFFh	-	1 = 1
96.54	Checksum action	List	04	-	1 = 1
96.55	Checksum control word	PB	0000hFFFFh	-	1 = 1
96.56	Approved checksum 1	Real	00000000hFFFFFFFh	-	1 = 1
96.57	Approved checksum 2	Real	00000000hFFFFFFFh	-	1 = 1
96.58	Approved checksum 3	Real	00000000hFFFFFFFh	-	1 = 1
96.59	Approved checksum 4	Real	00000000hFFFFFFFh	-	1 = 1
96.61	User data logger status word	PB	0000hFFFFh	-	1 = 1
96.63	User data logger trigger	Binary src	-	-	-
96.64	User data logger start	Binary src	-	-	-
96.65	Factory data logger time level	List	-	-	1 = 1
96.70	Disable adaptive program	List	01	-	1 = 1
	(Parameters 96.10096	.102 only v	isible when enabled by paran	neter <mark>96.02</mark>))
96.100	Change user pass code	Data	100000099999999	-	1 = 1
96.101	Confirm user pass code	Data	100000099999999	-	1 = 1
96.102	User lock functionality	PB	0000hFFFFh	-	1 = 1
	(Parameter <mark>96.108</mark> only vis	ible when l	GBT supply unit control active	ated by <mark>95</mark> .2	20)
96.108	LSU control board boot	Real	01	-	1 = 1
97 Moto	r control				1
97.01	Switching frequency reference	Real	024.000	kHz	1000 = 1%
97.02	Minimum switching frequency	Real	024.000	kHz	1000 = 1%
97.03	Slip gain	Real	0200	%	1 = 1%
97.04	Voltage reserve	Real	-450	%	1 = 1%
97.05	Flux braking	List	02	-	1 = 1
97.06	Flux reference select	Binary src	-	-	1 = 1
97.07	User flux reference	Real	0.00 200.00	%	100 = 1%
97.08	Optimizer minimum torque	Real	0.0 1600.0	%	10 = 1%
97.09	Switching freq mode	List	03	-	1 = 1
97.10	Signal injection	List	04	-	1 = 1
97.11	TR tuning	Real	25400	%	1 = 1%
97.12	IR comp step-up frequency	Real	0.0 50.0	Hz	10 = 1 Hz
97.13	IR compensation	Real	0.00 50.00	%	100 = 1%
97.15	Motor model temperature adaptation	List	03	-	1 = 1
97.18	Hexagonal field weakening	List	01		1 = 1
97.19	Hexagonal field weakening point	Real	0.0500.0	%	10 = 1%
97.32	Motor torque unfiltered	Real	-1600.0 1600.0	%	10 = 1%
97.33	Speed estimate filter time	Real	0.00 100.00	ms	100 = 1 ms

No.	Name	Туре	Range	Unit	FbEq32
98 User	motor parameters				
98.01	User motor model mode	List	03	-	1 = 1
98.02	Rs user	Real	0.0000 0.50000	p.u.	100000 = 1 p.u.
98.03	Rr user	Real	0.0000 0.50000	p.u.	100000 = 1 p.u.
98.04	Lm user	Real	0.00000 10.00000	p.u.	100000 = 1 p.u.
98.05	SigmaL user	Real	0.00000 1.00000	p.u.	100000 = 1 p.u.
98.06	Ld user	Real	0.00000 10.00000	p.u.	100000 = 1 p.u.
98.07	Lq user	Real	0.00000 10.00000	p.u.	100000 = 1 p.u.
98.08	PM flux user	Real	0.00000 2.00000	p.u.	100000 = 1 p.u.
98.09	Rs user SI	Real	0.00000 100.00000	ohm	100000 = 1 p.u.
98.10	Rr user SI	Real	0.00000 100.00000	ohm	100000 = 1 p.u.
98.11	Lm user SI	Real	0.00 100000.00	mH	100 = 1 mH
98.12	SigmaL user SI	Real	0.00 100000.00	mH	100 = 1 mH
98.13	Ld user SI	Real	0.00 100000.00	mH	100 = 1 mH
98.14	Lq user SI	Real	0.00 100000.00	mH	100 = 1 mH
98.15	Position offset user	Real	0360	degrees electrical	1 = 1 deg
99 Moto	or data		l		
99.03	Motor type	List	02	-	1 = 1
99.04	Motor control mode	List	01	-	1 = 1
99.06	Motor nominal current	Real	0.0 6400.0	A	10 = 1 A
99.07	Motor nominal voltage	Real	0.0 800.0	V	10 = 1 V
99.08	Motor nominal frequency	Real	0.00 1000.00	Hz	10 = 1 Hz
99.09	Motor nominal speed	Real	0 30000	rpm	1 = 1 rpm
99.10	Motor nominal power	Real	0.00 … 10000.00 kW or 0.00 … 13404.83 hp	kW or hp	100 = 1 unit
99.11	Motor nominal cos Φ	Real	0.00 1.00	-	100 = 1
99.12	Motor nominal torque	Real	0.000 4000000.000	N·m or Ib∙ft	1000 = 1 unit
99.13	ID run requested	List	07	-	1 = 1
99.14	Last ID run performed	List	07	-	1 = 1
99.15	Motor polepairs calculated	Real	01000	-	1 = 1
99.16	Motor phase order	List	01	-	1 = 1
99.18	Sine filter inductance	Real	0.000 100000.000	mH	1000 = 1 mH
99.19	Sine filter capacitance	Real	0.000 10000.00	μF	100 = 1 µF
99.200	Application select	List	02	-	1 = 1

548 Additional Parameter data

No.	Name	Туре	Range	Unit	FbEq32	
200 Safe	200 Safety					
This group contains parameters related to the optional FSO-xx safety functions module. For details on the parameters in this group, refer to the documentation of the FSO-xx module.						

9

Fault tracing

Contents of this chapter

This chapter lists the warning and fault messages including possible causes and corrective actions. The causes of most warnings and faults can be identified and corrected using the information in this chapter. If not, an ABB service representative should be contacted.

Warnings and faults are listed below in separate tables. Each table is sorted by warning/fault code.

Safety

WARNING! Only qualified electricians are allowed to service the drive. Read the *Safety instructions* on the first pages of the Hardware manual before working on the drive.

Indications

Warnings and faults

Warnings and faults indicate an abnormal drive status. The codes and names of active warnings/faults are displayed on the control panel of the drive as well as the Drive composer PC tool. Only the codes of warnings/faults are available over fieldbus.

Warnings do not need to be reset; they stop showing when the cause of the warning ceases. Warnings do not latch and the drive will continue to operate the motor.

Faults do latch inside the drive and cause the drive to trip, and the motor stops. After the cause of a fault is removed, the fault can be reset from a selectable source (see

parameter 31.11 Fault reset selection) such as the control panel, Drive composer PC tool, the digital inputs of the drive, or fieldbus. After the fault is reset, the drive can be restarted. Note that some faults require a reboot of the control unit either by switching the power off and on, or using parameter 96.08 Control board boot – this is mentioned in the fault listing wherever appropriate.

Warning and fault indications can be directed to a relay output or a digital input/output by selecting *Warning*, *Fault* or *Fault (-1)* in the source selection parameter. See sections

- Programmable digital inputs and outputs (page 61)
- Programmable relay outputs (page 62), and
- Programmable I/O extensions (page 62).

Pure events

In addition to warnings and faults, there are pure events that are only recorded in the event logs of the drive. The codes of these events are included in the *Warning messages* table.

Editable messages

For some warnings and faults, the message text can be edited and instructions and contact information added. To edit these messages, choose **Menu** - **Settings** - **Edit texts** on the control panel.

Warning/fault history and analysis

Event logs

The drive has two event logs. One log contains faults and fault resets; the other contains warnings, pure events, and clearing entries. Each log contains the 64 most recent events with a time stamp and other information.

The logs can be accessed separately from the main Menu on the control panel. The logs are displayed as a single list when viewed using the Drive composer PC tool.

Auxiliary codes

Some events generate an auxiliary code that often helps in pinpointing the problem. The auxiliary code is displayed on the control panel together with the message. It is also stored in the event log details. In the Drive composer PC tool, the auxiliary code (if any) is shown in the event listing.

Factory data logger

The drive has a data logger that samples preselected drive values at 500microsecond (default; see parameter 96.65 *Factory data logger time level*) intervals. By default, approximately 700 samples recorded immediately before and after a fault are saved to the memory unit of the drive. The fault data of the last five faults is accessible in the event log when viewed in the Drive composer pro PC tool. (The fault data is not accessible through the control panel.)

The values that are recorded in the factory data log are 01.07 Motor current, 01.10 Motor torque, 01.11 DC voltage, 01.24 Flux actual %, 06.01 Main control word, 06.11 Main status word 24.01 Used speed reference, 30.01 Limit word 1, 30.02 Torque limit status and 90.01 Motor speed for control. The selection of parameters cannot be changed by the user.

Other data loggers

User data logger

A custom data logger can be configured using the Drive composer pro PC tool. This functionality enables the free selection of up to eight drive parameters to be sampled at selectable intervals. The triggering conditions and the length of the monitoring period can also be defined by the user within the limit of approximately 8000 samples. In addition to the PC tool, the status of the logger is shown by drive parameter *96.61 User data logger status word*. The triggering sources can be selected by parameters *96.63 User data logger trigger* and *96.64 User data logger start*). The configuration, status and collected data is saved to the memory unit for later analysis.

PSL2 data logger

The BCU control unit used with certain drive types (especially those with parallelconnected inverter modules) contains a data logger that collects data from the inverter modules to help fault tracing and analysis. The data is saved onto the SD memory card attached to the BCU, and can be analyzed by ABB service personnel.

Parameters that contain warning/fault information

The drive is able to store a list of the active faults actually causing the drive to trip at the present time. The faults are displayed in parameter group *04 Warnings and faults* (page *142*). The parameter group also displays a list of faults and warnings that have previously occurred.

Event word (parameters 04.40...04.72)

Parameter 04.40 Event word 1 can be configured by the user to indicate the status of 16 selectable events (ie. faults, warnings or pure events). It is possible to specify an auxiliary code for each event to filter out other auxiliary codes.

QR Code generation for mobile service application

A QR Code (or a series of QR Codes) can be generated by the drive for display on the control panel. The QR code contains drive identification data, information on the latest events, and values of status and counter parameters. The code can be read with a mobile device containing the ABB service application, which then sends the data to ABB for analysis. For more information on the application, contact your local ABB service representative.

The QR Code can be generated by choosing **Menu** - **Assistants** - **QR code** on the control panel.

Warning messages

Code (hex)	Warning	Cause	What to do
A2A1	Current calibration	Current offset and gain measurement calibration will occur at next start.	Informative warning. (See parameter 99.13 ID run requested.)
A2B3	Earth leakage Programmable fault: <i>31.20 Earth fault</i>	Drive has detected load unbalance typically due to earth fault in motor or motor cable.	Check there are no power factor correction capacitors or surge absorbers in motor cable. Check for an earth fault in motor or motor cables by measuring the insulation resistances of motor and motor cable. Try running the motor in scalar control mode if allowed. (See parameter 99.04 <i>Motor control mode.</i>) If no earth fault can be detected, contact your local ABB representative.
A2B4	Short circuit	Short-circuit in motor cable(s) or motor.	Check motor and motor cable for cabling errors. Check there are no power factor correction capacitors or surge absorbers in motor cable.
A2BA	IGBT overload	Excessive IGBT junction to case temperature. This warning protects the IGBT(s) and can be activated by a short circuit in the motor cable.	Check motor cable. Check ambient conditions. Check air flow and fan operation. Check heatsink fins for dust pick-up. Check motor power against drive power.
A3A1	DC link overvoltage	Intermediate circuit DC voltage too high (when the drive is stopped).	Check the supply voltage setting (parameter <i>95.01 Supply voltage</i>). Note that the wrong setting of the parameter
A3A2	DC link undervoltage	Intermediate circuit DC voltage too low (when the drive is stopped).	may cause the motor to rush uncontrollably, or may overload the brake chopper or resistor Check the supply voltage.
A3AA	DC not charged	The voltage of the intermediate DC circuit has not yet risen to operating level.	With A3A1 or A3A2 on parallel- connected inverter modules, the auxiliary code indicates the affected module. The format of the code is 0x000X XX00, where "XXX" specifies the channel on the BCU control unit. If the problem persists, contact your local ABB representative.
A480	Motor cable overload	Calculated motor cable temperature has exceeded warning limit.	Check the settings of parameters 35.61 and 35.62. Check the dimensioning of the motor cable in regard to required load.

Code (hex)	Warning	Cause	What to do
A490	Incorrect temperature sensor setup	Problem with motor temperature measurement.	Check the auxiliary code (format 0XYY ZZZZ). "X" identifies the affected temperature monitoring function (0 = parameter 35.11, 1 = parameter 35.21). "YY" indicates the selected temperature source, ie. the setting of the selection parameter in hexadecimal. "ZZZZ" indicates the problem (see actions for each code below).
	0001	Sensor type mismatch	Check parameters 35.11/35.21 against 35.21/35.24.
	0002	Temperature under limit	Check parameters
	0003	Short circuit	35.1135.14/35.2135.24 (and 35.21/35.24 if sensor is connected to an
	0004	Open circuit	encoder interface). Check the sensor and its wiring.
A491	External temperature 1 (Editable message text)	Measured temperature 1 has exceeded warning limit.	Check the value of parameter 35.02 Measured temperature 1. Check the cooling of the motor (or other equipment whose temperature is being measured). Check the value of 35.13 Temperature 1 warning limit.
A492	External temperature 2 (Editable message text)	Measured temperature 2 has exceeded warning limit.	Check the value of parameter 35.03 Measured temperature 2. Check the cooling of the motor (or other equipment whose temperature is being measured). Check the value of 35.23 Temperature 2 warning limit.
A497	Motor temperature 1 (Editable message text)	The thermistor protection module installed in slot 1 indicates overtemperature.	Check the cooling of the motor. Check the motor load and drive ratings. Check the wiring of the temperature
A498	Motor temperature 2 (Editable message text)	The thermistor protection module installed in slot 2 indicates overtemperature.	sensor. Repair wiring if faulty. Measure the resistance of the sensor. Replace sensor if faulty.
A499	Motor temperature 3 (Editable message text)	The thermistor protection module installed in slot 3 indicates overtemperature.	
A4A0	Control board temperature	Control unit temperature is excessive.	Check the auxiliary code. See actions for each code below.
	(none)	Temperature above warning limit	Check ambient conditions. Check air flow and fan operation. Check heatsink fins for dust pick-up.
	1	Thermistor broken	Contact an ABB service representative for control unit replacement.

Code (hex)	Warning	Cause	What to do
A4A9	Cooling	Drive module temperature is excessive.	Check ambient temperature. If it exceeds 40 °C (104 °F), ensure that load current does not exceed derated load capacity of drive. See appropriate <i>Hardware manual</i> . Check drive module cooling air flow and fan operation. Check inside of cabinet and heatsink of drive module for dust pick-up. Clean whenever necessary.
A4B0	Excess temperature	Power unit temperature is excessive.	Check ambient conditions. Check air flow and fan operation. Check heatsink fins for dust pick-up. Check motor power against drive power. Check the auxiliary code (format XXXY YYZZ). "Y YY" specifies through which BCU control unit channel the fault was received. "ZZ" specifies the location (1: U-phase, 2: V-phase, 3: W-phase, 4: INT board, 5: Brake chopper, 6: Air inlet (sensor connected to INT board X10), 7: PCB compartment fan or power supply board, 8: du/dt filter or temperature switch (XT) (sensor connected to INT board X7), 9: Sensor connected to INT board X6, 0FA: Ambient temperature).
A4B1	Excess temperature difference	High temperature difference between the IGBTs of different phases.	Check the motor cabling. Check cooling of drive module(s). Check the auxiliary code (format XXXY YYZZ). "XXX" indicates the source of difference (0 : Single module, difference between phase IGBTs, 1 : parallel- connected modules, minimum-maximum difference between all IGBTs of all modules). With parallel-connected modules, "Y YY" specifies through which BCU control unit channel the fault was received. "ZZ" specifies the phase (0 : single module, 1 : U-phase [parallel connection], 2 : W-phase [parallel connection], 3 : W-phase [parallel connection]).
A4B2	PCB space cooling	Temperature difference between ambient and drive module PCB space is excessive.	Check the cooling fan inside the PCB space. With parallel-connected modules, check the auxiliary code (format XXXY YYZZ). "Y YY" specifies through which BCU control unit channel the fault was received.
A4F6	IGBT temperature	Drive IGBT temperature is excessive.	Check ambient conditions. Check air flow and fan operation. Check heatsink fins for dust pick-up. Check motor power against drive power.

Code (hex)	Warning	Cause	What to do
A580	PU communication	Communication errors detected between the drive control unit and the power unit.	Check the connections between the drive control unit and the power unit. Check the auxiliary code (format XXXY YYZZ). With parallel-connected modules, "Y YY" specifies the affected BCU control unit channel (0: broadcast). "ZZ" specifies the error source (8: Transmission errors in PSL link [see "XXX"], 9: Transmitter FIFO warning limit hit). "XXX" specifies the transmission error direction and detailed warning code (0: Rx/communication error, 1: Tx/Reed- Solomon symbol error, 2: Tx/no synchronization error, 3: Tx/Reed- Solomon decoder failures, 4: Tx/Manchester coding errors).
A581	Fan	Cooling fan stuck or disconnected.	Check the setting of parameter 95.20 <i>HW options word 1</i> , bit 14. Check the auxiliary code to identify the fan. Code 0 denotes main fan 1. Other codes (format XYZ): "X" specifies state code (1 : ID run, 2 : normal). "Y" specifies the index of the inverter unit connected to BCU (0n , always 0 for ZCU control units). "Z" specifies the index of the fan (1 : Main fan 1, 2 : Main fan 2, 3 : Main fan 3). Check fan operation and connection. Replace fan if faulty.
A582	Auxiliary fan missing	An auxiliary cooling fan (connected to the fan connectors on the control unit) is stuck or disconnected.	The auxiliary code identifies the fan (1 : Auxiliary fan 1, 2 : Auxiliary fan 2). Check auxiliary fan(s) and connection(s). Replace faulty fan. Make sure the front cover of the drive module is in place and tightened. If the commissioning of the drive requires that the cover is off, this warning will be generated even if the corresponding fault is defeated. See fault <i>5081 Auxiliary fan</i> <i>broken</i> (page <i>574</i>).
A5A0	Safe torque off Programmable warning: 31.22 STO indication run/stop	Safe torque off function is active, i.e. safety circuit signal(s) connected to connector XSTO is lost.	Check safety circuit connections. For more information, see appropriate drive hardware manual and description of parameter <i>31.22 STO indication run/stop</i> (page <i>291</i>).
A5EA	Measurement circuit temperature	Problem with internal temperature measurement of the drive.	Check the auxiliary code (format XXXY YYZZ). "Y YY" specifies through which BCU control unit channel the fault was received ("0 00" with a ZCU control unit). "ZZ" specifies the location (1: U-phase IGBT, 2: V-phase IGBT, 3: W-phase IGBT, 4: Power unit INT board, 5: Brake chopper, 6: Air inlet, 7: Power supply board, 8: du/dt filter, FAh: Air in temp).
A5EB	PU board powerfail	Power unit power supply failure.	Contact your local ABB representative.

Code (hex)	Warning	Cause	What to do
A5EC	PU communication internal	Communication errors detected between the drive control unit and the power unit.	Check the connections between the drive control unit and the power unit.
A5ED	Measurement circuit ADC	Problem with measurement circuit of power unit (analog to digital converter)	Contact your local ABB representative.
A5EE	Measurement circuit DFF	Problem with current or voltage measurement of power unit	Contact your local ABB representative.
A5EF	PU state feedback	State feedback from output phases does not match control signals.	Contact your local ABB representative.
A5F0	Charging feedback	Charging in progress	Informative warning. Wait until charging finishes before starting the inverter unit.
A5F3	Switching frequency below requested	Adequate motor control at requested output frequency cannot be reached because of limited switching frequency (eg. by parameter <i>95.15</i>).	Informative warning.
A5F4	Control unit battery	The battery of the control unit is low.	Replace control unit battery. This warning can be suppressed using parameter <i>31.40</i> .
A682	Flash erase speed exceeded	The flash memory (in the memory unit) has been erased too frequently, compromising the lifetime of the memory.	Avoid forcing unnecessary parameter saves by parameter 96.07 or cyclic parameter writes. Check the auxiliary code (format XYYY YZZZ). "X" specifies the source of warning (1: generic flash erase supervision). "ZZZ" specifies the flash subsector number that generated the warning.
A683	Data saving to power unit	An error in saving data to the power unit.	Check the auxiliary code. See actions for each code below.
	0 1 2	An error is preventing saving from initializing. Write error.	Cycle the power to the drive. If the control unit is externally powered, also reboot the control unit (using parameter <i>96.08 Control board boot</i>) or by cycling its power. If the problem persists, contact your local ABB representative.
A684	SD card	Error related to SD card used to store data (BCU control unit only).	Check the auxiliary code. See actions for each code below.
	1	No SD card	Insert a compatible, writable SD card into
	2	SD card write-protected	the SD CARD slot of the BCU control unit.
	3	SD card unreadable	
A686	Checksum mismatch Programmable warning: 96.54 Checksum action	The calculated parameter checksum does not match any enabled reference checksum.	Check that all necessary approved (reference) checksums (96.5696.59) are enabled in 96.55 Checksum control word. Check the parameter configuration. Using 96.55 Checksum control word, enable a checksum parameter and copy the actual checksum into that parameter.

Code (hex)	Warning	Cause	What to do
A687	Checksum configuration	An action has been defined for a parameter checksum mismatch but the feature has not been configured.	Contact your local ABB representative for configuring the feature, or disable the feature in <i>96.54 Checksum action</i> .
A688	Parameter map configuration	Too much data in parameter mapping table created in Drive customizer.	See the <i>Drive customizer PC tool user's manual</i> (3AUA0000104167 [English]).
A689	Mapped parameter value cut	Parameter value saturated eg. by the scaling specified in parameter mapping table (created in Drive customizer).	Check parameter scaling and format in parameter mapping table. See the <i>Drive</i> <i>customizer PC tool user's manual</i> (3AUA0000104167 [English]).
A6A4	Motor nominal value	The motor parameters are set incorrectly.	Check the auxiliary code. See actions for each code below.
		The drive is not dimensioned correctly.	
	1	Slip frequency is too small	Check the settings of the motor
	2	Synchronous and nominal speeds differ too much	configuration parameters in groups 98 and 99. Check that the drive is sized correctly for
	3	Nominal speed is higher than synchronous speed with 1 pole pair	the motor.
	4	Nominal current is outside limits	
	5	Nominal voltage is outside limits	
	6	Nominal power is higher than apparent power	
	7	Nominal power not consistent with nominal speed and torque	
A6A5	No motor data	Parameters in group 99 have not been set.	Check that all the required parameters in group 99 have been set. Note: It is normal for this warning to appear during the start-up and continue until the motor data is entered.
A6A6	Supply voltage unselected	The supply voltage has not been defined.	Set supply voltage in parameter <i>95.01</i> <i>Supply voltage</i> .
A6B0	User lock is open	The user lock is open, ie. user lock configuration parameters 96.10096.102 are visible.	Close the user lock by entering an invalid pass code in parameter 96.02 Pass code. See section User lock (page 124).
A6B1	User pass code not confirmed	A new user pass code has been entered in parameter 96.100 but not confirmed in 96.101.	Confirm the new pass code by entering the same code in <i>96.101</i> . To cancel, close the user lock without confirming the new code. See section <i>User lock</i> (page <i>124</i>).
A6D1	FBA A parameter conflict	The drive does not have a functionality requested by a PLC, or requested functionality has not been activated.	Check PLC programming. Check settings of parameter groups 50 Fieldbus adapter (FBA) and 54 FBA B settings.

Code (hex)	Warning	Cause	What to do
A6D2	FBA B parameter conflict	The drive does not have a functionality requested by a PLC, or requested functionality has not been activated.	Check PLC programming. Check settings of parameter groups 50 <i>Fieldbus adapter (FBA)</i> and 54 <i>FBA B</i> <i>settings</i> .
A6DA	Reference source parametrization	A reference source is simultaneously connected to multiple parameters with different units.	Check the reference source selection parameters. Check the auxiliary code (format XXYY 00ZZ). "XX" and "YY" specify the two sets of parameters where the source was connected to (01 = speed reference chain [22.11, 22.12, 22.15, 22.17], 02 = frequency reference chain [28.11, 28.12], 03 = torque reference chain [26.11, 26.12, 26.16], 04 = other torque-related parameters [26.25, 30.21, 30.22, 44.09], 05 = process PID control parameters [40.16, 40.17, 40.50, 41.16, 41.17, 41.50]). "ZZ" indicates the conflicting reference source (010E = index in parameter group 3, 33 = process PID control, 3D = motor potentiometer, 65 = AI1, 66 = AI2, 6F = frequency input).
A6E5	AI parametrization	The current/voltage hardware setting of an analog input does not correspond to parameter settings.	Check the auxiliary code. The code identifies the analog input whose settings are in conflict. Adjust either the hardware setting (on the drive control unit) or parameter 12.15/12.25. Note: Control board reboot (either by cycling the power or through parameter 96.08 Control board boot) is required to validate any changes in the hardware settings.
A6E6	ULC configuration	User load curve configuration error.	Check the auxiliary code (format XXXX ZZZZ). "ZZZZ" indicates the problem (see actions for each code below).
	0000	Speed points inconsistent.	Check that each speed point (parameters 37.1137.15) has a higher value than the previous point.
	0001	Frequency points inconsistent.	Check that each frequency point $(37.1637.20)$ has a higher value than the previous point.
	0002	Underload point above overload point.	Check that each overload point (37.3137.35) has a higher value than
	0003	Overload point below underload point.	the corresponding underload point (37.2137.25).
A780	Motor stall Programmable warning: 31.24 Stall function	Motor is operating in stall region because of e.g. excessive load or insufficient motor power.	Check motor load and drive ratings. Check fault function parameters.
A781	Motor fan Programmable warning: 35.106 DOL starter event type	No feedback received from external fan.	Check external fan (or other equipment controlled) by the logic. Check settings of parameters 35.10035.106.

Code (hex)	Warning	Cause	What to do
A782	FEN temperature	Error in temperature measurement when temperature sensor (KTY or PTC) connected to encoder interface FEN-xx is used.	Check that parameter 35.11 Temperature 1 source / 35.21 Temperature 2 source setting corresponds to actual encoder interface installation. Check the settings of parameters 91.21 and 91.24. Check that the corresponding module is activated in parameters 91.1191.14. Use parameter 91.10 Encoder parameter refresh to validate any changes in the settings.
		Error in temperature measurement when KTY sensor connected to encoder interface FEN-01 is used.	FEN-01 does not support temperature measurement with KTY sensor. Use PTC sensor or other encoder interface module.
A791	Brake resistor	Brake resistor broken or not connected.	Check that a brake resistor has been connected. Check the condition of the brake resistor.
A793	BR excess temperature	Brake resistor temperature has exceeded warning limit defined by parameter 43.12 Brake resistor warning limit.	Stop drive. Let resistor cool down. Check resistor overload protection function settings (parameter group 43 <i>Brake chopper</i>). Check warning limit setting, parameter 43.12 Brake resistor warning limit. Check that the resistor has been dimensioned correctly. Check that braking cycle meets allowed limits.
A794	BR data	Brake resistor data has not been given.	One or more of the resistor data settings (parameters 43.0843.10) is incorrect. The parameter is specified by the auxiliary code.
	0000 0001	Resistance value too low.	Check value of 43.10.
	0000 0002	Thermal time constant not given.	Check value of 43.08.
	0000 0003	Maximum continuous power not given.	Check value of 43.09.
A797	Speed feedback configuration	Speed feedback configuration has changed.	Check the auxiliary code (format XXYY ZZZZ). "XX" specifies the number of the encoder interface module (01 : 91.11/91.12, 02 : 91.13/91.14), "YY" specifies the encoder (01 : 92 Encoder 1 configuration, 02 : 93 Encoder 2 configuration). "ZZZZ" indicates the problem (see actions for each code below).
	0001	Adapter not found in specified slot.	Check module location (91.12 or 91.14).
	0002	Detected type of interface module does not match parameter setting.	Check the module type (91.11 or 91.13) against status (91.02 or 91.03).
	0003	Logic version too old.	Contact your local ABB representative.
	0004	Software version too old.	Contact your local ABB representative.

0006 0007 0008 0009	Encoder type incompatible with interface module type. Adapter not configured. Speed feedback configuration has changed.	Check module type (91.11 or 91.13) against encoder type (92.01 or 93.01). Check module location (91.12 or 91.14). Use parameter 91.10 Encoder parameter
0008	Speed feedback configuration	, ,
		Use parameter 91.10 Encoder parameter
0009		refresh to validate any changes in the settings.
	No encoders configured to encoder module	Configure the encoder in group 92 Encoder 1 configuration or 93 Encoder 2 configuration.
000A	Non-existing emulation input.	Check input selection (91.31 or 91.41).
000B	Echo not supported by selected input (for example, resolver or absolute encoder).	Check input selection (91.31 or 91.41), interface module type, and encoder type.
000C	Emulation in continuous mode not supported.	Check input selection (91.31 or 91.41) and serial link mode (92.30 or 93.30) settings.
Encoder option comm loss	Encoder feedback not used as actual feedback, or measured motor feedback lost (and parameter 90.45/90.55 is set to <i>Warning</i>).	Check that the encoder is selected as feedback source in parameter 90.41 or 90.51. Check that the encoder interface module is properly seated in its slot. Check that the encoder interface module or slot connectors are not damaged. To pinpoint the problem, try installing the module into a different slot. If the module is installed on an FEA-03 extension adapter, check the fiber optic connections. Check the auxiliary code (format XXXX YYYY). "YYYY" indicates the problem (see actions for each code below).
	Failed answer to encoder configuration message.	Contact your local ABB representative.
	watchdog disable message.	Contact your local ABB representative.
0003	Failed answer to adapter watchdog enable message.	Contact your local ABB representative.
0004	Failed answer to adapter configuration message.	Contact your local ABB representative.
0005	Too many failed answers inline to speed and position messages.	Contact your local ABB representative.
0006	DDCS driver failed.	Contact your local ABB representative.
BC short circuit	Short circuit in brake chopper IGBT	Replace brake chopper if external. Drives with internal choppers will need to be returned to ABB. Ensure brake resistor is connected and not damaged.
	000B 000C Encoder option comm loss 0001 0001 0002 0003 0003 0004 0005	000ANon-existing emulation input.000BEcho not supported by selected input (for example, resolver or absolute encoder).000CEmulation in continuous mode not supported.Encoder option comm lossEncoder feedback not used as actual feedback, or measured motor feedback lost (and parameter 90.45/90.55 is set to Warning).0001Failed answer to encoder configuration message.0002Failed answer to adapter watchdog disable message.0003Failed answer to adapter watchdog enable message.0004Failed answer to adapter configuration message.0005Too many failed answers inline to speed and position messages.0006DDCS driver failed.BC short circuitShort circuit in brake chopper

Code (hex)	Warning	Cause	What to do
A79C	BC IGBT excess temperature	Brake chopper IGBT temperature has exceeded internal warning limit.	Let chopper cool down. Check for excessive ambient temperature. Check for cooling fan failure. Check for obstructions in the air flow. Check the dimensioning and cooling of the cabinet. Check resistor overload protection function settings (parameters 43.0643.10). Check minimum allowed resistor value for the chopper being used. Check that braking cycle meets allowed limits. Check that drive supply AC voltage is not excessive.
A7A1	Mechanical brake closing failed Programmable warning: 44.17 Brake fault function	Status of mechanical brake acknowledgement is not as expected during brake close.	Check mechanical brake connection. Check mechanical brake settings in parameter group <i>44 Mechanical brake</i> <i>control</i> . Check that acknowledgement signal matches actual status of brake.
A7A2	Mechanical brake opening failed Programmable warning: 44.17 Brake fault function	Status of mechanical brake acknowledgement is not as expected during brake open.	Check mechanical brake connection. Check mechanical brake settings in parameter group 44 Mechanical brake control. Check that acknowledgement signal matches actual status of brake.
A7A5	Mechanical brake opening not allowed Programmable warning: 44.17 Brake fault function	Open conditions of mechanical brake cannot be fulfilled (for example, brake has been prevented from opening by parameter 44.11 Keep brake closed).	Check mechanical brake settings in parameter group 44 Mechanical brake control (especially 44.11 Keep brake closed). Check that acknowledgement signal (if used) matches actual status of brake.
A7AA	Extension AI parametrization	The hardware current/voltage setting of an analog input (on an I/O extension module) does not correspond to parameter settings.	Check the auxiliary code (format XX00 00YY). "XX" specifies the number of the I/O extension module (01 : parameter group 14 I/O extension module 1, 02 : 15 I/O extension module 2, 03 : 16 I/O extension module 3). "YY" specifies the analog input on the module. For example, in case of I/O extension module 1, analog input Al1 (auxiliary code 0000 0101), the hardware current/voltage setting on the module is shown by parameter 14.29. The corresponding parameter setting is 14.30. Adjust either the hardware setting on the module or the parameter to solve the mismatch. Note: Control board reboot (either by cycling the power or through parameter 96.08 Control board boot) is required to validate any changes in the hardware settings.

Code (hex)	Warning	Cause	What to do
A7AB	Extension I/O configuration failure	The I/O extension module types and locations specified by parameters do not match the detected configuration.	Check the type and location settings of the modules (parameters 14.01, 14.02, 15.01, 15.02, 16.01 and 16.02). Check that the modules are properly installed. Check the auxiliary code. See Drive application programming manual (IEC 61131-3) (3AUA0000127808 [English]).
A7B0	Motor speed feedback Programmable warning: 90.45 Motor feedback fault	No motor speed feedback is received.	Check the auxiliary code (format XXYY ZZZZ). "XX" specifies the number of the encoder interface module (01 : 91.11/91.12, 02 : 91.13/91.14), "YY" specifies the encoder (01 : 92 Encoder 1 configuration, 02 : 93 Encoder 2 configuration). "ZZZZ" indicates the problem (see actions for each code below).
	0001	Motor gear definition invalid or outside limits.	Check motor gear settings (90.43 and 90.44).
	0002	Encoder not configured.	Check encoder settings (92 Encoder 1 configuration or 93 Encoder 2 configuration). Use parameter 91.10 Encoder parameter refresh) to validate any changes in the settings.
	0003	Encoder stopped working.	Check encoder status.
	0004	Encoder drift detected.	Check for slippage between encoder and motor.
A7B1	Load speed feedback Programmable warning: 90.55 Load feedback fault	No load speed feedback is received.	Check the auxiliary code (format XXYY ZZZZ). "XX" specifies the number of the encoder interface module (01 : 91.11/91.12, 02 : 91.13/91.14), "YY" specifies the encoder (01 : 92 Encoder 1 configuration, 02 : 93 Encoder 2 configuration). "ZZZZ" indicates the problem (see actions for each code below).
	0001	Load gear definition invalid or outside limits.	Check load gear settings (90.53 and 90.54).
	0002	Feed constant definition invalid or outside limits.	Check feed constant settings (90.63 and 90.64).
	0003	Encoder stopped working.	Check encoder status.
A7C1	FBA A communication Programmable warning: 50.02 FBA A comm loss func	Cyclical communication between drive and fieldbus adapter module A or between PLC and fieldbus adapter module A is lost.	Check status of fieldbus communication. See user documentation of fieldbus interface. Check settings of parameter groups 50 Fieldbus adapter (FBA), 51 FBA A settings, 52 FBA A data in and 53 FBA A data out. Check cable connections. Check if communication master is able to communicate.

Code (hex)	Warning	Cause	What to do
A7C2	FBA B communication Programmable warning: 50.32 FBA B comm loss func	Cyclical communication between drive and fieldbus adapter module B or between PLC and fieldbus adapter module B is lost.	Check status of fieldbus communication. See user documentation of fieldbus interface. Check settings of parameter group 50 <i>Fieldbus adapter (FBA)</i> . Check cable connections. Check if communication master is able to communicate.
A7CA	DDCS controller comm loss Programmable warning: 60.59 DDCS controller comm loss function	DDCS (fiber optic) communication between drive and external controller is lost.	Check status of controller. See user documentation of controller. Check settings of parameter group 60 DDCS communication. Check cable connections. If necessary, replace cables.
A7CB	MF comm loss Programmable warning: 60.09 M/F comm loss function	Master/follower communication is lost.	Check the auxiliary code. The code indicates which node address (defined by parameter 60.02 in each drive) on the master/follower link is affected. Check settings of parameter group 60 DDCS communication. On the FDCO module (if present), check that the DDCS link switch is not set to 0 (OFF). Check cable connections. If necessary, replace cables.
A7CE	EFB comm loss Programmable warning: 58.14 Communication loss action	Communication break in embedded fieldbus (EFB) communication.	Check the status of the fieldbus master (online/offline/error etc.). Check cable connections to the XD2D connector on the control unit.
A7E1	Encoder Programmable warning: 90.45 Motor feedback fault	Encoder error.	Check the auxiliary code (format XXYY ZZZZ). "XX" specifies the number of the encoder interface module (01 : 91.11/91.12, 02 : 91.13/91.14), "YY" specifies the encoder (01 : 92 Encoder 1 configuration, 02 : 93 Encoder 2 configuration). "ZZZZ" indicates the problem (see actions for each code below).
	0001	Cable fault	Check the conductor order at both ends of the encoder cable. Check the groundings of the encoder cable. If the encoder was working previously, check the encoder, encoder cable and encoder interface module for damage. See also parameter <i>92.21 Encoder cable</i> <i>fault mode</i> .
	0002	No encoder signal	Check the condition of the encoder.
	0003	Overspeed	Contact your local ABB representative.
	0004	Overfrequency	Contact your local ABB representative.
	0005	Resolver ID run failed	Contact your local ABB representative.
	0006	Resolver overcurrent fault	Contact your local ABB representative.
	0007	Speed scaling error	Contact your local ABB representative.

Code (hex)	Warning	Cause	What to do
A7EE	Control panel loss Programmable warning: 49.05 Communication loss action	Control panel (or PC tool) has stopped communicating.	Check PC tool or control panel connection. Check control panel connector. Check mounting platform if being used. Disconnect and reconnect the control panel.
A880	Motor bearing Programmable warnings: 33.14 On-time 1 warn message 33.24 On-time 2 warn message 33.55 Value counter 1 warn message 33.65 Value counter 2 warn message	Warning generated by an on- time timer or a value counter.	Check the auxiliary code. Check the source of the warning corresponding to the code: 0: 33.13 On-time 1 source 1: 33.23 On-time 2 source 4: 33.53 Value counter 1 source 5: 33.63 Value counter 2 source.
A881	Output relay	Warning generated by an edge	Check the auxiliary code. Check the
A882	Motor starts	counter. Programmable warnings:	source of the warning corresponding to the code:
A883	Power ups	33.35 Edge counter 1 warn	2: 33.33 Edge counter 1 source
A884	Main contactor	message 33.45 Edge counter 2 warn	3: 33.43 Edge counter 2 source.
A885	DC charge	message	
A886	On-time 1 (Editable message text) Programmable warning: 33.14 On-time 1 warn message	Warning generated by on-time timer 1.	Check the source of the warning (parameter 33.13 On-time 1 source).
A887	On-time 2 (Editable message text) Programmable warning: 33.24 On-time 2 warn message	Warning generated by on-time timer 2.	Check the source of the warning (parameter 33.23 On-time 2 source).
A888	Edge counter 1 (Editable message text) Programmable warning: 33.35 Edge counter 1 warn message	Warning generated by edge counter 1.	Check the source of the warning (parameter 33.33 Edge counter 1 source).
A889	Edge counter 2 (Editable message text) Programmable warning: 33.45 Edge counter 2 warn message	Warning generated by edge counter 2.	Check the source of the warning (parameter 33.43 Edge counter 2 source).
A88A	Value counter 1 (Editable message text) Programmable warning: 33.55 Value counter 1 warn message	Warning generated by value counter 1.	Check the source of the warning (parameter 33.53 Value counter 1 source).
A88B	Value counter 2 (Editable message text) Programmable warning: 33.65 Value counter 2 warn message	Warning generated by value counter 2.	Check the source of the warning (parameter 33.63 Value counter 2 source).

Code (hex)	Warning	Cause	What to do
A88C	Device clean	Warning generated by an on-	Check the auxiliary code. Check the source of the warning corresponding to the code: 0: 33.13 On-time 1 source
A88D	DC capacitor	time timer. Programmable warnings: 33.14 On-time 1 warn message	
A88E	Cabinet fan		
A88F	Cooling fan	33.24 On-time 2 warn message	1: 33.23 On-time 2 source
A890	Additional cooling		10: 05.04 Fan on-time counter.
A8A0	Al supervision Programmable warning: 12.03 Al supervision function	An analog signal is outside the limits specified for the analog input.	Check the auxiliary code (format XYY). "X" specifies the location of the input (0: Al on control unit; 1: I/O extension module 1, etc.), "YY" specifies the input and limit (01: Al1 under minimum, 02: Al1 over maximum, 03: Al2 under minimum, 04: Al2 over maximum). Check signal level at the analog input. Check the wiring connected to the input. Check the minimum and maximum limits of the input in parameter group 12 Standard Al. 14 I/O extension module 1, 15 I/O extension module 2 or 16 I/O extension module 3.
A8B0	Signal supervision (Editable message text) Programmable warning: 32.06 Supervision 1 action	Warning generated by the signal supervision 1 function.	Check the source of the warning (parameter <i>32.07 Supervision 1 signal</i>).
A8B1	Signal supervision 2 (Editable message text) Programmable warning: 32.16 Supervision 2 action	Warning generated by the signal supervision 2 function.	Check the source of the warning (parameter <i>32.17 Supervision 2 signal</i>).
A8B2	Signal supervision 3 (Editable message text) Programmable warning: 32.26 Supervision 3 action	Warning generated by the signal supervision 3 function.	Check the source of the warning (parameter <i>32.28 Supervision 3 signal</i>).
A8BE	ULC overload warning Programmable fault: 37.03 ULC overload actions	Selected signal has exceeded the user overload curve.	Check for any operating conditions increasing the monitored signal (for example, the loading of the motor if the torque or current is being monitored). Check the definition of the load curve (parameter group <i>37 User load curve</i>).
A8BF	ULC underload warning Programmable fault: 37.04 ULC underload actions	Selected signal has fallen below the user underload curve.	Check for any operating conditions decreasing the monitored signal (for example, loss of load if the torque or current is being monitored). Check the definition of the load curve (parameter group 37 User load curve).
A8C0	Fan service counter	A cooling fan has reached the end of its estimated lifetime. See parameters 05.41 and 05.42.	Check the auxiliary code. The code indicates which fan is to be replaced. 0: Main cooling fan 1:Auxiliary cooling fan 2:Auxiliary cooling fan 2 3:Cabinet cooling fan 4:PCB compartment fan Refer to the hardware manual of the drive for fan replacement instructions.

Code (hex)	Warning	Cause	What to do
A981	External warning 1 (Editable message text) Programmable warning: 31.01 External event 1 source 31.02 External event 1 type	Fault in external device 1.	Check the external device. Check setting of parameter <i>31.01</i> <i>External event 1 source</i> .
A982	External warning 2 (Editable message text) Programmable warning: 31.03 External event 2 source 31.04 External event 2 type	Fault in external device 2.	Check the external device. Check setting of parameter <i>31.03</i> <i>External event 2 source</i> .
A983	External warning 3 (Editable message text) Programmable warning: 31.05 External event 3 source 31.06 External event 3 type	Fault in external device 3.	Check the external device. Check setting of parameter <i>31.05</i> <i>External event 3 source</i> .
A984	External warning 4 (Editable message text) Programmable warning: 31.07 External event 4 source 31.08 External event 4 type	Fault in external device 4.	Check the external device. Check setting of parameter <i>31.07</i> <i>External event 4 source</i> .
A985	External warning 5 (Editable message text) Programmable warning: 31.09 External event 5 source 31.10 External event 5 type	Fault in external device 5.	Check the external device. Check setting of parameter <i>31.09</i> <i>External event 5 source</i> .
AF80	INU-LSU comm loss Programmable warning: 60.79 INU-LSU comm loss function	DDCS (fiber optic) communication between converters (for example, the inverter unit and the supply unit) is lost. Note that the inverter unit will continue operating based on the status information that was last received from the other converter.	Check status of other converter (parameters 06.36 and 06.39). Check settings of parameter group 60 DDCS communication. Check the corresponding settings in the control program of the other converter. Check cable connections. If necessary, replace cables.
AF85	Line side unit warning	The supply unit (or other converter) has generated a warning.	The auxiliary code specifies the original warning code in the supply unit control program. Refer to the firmware manual of the supply unit.
AF8C	Process PID sleep mode	The drive is entering sleep mode.	Informative warning. See section <i>Sleep</i> <i>function for process PID control</i> (page 101), and parameters 40.4140.48.
AF90	Speed controller autotuning	The speed controller autotune routine did not complete successfully.	Check the auxiliary code (format XXXX YYYY). "YYYY" indicates the problem (see actions for each code below).
	0000	The drive was stopped before the autotune routine finished.	Repeat autotune until successful.

Code (hex)	Warning	Cause	What to do
	0001	The drive was started but was not ready to follow the autotune command.	Make sure the prerequisites of the autotune run are fulfilled. See section <i>Before activating the autotune routine</i> (page 78).
	0002	Required torque reference could not be reached before the drive reached maximum speed.	Decrease torque step (parameter 25.38) or increase speed step (25.39).
	0003	Motor could not accelerate/decelerate to maximum/minimum speed.	Increase torque step (parameter 25.38) or decrease speed step (25.39).
	0005	Motor could not decelerate with full autotune torque.	Decrease torque step (parameter 25.38) or speed step (25.39).
AFAA	Autoreset	A fault is about to be autoreset.	Informative warning. See the settings in parameter group <i>31 Fault functions</i> .
AFE1	Emergency stop (off2)	Drive has received an emergency stop (mode selection off2) command.	Check that it is safe to continue operation. Reset the source of the emergency stop signal (such as an emergency stop push button). Restart drive. If the emergency stop was unintentional, check the source of the stop signal (for example, <i>21.05 Emergency stop source</i> , or control word received from an external control system).
		(Follower drive in a master/follower configuration) Drive has received a stop command from the master.	Informative warning. After stopping on a ramp stop (Off1 or Off3) command, the master sends a short, 10-millisecond coast stop (Off2) command to the follower(s). The Off2 stop is stored in the event log of the follower.
AFE2	Emergency stop (off1 or off3)	Drive has received an emergency stop (mode selection Off1 or Off3) command.	Check that it is safe to continue operation. Reset the source of the emergency stop signal (such as an emergency stop push button). Restart drive. If the emergency stop was unintentional, check the source of the stop signal (for example, <i>21.05 Emergency stop source</i> , or control word received from an external control system).
AFE7	Follower	A follower drive has tripped.	Check the auxiliary code. Add 2 to the code to find out the node address of the faulted drive. Correct the fault in the follower drive.
AFEA	Enable start signal missing (Editable message text)	No enable start signal received.	Check the setting of (and the source selected by) parameter 20.19 Enable start command.
AFEB	Run enable missing	No run enable signal is received.	Check setting of parameter 20.12 Run enable 1 source. Switch signal on (e.g. in the fieldbus Control Word) or check wiring of selected source.

Code (hex)	Warning	Cause	What to do
AFEC	External power signal missing	95.04 Control board supply is set to External 24V but no voltage is connected to the XPOW connector of the control unit.	Check the external 24 V DC power supply to the control unit, or change the setting of parameter 95.04.
AFF6	Identification run	Motor ID run will occur at next start.	Informative warning.
AFF7	Autophasing	Autophasing will occur at next start.	Informative warning.
B5A0	STO event Programmable event: 31.22 STO indication run/stop	Safe torque off function is active, i.e. safety circuit signal(s) connected to connector XSTO is lost.	Check safety circuit connections. For more information, see appropriate drive hardware manual and description of parameter <i>31.22 STO indication run/stop</i> (page <i>291</i>).
B5A2	Power up Programmable event: 96.39 Power up event logging	The drive has been powered up.	Informative event.
B5A4	SW internal diagnostics	Control unit rebooted unexpectedly.	Informative event.
B686	Checksum mismatch Programmable event: 96.54 Checksum action	The calculated parameter checksum does not match any enabled reference checksum.	See A686 Checksum mismatch (page 557).
D200	Section sum not 100%	Sum of total sections (parameters 75.36, 76.36, 77.36, 78.36) of the current pattern in Length [%] mode is not equal to 100%.	Set the section values in parameter groups 7578 so that sum of total sections is equal to 100%.
D201	Doff end	Manual doff is activated and pattern ends at the time defined in parameter 81.06 Doff end alarm time or the length defined in parameter 81.07 Doff End alarm length based on the Time or Length mode selected.	No action is required.This is only an indication

Fault messages

Code (hex)	Fault	Cause	What to do
2281	Calibration	Measured offset of output phase current measurement or difference between output phase U2 and W2 current measurement is too great (the values are updated during current calibration).	Try performing the current calibration again (select <i>Current measurement</i> <i>calibration</i> at parameter <i>99.13</i>). If the fault persists, contact your local ABB representative.
2310	Overcurrent	Output current has exceeded internal fault limit.	Check motor load. Check acceleration times in parameter group 23 Speed reference ramp (speed control), 26 Torque reference chain (torque control) or 28 Frequency reference chain (frequency control). Also check parameters 46.01 Speed scaling, 46.02 Frequency scaling and 46.03 Torque scaling. Check motor and motor cable (including phasing and delta/star connection). Check there are no contactors opening and closing in motor cable. Check that the start-up data in parameter group 99 corresponds to the motor rating plate. Check that there are no power factor correction capacitors or surge absorbers in motor cable. Check the auxiliary code (format XXXY YYZZ). With parallel-connected inverter modules, "Y YY" specifies through which BCU control unit channel the fault was received. "ZZ" indicates the phase that triggered the fault (0: No detailed information available, 1: U-phase, 2: Vphase, 4: W-phase, 3/5/6/7: multiple phases)
2330	Earth leakage Programmable fault: 31.20 Earth fault	Drive has detected load unbalance typically due to earth fault in motor or motor cable.	Check there are no power factor correction capacitors or surge absorbers in motor cable. Check for an earth fault in motor or motor cables by measuring the insulation resistances of motor and motor cable. Try running the motor in scalar control mode if allowed. (See parameter 99.04 <i>Motor control mode</i> .) With parallel-connected modules, check the auxiliary code (format XXXY YYZZ). "Y YY" specifies through which BCU control unit channel the fault was received. If no earth fault can be detected, contact your local ABB representative.

Code (hex)	Fault	Cause	What to do
2340	Short circuit	Short-circuit in motor cable(s) or motor	Check motor and motor cable for cabling errors. Check that parameter 99.10 Motor nominal power has been set correctly. Check there are no power factor correction capacitors or surge absorbers in motor cable. Check the auxiliary code (format XXXY YYZZ). With parallel-connected inverter modules, "Y YY" specifies through which BCU control unit channel the fault was received. "ZZ" indicates the location of the short circuit (0: No detailed information available, 1: Upper branch of U-phase, 2: Lower branch of U-phase, 4: Upper branch of V-phase, 8: Lower branch of V-phase, 10: Upper branch of W-phase, 20: Lower branch of W-phase, other: combinations of the above). After correcting the cause of the fault, reboot the control unit (using parameter 96.08 Control board boot) or by cycling power.
2381	IGBT overload	Excessive IGBT junction to case temperature. This fault protects the IGBT(s) and can be activated by a short circuit in the motor cable.	Check motor cable. Check ambient conditions. Check air flow and fan operation. Check heatsink fins for dust pick-up. Check motor power against drive power.
2391	BU current difference	AC phase current difference between parallel-connected inverter modules is excessive.	Check motor cabling. Check there are no power factor correction capacitors or surge absorbers in motor cable. Check the auxiliary code (format XXXY YYZZ). "XXX" specifies the source of the first error (see "YYY"). "YYY" specifies the module through which BCU control unit channel the fault was received (0: Channel 1, 1: Channel 2, 2: Channel 3, 4: Channel 4, 8: Channel 5,, 400: Channel 12, other: combinations of the above). "ZZ" indicates the phase (1: U, 2: V, 3: W).
2392	BU earth leakage	Total earth leakage of inverter modules is excessive.	Check there are no power factor correction capacitors or surge absorbers in motor cable. Measure insulation resistances of motor cables and motor. Contact your local ABB representative.
3130	Input phase loss Programmable fault: 31.21 Supply phase loss	Intermediate circuit DC voltage is oscillating due to missing input power line phase or blown fuse.	Check input power line fuses. Check for loose power cable connections. Check for input power supply imbalance.
3180	Charge relay lost	No acknowledgement received from charge relay.	Contact your local ABB representative.

Code (hex)	Fault	Cause	What to do
3181	Wiring or earth fault Programmable fault: <i>31.23</i> <i>Wiring or earth fault</i>	The drive hardware is supplied from a common DC bus.	Switch off the protection in parameter <i>31.23</i> .
		Incorrect input power and motor cable connection (i.e. input power cable is connected to drive motor connection).	Check the power connections.
		Drive has detected load unbalance typically due to earth fault in motor or motor cable.	Check there are no power factor correction capacitors or surge absorbers in motor cable. Check for an earth fault in motor or motor cables by measuring the insulation resistances of motor and motor cable. Try running the motor in scalar control mode if allowed. (See parameter 99.04 <i>Motor control mode</i> .)
3210	DC link overvoltage	Excessive intermediate circuit DC voltage.	Check that overvoltage control is on (parameter 30.30 Overvoltage control). Check that the supply voltage matches the nominal input voltage of the drive. Check the supply line for static or transient overvoltage. Check brake chopper and resistor (if present). Check deceleration time. Use coast-to-stop function (if applicable). Retrofit drive with brake chopper and brake resistor.With parallel-connected modules, check the auxiliary code (format XXXY YYZZ). "Y YY" specifies through which BCU control unit channel the fault was received.
3220	DC link undervoltage	Intermediate circuit DC voltage is not sufficient because of a missing supply phase, blown fuse or fault in the rectifier bridge.	Check supply cabling, fuses and switchgear. With parallel-connected modules, check the auxiliary code (format XXXY YYZZ). "Y YY" specifies through which BCU control unit channel the fault was received.
3280	Standby timeout	Automatic restart failed (see section <i>Automatic restart</i> on page <i>110</i>).	Check the condition of the supply (voltage, cabling, fuses, switchgear).
3291	BU DC link difference	Difference in DC voltages between parallel-connected inverter modules.	Check the auxiliary code (format XXXY YYZZ). "XXX" specifies the source of the first error (see "YYY"). "YYY" specifies the module through which BCU control unit channel the fault was received (0: Channel 1, 1: Channel 2, 2: Channel 3, 4: Channel 4, 8: Channel 5,, 400: Channel 12).
3381	Output phase loss Programmable fault: 31.19 Motor phase loss	Motor circuit fault due to missing motor connection (all three phases are not connected).	Connect motor cable.

Code (hex)	Fault	Cause	What to do
3385	Autophasing	Autophasing routine (see section <i>Parameter group 28</i> <i>Frequency reference chain</i> (<i>page 270</i>). on page 92) has failed.	Try other autophasing modes (see parameter 21.13 Autophasing mode) if possible. If the Turning with Z-pulse mode is selected, check the zero pulse given by the encoder. Check that the motor ID run has been successfully completed. Clear parameter 98.15 Position offset user. Check that the encoder is not slipping on the motor shaft. Check that the motor is not already turning when the autophasing routine starts. Check the setting of parameter 99.03 Motor type.
4000	Motor cable overload	Calculated motor cable temperature has exceeded warning limit.	Check the settings of parameters 35.61 and 35.62. Check the dimensioning of the motor cable in regard to required load.
4210	IGBT overtemperature	Estimated drive IGBT temperature is excessive.	Check ambient conditions. Check air flow and fan operation. Check heatsink fins for dust pick-up. Check motor power against drive power.
4290	Cooling	Drive module temperature is excessive.	Check ambient temperature. If it exceeds 40 °C (104 °F), ensure that load current does not exceed derated load capacity of drive. See appropriate <i>Hardware manual</i> . Check drive module cooling air flow and fan operation. Check inside of cabinet and heatsink of drive module for dust pick-up. Clean whenever necessary.
42F1	IGBT temperature	Drive IGBT temperature is excessive.	Check ambient conditions. Check air flow and fan operation. Check heatsink fins for dust pick-up. Check motor power against drive power.
4310	Excess temperature	Power unit module temperature is excessive.	See A4B0 Excess temperature (page 555).
4380	Excess temperature difference	High temperature difference between the IGBTs of different phases.	See A4B1 Excess temperature difference (page 555).
4981	External temperature 1 (Editable message text)	Measured temperature 1 has exceeded fault limit.	Check the value of parameter <i>35.02</i> <i>Measured temperature 1</i> . Check the cooling of the motor (or other equipment whose temperature is being measured). Check the value of parameter <i>35.12</i> <i>Temperature 1 fault limit</i> .

Code (hex)	Fault	Cause	What to do
4982	External temperature 2 (Editable message text)	Measured temperature 2 has exceeded fault limit.	Check the value of parameter 35.03 Measured temperature 2. Check the cooling of the motor (or other equipment whose temperature is being measured). Check the value of parameter 35.22 Temperature 2 fault limit.
4990	FPTC not found	A temperature monitoring module has been activated by parameter 35.30 but cannot be detected.	Power down the control unit and check that the module is properly inserted in the correct slot. The last digit of the auxiliary code identifies the slot.
4991	Safe motor temperature 1 (Editable message text)	The temperature monitoring module installed in slot 1 indicates overtemperature.	Check the cooling of the motor. Check the motor load and drive ratings. Check the wiring of the temperature
4992	Safe motor temperature 2 (Editable message text)	The temperature monitoring module installed in slot 2 indicates overtemperature.	sensor. Repair wiring if faulty. Measure the resistance of the sensor. Replace sensor if faulty.
4993	Safe motor temperature 3 (Editable message text)	The temperature monitoring module installed in slot 3 indicates overtemperature.	
5080	Fan	Cooling fan feedback missing.	See A581 Fan (page 556).
5081	Auxiliary fan broken	An auxiliary cooling fan (connected to the fan connectors on the control unit) is stuck or disconnected.	Check the auxiliary code. The auxiliary code identifies the fan (1: Auxiliary fan 1, 2: Auxiliary fan 2). Check auxiliary fan(s) and connection(s). Replace faulty fan. Make sure the front cover of the drive module is in place and tightened. If the commissioning of the drive requires that the cover is off, activate parameter <i>31.36</i> <i>Aux fan fault bypass</i> within 2 minutes from control unit reboot to temporarily suppress the fault.
5090	STO hardware failure	Safe torque off hardware failure.	Contact your local ABB representative, quoting the auxiliary code. The code contains location information, especially with parallel-connected inverter modules. When converted into a 32-bit binary number, the bits of the code indicate the following: 3128: Number of faulty inverter module (011 decimal). 1111: STO_ACT states of control unit and inverter modules in conflict 27: STO_ACT state of inverter modules 26: STO_ACT state of control unit 25: STO1 of control unit 24: STO2 of control unit 2312: STO1 of inverter modules 121 (Bits of non-existing modules set to 1) 110: STO2 of inverter modules 121 (Bits of non-existing modules set to 1).

Code (hex)	Fault	Cause	What to do
5091	Safe torque off Programmable fault: 31.22 STO indication run/stop	Safe torque off function is active, i.e. safety circuit signal(s) connected to connector XSTO is broken during start or run.	Check safe torque off circuit connections. For more information, see appropriate drive hardware manual and description of parameter <i>31.22 STO indication run/stop</i> (page <i>291</i>).
5092	PU logic error	Power unit memory has cleared.	Cycle the power to the drive. If the control unit is externally powered, also reboot the control unit (using parameter 96.08 Control board boot) or by cycling its power. If the problem persists, contact your local ABB representative.
5093	Rating ID mismatch	The hardware of the drive does not match the information stored in the memory unit. This may occur eg. after a firmware update or memory unit replacement.	Cycle the power to the drive. Check the auxiliary code. The auxiliary code categories are as follows: 1 = PU and CU ratings not the same. Rating ID has changed. 2 = Parallel connection rating ID has changed. 3 = PU types not the same in all power units. 4 = Parallel connection rating ID is active in a single power unit setup. 5 = It is not possible to implement the selected rating with the current PUs. 6 = PU rating ID is 0. 7 = Reading PU rating ID or PU type failed on PU connection. 8 = PU not supported (illegal rating ID). 9 = Incompatible module current rating (unit contains a module with too low a current rating). 10 = Selected parallel rating ID not found from database. With parallel connection faults, (BCU control unit), the format of the auxiliary code is 0X0Y. "Y" indicates the first faulty PU channel in hexadecimal (1C). (With a ZCU control unit, "X" can be 1 or 2 but this is irrelevant to the fault.)
5094	Measurement circuit temperature	Problem with internal temperature measurement of the drive.	See A5EA Measurement circuit temperature (page 556).

Code (hex)	Fault	Cause	What to do
5681	PU communication	The way the control unit is powered does not correspond to parameter setting.	Check setting of 95.04 Control board supply.
		Communication errors detected between the drive control unit and the power unit.	Check the connection between the control unit and the power unit. Check the auxiliary code (format XXXY YYZZ). With parallel-connected modules, "Y YY" specifies the affected BCU control unit channel (0: broadcast). "ZZ" specifies the error source (1: Transmitter side [link error], 2: Transmitter side [no communication], 3: Receiver side [link error], 4: Receiver side [no communication], 5: Transmitter FIFO error [see "XXX"], 6: Module [xINT board] not found, 7: BAMU board not found). "XXX" specifies the transmitter FIFO error code (1: Internal error [invalid call parameter], 2: Internal error [configuration not supported], 3: Transmission buffer full).
5682	Power unit lost	Connection between the drive control unit and the power unit is lost.	Check the connection between the control unit and the power unit.
5690	PU communication internal	Internal communication error.	Contact your local ABB representative.
5691	Measurement circuit ADC	Measurement circuit fault.	Contact your local ABB representative, quoting the auxiliary code.
5692	PU board powerfail	Power unit power supply failure.	Check the auxiliary code (format ZZZY YYXX). "YY Y" specifies the affected inverter module (0C , always 0 for ZCU control units). "XX" specifies the affected power supply (1 : Power supply 1, 2 : Power supply 2, 3: both supplies).
5693	Measurement circuit DFF	Measurement circuit fault.	Contact your local ABB representative, quoting the auxiliary code.
5694	PU communication configuration	Number of connected power modules differs from expected.	Check setting of 95.31 Parallel connection rating id. Cycle the power to the drive. If the control unit is externally powered, also reboot the control unit (using parameter 96.08 Control board boot) or by cycling its power. If the problem persists, contact your local ABB representative.
5695	Reduced run	Number of inverter modules detected does not match the value of parameter <i>95.13</i> <i>Reduced run mode</i> .	Check that the value of 95.13 Reduced run mode corresponds to the number of inverter modules present. Check that the modules present are powered from the DC bus and connected by fiber optic cables to the BCU control unit. If all modules of the inverter unit are in fact available (eg. maintenance work has been completed), check that parameter 95.13 is set to 0 (reduced run function disabled).

Code (hex)	Fault	Cause	What to do
5696	PU state feedback	State feedback from output phases does not match control signals.	Contact your local ABB representative, quoting the auxiliary code.
5697	Charging feedback	Incorrect parameter setting.	Check the setting of <i>95.09 Switch fuse</i> <i>controller</i> . The parameter should be enabled only if an xSFC charging controller is installed.
		The charging switch and DC switch were operated out of sequence, or a start command was issued before the unit was ready.	 The normal power-up sequence is: 1. Close charging switch. 2. After charging finishes (charging OK lamp lights), close DC switch. 3. Open charging switch.
		Charging circuit fault.	Check the charging circuit. With a frame R6i/R7i inverter module, the auxiliary code "FA" indicates that the charging contactor status feedback does not match the control signal. With parallel-connected frame R8i modules, the auxiliary code (format XX00), "XX" specifies the affected BCU control unit channel.
5698	Unknown power unit fault	Unidentified power unit logic fault.	Check power unit logic and firmware compatibility. Contact your local ABB representative.
6000	Internal SW error	Internal error.	Contact your local ABB representative. Quote the auxiliary code (check the event details in the event log).
6181	FPGA version incompatible	Firmware and FPGA file version in the power unit are incompatible.	Reboot the control unit (using parameter 96.08 Control board boot) or by cycling power. If the problem persists, contact your local ABB representative.
		Update of power unit logic failed.	Retry.
6200	Checksum mismatch Programmable fault: 96.54 Checksum action	The calculated parameter checksum does not match any enabled reference checksum.	See A686 Checksum mismatch (page 557).
6306	FBA A mapping file	Fieldbus adapter A mapping file read error.	Contact your local ABB representative.
6307	FBA B mapping file	Fieldbus adapter B mapping file read error.	Contact your local ABB representative.
6481	Task overload	Internal fault.	Reboot the control unit (using parameter 96.08 Control board boot) or by cycling power. If the problem persists, contact your local ABB representative.
6487	Stack overflow	Internal fault.	Reboot the control unit (using parameter 96.08 Control board boot) or by cycling power. If the problem persists, contact your local ABB representative.
64A1	Internal file load	File read error.	Reboot the control unit (using parameter 96.08 Control board boot) or by cycling power. If the problem persists, contact your local ABB representative.

Code (hex)	Fault	Cause	What to do
64A2	Internal record load	Internal record load error.	Contact your local ABB representative.
64A3	Application loading	Application file incompatible or corrupted.	Check the auxiliary code. See actions for each code below.
	8006	Not enough memory for the application.	Reduce the size of the application. Reduce the number of parameter mappings. See the drive-specific log generated by Automation Builder.
	8007	The application contains the wrong system library version.	Update the system library or reinstall Automation Builder. See the drive-specific log generated by Automation Builder.
	8008	The application is empty.	In Automation Builder, give a "Clean" command and reload the application.
	8009	The application contains invalid tasks.	In Automation Builder, check application task configuration, give a "Clean all" command, and reload the application.
	800A	The application contains an unknown target (system) library function.	Update the system library or reinstall Automation Builder. See the drive-specific log generated by Automation Builder.
64A5	Licensing fault	Running the control program is prevented either because a restrictive license exists, or because a required license is missing.	Record the auxiliary codes of all active licensing faults and contact your product vendor for further instructions.
64A6	Adaptive program	Error running the adaptive program.	Check the auxiliary code (format XXXX YYYY). "XXXX" specifies the number of the function block (0000 = generic error). "YYYY" indicates the problem (see actions for each code below).
	A000	Program corrupted or block non-existent	Restore the template program or download the program to the drive.
	000C	Required block input missing	Check the inputs of the block.
	000E	Program corrupted or block non-existent	Restore the template program or download the program to the drive.
	0011	Program too large.	Remove blocks until the error stops.
	0012	Program is empty.	Correct the program and download it to the drive.
	001C	A nonexisting parameter or block is used in the program.	Edit the program to correct the parameter reference, or to use an existing block.
	001D	Parameter type invalid for selected pin.	Edit the program to correct the parameter reference.
	001E	Output to parameter failed because the parameter was write-protected.	Check the parameter reference in the program. Check for other sources affecting the target parameter.
	0023	Program file incompatible with	Adapt the program to current block
	0024	current firmware version.	library and firmware version.

Code (hex)	Fault	Cause	What to do
	002A	Too many blocks.	Edit the program to reduce the number of blocks.
	Other	-	Contact your local ABB representative, quoting the auxiliary code.
64B0	Memory unit detached	The memory unit was detached when the control unit was powered.	Switch off the power to the control unit and reinstall the memory unit. In case the memory unit was not actually removed when the fault occurred, check that the memory unit is properly inserted into its connector and its mounting screw is tight. Reboot the control unit (using parameter <i>96.08 Control board boot</i>) or by cycling power. If the problem persists, contact your local ABB representative.
64B1	Internal SSW fault	Internal fault.	Reboot the control unit (using parameter 96.08 Control board boot) or by cycling power. If the problem persists, contact your local ABB representative.
64B2	User set fault	 Loading of user parameter set failed because requested set does not exist set is not compatible with control program drive was switched off during loading. 	Ensure that a valid user parameter set exists. Reload if uncertain.
64E1	Kernel overload	Operating system error.	Reboot the control unit (using parameter 96.08 Control board boot) or by cycling power. If the problem persists, contact your local ABB representative.
6581	Parameter system	Parameter load or save failed.	Try forcing a save using parameter 96.07 <i>Parameter save manually</i> . Retry.
65A1	FBA A parameter conflict	The drive does not have a functionality requested by PLC, or requested functionality has not been activated.	Check PLC programming. Check settings of parameter groups 50 <i>Fieldbus adapter (FBA)</i> and 51 <i>FBA A</i> <i>settings</i> .
65A2	FBA B parameter conflict	The drive does not have a functionality requested by PLC, or requested functionality has not been activated.	Check PLC programming. Check settings of parameter groups 50 <i>Fieldbus adapter (FBA)</i> and 54 <i>FBA B</i> <i>settings</i> .
65B1	Reference source parametrization	A reference source is simultaneously connected to multiple parameters with different units.	See A6DA Reference source parametrization (page 559).
6681	EFB comm loss Programmable fault: 58.14 Communication loss action	Communication break in embedded fieldbus (EFB) communication.	Check the status of the fieldbus master (online/offline/error etc.). Check cable connections to the XD2D connector on the control unit.
6682	EFB config file	Embedded fieldbus (EFB) configuration file could not be read.	Contact your local ABB representative.

Code (hex)	Fault	Cause	What to do
6683	EFB invalid parameterization	Embedded fieldbus (EFB) parameter settings inconsistent or not compatible with selected protocol.	Check the settings in parameter group 58 <i>Embedded fieldbus</i> .
6684	EFB load fault	Embedded fieldbus (EFB) protocol firmware could not be loaded.	Contact your local ABB representative.
		Version mismatch between EFB protocol firmware and drive firmware.	
6881	Text data overflow	Internal fault.	Reset the fault. Contact your local ABB representative if the fault persists.
6882	Text 32-bit table overflow	Internal fault.	Reset the fault. Contact your local ABB representative if the fault persists.
6883	Text 64-bit table overflow	Internal fault.	Reset the fault. Contact your local ABB representative if the fault persists.
6885	Text file overflow	Internal fault.	Reset the fault. Contact your local ABB representative if the fault persists.
7080	Option module comm loss	Communication between drive and an option module is lost.	Check that all option modules are properly seated in their slots. Check that all option modules or slot connectors are not damaged. To pinpoint the problem, try installing the modules into different slots one at a time.
7081	Panel port communication Programmable fault: 49.05 Communication loss action	Control panel or PC tool selected as active control location for drive has ceased communicating.	Check PC tool or control panel connection. Check control panel connector. Disconnect and reconnect the control panel. Check the auxiliary code. The code specifies the I/O port used as follows: 0: Panel, 1: Fieldbus interface A, 2: Fieldbus interface B, 3: Ethernet, 4: D2D/EFB port).
7082	Ext I/O comm loss	The I/O extension module types specified by parameters do not match the detected configuration.	Check the auxiliary code (format XXYY YYYY). "XX" specifies the number of the I/O extension module (01 : parameter group 14 I/O extension module 1, 02 : 15 I/O extension module 2, 03 : 16 I/O extension module 3). "YY YYYY" indicates the problem (see actions for each code below).
	00 0001	Communication with module failed.	Check that the module is properly seated in its slot. Check that the module and the slot connector is not damaged. Try installing the module into another slot.

Code (hex)	Fault	Cause	What to do
	00 0002		Check the type and location settings of the modules (parameters <i>14.01/14.02</i> ,
	00 0003	Configuration of module failed.	15.01/15.02 or 16.01/16.02).
	00 0004	Configuration of module failed.	Check that the module is properly seated in its slot. Check that the module and the slot connector is not damaged. Try installing the module into another slot.
7083	Panel reference conflict	Use of saved control panel reference in multiple control modes attempted.	The control panel reference can only be saved for one reference type at a time. Consider the possibility of using a copied reference instead of saved reference (see the reference selection parameter).
7084	Panel/PC tool version conflict	The current version of the control panel and/or PC tool does not support a function. (For example, older panel versions cannot be used as a source of external reference.)	Update control panel and/or PC tool. Contact your local ABB representative if necessary.
7085	Incompatible option module	Option module not supported. (For example, type Fxxx-xx-M fieldbus adapter modules are not supported.)	Check the auxiliary code. The code specifies the interface to which the unsupported module is connected: 1: Fieldbus interface A, 2: Fieldbus interface B. Replace the module with a supported type.
7121	Motor stall Programmable fault: 31.24 Stall function	Motor is operating in stall region because of e.g. excessive load or insufficient motor power.	Check motor load and drive ratings. Check fault function parameters.
7181	Brake resistor	Brake resistor broken or not connected.	Check that a brake resistor has been connected. Check the condition of the brake resistor. Check the dimensioning of the brake resistor.
7183	BR excess temperature	Brake resistor temperature has exceeded fault limit defined by parameter 43.11 Brake resistor fault limit.	Stop drive. Let resistor cool down. Check resistor overload protection function settings (parameter group 43 <i>Brake chopper</i>). Check fault limit setting, parameter 43.11 <i>Brake resistor fault limit.</i> Check that braking cycle meets allowed limits.
7184	Brake resistor wiring	Brake resistor short circuit or brake chopper control fault.	Check brake chopper and brake resistor connection. Ensure brake resistor is not damaged. Ensure brake resistor is not damaged. After correcting the cause of the fault, reboot the control unit (using parameter 96.08 Control board boot) or by cycling power.

Code (hex)	Fault	Cause	What to do
7191	BC short circuit	Short circuit in brake chopper IGBT.	Ensure brake resistor is connected and not damaged. Check the electrical specifications of the brake resistor against the <i>Hardware</i> <i>manual</i> . Replace brake chopper (if replaceable). After correcting the cause of the fault, reboot the control unit (using parameter <i>96.08 Control board boot</i>) or by cycling power.
7192	BC IGBT excess temperature	Brake chopper IGBT temperature has exceeded internal fault limit.	Let chopper cool down. Check for excessive ambient temperature. Check for cooling fan failure. Check for obstructions in the air flow. Check the dimensioning and cooling of the cabinet. Check resistor overload protection function settings (parameter group 43 <i>Brake chopper</i>). Check that braking cycle meets allowed limits. Check that drive supply AC voltage is not excessive.
71A2	Mechanical brake closing failed Programmable fault: 44.17 Brake fault function	Mechanical brake control fault. Activated eg. if brake acknowledgement is not as expected during brake closing.	Check mechanical brake connection. Check mechanical brake settings in parameter group <i>44 Mechanical brake</i> <i>control.</i> Check that acknowledgement signal matches actual status of brake.
71A3	Mechanical brake opening failed Programmable fault: 44.17 Brake fault function	Mechanical brake control fault. Activated eg. if brake acknowledgement is not as expected during brake opening.	Check mechanical brake connection. Check mechanical brake settings in parameter group <i>44 Mechanical brake</i> <i>control.</i> Check that acknowledgement signal matches actual status of brake.
71A5	Mechanical brake opening not allowed Programmable fault: 44.17 Brake fault function	Open conditions of mechanical brake cannot be fulfilled (for example, brake has been prevented from opening by parameter 44.11 Keep brake closed). In an encoderless application, the brake is kept closed by a brake close request (either from parameter 44.12 Brake	Check mechanical brake settings in parameter group 44 Mechanical brake control (especially 44.11 Keep brake closed). Check that acknowledgement signal (if used) matches actual status of brake. Check the source signal selected by parameter 44.12 Brake close request. Check the safety circuits connected to the FSO-xx safety functions module.
7404	Motor for	<i>close request</i> or from an FSO-xx safety functions module) against a modulating drive for longer than 5 seconds.	
71B1	Motor fan Programmable fault: 35.106 DOL starter event type	No feedback received from external fan.	Check external fan (or other equipment controlled) by the logic. Check settings of parameters 35.10035.106.

Code (hex)	Fault	Cause	What to do
7301	Motor speed feedback Programmable fault: 90.45 Motor feedback fault	No motor speed feedback received.	See A7B0 Motor speed feedback (page 563).
7310	Overspeed	Motor is turning faster than highest allowed speed due to incorrectly set minimum/maximum speed, insufficient braking torque or changes in load when using torque reference.	Check minimum/maximum speed settings, parameters 30.11 Minimum speed, 30.12 Maximum speed and 31.30 Overpeed trip margin. Check adequacy of motor braking torque. Check applicability of torque control. Check need for brake chopper and resistor(s).
		Incorrect estimated speed.	Check the status of motor current measurement. Perform a <i>Normal, Advanced</i> or <i>Advanced Standstill</i> ID run instead of, for example, a <i>Reduced</i> or <i>Standstill</i> ID run. See parameter 99.13 ID run requested (page 478).
7380	Encoder internal	Internal fault.	Contact your local ABB representative.
7381	Encoder Programmable fault: 90.45 Motor feedback fault	Encoder feedback fault.	See A7E1 Encoder (page 564).
73A0	Speed feedback configuration	Speed feedback configuration incorrect.	See A797 Speed feedback configuration (page 560).
73A1	Load feedback Programmable fault: 90.55 Load feedback fault	No load feedback received.	Check the auxiliary code (format XXYY ZZZZ). "XX" specifies the number of the encoder interface module (01 : 91.11/91.12, 02 : 91.13/91.14), "YY" specifies the encoder (01 : 92 Encoder 1 configuration, 02 : 93 Encoder 2 configuration). "ZZZZ" indicates the problem (see actions for each code below).
	0001	Load gear definition invalid or outside limits.	Check load gear settings (90.53 and 90.54).
	0002	Feed constant definition invalid or outside limits.	Check feed constant settings (90.63 and 90.64).
	0003	Motor/load gear definition invalid or outside limits.	Check motor/load gear settings (90.61 and 90.62).
	0004	Encoder not configured.	Check encoder settings (92 Encoder 1 configuration or 93 Encoder 2 configuration). Use parameter 91.10 Encoder parameter refresh) to validate any changes in the settings.
	0005	Encoder stopped working.	Check encoder status.
73B0	Emergency ramp failed	Emergency stop did not finish within expected time.	Check the settings of parameters 31.32 Emergency ramp supervision and 31.33 Emergency ramp supervision delay. Check the predefined ramp time (23.23 for mode Off3).

Code (hex)	Fault	Cause	What to do
73B1	Stop failed	Ramp stop did not finish within expected time.	Check the settings of parameters 31.37 Ramp stop supervision and 31.38 Ramp stop supervision delay. Check the predefined ramp times in parameter group 23 Speed reference ramp.
73F0	Overfrequency	Maximum allowed output frequency exceeded.	Without a dual-use license, the fault limit is 598 Hz. Contact your local ABB representative for dual-use licensing information.
7510	FBA A communication Programmable fault: 50.02 FBA A comm loss func	Cyclical communication between drive and fieldbus adapter module A or between PLC and fieldbus adapter module A is lost.	Check status of fieldbus communication. See user documentation of fieldbus interface. Check settings of parameter groups 50 <i>Fieldbus adapter (FBA)</i> , 51 <i>FBA A</i> <i>settings</i> , 52 <i>FBA A data in</i> and 53 <i>FBA A</i> <i>data out</i> . Check cable connections. Check if communication master is able to communicate.
7520	FBA B communication Programmable fault: 50.32 FBA B comm loss func	Cyclical communication between drive and fieldbus adapter module B or between PLC and fieldbus adapter module B is lost.	Check status of fieldbus communication. See user documentation of fieldbus interface. Check settings of parameter group 50 <i>Fieldbus adapter (FBA)</i> . Check cable connections. Check if communication master is able to communicate.
7580	INU-LSU comm loss Programmable fault: 60.79 INU-LSU comm loss function	DDCS (fiber optic) communication between converters (for example, the inverter unit and the supply unit) is lost.	Check status of other converter (parameter group <i>06 Control and status</i> <i>words</i>). Check settings of parameter group <i>60</i> <i>DDCS communication</i> . Check the corresponding settings in the control program of the other converter. Check cable connections. If necessary, replace cables.
7581	DDCS controller comm loss Programmable fault: 60.59 DDCS controller comm loss function	DDCS (fiber optic) communication between drive and external controller is lost.	Check status of controller. See user documentation of controller. Check settings of parameter group 60 DDCS communication. Check cable connections. If necessary, replace cables.
7582	MF comm loss Programmable fault: 60.09 M/F comm loss function	Master/follower communication is lost.	See A7CB MF comm loss (page 564).
7583	Line side unit faulted	The supply unit (or other converter) connected to the inverter unit has generated a fault.	The auxiliary code specifies the original fault code in the supply unit control program. Refer to the firmware manual of the supply unit.

Code (hex)	Fault	Cause	What to do
7584	LSU charge failed	The supply unit was not ready (ie. the main contactor/breaker could not be closed) within expected time.	Check that communication to the supply unit has been activated by 95.20 HW options word 1. Check setting of parameter 94.10 LSU max charging time. Check that the supply unit is enabled, allowed to start, and can be controlled by the inverter unit (eg. not in mode).
8001	ULC underload fault Programmable fault: 37.04 ULC underload actions	Selected signal has fallen below the user underload curve.	See A8BF ULC underload warning (page 566).
8002	ULC overload fault Programmable fault: 37.03 ULC overload actions	Selected signal has exceeded the user overload curve.	See A8BE ULC overload warning (page 566).
80A0	AI supervision Programmable fault: 12.03 AI supervision function	An analog signal is outside the limits specified for the analog input.	Check the auxiliary code (format XXXX XYZZ). "Y" specifies the location of the input (0 : Control unit, 1 : I/O extension module 1, 2 : I/O extension module 2, 3 : I/O extension module 3). "ZZ" specifies the limit (01 : Al1 under minimum, 02 : Al1 above maximum, 03 : Al2 under minimum, 04 : Al2 above maximum). Check signal level at the analog input. Check the wiring connected to the input. Check the minimum and maximum limits of the input in parameter group <i>12</i> <i>Standard Al.</i>
80B0	Signal supervision (Editable message text) Programmable fault: 32.06 Supervision 1 action	Fault generated by the signal supervision 1 function.	Check the source of the fault (parameter 32.07 Supervision 1 signal).
80B1	Signal supervision 2 (Editable message text) Programmable fault: 32.16 Supervision 2 action	Fault generated by the signal supervision 2 function.	Check the source of the fault (parameter <i>32.17 Supervision 2 signal</i>).
80B2	Signal supervision 3 (Editable message text) Programmable fault: 32.26 Supervision 3 action	Fault generated by the signal supervision 3 function.	Check the source of the fault (parameter <i>32.27 Supervision 3 signal</i>).
9081	External fault 1 (Editable message text) Programmable fault: 31.01 External event 1 source 31.02 External event 1 type	Fault in external device 1.	Check the external device. Check setting of parameter <i>31.01</i> <i>External event 1 source</i> .
9082	External fault 2 (Editable message text) Programmable fault: 31.03 External event 2 source 31.04 External event 2 type	Fault in external device 2.	Check the external device. Check setting of parameter <i>31.03</i> <i>External event 2 source</i> .

Code (hex)	Fault	Cause	What to do
9083	External fault 3 (Editable message text) Programmable fault: 31.05 External event 3 source 31.06 External event 3 type	Fault in external device 3.	Check the external device. Check setting of parameter <i>31.05</i> <i>External event 3 source</i> .
9084	External fault 4 (Editable message text) Programmable fault: 31.07 External event 4 source 31.08 External event 4 type	Fault in external device 4.	Check the external device. Check setting of parameter <i>31.07</i> <i>External event 4 source</i> .
9085	External fault 5 (Editable message text) Programmable fault: 31.09 External event 5 source 31.10 External event 5 type	Fault in external device 5.	Check the external device. Check setting of parameter <i>31.09</i> <i>External event 5 source</i> .
FA81	Safe torque off 1 loss	Safe torque off function is active, ie. STO circuit 1 is broken.	Check safety circuit connections. For more information, see appropriate drive hardware manual and description of
FA82	Safe torque off 2 loss	Safe torque off function is active, ie. STO circuit 2 is broken.	parameter <i>31.22</i> STO indication run/stop (page <i>291</i>). Check the auxiliary code, The code contains location information, especially with parallel-connected inverter modules. When converted into a 32-bit binary number, the bits of the code indicate the following: 3128: Number of faulty inverter module (011 decimal). 1111: STO_ACT states of control unit and inverter modules in conflict 27: STO_ACT state of inverter modules 26: STO_ACT state of control unit 25: STO1 of control unit 24: STO2 of control unit 2312: STO1 of inverter modules 121 (Bits of non-existing modules set to 1) 110: STO2 of inverter modules 121 (Bits of non-existing modules set to 1).
FB11	Memory unit missing	No memory unit is attached to the drive control unit.	Power down the control unit. Check that the memory unit is properly inserted into the control unit.
		The memory unit attached to the drive control unit is empty.	Power down the control unit. Attach a memory unit (with the appropriate firmware) to the control unit.
FB12	Memory unit incompatible	The memory unit attached to the control unit is incompatible.	Power down the control unit. Attach a compatible memory unit.
FB13	Memory unit FW incompatible	The firmware on the attached memory unit is incompatible with the drive.	Power down the control unit. Attach a memory unit with compatible firmware.

Code (hex)	Fault	Cause	What to do
FB14	Memory unit FW load failed	The firmware on the attached memory unit could not be loaded to the drive.	Power down the control unit. Check that the memory unit is properly inserted into the control unit. If the problem persists, replace the memory unit.
FF61	ID run	Motor ID run was not completed successfully.	Check the nominal motor values in parameter group <i>99 Motor data</i> . Check that no external control system is connected to the drive. Cycle the power to the drive (and its control unit, if powered separately). Check that the motor shaft is not locked. Check the auxiliary code. The second number of the code indicates the problem (see actions for each code below).
	0001	Maximum current limit too low.	Check settings of parameters 99.06 Motor nominal current and 30.17 Maximum current. Make sure that 30.17 > 99.06. Check that the drive is dimensioned correctly according to the motor.
	0002	Maximum speed limit or calculated field weakening point too low.	Check settings of parameters • 30.11 Minimum speed • 30.12 Maximum speed • 99.07 Motor nominal voltage • 99.08 Motor nominal frequency • 99.09 Motor nominal speed. Make sure that • $30.12 > (0.55 \times 99.09) >$ ($0.50 \times$ synchronous speed) • $30.11 \le 0$, and • supply voltage $\ge (0.66 \times 99.07)$.
	0003	Maximum torque limit too low.	Check settings of parameter 99.12 Motor nominal torque, and the torque limits in group 30 Limits. Make sure that the maximum torque limit in force is greater than 100%.
	0004	Current measurement calibration did not finish within reasonable time.	Contact your local ABB representative.
	00050008	Internal error.	Contact your local ABB representative.
	0009	(Asynchronous motors only) Acceleration did not finish within reasonable time.	Contact your local ABB representative.
	000A	(Asynchronous motors only) Deceleration did not finish within reasonable time.	Contact your local ABB representative.
	000B	(Asynchronous motors only) Speed dropped to zero during ID run.	Contact your local ABB representative.

Code (hex)	Fault	Cause	What to do
	000C	(Permanent magnet motors only) First acceleration did not finish within reasonable time.	Contact your local ABB representative.
	000D	(Permanent magnet motors only) Second acceleration did not finish within reasonable time.	Contact your local ABB representative.
	000E0010	Internal error.	Contact your local ABB representative.
FF7E	Follower	A follower drive has tripped.	Check the auxiliary code. Add 2 to the code to find out the node address of the faulted drive. Correct the fault in the follower drive
FF81	FB A force trip	A fault trip command has been received through fieldbus adapter A.	Check the fault information provided by the PLC.
FF82	FB B force trip	A fault trip command has been received through fieldbus adapter B.	Check the fault information provided by the PLC.
FF8E	EFB force trip	A fault trip command has been received through the embedded fieldbus interface.	Check the fault information provided by the Modbus controller.
D100	TPI mismatch trip	Deviation between calculated TPI and actual TPI exceeds predefined level.	Check the front roller speed measurement.



Fieldbus control through the embedded fieldbus interface (EFB)

What this chapter contains

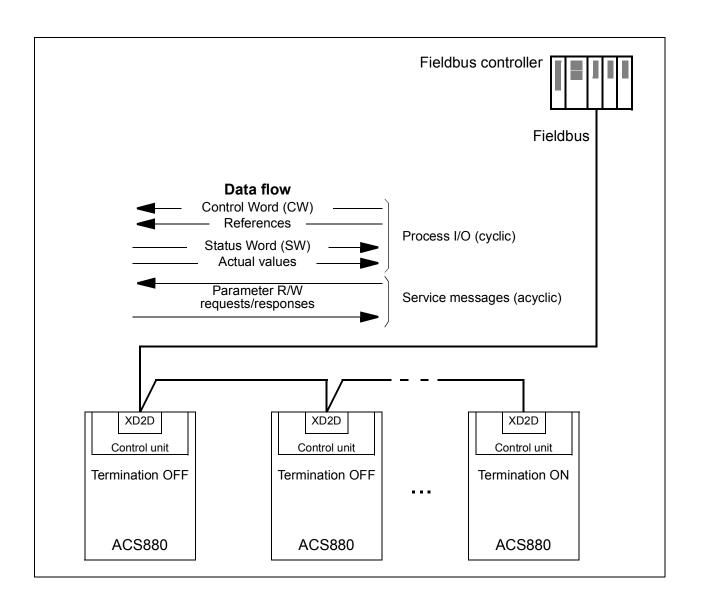
The chapter describes how the drive can be controlled by external devices over a communication network (fieldbus) using the embedded fieldbus interface.

System overview

The drive can be connected to an external control system through a communication link using either a fieldbus adapter or the embedded fieldbus interface.

The embedded fieldbus interface supports the Modbus RTU protocol. The drive control program can handle 10 Modbus registers in a 10-millisecond time level. For example, if the drive receives a request to read 20 registers, it will start its response within 22 ms of receiving the request – 20 ms for processing the request and 2 ms overhead for handling the bus. The actual response time depends on other factors as well, such as the baud rate (a parameter setting in the drive).

The drive can be set to receive all of its control information through the fieldbus interface, or the control can be distributed between the embedded fieldbus interface and other available sources, for example, digital and analog inputs.



Connecting the fieldbus to the drive

Connect the fieldbus to terminal XD2D on the control unit of the drive. See the appropriate *Hardware Manual* for more information on the connection, chaining and termination of the link.

Note: If the XD2D connector is reserved by the embedded fieldbus interface (parameter *58.01 Protocol enable* is set to *Modbus RTU*), the drive-to-drive link functionality is automatically disabled.

Setting up the embedded fieldbus interface

Set the drive up for the embedded fieldbus communication with the parameters shown in the table below. The **Setting for fieldbus control** column gives either the value to use or the default value. The **Function/Information column** gives a description of the parameter.

Parameter		Setting for fieldbus control	Function/Information				
COMM	COMMUNICATION INITIALIZATION						
58.01 Protocol enable M		Modbus RTU	Initializes embedded fieldbus communication. Drive-to-drive link operation is automatically disabled.				
EMBED	DED MODBUS CO	ONFIGURATION					
58.03	Node address	1 (default)	Node address. There must be no two nodes with the same node address online.				
58.04	Baud rate	19.2 kbps (default)	Defines the communication speed of the link. Use the same setting as in the master station.				
58.05	Parity	8 EVEN 1 (default)	Selects the parity and stop bit setting. Use the same setting as in the master station.				
58.14	Communication loss action	Fault (default)	Defines the action taken when a communication loss is detected.				
58.15	Communication loss mode	<i>Cw / Ref1 / Ref2</i> (default)	Enables/disables communication loss monitoring and defines the means for resetting the counter of the communication loss delay.				
58.16	Communication loss time	3.0 s (default)	Defines the timeout limit for the communication monitoring.				
58.17	Transmit delay	0 ms (default)	Defines a response delay for the drive.				
58.25	Control profile	ABB Drives (default), Transparent	Selects the control profile used by the drive. See section <i>Basics of the embedded fieldbus</i> <i>interface</i> (page 594).				
58.26 58.29	EFB ref1 type EFB act2 type	Auto, Transparent, General, Torque, Speed, Frequency	Selects the reference and actual value types. With the <i>Auto</i> setting, the type is selected automatically according to the currently active drive control mode.				
58.30	EFB status word transparent source	Other	Defines the source of status word when 58.25 Control profile = Transparent.				
58.31	EFB act1 transparent source	Other	Defines the source of actual value 1 when 58.28 EFB act1 type = Transparent or General.				
58.32	EFB act2 transparent source	Other	Defines the source of actual value 2 when 58.29 <i>EFB</i> act2 type = <i>Transparent</i> or <i>General</i> .				

Parameter	Setting for fieldbus control	Function/Information
58.33 Addressing mode	Mode 1 (default)	Defines the mapping between parameters and holding registers in the 400001465536 (10065535) Modbus register range.
58.34 Word order	LO-HI (default)	Defines the order of the data words in the Modbus message frame.
58.101 Data I/O 1 58.124 Data I/O 24	For example, the default settings (I/Os 16 contain the control word, the status word, two references and two actual values)	Define the address of the drive parameter which the Modbus master accesses when it reads from or writes to the register address corresponding to Modbus In/Out parameters. Select the parameters that you want to read or write through the Modbus I/O words.
	RO/DIO control word, AO1 data storage, AO2 data storage	These settings write the incoming data into storage parameters 10.99 RO/DIO control word, 13.91 AO1 data storage, 13.92 AO2 data storage.
58.06 Communication control	Refresh settings	Validates the settings of the configuration parameters.

The new settings will take effect when the drive is powered up the next time, or when they are validated by parameter *58.06 Communication control*.

Setting the drive control parameters

After the embedded fieldbus interface has been set up, check and adjust the drive control parameters listed in the table below. The **Setting for fieldbus control** column gives the value or values to use when the embedded fieldbus signal is the desired source or destination for that particular drive control signal. The

Function/Information column gives a description of the parameter.

Parameter Setting for fieldbus control		Function/Information
CONTROL COMMAND	SOURCE SELECTION	
20.01 Ext1 commands	Embedded fieldbus	Selects fieldbus as the source for the start and stop commands when EXT1 is selected as the active control location.
20.06 Ext2 commands	Embedded fieldbus	Selects fieldbus as the source for the start and stop commands when EXT2 is selected as the active control location.
SPEED REFERENCE	SELECTION	
22.11 Speed ref1 source	EFB ref1 or EFB ref2	Selects a reference received through the embedded fieldbus interface as speed reference 1.
22.12 Speed ref2 source	EFB ref1 or EFB ref2	Selects a reference received through the embedded fieldbus interface as speed reference 2.

Parameter	Setting for fieldbus control	Function/Information				
TORQUE REFERENCE	TORQUE REFERENCE SELECTION					
26.11 Torque ref1 source	EFB ref1 or EFB ref2	Selects a reference received through the embedded fieldbus interface as torque reference 1.				
26.12 Torque ref2 source	EFB ref1 or EFB ref2	Selects a reference received through the embedded fieldbus interface as torque reference 2.				
FREQUENCY REFERE	ENCE SELECTION					
28.11 Frequency ref1 source	EFB ref1 or EFB ref2	Selects a reference received through the embedded fieldbus interface as frequency reference 1.				
28.12 Frequency ref2 source	EFB ref1 or EFB ref2	Selects a reference received through the embedded fieldbus interface as frequency reference 2.				
OTHER SELECTIONS						
EFB references can be selected as the source at virtually any signal selector parameter by selecting <i>Other</i> , then either 03.09 <i>EFB reference 1</i> or 03.10 <i>EFB reference 2</i> .						
CONTROL OF RELAY OUTPUTS, ANALOG OUTPUTS AND DIGITAL INPUT/OUTPUTS						
10.24 RO1 source	RO/DIO control word bit0	Connects bit 0 of storage parameter <i>10.99</i> <i>RO/DIO control word</i> to relay output RO1.				

	bit0	RO/DIO control word to relay output RO1.
10.27 RO2 source	RO/DIO control word bit1	Connects bit 1 of storage parameter <i>10.99</i> <i>RO/DIO control word</i> to relay output RO2.
10.30 RO3 source	RO/DIO control word bit2	Connects bit 2 of storage parameter <i>10.99</i> <i>RO/DIO control word</i> to relay output RO3.
11.05 DIO1 function 11.09 DIO2 function	Output (default)	Sets the digital input/output to output mode.
11.06 DIO1 output source	RO/DIO control word bit8	Connects bit 8 of storage parameter <i>10.99</i> <i>RO/DIO control word</i> to digital input/output DIO1.
11.10 DIO2 output source	RO/DIO control word bit9	Connects bit 9 of storage parameter <i>10.99</i> <i>RO/DIO control word</i> to digital input/output DIO2.
13.16 AO1 source	AO1 data storage	Connects storage parameter 13.91 AO1 data storage to analog output AO1.
13.22 AO2 source	AO2 data storage	Connects storage parameter <i>13.92 AO2 data storage</i> to analog output AO2.

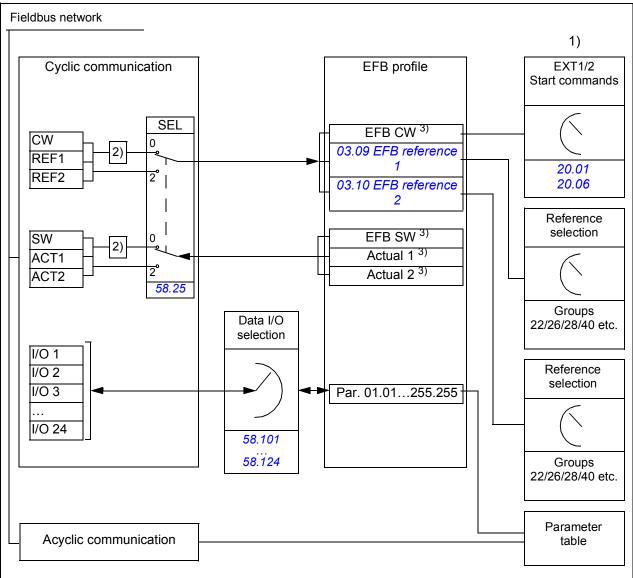
PROCESS PID FEEDBACK AND SETPOINT					
40.08 Set 1 feedback 1 Feedback data storage Connect the bits of the storage parameter source (10.99 RO/DIO control word) to the digital					
40.16 Set 1 setpoint 1 Setpoint data storage input/outputs of the drive.					

SYSTEM CONTROL INPUTS					
	96.07 Parameter save Save (reverts to Done) Saves parameter value changes (including				
manually		those made through fieldbus control) to			
		permanent memory.			

Basics of the embedded fieldbus interface

The cyclic communication between a fieldbus system and the drive consists of 16-bit data words or 32-bit data words (with the transparent control profiles).

The diagram below illustrates the operation of the embedded fieldbus interface. The signals transferred in the cyclic communication are explained further below the diagram.



- 1. See also other parameters which can be controlled through fieldbus.
- 2. Data conversion if parameter 58.25 Control profile is set to ABB Drives. See section About the control profiles (page 597).
- 3. If parameter 58.25 Control profile is set to Transparent,
- the sources of the status word and actual values are selected by parameters 58.30...58.32 (otherwise, actual values 1 and 2 are automatically selected according to reference type), and
- the control word is displayed by 06.05 EFB transparent control word.

Control word and Status word

The Control Word (CW) is a 16-bit or 32-bit packed boolean word. It is the principal means of controlling the drive from a fieldbus system. The CW is sent by the fieldbus controller to the drive. By drive parameters, the user selects the EFB CW as the source of drive control commands (such as start/stop, emergency stop, selection between external control locations 1/2, or fault reset). The drive switches between its states according to the bit-coded instructions of the CW.

The fieldbus CW is either written to the drive as it is (see parameter 06.05 EFB transparent control word), or the data is converted. See section About the control profiles (page 597).

The fieldbus Status Word (SW) is a 16-bit or 32-bit packed boolean word. It contains status information from the drive to the fieldbus controller. The drive SW is either written to the fieldbus SW as it is or the data is converted. See section *About the control profiles* (page 597).

References

EFB references 1 and 2 are 16-bit or 32-bit signed integers. The contents of each reference word can be used as the source of virtually any signal, such as the speed, frequency, torque or process reference. In embedded fieldbus communication, references 1 and 2 are displayed by 03.09 EFB reference 1 and 03.10 EFB reference 2 respectively. Whether the references are scaled or not depends on the settings of 58.26 EFB ref1 type and 58.27 EFB ref2 type. See section About the control profiles (page 597).

Actual values

Fieldbus actual signals (ACT1 and ACT2) are 16-bit or 32-bit signed integers. They convey selected drive parameter values from the drive to the master. Whether the actual values are scaled or not depends on the settings of *58.28 EFB act1 type* and *58.29 EFB act2 type*. See section *About the control profiles* (page 597).

Data input/outputs

Data input/outputs are 16-bit or 32-bit words containing selected drive parameter values. Parameters *58.101 Data I/O 1 ... 58.124 Data I/O 24* define the addresses from which the master either reads data (input) or to which it writes data (output).

Control of drive outputs through EFB

The address selection parameters of the data input/outputs have a setting with which the data can be written into a storage parameter in the drive. These storage parameters are readily selectable as signal sources of the drive outputs. The desired values of the relay outputs (RO) and digital input/outputs (DIO) can be written in a 16-bit word into *10.99 RO/DIO control word*, which is then selected as the source of those outputs. Each of the analog outputs (AO) of the drive have a dedicated storage parameter (*13.91 AO1 data storage* and *13.92 AO2 data storage*), which are available in the source selection parameters *13.12 AO1 source* and *13.22 AO2 source*.

Sending process PID feedback and setpoint values through EFB

The drive also has storage parameters for incoming process PID feedback (40.92 *Feedback data storage*) as well as a process PID setpoint (40.92 *Feedback data storage*). The feedback storage parameter is selectable in the source selection parameters 40.08 Set 1 feedback 1 source and 40.09 Set 1 feedback 2 source.

The corresponding parameters in process PID control set 2 (group *41 Process PID set 2*) have the same selections.

Register addressing

The address field of Modbus requests for accessing holding registers is 16 bits. This allows the Modbus protocol to support addressing of 65536 holding registers.

Historically, Modbus master devices used 5-digit decimal addresses from 40001 to 49999 to represent holding register addresses. The 5-digit decimal addressing limited to 9999 the number of holding registers that could be addressed.

Modern Modbus master devices typically provide a means to access the full range of 65536 Modbus holding registers. One of these methods is to use 6-digit decimal addresses from 400001 to 465536. This manual uses 6-digit decimal addressing to represent Modbus holding register addresses.

Modbus master devices that are limited to the 5-digit decimal addressing may still access registers 400001 to 409999 by using 5-digit decimal addresses 40001 to 49999. Registers 410000 to 465536 are inaccessible to these masters.

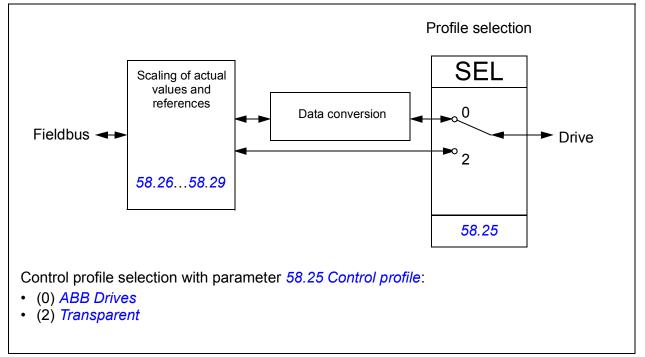
Note: Register addresses of 32-bit parameters cannot be accessed by using 5-digit register numbers.

About the control profiles

A control profile defines the rules for data transfer between the drive and the fieldbus master, for example:

- · if packed boolean words are converted and how
- how drive register addresses are mapped for the fieldbus master.

You can configure the drive to receive and send messages according to the ABB Drives profile or the Transparent profile. With the ABB Drives profile, the embedded fieldbus interface of the drive converts the control word and status word to and from the native data used in the drive. The Transparent profile involves no data conversion. The figure below illustrates the effect of the profile selection.



Note that scaling of references and actual values can be selected independent of the profile selection by parameters <u>58.26...58.29</u>.

The ABB Drives profile

Control Word

The table below shows the contents of the fieldbus Control Word for the ABB Drives control profile. The embedded fieldbus interface converts this word to the form in which it is used in the drive. The upper case boldface text refers to the states shown in *State transition diagram* on page *601*.

Bit	Name	Value	STATE/Description
0	OFF1_	1	Proceed to READY TO OPERATE.
	CONTROL	0	Stop along currently active deceleration ramp. Proceed to OFF1 ACTIVE ; proceed to READY TO SWITCH ON unless other interlocks (OFF2, OFF3) are active.
1	OFF2_	1	Continue operation (OFF2 inactive).
	CONTROL	0	Emergency OFF, coast to stop. Proceed to OFF2 ACTIVE, proceed to SWITCH-ON INHIBITED.
2	OFF3_	1	Continue operation (OFF3 inactive).
	CONTROL	0	Emergency stop, stop within time defined by drive parameter. Proceed to OFF3 ACTIVE; proceed to SWITCH-ON INHIBITED.
			Warning: Ensure that the motor and driven machine can be stopped using this stop mode.
3	INHIBIT_	1	Proceed to OPERATION ENABLED.
	OPERATION		Note: Run enable signal must be active; see the drive documentation. If the drive is set to receive the Run enable signal from the fieldbus, this bit activates the signal.
		0	Inhibit operation. Proceed to OPERATION INHIBITED .
4	RAMP_OUT_ ZERO	1	Normal operation. Proceed to RAMP FUNCTION GENERATOR: OUTPUT ENABLED .
		0	Force Ramp Function Generator output to zero. Drive ramps to stop (current and DC voltage limits in force).
5	RAMP_HOLD	1	Enable ramp function.
			Proceed to RAMP FUNCTION GENERATOR: ACCELERATOR ENABLED.
		0	Halt ramping (Ramp Function Generator output held).
6	RAMP_IN_ ZERO	1	Normal operation. Proceed to OPERATING .
			Note: This bit is effective only if the fieldbus interface is set as the source for this signal by drive parameters.
		0	Force Ramp Function Generator input to zero.
7	RESET	0=>1	Fault reset if an active fault exists. Proceed to SWITCH-ON INHIBITED .
			Note: This bit is effective only if the fieldbus interface is set as the source for this signal by drive parameters.
		0	Continue normal operation.

Bit	Name	Value	STATE/Description
8	8 JOGGING_1		Accelerate to jogging 1 reference. Notes: • Bits 46 must be 0.
		0	Jogging 1 disabled.
9	JOGGING_2	1	Accelerate to jogging 2 reference. See notes at bit 8.
		0	Jogging 2 disabled.
10	REMOTE_	1	Fieldbus control enabled.
	CMD	0	Control word and reference will not get through to the drive, except for CW bits OFF1, OFF2 and OFF3.
11	11 EXT_CTRL_ LOC		Select External Control Location EXT2. Effective if the control location is parameterized to be selected from the fieldbus.
		0	Select External Control Location EXT1. Effective if the control location is parameterized to be selected from the fieldbus.
1215	Reserved		

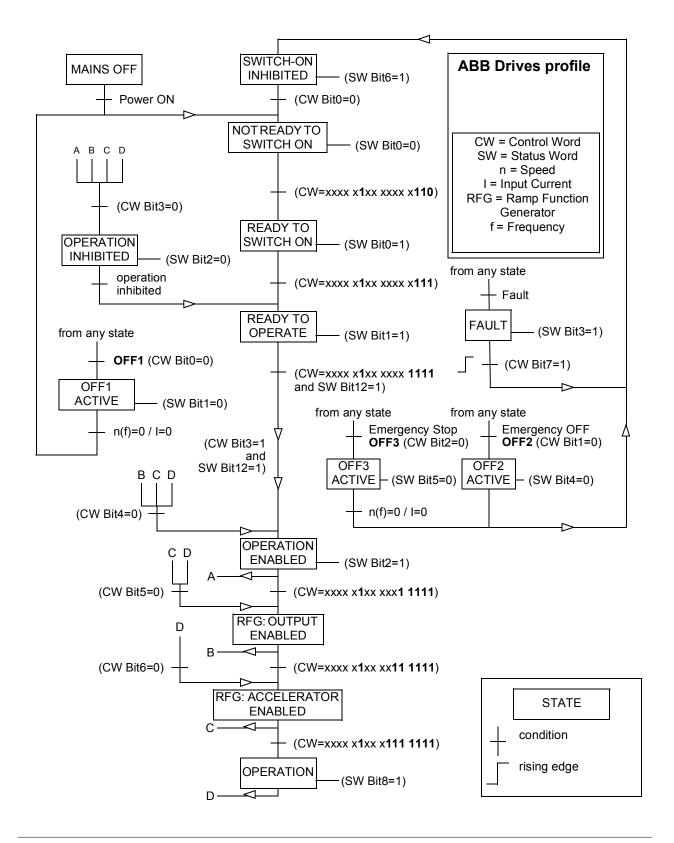
Status Word

The table below shows the fieldbus Status Word for the ABB Drives control profile. The embedded fieldbus interface converts the drive Status Word into this form for the fieldbus. The upper case boldface text refers to the states shown in *State transition diagram* on page *601*.

Bit	Name	Value	STATE/Description
0	RDY_ON	1	READY TO SWITCH ON.
		0	NOT READY TO SWITCH ON.
1	RDY_RUN	1	READY TO OPERATE.
		0	OFF1 ACTIVE.
2	RDY_REF	1	OPERATION ENABLED.
		0	OPERATION INHIBITED.
3	TRIPPED	1	FAULT.
		0	No fault.
4	OFF_2_STA	1	OFF2 inactive.
		0	OFF2 ACTIVE.
5	OFF_3_STA	1	OFF3 inactive.
		0	OFF3 ACTIVE.
6	SWC_ON_ INHIB	1	SWITCH-ON INHIBITED.
		0	-
7	ALARM	1	Warning/Alarm.
		0	No warning/alarm.
8	AT_ SETPOINT	1	OPERATING. Actual value equals Reference = is within tolerance limits, i.e. in speed control, speed error is 10% max. of nominal motor speed.
		0	Actual value differs from Reference = is outside tolerance limits.
9	REMOTE	1	Drive control location: REMOTE (EXT1 or EXT2).
		0	Drive control location: LOCAL.
10	ABOVE_ LIMIT	1	Actual frequency or speed equals or exceeds supervision limit (set by drive parameter). Valid in both directions of rotation.
		0	Actual frequency or speed within supervision limit.
11	USER_0		S
12	EXT_RUN_	1	External Run enable signal received.
	ENABLE	0	No external Run enable signal received.
1315	Reserved		

State transition diagram

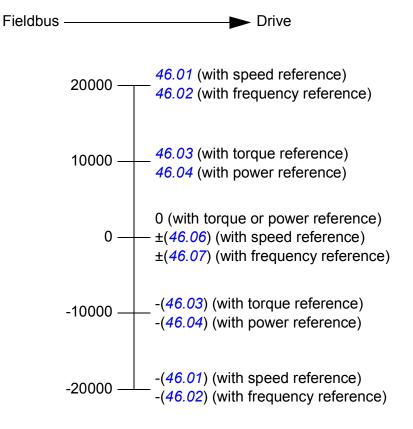
The diagram below shows the state transitions in the drive when the drive is using the ABB Drives profile, and configured to follow the commands of the control word from the embedded fieldbus interface. The upper case texts refer to the states which are used in the tables representing the fieldbus Control and Status words. See sections *Control Word* on page *598* and *Status Word* on page *600*.



References

The ABB drives profile supports the use of two references, EFB reference 1 and EFB reference 2. The references are 16-bit words each containing a sign bit and a 15-bit integer. A negative reference is formed by calculating the two's complement from the corresponding positive reference.

The references are scaled as defined by parameters 46.01...46.07; which scaling is in use depends on the setting of 58.26 *EFB ref1 type* and 58.27 *EFB ref2 type* (see page 374).

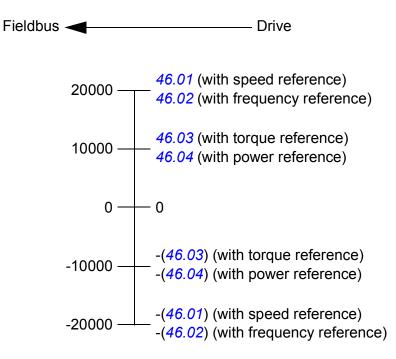


The scaled references are shown by parameters 03.09 *EFB* reference 1 and 03.10 *EFB* reference 2.

Actual values

The ABB Drives profile supports the use of two fieldbus actual values, ACT1 and ACT2. The actual values are 16-bit words each containing a sign bit and a 15-bit integer. A negative value is formed by calculating the two's complement from the corresponding positive value.

The actual values are scaled as defined by parameters 46.01...46.04; which scaling is in use depends on the setting of parameters 58.28 EFB act1 type and 58.29 EFB act2 type (see page 374).



Modbus holding register addresses

The table below shows the default Modbus holding register addresses for drive data. This profile provides a converted 16-bit access to the data.

Register address	Register data (16-bit words)	
400001	Control word. See section Control Word (page 598).	
	The selection can be changed using parameter 58.101 Data I/O 1.	
400002	Reference 1 (REF1).	
	The selection can be changed using parameter 58.102 Data I/O 2.	
400003	Reference 2 (REF2).	
	The selection can be changed using parameter 58.103 Data I/O 3.	
400004	Status Word (SW). See section Status Word (page 600).	
	The selection can be changed using parameter 58.104 Data I/O 4.	
400005	Actual value 1 (ACT1).	
	The selection can be changed using parameter 58.105 Data I/O 5.	
400006	Actual value 2 (ACT2).	
	The selection can be changed using parameter 58.106 Data I/O 6.	
400007400024	Data in/out 724.	
	Selected by parameters 58.107 Data I/O 7 58.124 Data I/O 24.	
400025400089	Unused	
400090400100	Error code access. See section <i>Error code registers (holding register 400090400100)</i> (page 611).	
400101465536	Parameter read/write.	
	Parameters are mapped to register addresses according to parameter <i>58.33 Addressing mode</i> .	

The Transparent profile

The Transparent profile enables a customizable access to the drive.

The contents of the control word are user-definable. The control word received from the fieldbus is visible in parameter *06.05 EFB transparent control word*, and can be used to control the drive using pointer parameters and/or application programming.

The status word to be sent to the fieldbus controller is selected by parameter 58.30 *EFB status word transparent source*. This can be, for example, the user-configurable status word in 06.50 User status word 1.

The Transparent profile involves no data conversion of the control or status word. Whether references or actual values are scaled depends on the setting of parameters *58.26...58.29*. The references received from the fieldbus are visible in parameters *03.09 EFB reference 1* and *03.10 EFB reference 2*.

The Modbus holding register addresses for the Transparent profile are as with the ABB Drives profile (see page 604).

Modbus function codes

The table below shows the Modbus function codes supported by the embedded fieldbus interface.

Code	Function name	Description
01h	Read Coils	Reads the 0/1 status of coils (0X references).
02h	Read Discrete Inputs	Reads the 0/1 status of discrete inputs (1X references).
03h	Read Holding Registers	Reads the binary contents of holding registers (4X references).
05h	Write Single Coil	Forces a single coil (0X reference) to 0 or 1.
06h	Write Single Register	Writes a single holding register (4X reference).
08h	Diagnostics	 Provides a series of tests for checking the communication, or for checking various internal error conditions. Supported subcodes: 00h Return Query Data: Echo/loopback test. 01h Restart Comm Option: Restarts and initializes the EFB, clears communications event counters. 04h Force Listen Only Mode 0Ah Clear Counters and Diagnostic Register 0Bh Return Bus Message Count 0Ch Return Bus Exception Error Count 0Dh Return Slave Message Count 0Fh Return Slave No Response Count 10h Return Slave NAK (negative acknowledge) Count 11h Return Slave Busy Count
		 12h Return Bus Character Overrun Count 14h Clear Overrun Counter and Flag
0Bh	Get Comm Event Counter	Returns a status word and an event count.
0Fh	Write Multiple Coils	Forces a sequence of coils (0X references) to 0 or 1.
10h	Write Multiple Registers	Writes the contents of a contiguous block of holding registers (4X references).
16h	Mask Write Register	Modifies the contents of a 4X register using a combination of an AND mask, an OR mask, and the register's current contents.
17h	Read/Write Multiple Registers	Writes the contents of a contiguous block of 4X registers, then reads the contents of another group of registers (the same or different than those written) in a server device.

Code	Function name	Description
2Bh / 0Eh	Encapsulated Interface Transport	Supported subcodes:
		OEh Read Device Identification: Allows reading the identification and other information.
		Supported ID codes (access type):
		 00h: Request to get the basic device identification (stream access)
	 04h: Request to get one specific identification object (individual access) 	
		Supported Object IDs:
		O0h: Vendor Name ("ABB")
		 01h: Product Code (for example, "AINFX")
	O2h: Major Minor Revision (combination of contents of parameters 07.05 <i>Firmware version</i> and 58.02 <i>Protocol ID</i>).	
		O3h: Vendor URL ("www.abb.com")
		04h: Product name (for example, "ACS880")

Exception codes

The table below shows the Modbus exception codes supported by the embedded fieldbus interface.

Code	Name	Description
01h	ILLEGAL FUNCTION	The function code received in the query is not an allowable action for the server.
02h	ILLEGAL DATA ADDRESS	The data address received in the query is not an allowable address for the server.
03h	ILLEGAL DATA VALUE	The requested Quantity of Registers is larger than the drive can handle.
		Note: This error does not mean that a value written to a drive parameter is outside the valid range.
04h	SLAVE DEVICE FAILURE	The value written to a drive parameter is outside the valid range. See section <i>Error code registers (holding registers 400090400100)</i> on page 611.
06h	SLAVE DEVICE BUSY	The server is engaged in processing a long-duration program command.

Coils (0xxxx reference set)

Coils are 1-bit read/write values. Control Word bits are exposed with this data type. The table below summarizes the Modbus coils (0xxxx reference set).

Reference	ABB drives profile	Transparent profile
00001	OFF1_CONTROL	Control Word bit 0
00002	OFF2_CONTROL	Control Word bit 1
00003	OFF3_CONTROL	Control Word bit 2
00004	INHIBIT_OPERATION	Control Word bit 3
00005	RAMP_OUT_ZERO	Control Word bit 4
00006	RAMP_HOLD	Control Word bit 5
00007	RAMP_IN_ZERO	Control Word bit 6
00008	RESET	Control Word bit 7
00009	JOGGING_1	Control Word bit 8
00010	JOGGING_2	Control Word bit 9
00011	REMOTE_CMD	Control Word bit 10
00012	EXT_CTRL_LOC	Control Word bit 11
00013	User-defined (0)	Control Word bit 12
00014	User-defined (1)	Control Word bit 13
00015	User-defined (2)	Control Word bit 14
00016	User-defined (3)	Control Word bit 15
00017	Reserved	Control Word bit 16
00018	Reserved	Control Word bit 17
00019	Reserved	Control Word bit 18
00020	Reserved	Control Word bit 19
00021	Reserved	Control Word bit 20
00022	Reserved	Control Word bit 21
00023	Reserved	Control Word bit 22
00024	Reserved	Control Word bit 23
00025	Reserved	Control Word bit 24
00026	Reserved	Control Word bit 25
00027	Reserved	Control Word bit 26
00028	Reserved	Control Word bit 27
00029	Reserved	Control Word bit 28
00030	Reserved	Control Word bit 29
00031	Reserved	Control Word bit 30
00032	Reserved	Control Word bit 31
00033	Reserved	10.99 RO/DIO control word, bit 0
00034	Reserved	10.99 RO/DIO control word, bit 1

Reference	ABB drives profile	Transparent profile
00035	Reserved	10.99 RO/DIO control word, bit 2
00036	Reserved	10.99 RO/DIO control word, bit 3
00037	Reserved	10.99 RO/DIO control word, bit 4
00038	Reserved	10.99 RO/DIO control word, bit 5
00039	Reserved	10.99 RO/DIO control word, bit 6
00040	Reserved	10.99 RO/DIO control word, bit 7
00041	Reserved	10.99 RO/DIO control word, bit 8
00042	Reserved	10.99 RO/DIO control word, bit 9

Discrete inputs (1xxxx reference set)

Discrete inputs are 1-bit read-only values. Status Word bits are exposed with this data type. The table below summarizes the Modbus discrete inputs (1xxxx reference set).

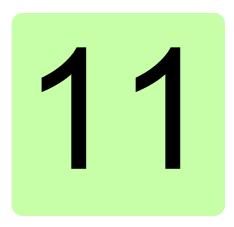
Reference	ABB drives profile	Transparent profile
10001	RDY_ON	Status Word bit 0
10002	RDY_RUN	Status Word bit 1
10003	RDY_REF	Status Word bit 2
10004	TRIPPED	Status Word bit 3
10005	OFF_2_STA	Status Word bit 4
10006	OFF_3_STA	Status Word bit 5
10007	SWC_ON_INHIB	Status Word bit 6
10008	ALARM	Status Word bit 7
10009	AT_SETPOINT	Status Word bit 8
10010	REMOTE	Status Word bit 9
10011	ABOVE_LIMIT	Status Word bit 10
10012	User-defined (0)	Status Word bit 11
10013	User-defined (1)	Status Word bit 12
10014	User-defined (2)	Status Word bit 13
10015	User-defined (3)	Status Word bit 14
10016	Reserved	Status Word bit 15
10017	Reserved	Status Word bit 16
10018	Reserved	Status Word bit 17
10019	Reserved	Status Word bit 18
10020	Reserved	Status Word bit 19
10021	Reserved	Status Word bit 20
10022	Reserved	Status Word bit 21
10023	Reserved	Status Word bit 22
10024	Reserved	Status Word bit 23

Reference	ABB drives profile	Transparent profile
10025	Reserved	Status Word bit 24
10026	Reserved	Status Word bit 25
10027	Reserved	Status Word bit 26
10028	Reserved	Status Word bit 27
10029	Reserved	Status Word bit 28
10030	Reserved	Status Word bit 29
10031	Reserved	Status Word bit 30
10032	Reserved	Status Word bit 31
10033	Reserved	10.02 DI delayed status, bit 0
10034	Reserved	10.02 DI delayed status, bit 1
10035	Reserved	10.02 DI delayed status, bit 2
10036	Reserved	10.02 DI delayed status, bit 3
10037	Reserved	10.02 DI delayed status, bit 4
10038	Reserved	10.02 DI delayed status, bit 5
10039	Reserved	10.02 DI delayed status, bit 6
10040	Reserved	10.02 DI delayed status, bit 7
10041	Reserved	10.02 DI delayed status, bit 8
10042	Reserved	10.02 DI delayed status, bit 9
10043	Reserved	10.02 DI delayed status, bit 10
10044	Reserved	10.02 DI delayed status, bit 11
10045	Reserved	10.02 DI delayed status, bit 12
10046	Reserved	10.02 DI delayed status, bit 13
10047	Reserved	10.02 DI delayed status, bit 14
10048	Reserved	10.02 DI delayed status, bit 15

Error code registers (holding registers 400090...400100)

These registers contain information about the last query. The error register is cleared when a query has finished successfully.

Reference	Name	Description
89	Reset Error Registers	1 = Reset internal error registers (9195).
90	Error Function Code	Function code of the failed query.
91	Error Code	 Set when exception code 04h is generated (see table above). 00h No error 02h Low/High limit exceeded 03h Faulty Index: Unavailable index of an array parameter 05h Incorrect Data Type: Value does not match the data type of the parameter 65h General Error: Undefined error when handling
		query
92	Failed Register	The last register (discrete input, coil, or holding register) that failed to be read or written.
93	Last Register Written Successfully	The last register that was written successfully.
94	Last Register Read Successfully	The last register that was read successfully.



Fieldbus control through a fieldbus adapter

Contents of this chapter

This chapter describes how the drive can be controlled by external devices over a communication network (fieldbus) through an optional fieldbus adapter module.

The fieldbus control interface of the drive is described first, followed by a configuration example.

System overview

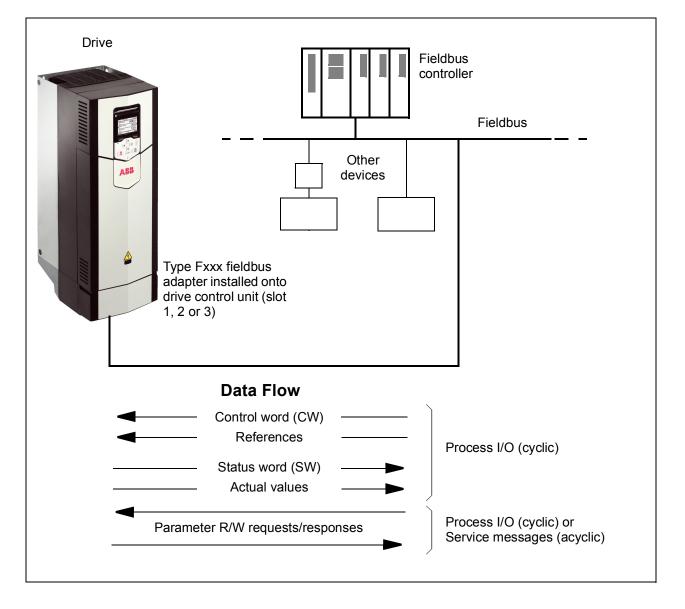
The drive can be connected to an external control system through an optional fieldbus adapter mounted onto the control unit of the drive. The drive actually has two independent interfaces for fieldbus connection, called "fieldbus adapter A" (FBA A) and "fieldbus adapter B" (FBA B). The drive can be configured to receive all of its control information through the fieldbus interface(s), or the control can be distributed between the fieldbus interface(s) and other available sources such as digital and analog inputs, depending on how control locations EXT1 and EXT2 are configured.

Note: The text and examples in this chapter describe the configuration of one fieldbus adapter (FBAA) by parameters *50.01...50.21* and parameter groups *51...53*. The second adapter (FBA B), if present, is configured in a similar fashion by parameters *50.31...50.51* and parameter groups *54...56*. It is recommended that the FBA B interface is only used for monitoring.

Fieldbus adapters are available for various communication systems and protocols, for example

- CANopen (FCAN-01 adapter)
- ControlNet (FCNA-01 adapter)
- DeviceNet (FDNA-01 adapter)
- EtherCAT[®] (FECA-01 adapter)
- EtherNet/IP[™] (FENA-11 or FENA-21 adapter)
- Modbus/RTU (FSCA-01 adapter)
- Modbus/TCP (FENA-11 or FENA-21 adapter)
- POWERLINK (FEPL-02 adapter)
- PROFIBUS DP (FPBA-01 adapter)
- PROFINET IO (FENA-11 or FENA-21 adapter).

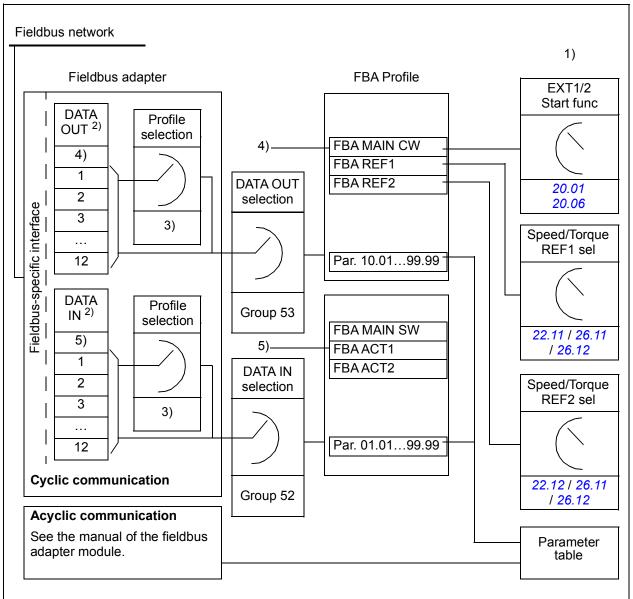
Note: Fieldbus adapters with the suffix "M" (eg. FPBA-01-M) are not supported.



Basics of the fieldbus control interface

The cyclic communication between a fieldbus system and the drive consists of 16- or 32-bit input and output data words. The drive is able to support a maximum of 12 data words (16 bits) in each direction.

Data transmitted from the drive to the fieldbus controller is defined by parameters *52.01 FBA A data in1* ... *52.12 FBA A data in12*. The data transmitted from the fieldbus controller to the drive is defined by parameters *53.01 FBA A data out1* ... *53.12 FBA A data out1* 2.



1) See also other parameters which can be controlled from fieldbus.

2) The maximum number of used data words is protocol-dependent.

3) Profile/instance selection parameters. Fieldbus module specific parameters. For more information, see the *User's Manual* of the appropriate fieldbus adapter module.

4) With DeviceNet, the control part is transmitted directly.

5) With DeviceNet, the actual value part is transmitted directly.

Control word and Status word

The Control word is the principal means for controlling the drive from a fieldbus system. It is sent by the fieldbus master station to the drive through the adapter module. The drive switches between its states according to the bit-coded instructions in the Control word, and returns status information to the master in the Status word.

The contents of the Control word and the Status word are detailed on pages 619 and 621 respectively. The drive states are presented in the state diagram (page 622).

Debugging the network words

If parameter 50.12 FBA A debug mode is set to Fast, the Control word received from the fieldbus is shown by parameter 50.13 FBA A control word, and the Status word transmitted to the fieldbus network by 50.16 FBA A status word. This "raw" data is very useful to determine if the fieldbus master is transmitting the correct data before handing control to the fieldbus network.

References

References are 16-bit words containing a sign bit and a 15-bit integer. A negative reference (indicating reversed direction of rotation) is formed by calculating the two's complement from the corresponding positive reference.

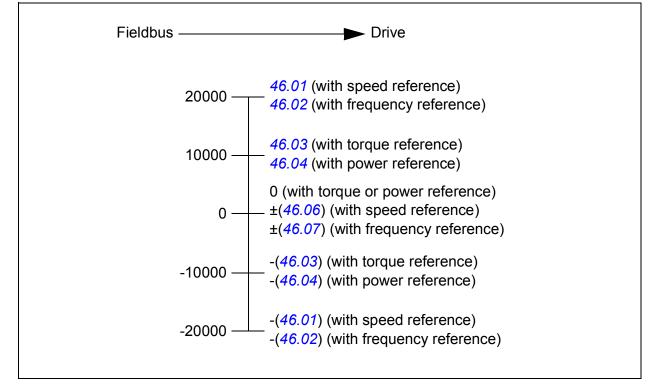
ABB drives can receive control information from multiple sources including analog and digital inputs, the drive control panel and a fieldbus adapter module. In order to have the drive controlled through the fieldbus, the module must be defined as the source for control information such as reference. This is done using the source selection parameters in groups 22 Speed reference selection, 26 Torque reference chain and 28 Frequency reference chain.

Debugging the network words

If parameter 50.12 FBA A debug mode is set to Fast, the references received from the fieldbus are displayed by 50.14 FBA A reference 1 and 50.15 FBA A reference 2.

Scaling of references

The references are scaled as defined by parameters 46.01...46.07; which scaling is in use depends on the setting of 50.04 FBA A ref1 type and 50.05 FBA A ref2 type.



The scaled references are shown by parameters 03.05 FB A reference 1 and 03.06 FB A reference 2.

Actual values

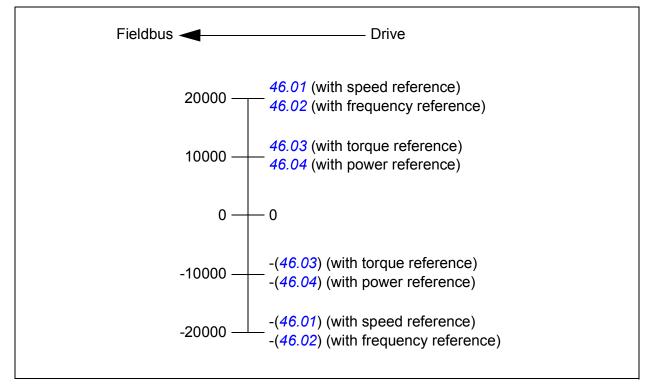
Actual values are 16-bit words containing information on the operation of the drive. The types of the monitored signals are selected by parameters 50.07 FBA A actual 1 type and 50.08 FBA A actual 2 type.

Debugging the network words

If parameter 50.12 FBA A debug mode is set to Fast, the actual values sent to the fieldbus are displayed by 50.17 FBA A actual value 1 and 50.18 FBA A actual value 2.

Scaling of actual values

The actual values are scaled as defined by parameters 46.01...46.04; which scaling is in use depends on the setting of parameters 50.07 FBA A actual 1 type and 50.08 FBA A actual 2 type.



Contents of the fieldbus Control word

The upper case boldface text refers to the states shown in the state diagram (page 622).

Bit	Name	Value	e STATE/Description		
0 Off1 control		1	Proceed to READY TO OPERATE .		
		0	Stop along currently active deceleration ramp. Proceed to OFF1 ACTIVE ; proceed to READY TO SWITCH ON unless other interlock (OFF2, OFF3) are active.		
1 Off2 control		1	Continue operation (OFF2 inactive).		
	0		Emergency OFF, coast to a stop. Proceed to OFF2 ACTIVE , proceed to SWITCH-ON INHIBITED .		
2	Off3 control	1	Continue operation (OFF3 inactive).		
0		0	Emergency stop, stop within time defined by drive parameter. Proceed to OFF3 ACTIVE; proceed to SWITCH-ON INHIBITED. WARNING: Ensure motor and driven machine can be stopped using this stop mode.		
3 Run		1	Proceed to OPERATION ENABLED . Note: Run enable signal must be active. If the drive is set to receive the Run enable signal from the fieldbus, this bit activates the signal. See also parameters <i>06.18 Start inhibit status word</i> and <i>06.25 Drive inhibit status word</i> 2.		
		0	Inhibit operation. Proceed to OPERATION INHIBITED .		
4	Ramp out zero	1	Normal operation. Proceed to RAMP FUNCTION GENERATOR: OUTPUT ENABLED .		
	0		Force Ramp function generator output to zero. The drive will immediately decelerate to zero speed (observing the torque limits).		
5 Ramp hold		1	Enable ramp function. Proceed to RAMP FUNCTION GENERATOR: ACCELERATOR ENABLED.		
		0	Halt ramping (Ramp Function Generator output held).		
6 Ramp in zero		1	Normal operation. Proceed to OPERATING . Note: This bit is effective only if the fieldbus interface is set as the source for this signal by drive parameters.		
		0	Force Ramp function generator input to zero.		
7	Reset	0=>1	Fault reset if an active fault exists. Proceed to SWITCH-ON INHIBITED . Note: This bit is effective only if the fieldbus interface is set as the source of the reset signal by drive parameters.		
		0	Continue normal operation.		
8 Inching 1		1	 Accelerate to inching (jogging) setpoint 1. Note: Bits 46 must be 0. See also section <i>Jogging</i> (page <i>89</i>). 		
		0	Inching (jogging) 1 disabled.		
9 Inching 2		1	Accelerate to inching (jogging) setpoint 2. See notes at bit 8.		
		0	Inching (jogging) 2 disabled.		
10	Remote cmd	1	Fieldbus control enabled.		
		0	Control word and reference not getting through to the drive, except for bits 02.		

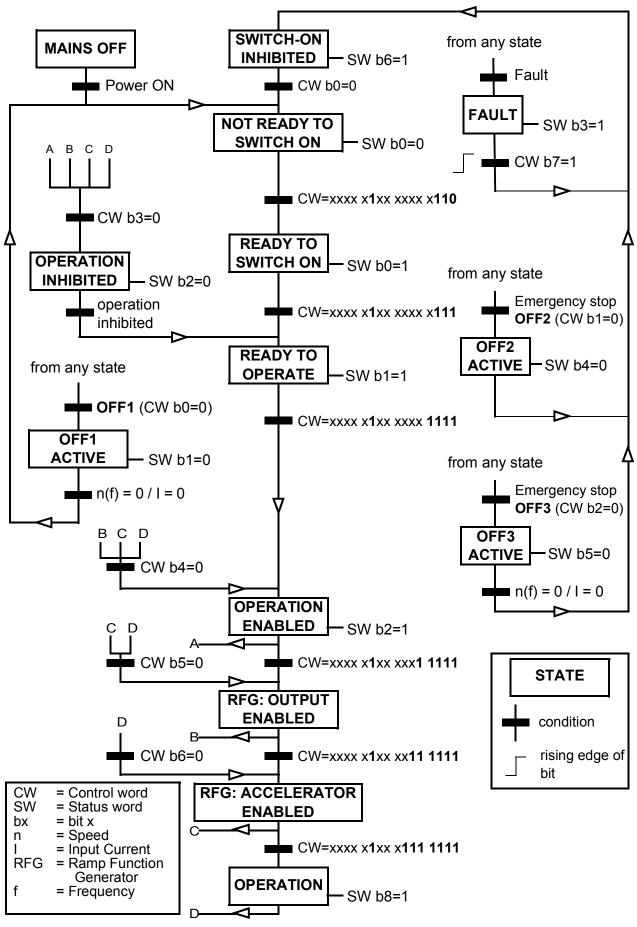
Bit	Name	Value	STATE/Description	
11	Ext ctrl loc	1	Select External Control Location EXT2. Effective if control location parameterized to be selected from fieldbus.	
		0	Select External Control Location EXT1. Effective if control location is parameterized to be selected from fieldbus.	
12 to 15	Reserved.			

Contents of the fieldbus Status word

The upper case boldface text refers to the states shown in the state diagram (page 622).

Bit	Name	Value	STATE/Description		
0	Ready to switch ON	1	READY TO SWITCH ON.		
		0	NOT READY TO SWITCH ON.		
1	Ready run	1	READY TO OPERATE.		
		0	OFF1 ACTIVE.		
2	Ready ref	1	OPERATION ENABLED.		
		0	OPERATION INHIBITED . See also parameters <i>06.18 Start</i> <i>inhibit status word</i> and <i>06.25 Drive inhibit status word 2</i> for the inhibiting condition.		
3	Tripped	1	FAULT.		
		0	No fault.		
4	Off 2 inactive	1	OFF2 inactive.		
		0	OFF2 ACTIVE.		
5	Off 3 inactive	1	OFF3 inactive.		
		0	OFF3 ACTIVE.		
6	Switch-on inhibited	1	SWITCH-ON INHIBITED.		
		0	-		
7	Warning	1	Warning active.		
		0	No warning active.		
8	At setpoint	1	OPERATING . Actual value equals reference = is within tolerance limits, i.e. in speed control, speed error is 10% max. of nominal motor speed.		
		0	Actual value differs from reference = is outside tolerance limits.		
9	Remote	1	Drive control location: REMOTE (EXT1 or EXT2).		
		0	Drive control location: LOCAL.		
10	Above limit	-	See parameter 06.29 MSW bit 10 sel.		
11	User bit 0	-	See parameter 06.30 MSW bit 11 sel.		
12	User bit 1	-	See parameter 06.31 MSW bit 12 sel.		
13	User bit 2	-	See parameter 06.32 MSW bit 13 sel.		
14	User bit 3	-	See parameter 06.33 MSW bit 14 sel.		
15	Reserved	•	·		





Setting up the drive for fieldbus control

- 1. Install the fieldbus adapter module mechanically and electrically according to the instructions given in the *User's manual* of the module.
- 2. Power up the drive.
- 3. Enable the communication between the drive and the fieldbus adapter module with parameter *50.01 FBA A enable*.
- With 50.02 FBA A comm loss func, select how the drive should react to a fieldbus communication break.
 Note: This function monitors both the communication between the fieldbus master and the adapter module and the communication between the adapter module and the drive.
- 5. With *50.03 FBA A comm loss t out*, define the time between communication break detection and the selected action.
- 6. Select application-specific values for the rest of the parameters in group 50 *Fieldbus adapter (FBA)*, starting from 50.04. Examples of appropriate values are shown in the tables below.
- 7. Set the fieldbus adapter module configuration parameters in group 51 FBA A settings. As a minimum, set the required node address and the communication profile.
- 8. Define the process data transferred to and from the drive in parameter groups 52 *FBA A data in* and 53 *FBA A data out*.

Note: Depending on the communication protocol and profile being used, the Control word and Status word may already be configured to be sent/received by the communication system.

- 9. Save the valid parameter values to permanent memory by setting parameter *96.07 Parameter save manually* to *Save*.
- 10. Validate the settings made in parameter groups 51, 52 and 53 by setting parameter *51.27 FBA A par refresh* to *Refresh*.
- 11. Configure control locations EXT1 and EXT2 to allow control and reference signals to come from the fieldbus. Examples of appropriate values are shown in the tables below.

Parameter setting example: FPBA (PROFIBUS DP)

This example shows how to configure a basic speed control application that uses the PROFIdrive communication profile with PPO Type 2. The start/stop commands and reference are according to the PROFIdrive profile, speed control mode.

The reference values sent over the fieldbus have to be scaled within the drive so they have the desired effect. The reference value ± 16384 (4000h) corresponds to the range of speed set in parameter 46.01 Speed scaling (both forward and reverse directions). For example, if 46.01 is set to 480 rpm, then 4000h sent over fieldbus will request 480 rpm.

Direction	PZD1	PZD2	PZD3	PZD4	PZD5	PZD6
Out	Control word	Speed reference	Acc time	1	Dec time	e 1
In	Status word	Speed actual value	Motor cu	rrent	DC volta	ge

The table below gives the recommended drive parameter settings.

Drive parameter	Setting for ACS880 drives	Description
50.01 FBA A enable	13 = [slot number]	Enables communication between the drive and the fieldbus adapter module.
50.04 FBA A ref1 type	4 = Speed	Selects the fieldbus A reference 1 type and scaling.
50.07 FBA A actual 1 type	0 = Auto	Selects the actual value type/source and scaling according to the currently active control mode (as displayed by parameter 19.01).
51.01 FBA A type	1 = FPBA ¹⁾	Displays the type of the fieldbus adapter module.
51.02 Node address	3 ²⁾	Defines the PROFIBUS node address of the fieldbus adapter module.
51.03 Baud rate	12000 ¹⁾	Displays the current baud rate on the PROFIBUS network in kbit/s.
51.04 MSG type	1 = PPO1 ¹⁾	Displays the telegram type selected by the PLC configuration tool.
51.05 Profile	0 = PROFIdrive	Selects the Control word according to the PROFIdrive profile (speed control mode).
51.07 RPBA mode	0 = Disabled	Disables the RPBA emulation mode.
52.01 FBA data in1	4 = SW 16bit ¹⁾	Status word
52.02 FBA data in2	5 = Act1 16bit	Actual value 1
52.03 FBA data in3	01.07 ²⁾	Motor current
52.05 FBA data in5	01.11 ²⁾	DC voltage
53.01 FBA data out1	1 = CW 16bit ¹⁾	Control word
53.02 FBA data out2	2 = Ref1 16bit	Reference 1 (speed)

Drive parameter	Setting for ACS880 drives	Description
53.03 FBA data out3	23.12 ²⁾	Acceleration time 1
53.05 FBA data out5	23.13 ²⁾	Deceleration time 1
51.27 FBA A par refresh	1 = Refresh	Validates the configuration parameter settings.
19.12 Ext1 control mode	2 = Speed	Selects speed control as the control mode 1 for external control location EXT1.
20.01 Ext1 commands	12 = Fieldbus A	Selects fieldbus adapter A as the source of the start and stop commands for external control location EXT1.
20.02 Ext1 start trigger type	1 = <i>Level</i>	Selects a level-triggered start signal for external control location EXT1.
22.11 Speed ref1 source	4 = FB A ref1	Selects fieldbus A reference 1 as the source for speed reference 1.

¹⁾ Read-only or automatically detected/set

²⁾ Example

The start sequence for the parameter example above is given below.

Control word:

- after power-on, fault or emergency stop:
 - 476h (1142 decimal) -> NOT READY TO SWITCH ON
- in normal operation:
 - 477h (1143 decimal) -> READY TO SWITCH ON (stopped)
 - 47Fh (1151 decimal) -> OPERATING (running)

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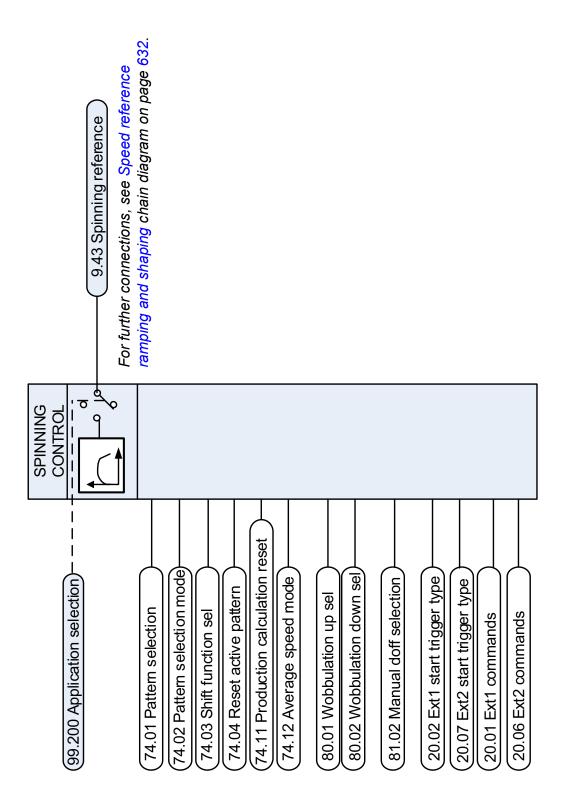
Control chain diagrams

Contents of this chapter

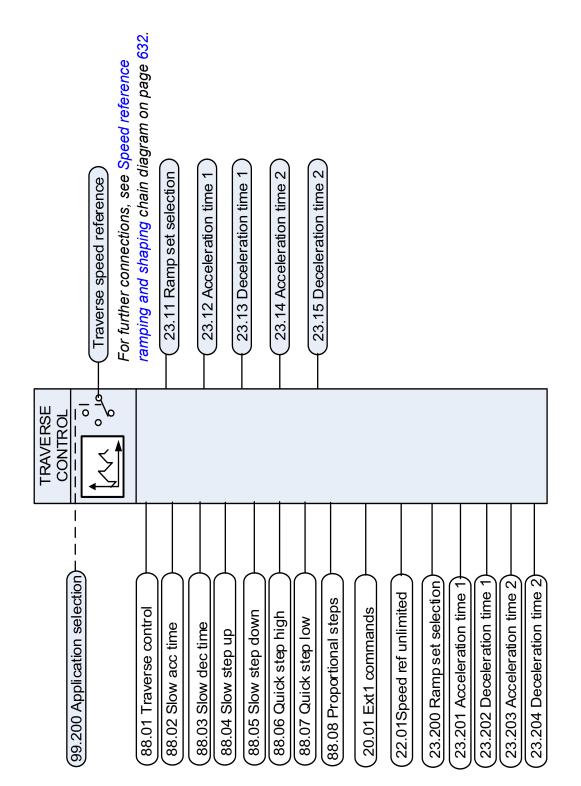
The chapter presents the reference chains of a drive equipped with the spinning and traverse control program. The control chain diagrams can be used to trace how parameters interact and where parameters have an effect within the drive parameter system.

For a more general diagram, see section Operating modes of the drive (page 57).

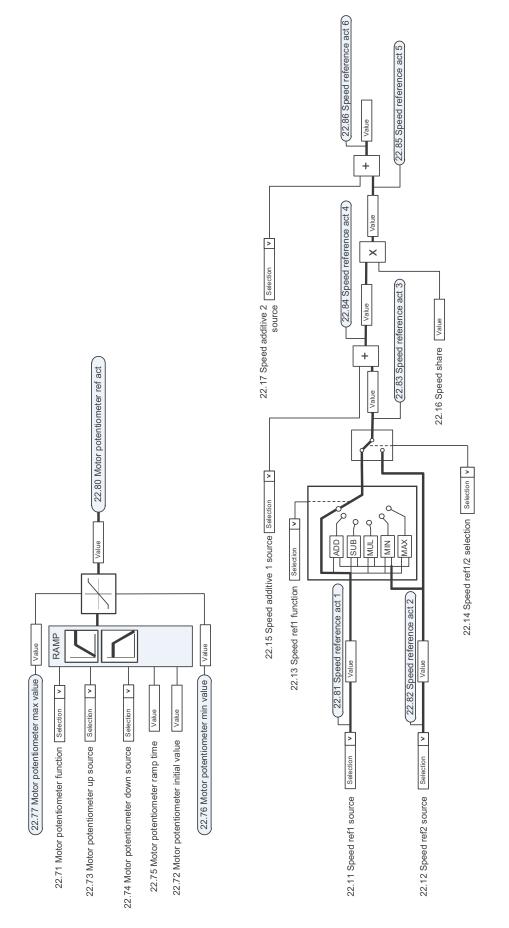
Spinning control function

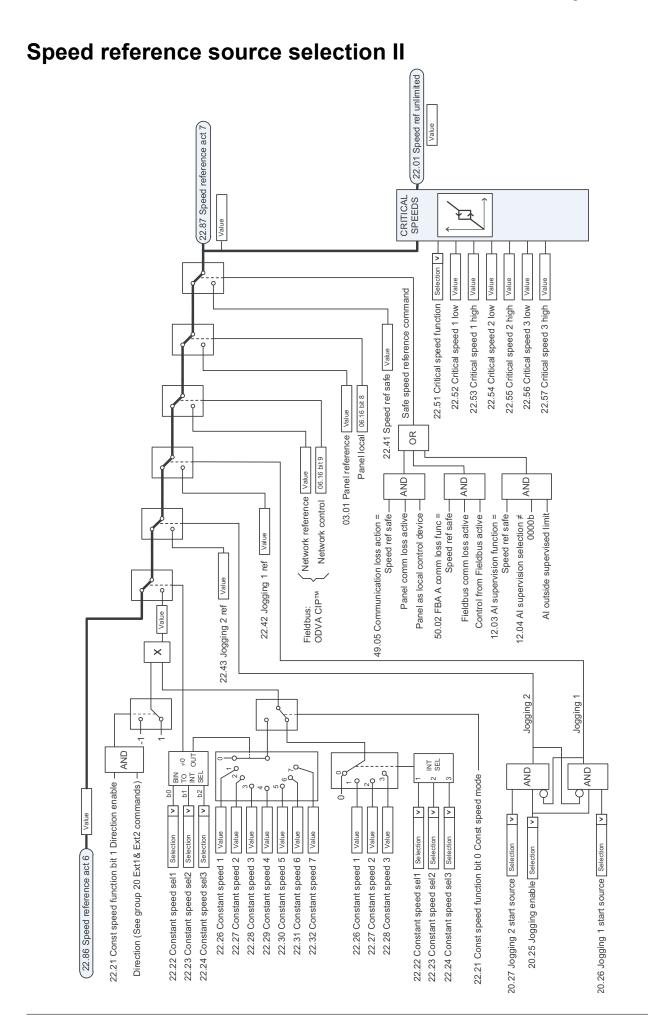


Traverse control function

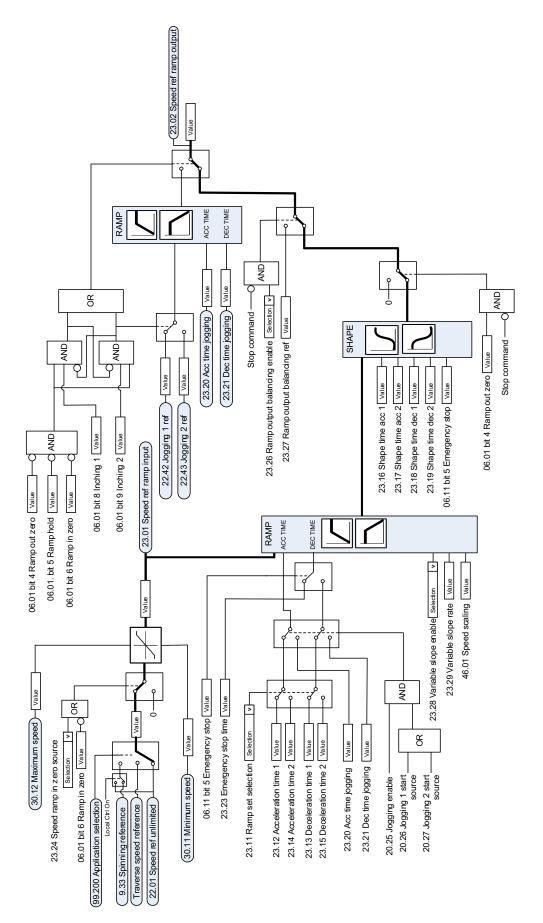


Speed reference source selection I

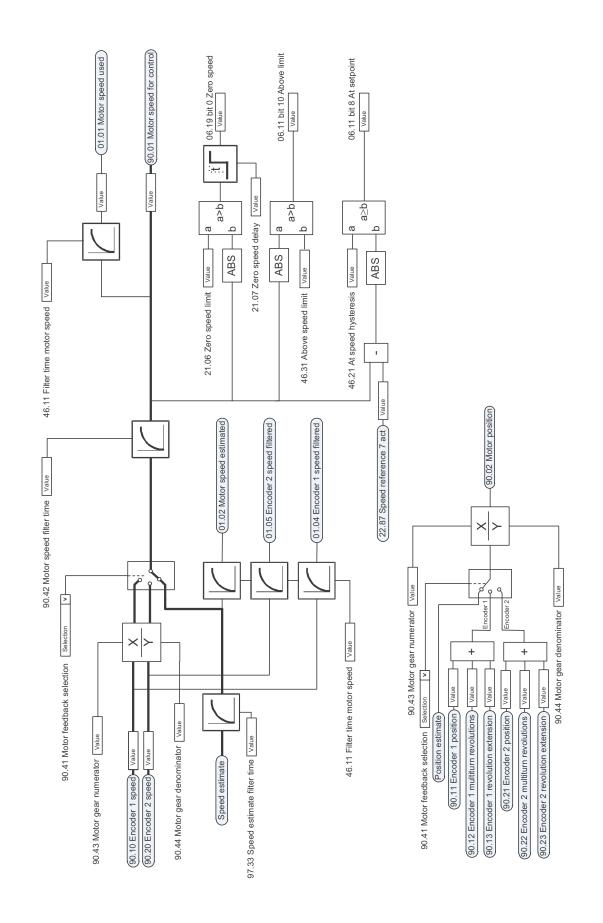




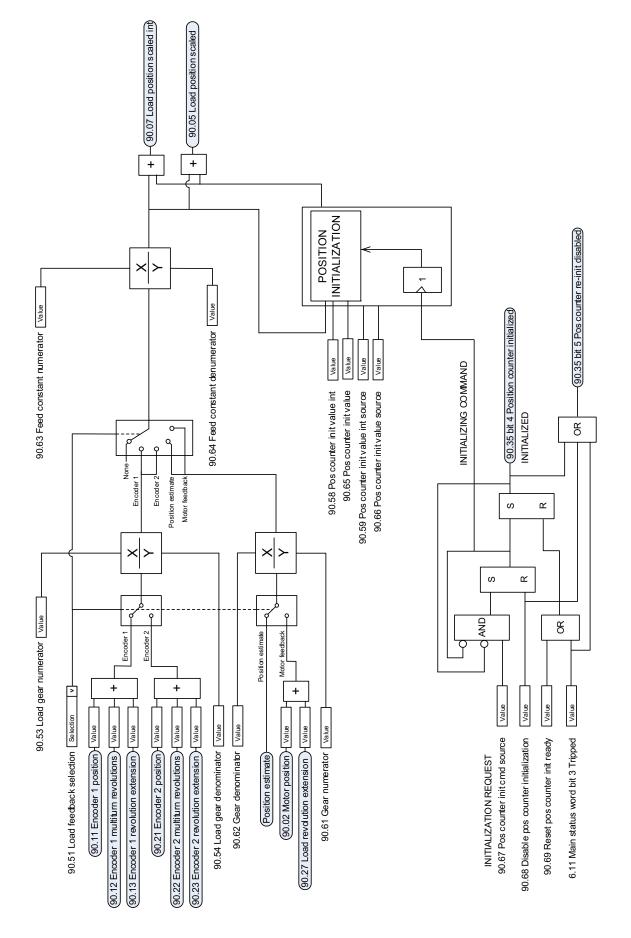


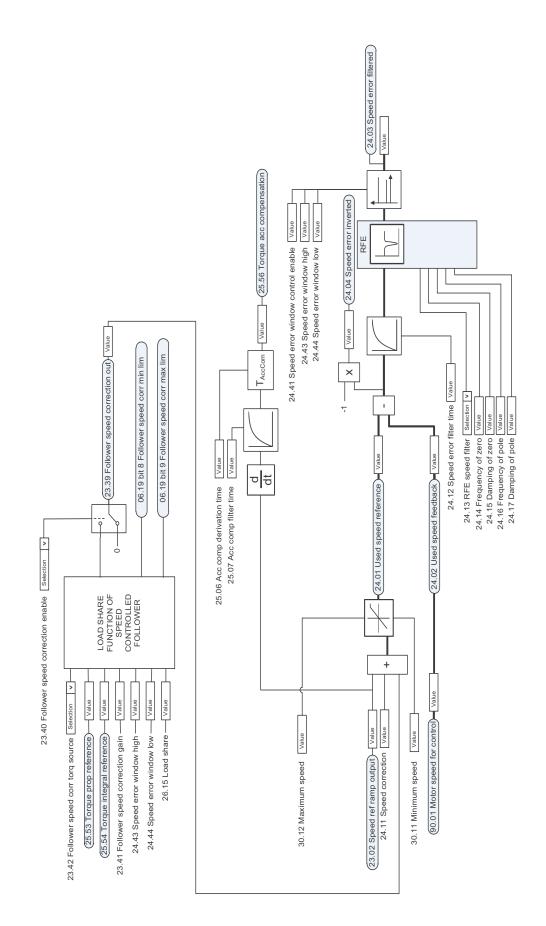


Motor feedback configuration



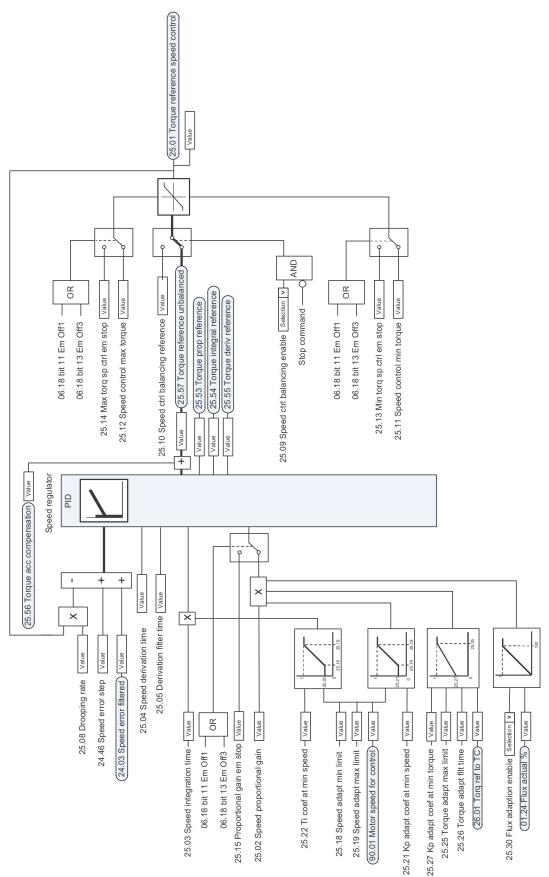


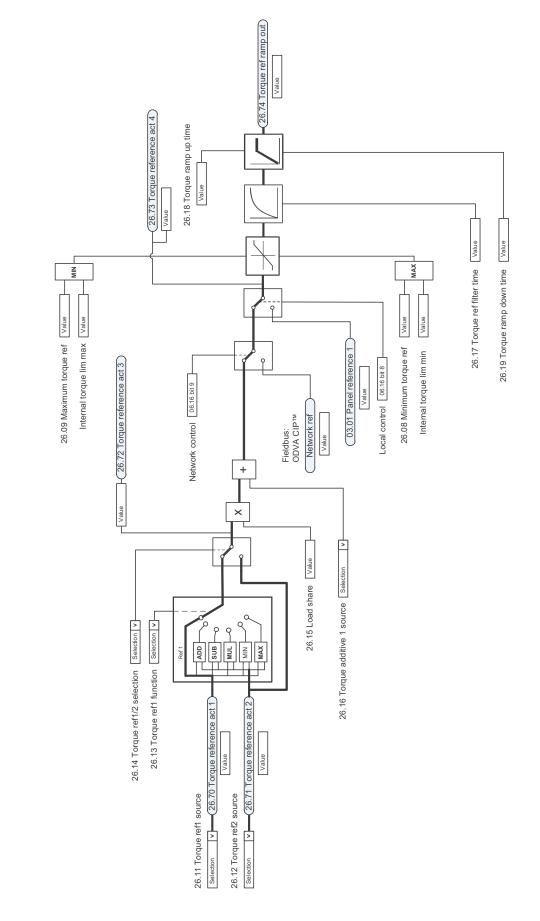




Speed error calculation

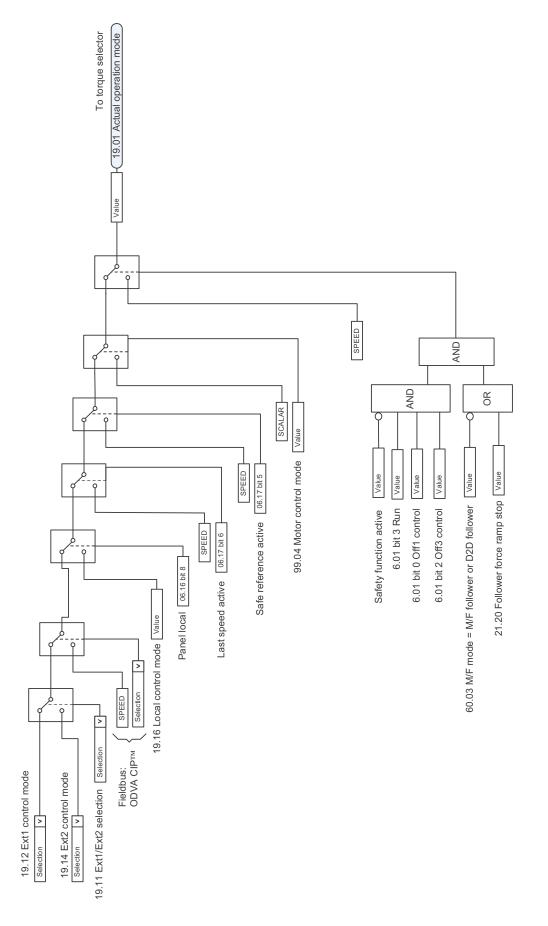
Speed controller



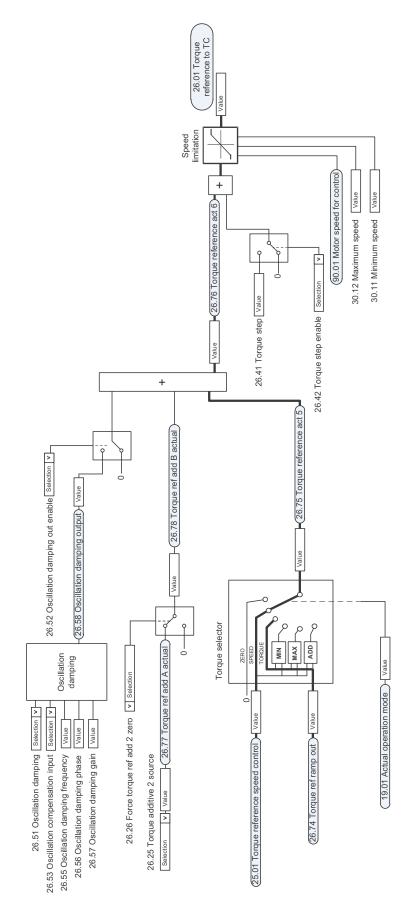


Torque reference source selection and modification

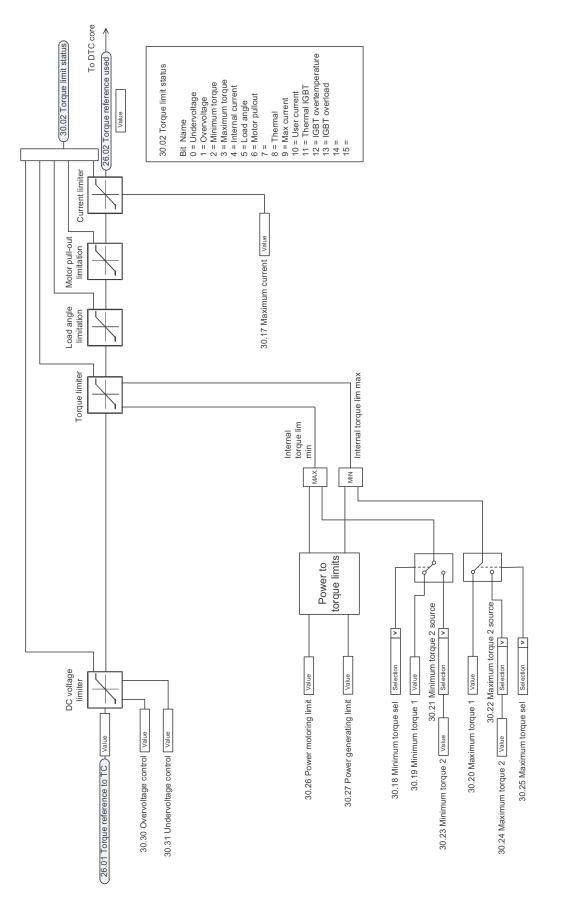
Operating mode selection



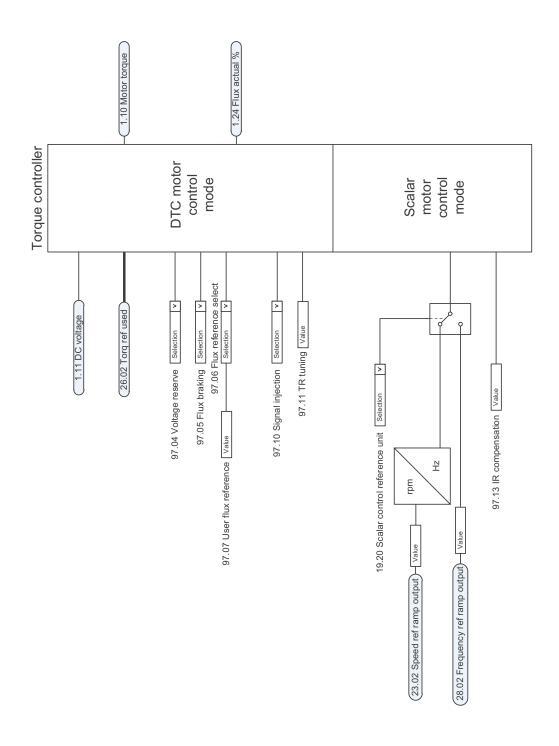
Reference selection for torque controller



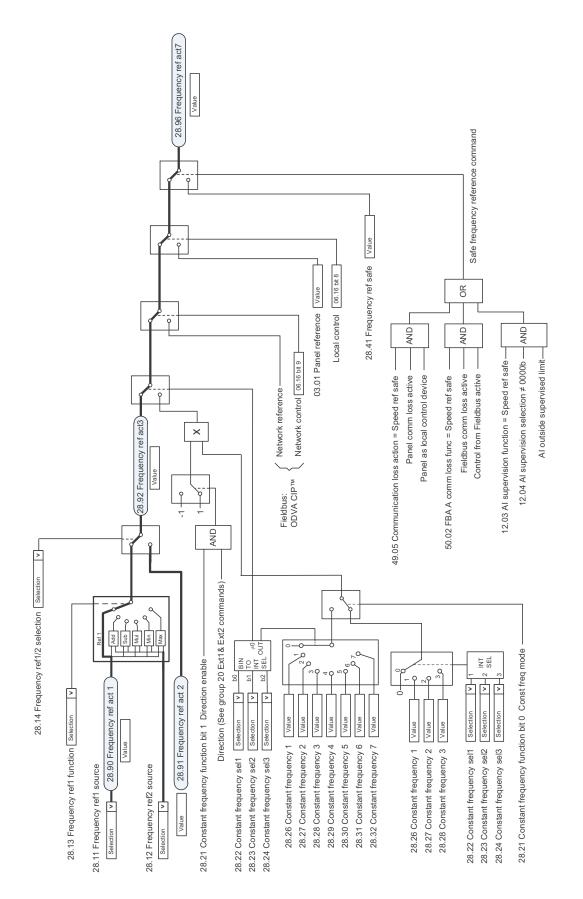
Torque limitation

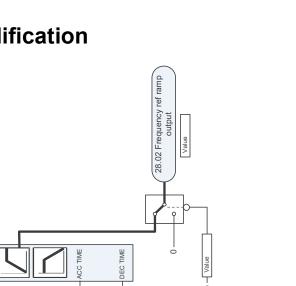


Torque controller

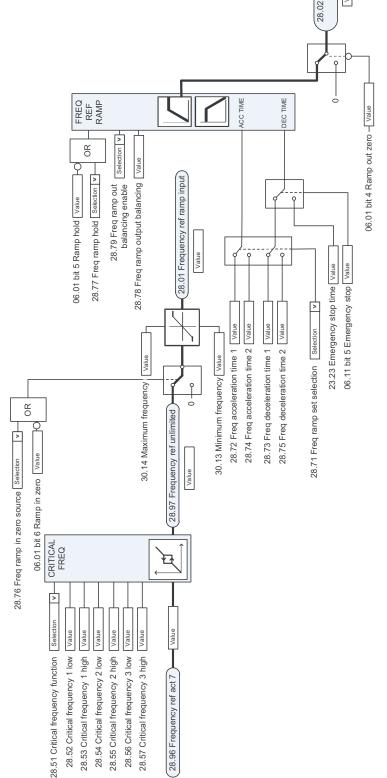


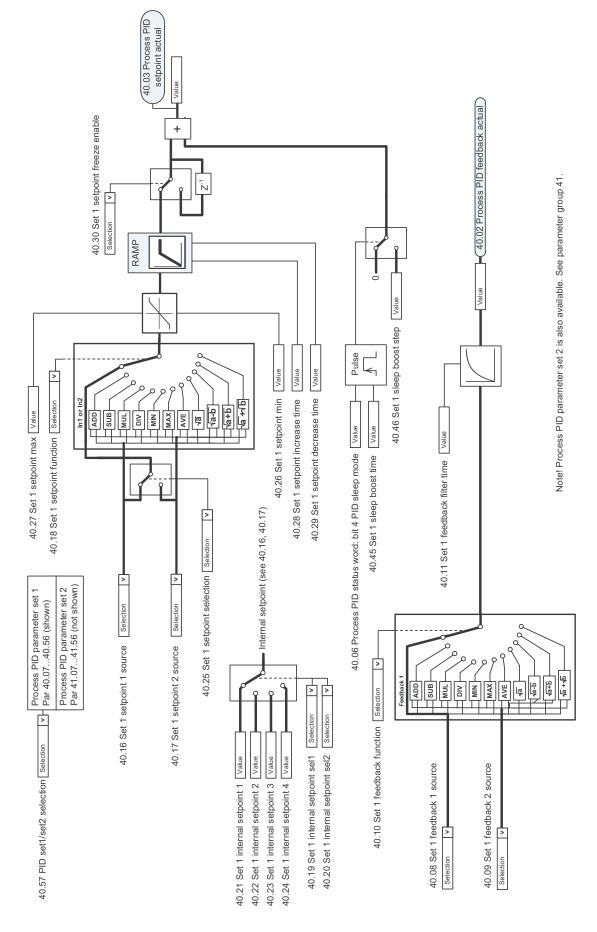
Frequency reference selection



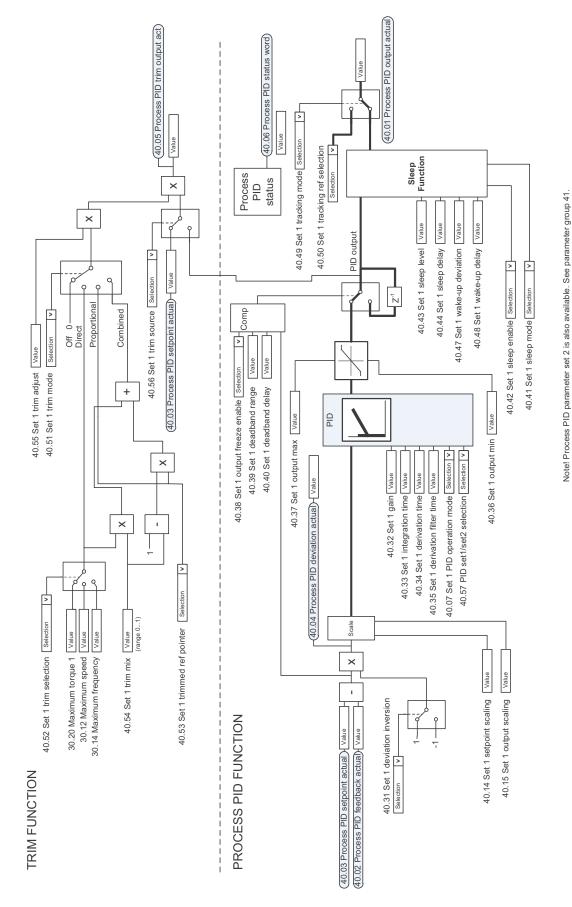


Frequency reference modification

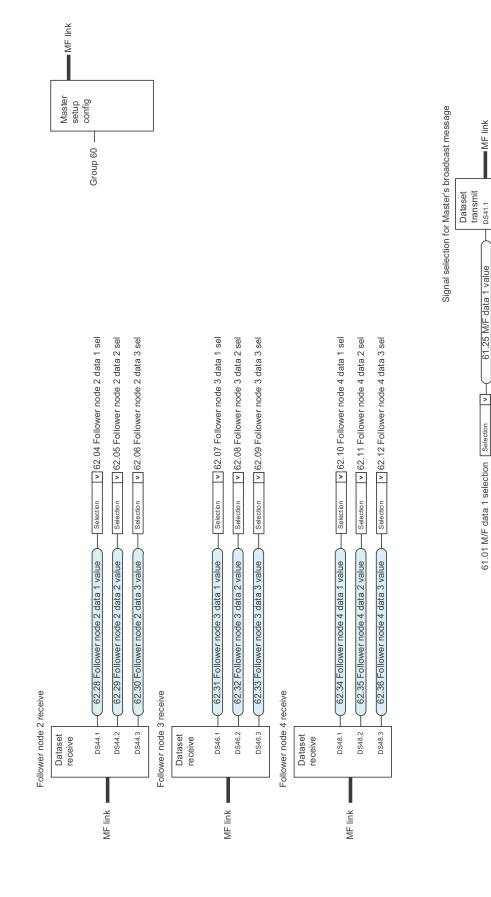




Process PID setpoint and feedback source selection



Process PID controller



DS41.2 DS41.3

61.26 M/F data 2 value 61.27 M/F data 3 value

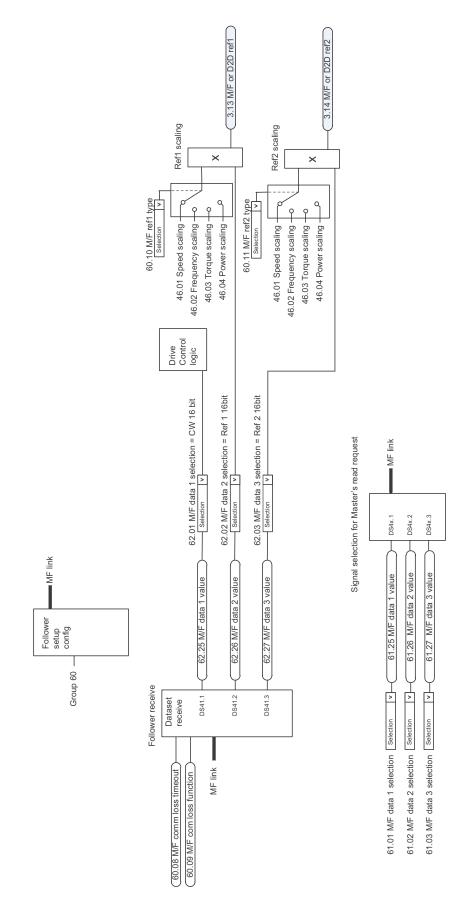
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Selection

61.02 M/F data 2 selection 61.03 M/F data 3 selection

Master/Follower communication I (Master)

Master/Follower communication II (Follower)



648 Control chain diagrams

Further information

Product and service inquiries

Address any inquiries about the product to your local ABB representative, quoting the type designation and serial number of the unit in question. A listing of ABB sales, support and service contacts can be found by navigating to <u>www.abb.com/searchchannels</u>.

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