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Sanyo Denki
PY Servo System

Installation and Operation Manual

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SANYO DENKI

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Table of Contents

TABLE OF CONTENTS 2

INTRODUCTION 5
- About this Guide 5
- Safety 7
- Technical Support 9
- Product Family Overview 10

INSTALLATION 13
- Chapter Overview 13
- Unpacking and Inspection Procedure 14
- Amplifier Installation 15
- Motor Installation 20
- Installation Check List 27

WIRING 28
- Chapter Overview 28
- Wiring Precautions 31
- Applicable Wire Sizes 32
- Input Power 33
- Leakage Current 33
- Connection Diagram (PY2 with P3/P5 Motor) 34
- Connection Diagram (PY2 with P2/P6 Motor) 35
- Connection Diagram (PY0 with P3/P5 Motor) 36
- Connection Diagram (PY0 with P2/P6 Motor) 37
- CNA, CND and CNB Connectors 38
- Input/Output Internal Circuits 39
- CN1 Control Connector 41
- CN2 Motor Encoder Connector 45
- Operator Terminal 46
- External Regeneration Resistors 47
- Wiring Check List 53

OPERATION 54
- Chapter Overview 54
- Pre-Operation 55
- Power “On” Sequence 56
- Stop Sequences 57
- Servo “OFF” Sequence 59
- Alarm Reset Sequence 61
- Over-travel Sequence 62

DRIVE SETUP 63
- Chapter Overview 63

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Using the Remote Operator 64
PY Setup Software 66
Jogging Operations 68
Amplifier Tuning 71
Monitor Screen 74
Alarm Trace Screen 75
Quick Setup 76

AMPLIFIER PARAMETERS 77
Chapter Overview 77
Parameter Summary, by Mode and Page 80
Detailed Description of Parameters 83

MAINTENANCE AND TROUBLESHOOTING 117
Chapter Overview 117
Maintenance 118
Troubleshooting 118

SPECIFICATIONS 128
Chapter Overview 128
Acceleration and Deceleration Time 129
Dynamic Brake 130
Miscellaneous Servo Motor Specifications 132

INDEX 133

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List of Tables

Table 1: Manual Syntax....6
Table 2: Valid Drive Systems....11
Table 3: Amplifier Environmental Requirements....18
Table 4: Power Dissipation....18
Table 5: Motor Environmental Requirements....20
Table 6: Motor IP Rating....23
Table 7: Allowable Radial and Thrust Loads....26
Table 8: Applicable Wire Sizes....32
Table 9: Power Supply Capacity Requirement....33
Table 10: System Leakage Current....33
Table 11: CNA, CND, and CNB Connector Pin Assignments....38
Table 12: CN1 Internal Circuits....39
Table 13: CN1 Pin Assignments....41
Table 14: CN2 Pin Assignments....45
Table 15: Amplifier Regeneration Power....47
Table 16: Regeneration Resistor Selection....50
Table 17: Amplifier Status Display....55
Table 18: Monitor Mode Page Descriptions....74
Table 19: Alarm Mode Page Descriptions....75
Table 20: Quick Setup Steps with Remote Operator....76
Table 21: Amplifier Alarm Codes....118
Table 22: Holding Brake Specifications....132

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Introduction

About this Guide

In this Chapter

This chapter covers the following topics:

About this Guide 5
In this Chapter 5
Introduction 5
Manual Organization 5
Syntax Information 6
Safety 7
Technical Support 9
Online Support 9
E-Mail Support ***Error! Bookmark not defined.***
Telephone Support 9
Field Service ***Error! Bookmark not defined.***
Product Family Overview 10
Amplifiers 10
Motors 10
Systems 11
Remote Operator / Software 11
Cables 12
External Regen Resistors 12

Introduction

This guide provides you with information needed to install, operate, and maintain PY model servo amplifiers and matching motors.

Manual Organization

This guide consists of the following chapters:

Chapter 1. **Introduction** provides an overview of the Safety issues associated with the application of servo motors and amplifiers, informs you about all your product support options, and finally provides an overview of the PY family of amplifiers, the P2, P3, P5, and P6 family of motors, and system options and accessories.

Chapter 2. **Installation** provides detailed directions that take you step by step from unpacking your system, through installing the motor and installing the amplifier, and concludes with an installation checklist.

Chapter 3. **Wiring** describes how to wire a system - starting first with a summary table indicating recommended wire sizes, followed by connection diagrams, and concluding with details for connecting external regeneration resistors and the remote operator. Detailed connector pin assignments are provided as well as a partial schematic for input and output signals.

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Chapter 4. **System Configuration** describes how to use the remote operator and then walks you through the configuring and tuning of your system. This chapter concludes with a detailed description of each amplifier parameter.

Chapter 5. **Operation** chapter provides a detailed description of the sequence and timing of operation within the amplifier.

Chapter 6, **Drive Setup** chapter provides information on setup of the drive configuration for operation

Chapter 7, **Amplifier Parameters** chapter provides a list of all parameters used for the drive configuration.

Chapter 8. **Maintenance and Troubleshooting** provides you with a recommended maintenance program designed to keep your system in top operating condition. Should you experience any difficulty with your system, a detailed troubleshooting guide is provided to help you restore normal operation quickly.

Chapter 9. **Specifications** section includes detailed specifications for PY drive systems. This includes a detailed reference for all the amplifier parameters.

Syntax Information

To help you locate and interpret information easily, this guide uses consistent visual cues and text formats. The different symbols and typefaces displayed in this guide are used for the following purposes:

Table 1: Manual Syntax

♫	This symbol is used to identify important information of which you should take note.
!	DANGER, WARNING or CAUTION require accompanying information notices to prevent potential personal injury and equipment damage. DANGER: Indicates an imminently hazardous situation which, if not avoided, will result in serious injury or death. This signal word is limited to the most extreme situations. WARNING: Indicates a potentially hazardous situation which, if not avoided, could result in serious injury or death. CAUTION: Indicates a potentially hazardous situation which, if not avoided, may result in equipment damage or minor or moderate injury.
Earth Gnd	Protective conductor terminal, Earth Ground.
Chassis Gnd	Chassis terminal, Not a protective ground.

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Safety

!	**DANGER** Only qualified personnel familiar with the construction and operation of this equipment and the hazards involved should install, adjust, operate, or service this equipment. Read and understand this manual and other applicable manuals in their entirety before proceeding. Failure to observe this could result in severe injury or loss of life.

!	**DANGER** The user is responsible for conforming with all applicable local, national, and international codes. The wiring examples in this manual are intended only as a guide. Wiring practices, grounding and disconnects, and over-current protection are of particular importance. Failure to observe this could result in severe injury or loss of life.

!	**DANGER** Do not operate the system in an explosive atmosphere. Failure to observe this could result in severe injury or loss of life and equipment damage.

!	**WARNING** Perform the initial power-up with the motor shaft disconnected from the load and the shaft key removed. Improper wiring or undiscovered shipping damage could result in undesired motion. Be prepared to remove power if excessive motion occurs. Failure to observe this precaution could result in bodily injury.

!	**WARNING** Large leakage currents exist in AC line filters. They must be grounded properly before applying power. Filter capacitors retain high voltages after power is removed. Before handling the equipment, voltage should be measured to determine safe levels. Failure to observe this precaution could result in severe bodily injury.

!	**WARNING** Avoid damaged cables. Cables may be damaged by applying excessive stress, placing a heavy object on them, or cutting them. Damaged cables may result in electrical shock which can cause severe bodily injury and damage equipment.

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!	**CAUTION**
	Observe all installation directions. Failure to do so may result in injury, damage to equipment, or poor performance. 1. Make sure nothing obstructs or impedes ventilation around the amplifier. 2. Observe all mounting clearance distances around the unit. 3. Never install the system in a location where water, or other fluids, may be splashed, or in a flammable gas atmosphere. 4. Never place objects on this equipment. Doing so may result in damage, burns or fire. 5. Avoid strong shocks to equipment. This may result in injury or damage to equipment.

!	**WARNING**
	During normal operation, the amplifier, motor and peripheral equipment could become hot enough to cause a burn.

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Technical Support

Online Support

The most convenient and effective method for support is online at our web site

www.MotionOnline.com

In addition to this manual, you may download our *Handbook of AC Servo Systems*, application notes and answers to frequently asked questions from this site.

Telephone Support

Sanyo Denki America maintains a Technical Support center that is staffed weekdays (except holidays) between 8:30 AM and 5:30 PM Eastern Standard Time.

- Telephone: 770-497-8086 or Toll Free 1-888-531-8213
- Facsimile: 770-497-8666

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Product Family Overview



Amplifiers

Sanyo Denki designs and manufactures a wide range of servo and stepper drives. Eight models from the PY family are available to you from Sanyo Denki America via MotionOnline.com.

- PY2A015 15A
- PY2A030 30A
- PY2A050 50A
- PY0A015 15A
- PY0A030 30A
- PY0A050 50A
- PY0A100 100A
- PY0A150 150A

Motors

Sanyo Denki designs and manufactures a wide range of servo and stepper motors. Twenty (10 without brakes and 10 with brakes) models from the P2, P3, P5 and P6 families are available to you from Sanyo Denki America via MotionOnline.com.

- P20B10150D 1.5kW 4.9Nm
- P20B10250D 2.5kW 8.8Nm
- P20B13300D 3.0kW 10.8Nm
- P20B13500D 5.0kW 18.1Nm
- P30B04010D 100W 0.35Nm
- P30B06040D 400W 1.37Nm
- P30B08075D 750W 2.55Nm
- P50N05020D 200W 0.686Nm
- P50N08100D 1kW 3.92Nm
- P60B13150H 1.5kW 7.5Nm

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Systems

From these motors and amplifiers, the following 17 systems can be assembled. All the systems can operate up to 4,500 RPM (except for the P6 motor that is 3000 RPM). The power listed is continuous at 3,000 RPM (except for the P6 motor at 2000 RPM) while the torque listed is continuous at 0 RPM.

Table 2: Valid Drive Systems

Motor Model	W	Nm	PY2 Amplifiers			PY0 Amplifiers				
			15A	30A	50A	15A	30A	50A	100A	150A
P30B04010D	100	0.35	⊙			⊙				
P30B06040D	400	1.37		⊙			⊙			
P30B08075D	750	2.55		⊙			⊙			
P20B10150D	1500	4.9			⊙			⊙		
P20B10250D	2500	8.8							⊙	
P20B13300D	3000	10.8							⊙	
P20B13500D	5000	18.1								⊙
P50N05020D	200	0.686	⊙			⊙				
P50N08100D	1000	3.92			⊙			⊙		
P60B13150H	1500	7.5			⊙			⊙		

Remote Operator / Software

The remote operator or PY software is required to set/change all the parameters in the traditional PY amplifiers.

The remote operator is not required for operation and may therefore be shared between all the drives in a system. The same remote operator is used for the PY amplifiers.

The PC-SETUP software can be used to set/change all parameters in the traditional PY amplifiers (except for power phasing). This item may be purchased instead of the remote operator.

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Cables

To lower life-cycle cost and improve reliability, Sanyo Denki America requires customers to use Sanyo Denki motor power and feedback cables. These cables may be ordered in standard (10, 15, 20, 30, 50, 75, or 100 ft) or custom lengths. Standard cables are usually available directly from stock.

External Regen Resistors

Optional external regeneration resistors are available to extend the continuous regeneration power of the amplifier.

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Installation

Chapter Overview

This chapter contains a guide for the installation of the amplifier and matching motor, from unpacking the equipment, performing an initial test, to mounting it in a panel.

Chapter Overview 13
Unpacking and Inspection Procedure 14
Unpack the Amplifier *14*
Inspection *14*
Amplifier Installation 15
General Requirement *15*
Mounting and Clearance Requirements *16*
Amplifier Environmental Requirements *18*
Power Dissipation *18*
Enclosure Size *19*
Motor Installation 20
Environmental Requirements *20*
Motor Mounting *21*
Motor Mounting *22*
Motor Orientation and Cable Routing *23*
Connecting the Load to the Motor *24*
Bearing Load Specifications *26*
Installation Check List 27

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Unpacking and Inspection Procedure

Unpack the Amplifier

- Before opening packages, verify that the model numbers of the box match your order. If they do not, please contact Sanyo Denki America (see page 9 - Technical Support).
- After opening, verify that the model numbers on the product match the box. If they do not, please contact Sanyo Denki America (see page 9 - Technical Support).

Inspection

- After unpacking, verify that the servo amplifier and motor are free from any physical damage that may have occurred during shipment. If you find damage, contact your Buyer to make a claim with the shipper.
- Perform the Inspection Test to verify functionality of the system.

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Amplifier Installation

General Requirement

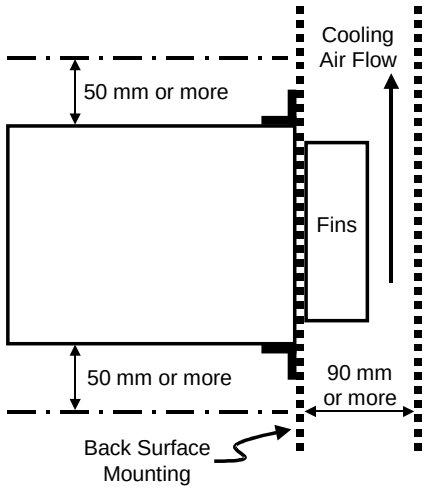
Condition	Recommended Precautions
Amplifier In An Enclosure	The temperature inside an enclosure may be higher than the outside temperature, depending on the power loss of internal equipment and the dimensions of the box. Be sure to determine the dimensions of the box, cooling method, and panel layout so that the ambient temperature is lower than 55C.
Amplifier Near A Vibrating Source	Install the amplifier with a shock absorber to dampen the vibration that is transmitted directly to amplifier.
Amplifier Near A Heat Source	Shield the amplifier so that convection or radiation does not raise the ambient temperature 55C.
Corrosive Gas Environment	If the amplifier is operated for extended time periods in a corrosive environment, contact failure will occur at contact points (e.g., connectors). Therefore, never install the amplifier in a corrosive gas environment.
Explosive Or Combustible Gas Environment	Never install the amplifier in an explosive gas or combustible gas environment. Relays and contactors, which generate arcs (sparks) inside boxes and hot parts such as regeneration brake resistor, may become ignition sources, causing a fire or explosion.
Dust And Oil Environments	Never install the amplifier in an environment containing dust or oil mist. Dust and oil mist, which adheres to or accumulates on the amplifier, will result in damage to the amplifier from lower insulation resistance or leakage currents between conductors or components.
Electrical Noise Environments	Induction noise will enter input signals and the power supply circuit, causing the amplifier to malfunction. When installing the amplifier in an electrically noisy environment, take proper measures such as inserting a noise filter, shielding, or suppressing the noise source.

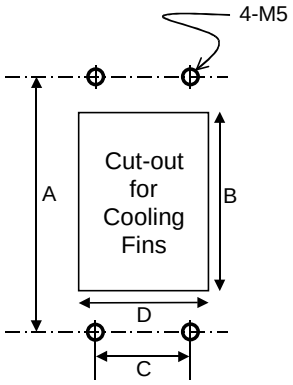
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Mounting and Clearance Requirements

Install the amplifier vertically as shown in the figure below, with the indicated clearances. Because the amplifier uses convection cooling it may not be mounted horizontally. Provide the indicated space above, below and to the side of the amplifier for airflow. If this space cannot be provided, install a fan to increase airflow around the amplifier. At least 10 mm space should be provided on each side of the amplifier to allow air flow.



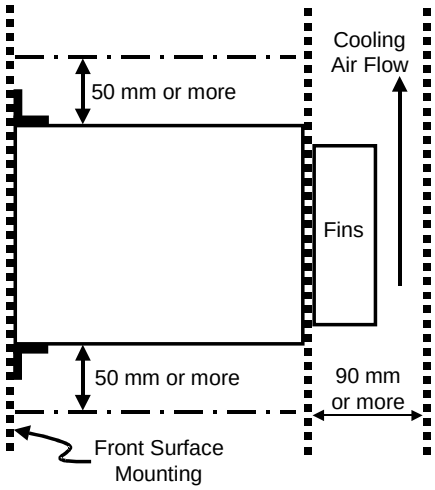


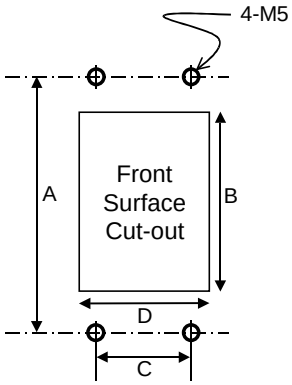
	A	B	C	D
PY2A015	160 mm	NA	25 mm	NA
PY2A030	160 mm	NA	25 mm	NA
PY2A050	160 mm	NA	50 mm	NA
PY0A015	225 mm	NA	25 mm	NA
PY0A030	225 mm	NA	25 mm	NA
PY0A050	225 mm	>197 mm	50 mm	>67 mm
PY0A100	225 mm	>197 mm	50 mm	>92 mm
PY0A150	225 mm	>197 mm	75 mm	>142 mm

- Only the PY0A050, PY0A100, and PY0A150 are equipped with the “cooling fins”.

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	A	B	C	D
PY2A015	160 mm	NA	25 mm	NA
PY2A030	160 mm	NA	25 mm	NA
PY2A050	160 mm	NA	50 mm	NA
PY0A015	225 mm	>205 mm	25 mm	NA
PY0A030	225 mm	>205 mm	25 mm	NA
PY0A050	225 mm	>212 mm	50 mm	>67 mm
PY0A100	225 mm	>212 mm	50 mm	>92 mm
PY0A150	225 mm	>212 mm	75 mm	>142 mm

- Only the PY0A050, PY0A100, and PY0A150 are equipped with the “cooling fins”.

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Amplifier Environmental Requirements

The amplifier should be installed in an environment that meets these requirements.

Table 3: Amplifier Environmental Requirements

Item	Specification
Ambient Temperature	
Operating	0 to 55C 32° to 131°F
Non-operating	-20 to 65C -4° to 149°F
Humidity Maximum	90% Non-condensing
Vibration Maximum	0.5G 10 to 55Hz
Shock Maximum	2G
Air Quality	Dust-free Oil-free Non-corrosive Non-combustible Non-explosive

Power Dissipation

During operation, the amplifier dissipates power that results in cabinet heating. The following table lists power dissipation values for valid system configurations. These values assume continuous rated load operation. Calculate the cabinet cooling requirements using the power dissipation information and the formulas that follow.

Table 4: Power Dissipation

Drive Model	Motor Model	Power Dissipation [W]		
		Total	PCB	Heatsink
PY2A015	P30B04010D	19	-	-
PY2A015	P50N05020D	23	-	-
PY2A030	P30B06040D	32	-	-
PY2A030	P30B08075D	45	-	-
PY2A050	P50N08100D	54	-	-
PY2A050	P20B10150D	85	55	30
PY2A050	P60B13150H	85	50	50
PY0A015	P30B04010D	19	-	-
PY0A015	P50N05020D	23	-	-
PY0A030	P30B06040D	32	-	-
PY0A030	P30B08075D	16	-	-
PY0A050	P50N08100D	80	50	30
PY0A050	P20B10150D	85	55	30
PY0A050	P60B13150H	85	50	50
PY0A100	P20B10250D	170	98	72
PY0A100	P20B13300D	175	103	72
PY0A150	P20B13500D	260	150	110

Power dissipation values shown in the table do not include values for the internal regeneration resistor.

When using an external regeneration resistor, the internal resistor is disconnected.

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Enclosure Size

When sizing a NEMA 12 or equivalent enclosure with no active method for cooling, the following equation approximates the size of enclosure required.

$$T = 4.08 \times \left(\frac{Q}{A} \right) + 1.1$$

Where:

T = Temperature difference between inside air (130 °F maximum) and outside air [°F]

Q = Total amount of heat generated in the enclosure [W]

A = Surface area of the enclosure in ft^2 = $(2DW + 2DH + 2WH) / 144$

D = Depth in inches

H = Height in inches

W = Width in inches

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Motor Installation

Environmental Requirements

The motor should be installed in an environment that meets these requirements.

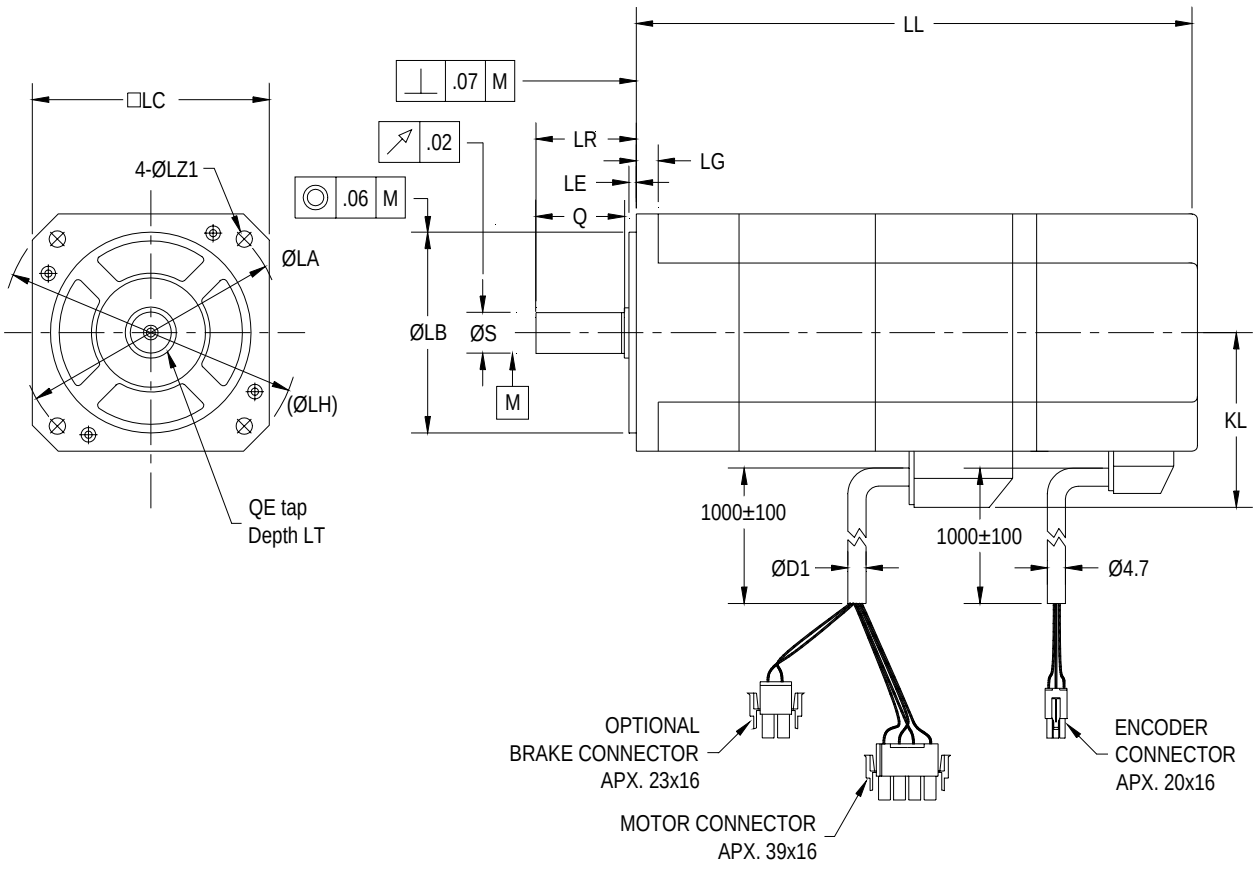
Table 5: Motor Environmental Requirements

Item	Specification
Ambient Temperature	
Operating	0 to 40C 32° to 104°F
Non-operating	-20 to 65C -4° to 149°F
Humidity Maximum	20% to 90% Non-condensing
Air Quality	Dust-free Oil-free Non-corrosive Non-combustible Non-explosive

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Motor Mounting *P3/P5 Motor Dimensions Diagram (all dimensions in mm)*

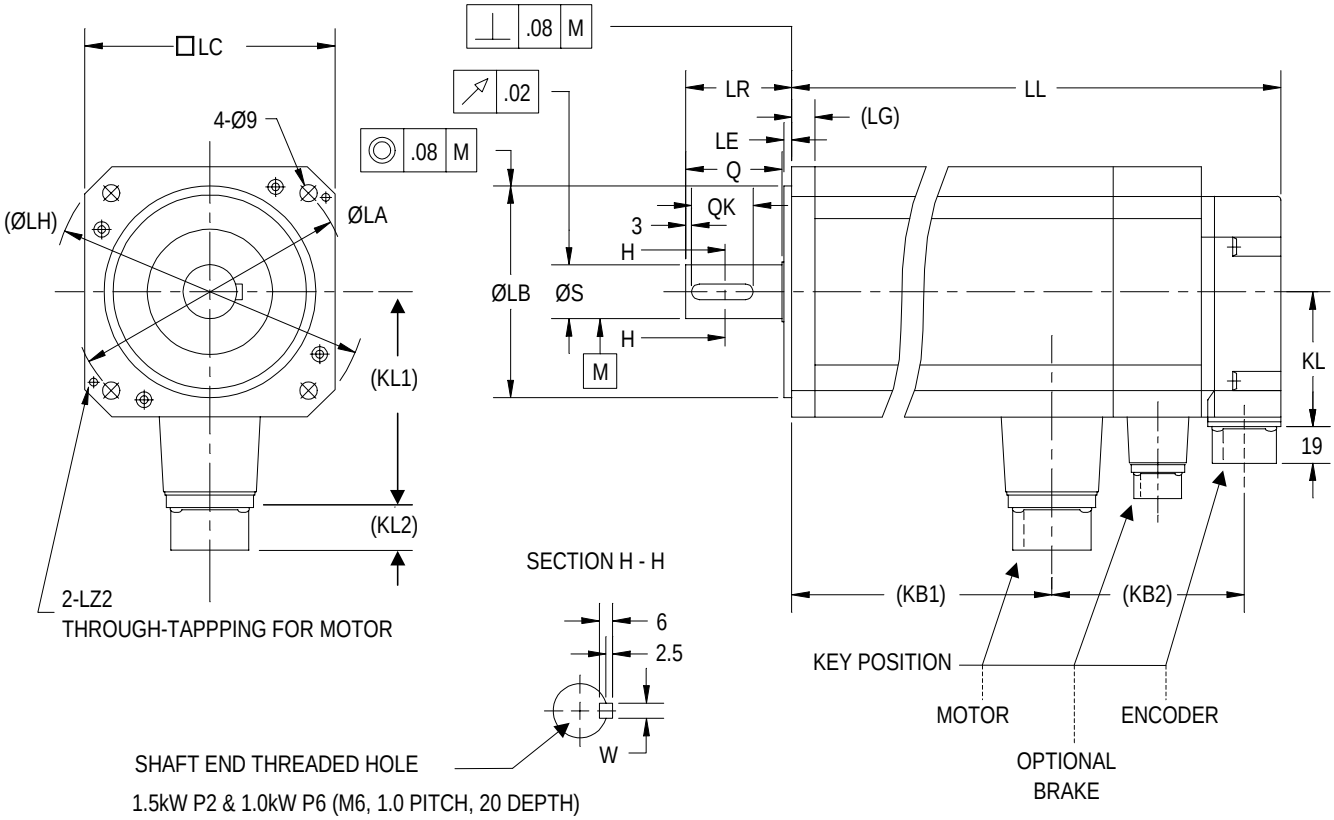


Type	LL w/o brake	LL w/ brake	LG	KL	LA	LB	LE	LH	LC	LZ1	LR	S	Q	QE	LT	D1
P30B04010	88	126.5	5	30	46	30 +0.000 -0.021	2.5	54	40	4.5	25	8 +0.000 -0.009	-	-	-	6
P30B06040	123.5	161.5	6	41	70	50 +0.000 -0.025	3	81	60	5.5	30	14 +0.000 -0.011	-	M5	12	6.7
P30B08075	140	180.5	8	52	90	70 +0.000 -0.030	3	107	80	6.6	40	16 +0.000 -0.011	35	M5	12	6.7
P50N05020	105	134	5	38	66.68	38.1 +0.000 -0.051	1.524	71.5	57.15	5.207	30	11 +0.000 -0.011	25	M4	10	7.5
P50N08100	172	212	8	55	98.43	73.025 +0.000 -0.051	2.5	115	86	5.588	35	16 +0.000 -0.011	30	M5	12	7.5

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Motor Mounting *P2/P6 Motor Dimension Diagram (all dimensions in mm)*



	w/o brake		w/ brake																	
Type	**LL**	**KB2**	**LL**	**KB2**	**KB1**	**KL1**	**KL2**	**LG**	**LA**	**LB**	**LE**	**LH**	**LC**	**LZ2**	**LR**	**S**	**Q**	**QK**	**W**
P20B10150	172	48	216	92	105	76	19	10	115	95 +0.000 -0.035	3	130	100	-	45	22 +0.000 -0.013	40	32	6	+0.000 -0.030
P20B10250	222		266		155															
P20B13300	194	58	236	100	117	98	21	12	145	110 +0.000 -0.035	4	165	130	M6	55	28 +0.000 -0.013	50	42	6	+0.000 -0.030
P20B13500	267		309		190															
P60B13150	152	57	185	90	75	98	21	12	145	110 +0.000 -0.035	4	165	130	M6	55	22 +0.000 -0.013	50	42	6	+0.000 -0.030

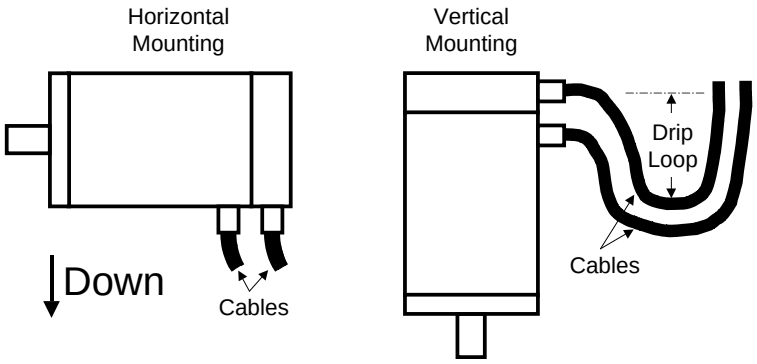
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Motor Orientation and Cable Routing

Cable and Motor Orientation

The servomotor can be installed horizontally or vertically with the shaft pointing down. If the motor is positioned horizontally, rotate the motor so that the cables exit downward. If the motor is mounted vertically, provide a cable trap to prevent oil or water from flowing down the cable to the motor.



Prevention Against Fluids

The motor, as a single unit, satisfies the IEC standard for sealing against water as indicated in the table below.

Table 6: Motor IP Rating

Motor	Rating	Conditions
P3	IP43	• Protected against solid objects (diameter 1 mm) and splashing water.
P5	IP55	• Motor shaft seal installed, standard • Cable with environmental connectors are connected to motor, standard. The motor is not protected when cables are not attached. • Protected against dust – limited ingress (no harmful deposit) and low pressure jets of water from all directions – limited ingress permitted.
P2 & P6	IP67	• Motor shaft seal installed, standard • Cable with environmental connectors are connected to motor, standard. The motor is not protected when cables are not attached. • Protected against dust and effects of immersion.

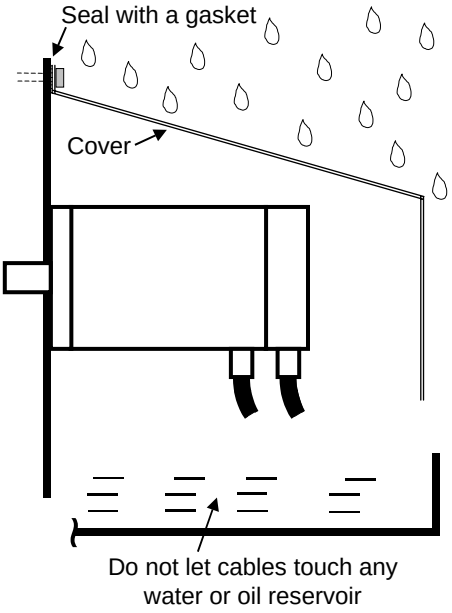
Since the IEC standard is intended to check performance over a short period of time, the following measures against fluids are required for actual usage.

- Handle the system carefully to prevent damage to cable jackets, which may deteriorate waterproofing.
- Mount the motor with the connectors (lead outlet) pointing downward.
- Install a cover, with a gradient, over the motor to prevent oil or water from splashing directly on the motor.

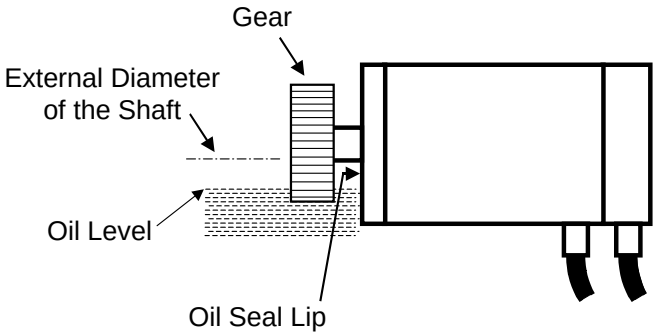
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- Avoid dipping the cable into oil or water.
- Slacken the cable outside the cover and provide a cable trap so that oil and water may not travel up the cable.



- If an oil-filled gearbox is used, make the oil level of the gearbox lower than the oil seal lip. Provide a vent in the gearbox to prevent internal pressure in the gearbox from rising and forcing oil into the motor.



Connecting the Load to the Motor

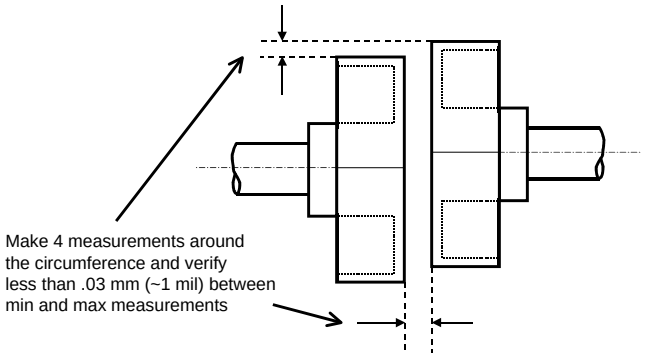
The mechanical connection between the motor and the load is critical. An improper connection can limit performance and shorten the life of the motor.

- Perform centering accurately between the motor shaft and the load as shown in the figure below. Note that with a rigid coupling, a slight offset will lead to damage of the output shaft.

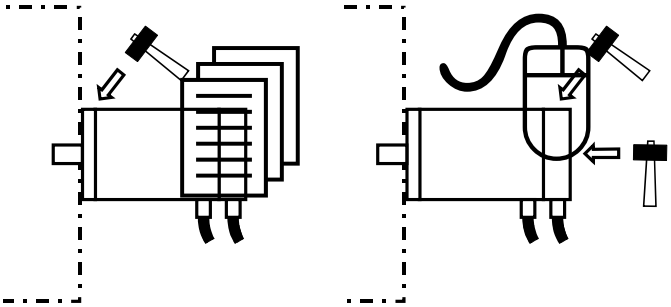
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- To check centering, make a measurement at 4 points on the circumference, the difference between maximum and minimum should be 0.03 mm or less.

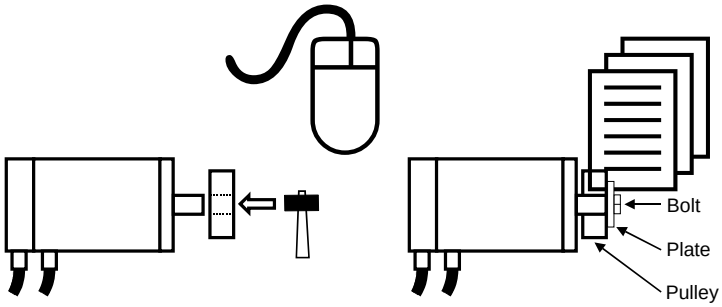


- A precision encoder is directly connected to the motor shaft. A shock to the motor shaft during installation may damage the encoder. If tapping on the motor is unavoidable for position adjustment or other reasons, tap on the front flange with a rubber or plastic hammer.



- When installing the motor to the machine, make the mounting holes precise. Also, make the mounting surface as flat as possible to avoid damage to the motor shaft or bearing.

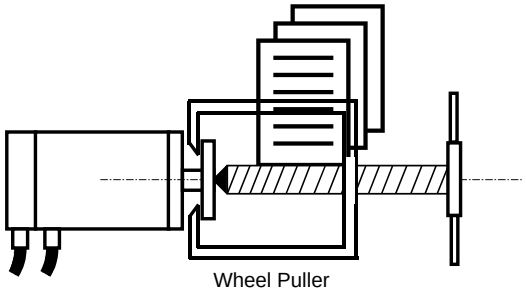
- When installing a gear, pulley, or coupling on the shaft avoid striking the shaft, which will damage the motor encoder. Use a bolt on the end of the shaft to pull tight fitting parts together.



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- When removing the gear, pulley, or coupling from the shaft, use a dedicated extracting tool to avoid damaging the shaft or motor encoder.



Wheel Puller

- When mounting motor to a timing belt drive, check that the shaft-converted value of the belt tension does not exceed the allowable value shown in Table 7: Allowable Radial and Thrust Loads.

Bearing Load Specifications

When attaching a pulley or gear directly to the motor shaft, do not apply an excessive thrust or radial load. The thrust and radial loads in the table below are the maximum allowable loads when independently applied to the shaft.

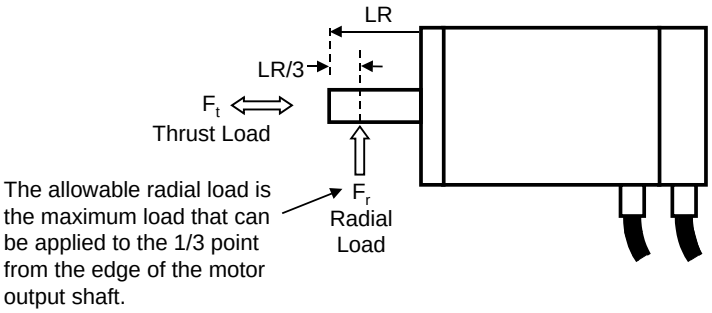


Table 7: Allowable Radial and Thrust Loads

Model	During Assembly		During Operation	
	Radial Load Fr [kg]	Thrust Load Ft [kg]	Radial Load Fr [kg]	Thrust Load Ft [kg]
P30B04010D	15	10	10	3
P30B06040D	40	20	25	10
P30B08075D	60	40	35	20
P50N05020D	25	20 → 15 ←	20	8
P50N08100D	60	80 → 30 ←	35	20
P20B10150D	100	30	70	30
P20B10250D	100	30	70	30
P60B13150H	173	194	65	50
P20B13300D	200	40	100	40
P20B13500D	200	40	120	40

(1kg = 2.2lb)

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Installation Check List

- ☑ Amplifier is mounted in a clean protected environment free from dust, water, oil mist, corrosive gas, and combustible gas.
- ☑ Proper amplifier ventilation has been provided. The ambient temperature near the amplifier does not exceed 55°C during operation.
- ☑ The motor has been securely mounted to the machine and the load has been securely attached to the motor shaft.
- ☑ The radial and perpendicular alignments of the motor and load have been measured and are within specification.
- ☑ The radial and thrust loading on the motor shaft have been measured and are within specification.

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Wiring

Chapter Overview

This chapter contains a guide for wiring of the amplifier and matching motor.

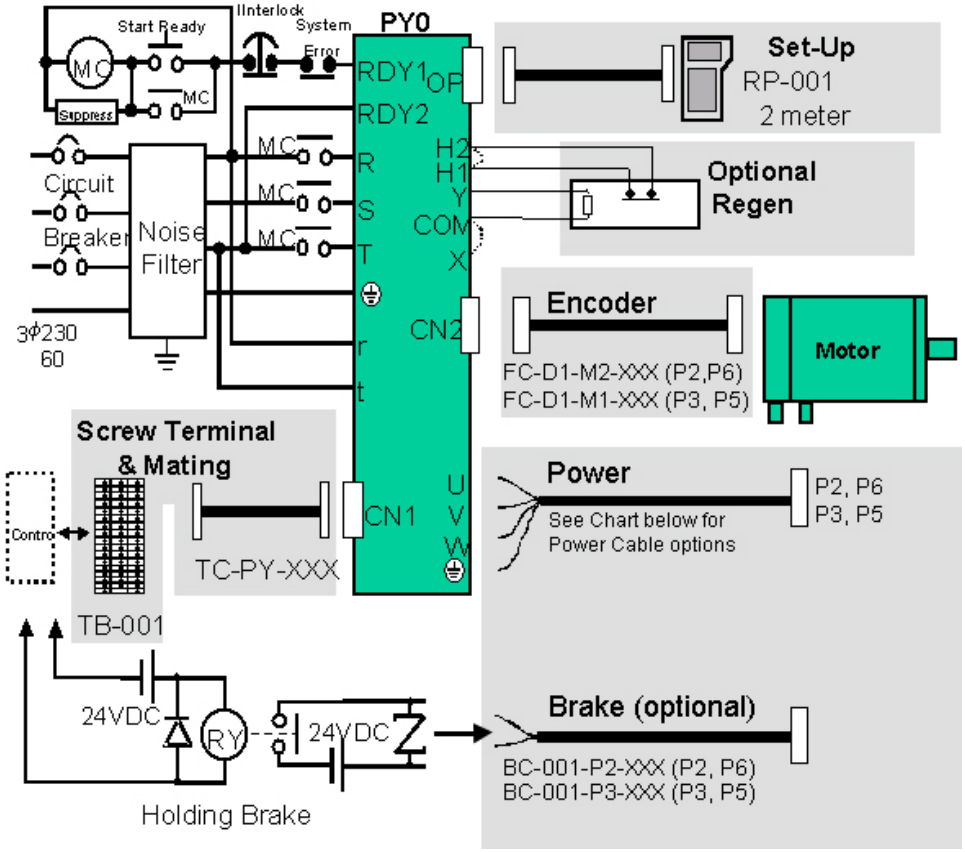
Chapter Overview 28
Cable Connection Diagram for PY0 *29*
Cable Connection Diagram for PY2 *30*
Wiring Precautions 31
Applicable Wire Sizes 32
Input Power 33
Leakage Current 33
Connection Diagram (PY2 with P3/P5 Motor) 34
Connection Diagram (PY2 with P2/P6 Motor) 35
Connection Diagram (PY0 with P3/P5 Motor) 36
Connection Diagram (PY0 with P2/P6 Motor) 37
CNA, CND and CNB Connectors 38
Input/Output Internal Circuits 39
CN1 Control Connector 41
CN2 Motor Encoder Connector 45
Operator Terminal 46
External Regeneration Resistors 47
When to use an External Regeneration Resistor *47*
Selecting the Right External Regen Resistor *50*
How to connect a Regen Resistor *51*
Regeneration Resistor Mounting *52*
Wiring Check List 53

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Cable Connection Diagram for PY0

Below is a simplified connection diagram for a PY0. This diagram shows how to connect a system using standard cables. A detailed connection diagram follows.



Power Cable Part #	Motor
PC-D2-M2-XXX	P2(1.5kW)
PC-D3-M2-XXX	P2(2.5kW)
PC-D3-M3-XXX	P2(3&5kW)
PC-D2-M3-XXX	P6(1.5kW)
PC-D1-M1-XXX	P3 & P5 (except P5 1kW)
PC-D2-M1-XXX	P5(1kW)

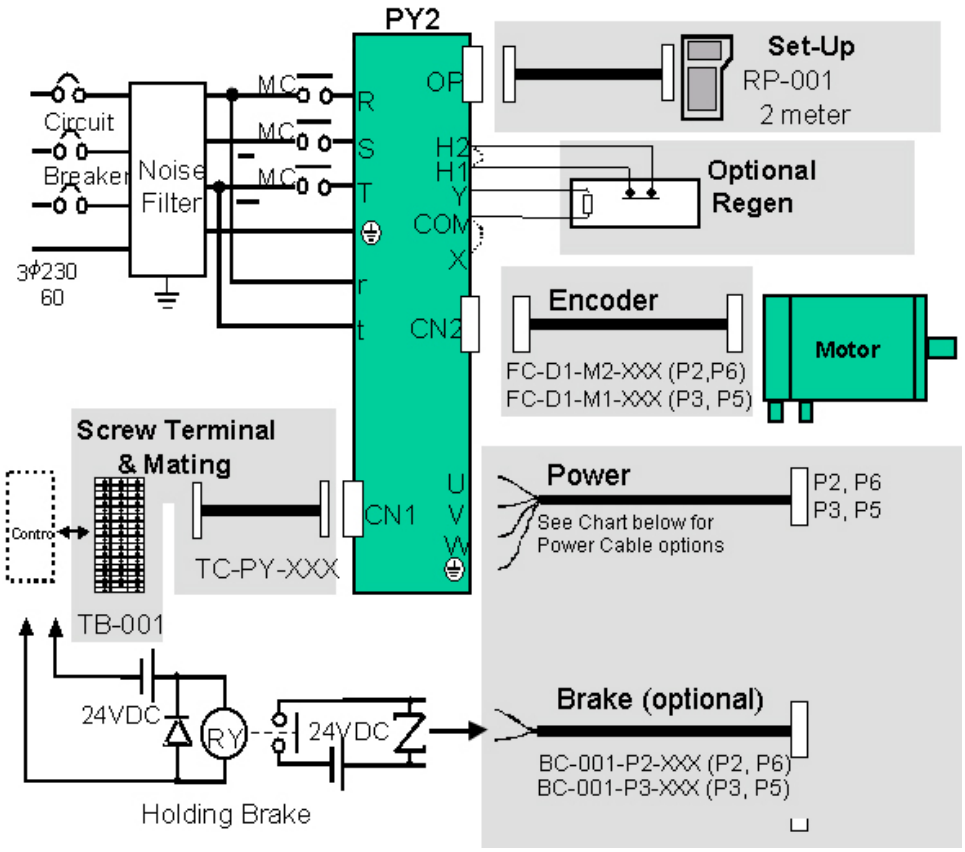
- For 1Φ (single phase) power, do not connect 230VAC to the "S" terminal of the bus power. Leave this terminal unconnected.

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Cable Connection Diagram for PY2

Below is a simplified connection diagram for a PY2. This diagram shows how to connect a system using standard cables. A detailed connection diagram follows.



Power Cable Part #	Motor
PC-D2-M2-XXX	P2(1.5kW)
PC-D2-M3-XXX	P6(1.5kW)
PC-D1-M1-XXX	P3 P5 (except P5 1kW)
PC-D2-M1-XXX	P5(1kW)

- For 1Φ (single phase) power, do not connect 230VAC to the "S" terminal of the bus power. Leave this terminal unconnected.

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Wiring Precautions

1. Always follow all local, regional, national and international electrical codes! In case of conflicts between regulations and this instruction manual please contact the factory.

2. Connect ground signals first and remove them last when installing or removing equipment.

3. Arrange the servo amplifier, noise filters and motion controller as closely to each other as possible to minimize signal length and reduce effects of noise.

4. Install surge suppression circuits on relays, electromagnetic contactors, brake solenoids and other inductive loads.

5. Do not pass the bus power and circuits and control signals in the same conduit or bind them together.

6. When a large electrical noise source such as an arc-welder is nearby, install noise filters.

7. Terminate all control signal inputs, digital and analog.

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Applicable Wire Sizes

The chart below identifies the recommended wire sizes for all connections. This is only a guide. The installer is responsible for satisfying all applicable codes and regulations.

!	**DANGER**
	The user is responsible for conforming with all applicable local, regional, national, and international codes. The wiring examples in this manual are intended only as a guide. Wiring practices, grounding, disconnects and over-current protection are of particular importance. Failure to observe this could result in severe injury or loss of life.

Table 8: Applicable Wire Sizes

	Terminal	PY2A015 PY0A015	PY2A030 PY0A030	PY2A050 PY0A050	PY0A100	PY0A150
Bus Power	R, S, T	16	14	12	10	8
Control Power	r, t	16				
Motor Power	U, V, W	16	14	12	10	8
Regen Resistor Power Thermostat	Y, COM (P) H1, H2	16 20		14 20		
Drive Ready Relay	RDY1, RDY2	20				
Encoder	CN2	28				
Control (CN1)	CN1	28				
Remote Operator	OP					

1. Wire sizes are AWG.
2. To avoid electrical interference, separate the bus circuit wiring (high voltage) from the signal wiring (CN1, CN2).

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Input Power

The table below shows the power supply capacity requirements for each of the systems.

Table 9: Power Supply Capacity Requirement

Drive Model	Motor Model	Bus Circuit			Control Circuit		
		Capacity KVA	Capacity (A)	In Rush § @600mS	Capacity VA	Capacity (A)	In Rush § @1mS
PY2A015	P30B04010D	0.3kVA	2.1A	18A	40VA	0.2A	40A
PY2A015	P50N05020D	0.8kVA	TBA	18A	40VA	0.2A	40A
PY2A030	P30B06040D	1.0kVA	6.6A	18A	40VA	0.2A	40A
PY2A030	P30B08075D	1.7kVA	9.5A	18A	40VA	0.2A	40A
PY2A050	P50N08100D	2.5kVA	5.5A	18A	40VA	0.2A	40A
PY2A050	P60B13150H	2.5kVA	7.3A	18A	40VA	0.2A	40A
PY2A050	P20B10150D	3.0kVA	8.7A	18A	40VA	0.2A	40A
PY0A015	P30B04010D	0.3kVA	1.2A	18A	40VA	0.2A	40A
PY0A015	P50N05020D	0.8kVA	3.0A	18A	40VA	0.2A	40A
PY0A030	P30B06040D	1.0kVA	3.8A	18A	40VA	0.2A	40A
PY0A030	P30B08075D	1.7kVA	5.5A	18A	40VA	0.2A	40A
PY0A050	P50N08100D	2.5kVA	7.3A	18A	40VA	0.2A	40A
PY0A050	P60B13150H	2.5kVA	7.3A	18A	40VA	0.2A	40A
PY0A050	P20B10150D	3.0kVA	8.7A	18A	40VA	0.2A	40A
PY0A100	P20B10250D	4.2kVA	12.2A	18A	40VA	0.2A	40A
PY0A100	P20B13300D	5.0kVA	14.5A	18A	40VA	0.2A	40A
PY0A150	P20B13500D	8.3kVA	24.0A	18A	40VA	0.2A	40A

§ Zero to peak currents, not RMS current.

Leakage Current

The servomotor is driven under the PWM control of an IGBT inverter in the amplifier. This produces a high-frequency leakage current, which flows through the floating capacitance of the motor winding, power cable and amplifier. This leakage current can cause the malfunction of leakage detection circuit breakers or protective relays installed on the power line.

Table 10: System Leakage Current

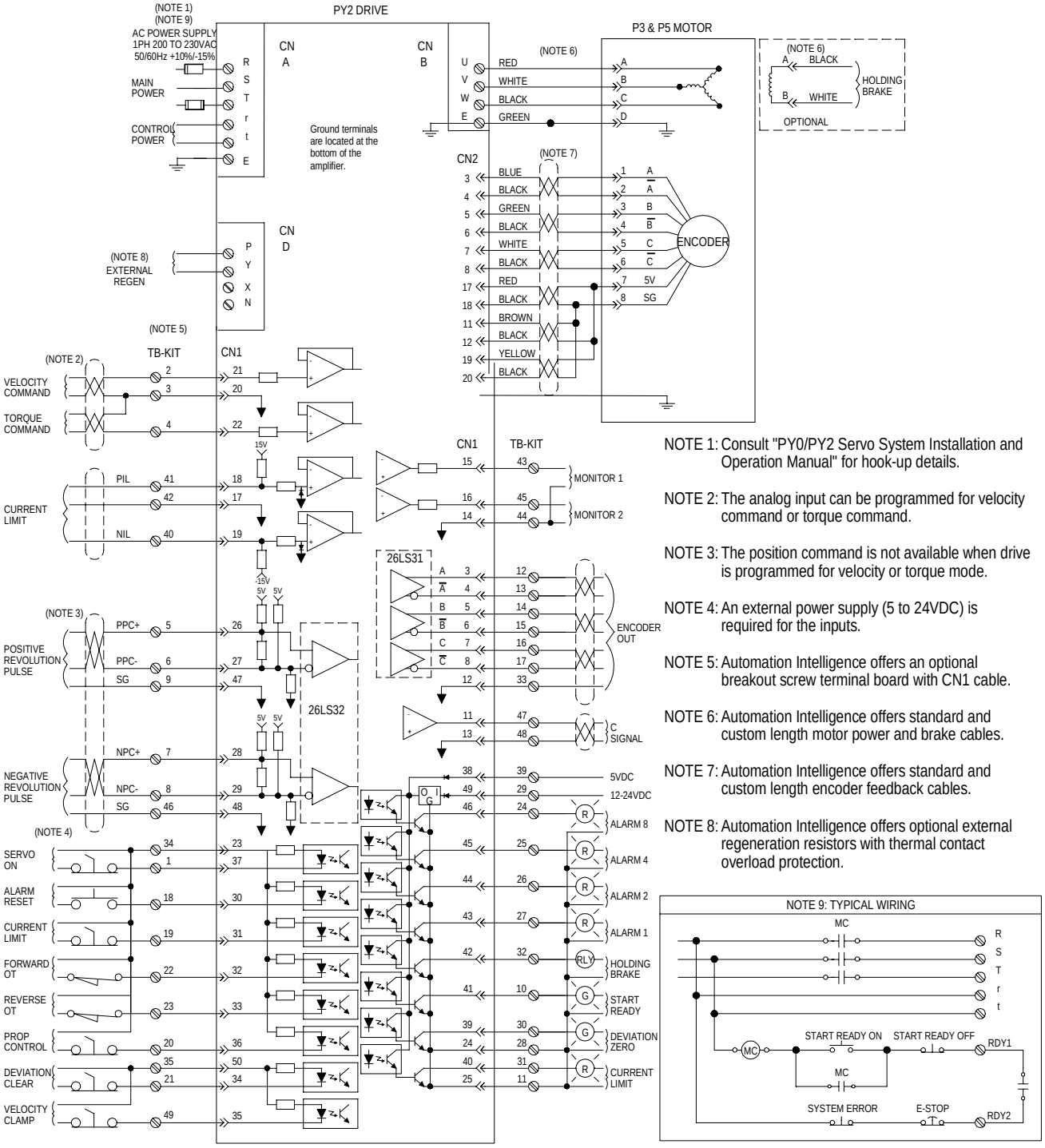
Motor Model	Leakage Current per Motor
P20B	3.0mA
P30B	3.0mA
P50N	3.0mA
P60B	3.0mA

1. When using two or more motors, add the leakage current of each motor to determine the system leakage current.
2. The table above assumes 2m cables. The leakage current will increase with longer cables and decrease with shorter cables.

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Connection Diagram (PY2 with P3/P5 Motor)



NOTE 1: Consult "PY0/PY2 Servo System Installation and Operation Manual" for hook-up details.

NOTE 2: The analog input can be programmed for velocity command or torque command.

NOTE 3: The position command is not available when drive is programmed for velocity or torque mode.

NOTE 4: An external power supply (5 to 24VDC) is required for the inputs.

NOTE 5: Automation Intelligence offers an optional breakout screw terminal board with CN1 cable.

NOTE 6: Automation Intelligence offers standard and custom length motor power and brake cables.

NOTE 7: Automation Intelligence offers standard and custom length encoder feedback cables.

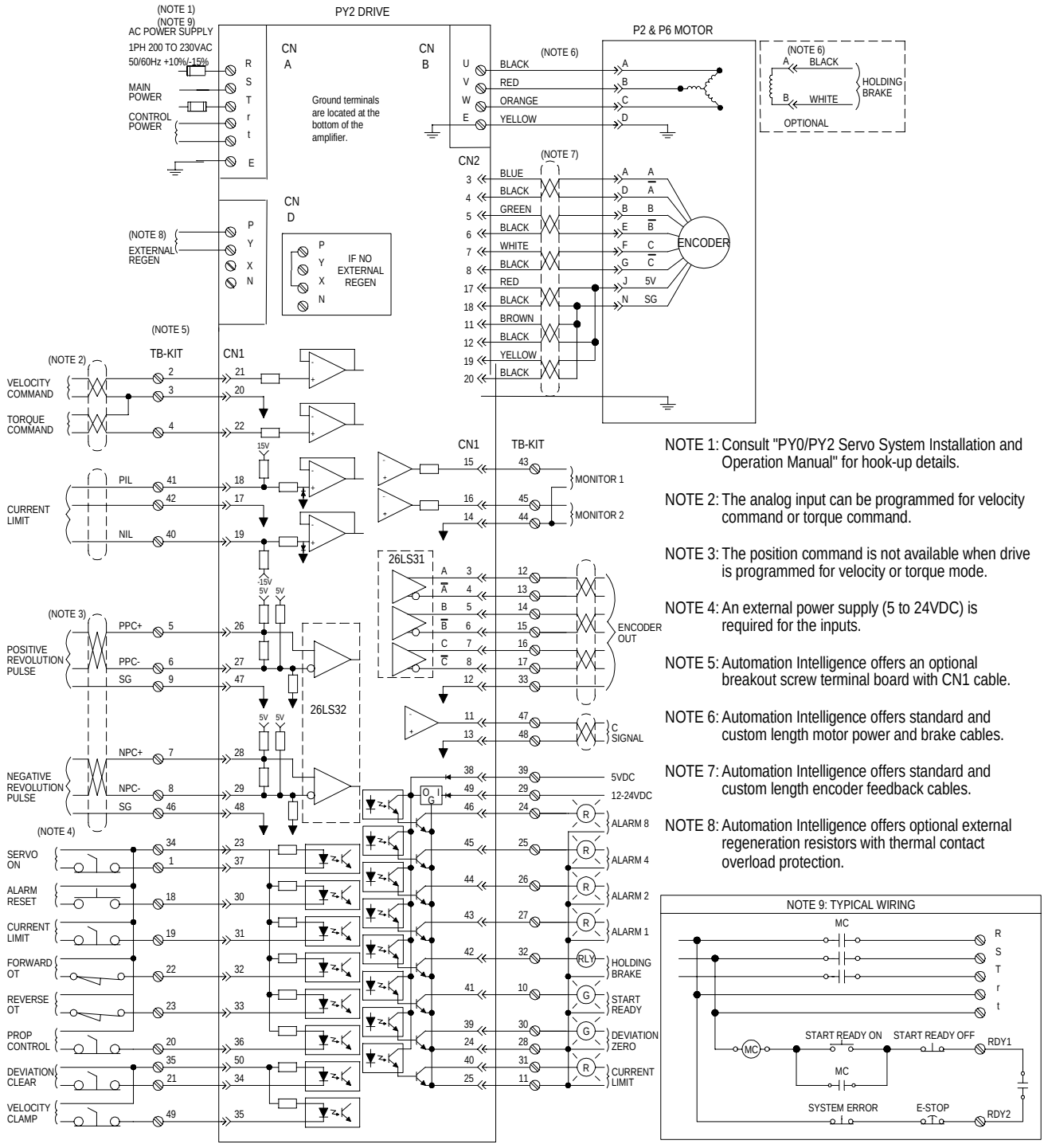
NOTE 8: Automation Intelligence offers optional external regeneration resistors with thermal contact overload protection.

Please note that PY2 drives do not provide RDY signals. Ignore references to this contact on all PY2 drawings.

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Connection Diagram (PY2 with P2/P6 Motor)



NOTE 1: Consult "PY0/PY2 Servo System Installation and Operation Manual" for hook-up details.

NOTE 2: The analog input can be programmed for velocity command or torque command.

NOTE 3: The position command is not available when drive is programmed for velocity or torque mode.

NOTE 4: An external power supply (5 to 24VDC) is required for the inputs.

NOTE 5: Automation Intelligence offers an optional breakout screw terminal board with CN1 cable.

NOTE 6: Automation Intelligence offers standard and custom length motor power and brake cables.

NOTE 7: Automation Intelligence offers standard and custom length encoder feedback cables.

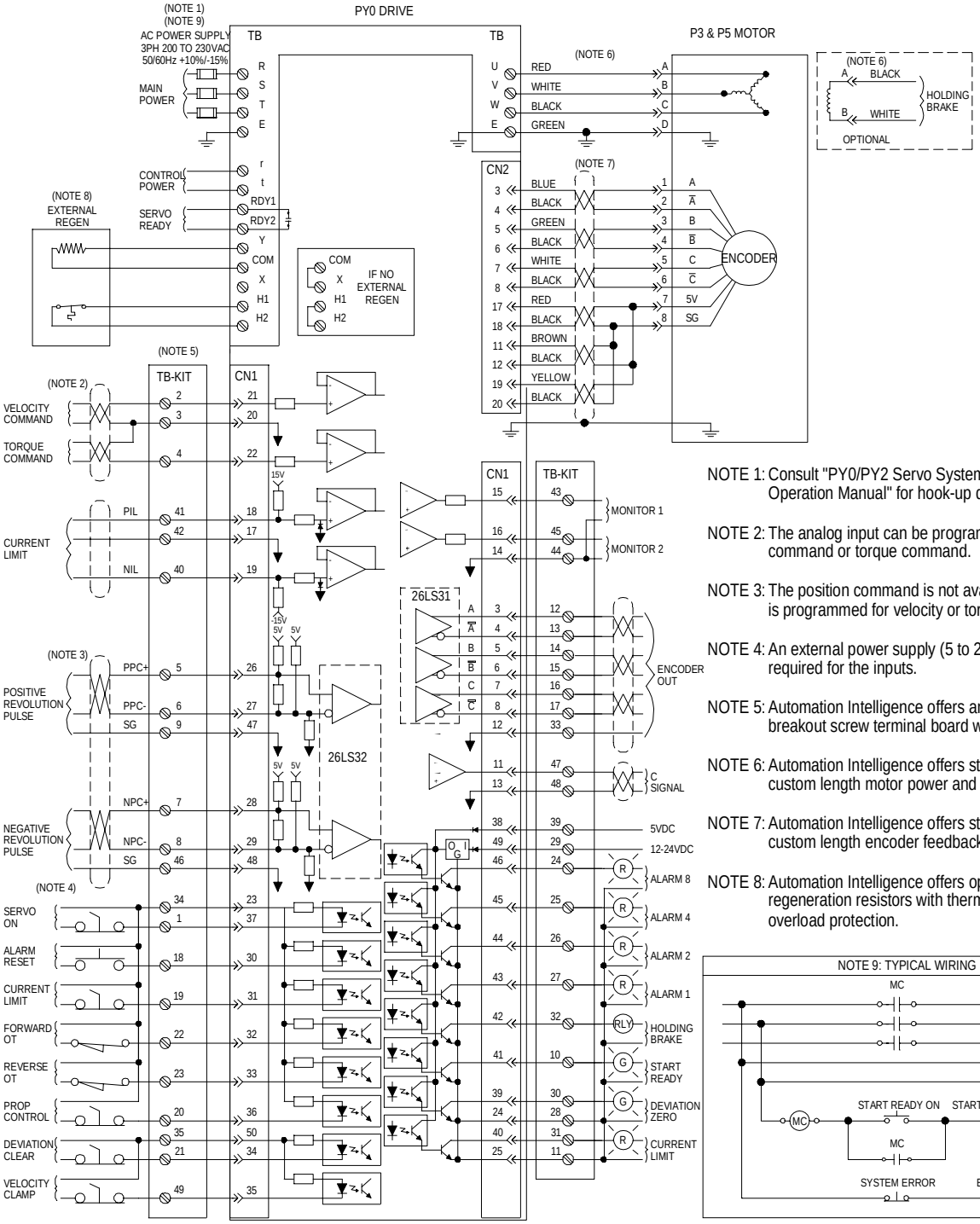
NOTE 8: Automation Intelligence offers optional external regeneration resistors with thermal contact overload protection.

Please note that PY2 drives do not provide RDY signals. Ignore references to this contact on all PY2 drawings.

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Connection Diagram (PY0 with P3/P5 Motor)



NOTE 1: Consult "PY0/PY2 Servo System Installation and Operation Manual" for hook-up details.

NOTE 2: The analog input can be programmed for velocity command or torque command.

NOTE 3: The position command is not available when drive is programmed for velocity or torque mode.

NOTE 4: An external power supply (5 to 24VDC) is required for the inputs.

NOTE 5: Automation Intelligence offers an optional breakout screw terminal board with CN1 cable.

NOTE 6: Automation Intelligence offers standard and custom length motor power and brake cables.

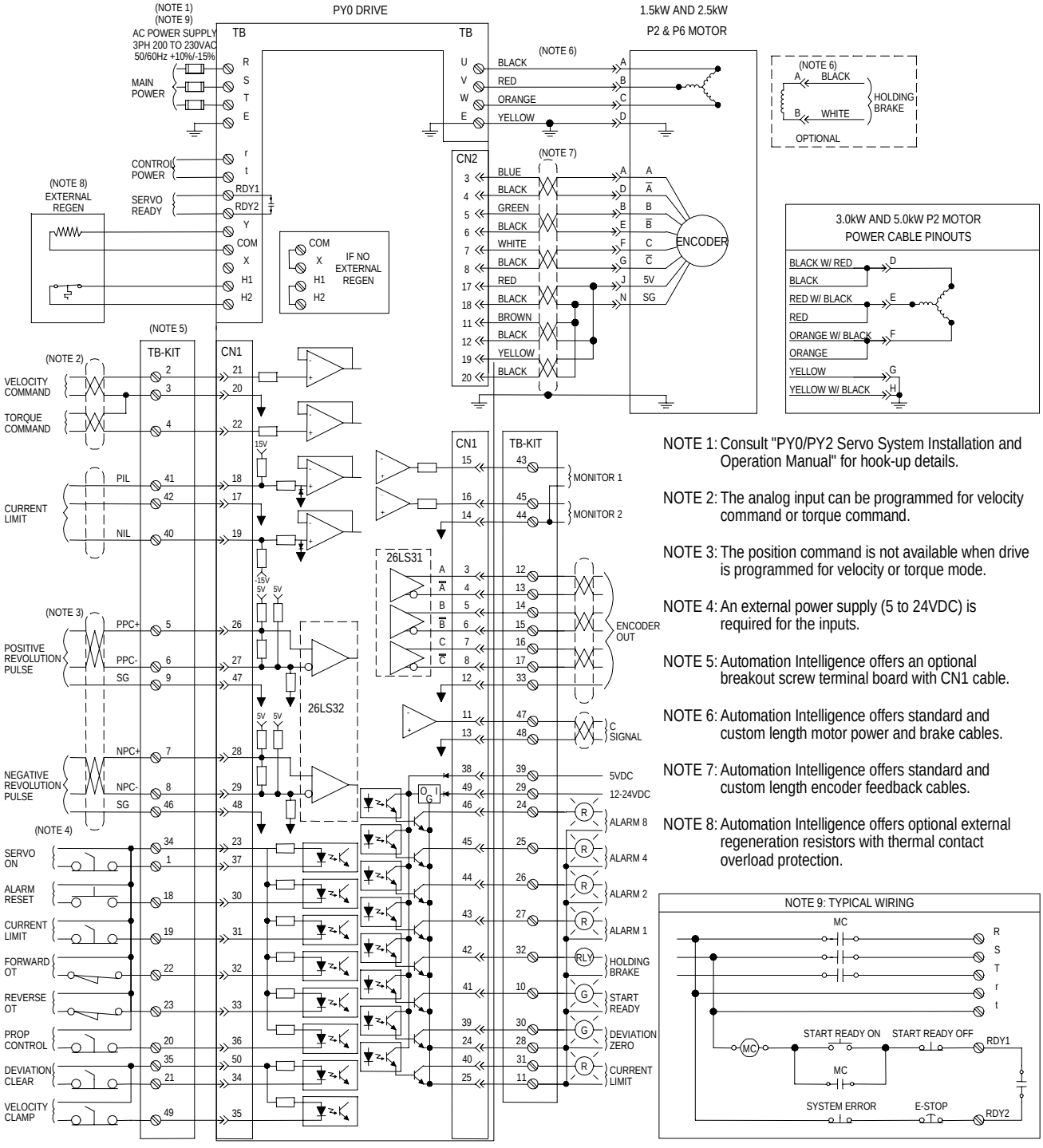
NOTE 7: Automation Intelligence offers standard and custom length encoder feedback cables.

NOTE 8: Automation Intelligence offers optional external regeneration resistors with thermal contact overload protection.

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Connection Diagram (PY0 with P2/P6 Motor)



NOTE 1: Consult "PY0/PY2 Servo System Installation and Operation Manual" for hook-up details.

NOTE 2: The analog input can be programmed for velocity command or torque command.

NOTE 3: The position command is not available when drive is programmed for velocity or torque mode.

NOTE 4: An external power supply (5 to 24VDC) is required for the inputs.

NOTE 5: Automation Intelligence offers an optional breakout screw terminal board with CN1 cable.

NOTE 6: Automation Intelligence offers standard and custom length motor power and brake cables.

NOTE 7: Automation Intelligence offers standard and custom length encoder feedback cables.

NOTE 8: Automation Intelligence offers optional external regeneration resistors with thermal contact overload protection.

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CNA, CND and CNB Connectors

Table 11: CNA, CND, and CNB Connector Pin Assignments

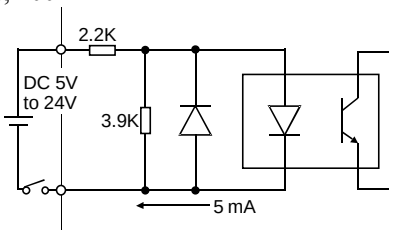
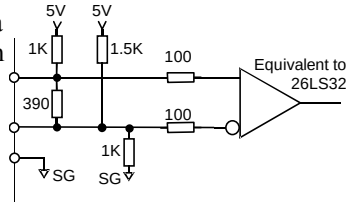
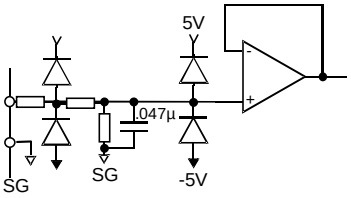
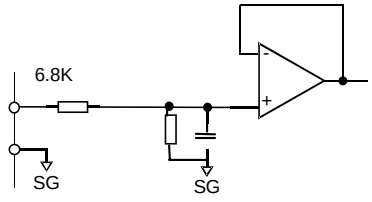
Symbol	Explanation
R S T W	Bus circuit power input. Single/Three-phase 200-230Vac (+10%, -15%) and grounding terminal. This is only the high power input for the amplifier. Control power for the amplifier is supplied on the "r" and "t" terminals. For single-phase connection, do not connect to the "S" terminal.
r t	Control circuit power input terminals. Single-phase 200-230Vac (+10%, -15%). This is the only control power input for the amplifier. The bus power (high power) for the amplifier is supplied on the "R", "S", and "T" terminals.
COM Y P	Regeneration Resistor power connections. When an external regeneration resistor is not used, the internal resistor is connected to "X" and "COM" (PY0 Drive) and "X" and "P" (PY2 Drive). When an external regeneration resistor is used, the internal resistor must be disconnected and the external resistor(s) are connected between "COM" and "Y" (PY0 Drive) and "P" and "Y" (PY2 Drive).
RDY1 RDY2	Amplifier ready output terminals. RDY1 and RDY2 are two terminals of a relay. When the control power supply is ON and there are no alarms, this relay closes; otherwise it is open. The RDY signal is only provided on PY0 drives.
H1 H2	(PY0 Drives only…) Input terminal for thermostat of external regeneration resistor. If an external regeneration resistor is not required, a shorting bar is connected between H1 and H2. An open circuit indicates an external regeneration resistor overheat condition.
U V W W	Motor power connection and grounding terminal.

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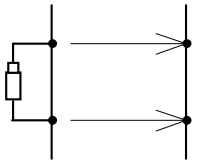
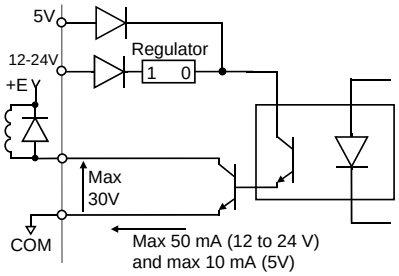
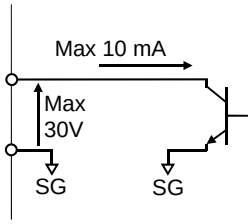
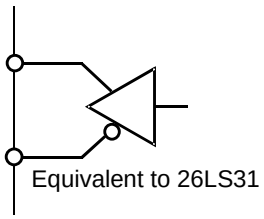
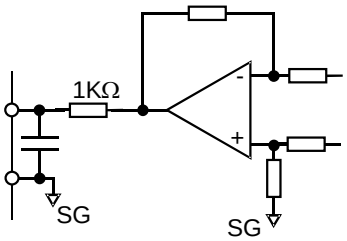
Input/Output Internal Circuits

Table 12: CN1 Internal Circuits

Circuit Type	Description	Figure
1	Photo-coupler Input These inputs share a common user-supplied 5 to 24VDC supply. Connecting the input pin to ground turns them "ON". The required power specification is 5-24VDC ±10%, 100 mA or more CN1-30 RST CN1-31 ILM CN1-32 PROT CN1-33 NROT CN1-34 CLE CN1-35 PCON/PMUL/INH/ZCMD CN1-36 PCON/PMUL/INH/ZCMD CN1-37 SON	
2	Line Driver Inputs This input circuit is designed to receive signals for a line driver output equivalent to a 26LS31. It may also be connected to an open collector type output. CN1-26 PPC+ CN1-27 PPC- CN1-28 NPC+ CN1-29 NPC-	
3	Analog Input CN1-21 VCMD CN1-22 TCOMP/TCMD	
4	Analog Input This input is designed to receive positive analog voltage. CN1-18 PIL	

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Circuit Type	Description	Figure
5	Analog Input This input is designed to receive negative analog voltage. CN1-19 NIL	
6	Isolated Open Collector Output All outputs share a common 5 or 12 to 24Vdc supply (5Vdc ±10% 20ma or more, 12-24Vdc ±10% 20mA or more) CN1-39 INP/LTG CN1-40 ILIM CN1-41 SRDY CN1-42 HBON CN1-43 ALM1 CN1-44 ALM2 CN1-45 ALM4 CN1-46 ALM8	
7	Open Collector Output CN1-11 COP	
8	Line Driver Output This line driver output circuit is designed to drive signals for a line receiver input equivalent to a 26LS32. Signals valid about 1 second after control power is applied. CN1-3 A+ CN1-4 A- CN1-5 B+ CN1-6 B- CN1-7 C+ CN1-8 C-	
9	Analog Output CN1-15 MON1 CN1-16 MON2	

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CN1 Control Connector

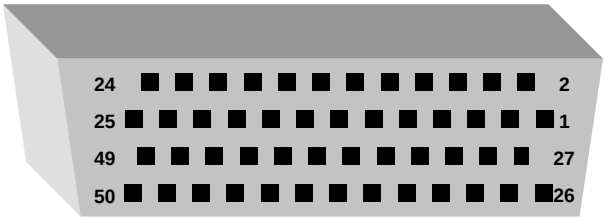


Table 13: CN1 Pin Assignments

Pin	TB Pos	Abbrev.	Description	Circuit Type
1	-	None	Reserved	N/A
2	-	None	Reserved	N/A
3	12	A+	Encoder Positive A Signal Output. Output by line driver (26LS31) after the encoder pulses are divided (ENCR). The divider is set using the Remote Operator, Mode 1 Page 4. This output is not specified for 1 second after the control supply is turned "ON".	8
4	13	A-	Encoder Negative A Signal Output	8
5	14	B+	Encoder Positive B Signal Output	8
6	15	B-	Encoder Negative B Signal Output	8
7	16	C+	Encoder Positive Index Signal Output	8
8	17	C-	Encoder Negative Index Signal Output	8
9	-	None	Reserved	N/A
10	-	None	Reserved	N/A
11	47	COP	Encoder C channel (Open Collector Output). The logic can be reversed using the Func5 parameter (Mode 2, Page 6, Bit 6).	7
12	33	SG	Encoder Signal Ground	N/A
13	48	COPG	Signal Ground for COP signal, Pin 11	N/A
14	44	SG	Monitor Signal Ground for MON1 and MON2, Pins 15 and 16	N/A
15	43	MON1	Monitor 1 Output. 2V ±10% per 1000RPM (velocity monitor). Positive voltage indicates CCW direction of rotation. Load less than 2mA (output resistance 1kΩ).	9
16	45	MON2	Monitor 2 Output. 2V ±20% per rated current (current monitor). Positive voltage indicates torque is being applied in the CCW direction. Load less than 2mA (output resistance 1kΩ).	9
17	42	SG	Signal Ground for analog current limits, Pins 18 and 19	N/A

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Pin	TB Pos	Abbrev.	Description	Circuit Type
18	41	PIL	Positive Current Limit. The current is limited to the rated current at +2V. This input is effective when the ILM (CN1 pin 31) input is "ON".	4
19	40	NIL	Negative Current Limit. The current is limited to the rated current at -2V. This input is effective when the ILM (CN1 pin 31) input is "ON".	5
20	3	VCMDG TCMDG	Velocity/Torque Command Common, see pins 21 and 22.	N/A
21	2	VCMD	Velocity Command. With a ±2V input, the velocity becomes ±1000 RPM (standard setting). The maximum input voltage is ±10V. The input impedance is approximately 20kΩ.	3
22	4	TCOMP	Torque Compensation (Position Control Mode) The rated torque (Tr) is obtained by inputting ± 2V, but is limited by the maximum instantaneous stall torque. To enable the torque compensation, use the Func1 parameter (Mode 2, Page 2, Bit 6).	3
		TCMD	Torque Command (Torque Control Mode). With a ±2V input, the commanded torque becomes the rated torque (Tr) and is limited to the instantaneous maximum stall torque.	
23	34	12-24 VDC	Input sequence power supply 1. External power for CN1-30, 31, 32, 33, 36 and 37.	N/A
24	28	12-24 VDC COM	Output sequence power common. Common for CN1-39, 40, 41, 42, 43, 44, 45, and 46.	N/A
25	11	12-24 VDC COM	Output sequence power common. Common for CN1-39, 40, 41, 42, 43, 44, 45, and 46.	N/A
26	5	PPC+	Positive Pulse Command. Counter clockwise (CCW) revolution pulse train command (positive signal).	2
27	6	PPC-	Positive Pulse Command. Counter clockwise (CCW) revolution pulse train command (complement signal).	2
28	7	NPC+	Negative Pulse Command. Clockwise (CW) revolution pulse train command (positive signal).	2
29	8	NPC-	Negative Pulse Command. Clockwise (CW) revolution pulse train command (complement signal).	2
30	18	RST	Alarm Reset input is used to clear error display, alarm code, and alarm bit outputs.	1
31	19	ILM	Current Limit Permit. Current is limited when this input is ON. The value that current is limited to may come from an internal drive source, IILM, or external inputs PIL (CN1-18) and NIL (CN1-19).	1

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Pin	TB Pos	Abbrev.	Description	Circuit Type
32	22	PROT	Positive Rotation Over-travel. Counter clockwise (CCW) over-travel limit. This input is used to indicate that a travel limit has been reached in the CCW direction of travel. When the input turns "ON", a 120% current limit is automatically applied, inhibiting commands in the CCW direction.	1
33	23	NROT	Negative Rotation Over-travel. Clockwise (CW) over-travel limit. This input is used to indicate that a travel limit has been reached in the CW direction of travel. When the input turns "ON", a 120% current limit is automatically applied, inhibiting commands in the CW direction.	1
34	21	GEN. PUR.	Several outputs can be selected: Clear Deviation Error—(Position Mode). Turning "ON" this input for 10mS or more will clear the contents of the position deviation counter. Internal Velocity Command—(Velocity Mode).	1
35/36	49/20	GEN. PUR.	Several outputs can be selected: This selection is set with Func3 parameter (Mode 2, Page 4, Bits 0 and 1).	1
		PCON	Proportional Control On. With this input "ON", the velocity loop becomes proportional control.	
		ECLR	This switch is turned "ON" to clear the position deviation.	
		PMUL/VCS1	Pulse Multiplier. With this input "ON", command pulses are multiplied by the gear ratio set by the PMUL parameter (Mode 1, Page 3).	
		INH/ZCMD	Inhibit. With this input "ON", incoming pulses are inhibited (position mode) or velocity is clamped (velocity mode).	
37	1	SON	Servo ON. Enables the amplifier, if there are no alarms.	N/A
38	39	5V	Output Sequence Power Supply. External power supply for CN1-39, 40, 41, 42, 43, 44, 45, and 46. Use only Pin 38 or 49, NOT both.	N/A
39/40	30/31	GEN. PUR	**Several outputs can be selected:**	6
			ILIM—Current Limit Status Output. This signal comes "ON" to indicate the amplifier is in current limit.	
			LTG—Low Speed (Velocity Mode). When the motor speed becomes ±50 RPM or less of the set value, this signal goes to low impedance.	
			HTG—High Speed (Velocity Mode). When the motor speed becomes ±1000 RPM or more of the set value, this signal goes to low impedance.	

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Pin	TB Pos	Abbrev.	Description	Circuit Type
			SPE—Speed Matching. When the velocity command and velocity feedback is smaller than the specified value, this signal goes to low impedance.	
			INP—In Position (Position Mode). This signal indicates that the content of the deviation counter is within the setting range, OVF. OVF many be set using the Remote Operator (Mode 1, Page 1).	
			CMD—Command Accept Permit	
41	10	SRDY	Start Ready Complete. This signal comes ON and goes to low impedance after the bus power (R, S, and T) is applied to signify readiness to receive the Servo "ON" (SON) signal.	6
42	32	HBON	Holding Brake. This output is used to control the holding brake relay.	6
43	27	ALM1	Alarm Output 1. Alarm output 1 may be set to indicate any alarm (Alarm bit) or to be the least significant bit of a four-bit alarm code. This choice is made using the Remote Operator to set Func2 bit 6 (Mode 2, page 3). The default is Alarm Code Output.	6
44	26	ALM2	Alarm Output 2 see ALM1	6
45	25	ALM4	Alarm Output 3 see ALM1	6
46	24	ALM8	Alarm Output 8 see ALM1	6
47	9	SG	Signal Ground for forward revolution pulse command pins 26 and 27.	N/A
48	46	SG	Signal Ground for reverse revolution pulse command pins 28 and 29.	N/A
49	29	12-24 VDC	Output Sequence Power Supply. External power supply for CN1-39, 40, 41, 42, 43, 44, 45, and 46. Use only pins 38 or 49, NOT BOTH.	N/A
50	35	12-24 VDC	Input sequence power supply 2. External power for CN1-34 and CN1-35.	N/A

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CN2 Motor Encoder Connector

The motor encoder is connected to the amplifier via the CN2 connector. The figure below identifies the pin assignment for this connector.

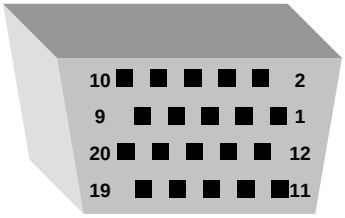


Table 14: CN2 Pin Assignments

Pin	Abbreviation	Description	Circuit Type
1	None	Reserved	N/A
2	None	Reserved	N/A
3	A+	Encoder Positive A Signal Input	2
4	A-	Encoder Negative A Signal Input	2
5	B+	Encoder Positive B Signal Input	2
6	B-	Encoder Negative B Signal Input	2
7	C+	Encoder Positive Index Signal Input	2
8	C-	Encoder Negative Index Signal Input	2
9	None	Reserved	N/A
10	None	Reserved	N/A
11	SG	Signal Ground	N/A
12	SEN	Sense. This signal is used to sense the power supply voltage at the motor. The amplifier then regulates the supply to maintain the proper voltage at the encoder.	N/A
13	None	Reserved	N/A
14	None	Reserved	N/A
15	None	Reserved	N/A
16	None	Reserved	N/A
17	+5V	5 Volt Power	N/A
18	SG	Signal Ground	N/A
19	+5V	5 Volt Power	N/A
20	SG	Signal Ground	N/A

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Operator Terminal

The operator terminal connector is only intended to be used with the optional cable for the Sanyo Denki Remote Operator or PY Setup Software. This connector is therefore not specified further.

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External Regeneration Resistors

When to use an External Regeneration Resistor

When operating, servo systems transform electrical energy to mechanical energy to accelerate the motor and to overcome system losses such as friction. When a moving load is decelerated, or another system is "pulling" the load, the servo system converts this mechanical energy into electrical energy, which is then dissipated as heat in a resistor. This resistor is called a regeneration resistor or regen resistor for short. The amplifier has an internal regen resistor which is adequate for most applications. Connections are provided for an external regen resistor if more capacity is required.

Applications with a load that moves in a vertical direction, applications with load inertia that is high relative to the motor (15:1), and applications where the motor is used to provide a tension load are most likely to require external regen resistors. In order to determine if an external resistor is required, the amount of energy generated must be calculated and then compared to the capacity of the internal resistor. An external regeneration (Regen) resistor is used when the internal regeneration resistor's allowable power is exceeded. See the table below.

Table 15: Amplifier Regeneration Power

Drive Model	Maximum Regeneration Power [W]	
	Internal	Maximum available from AI
PY2A015	0	220
PY2A030	0	220
PY2A050	60	220
PY0A015	20	220
PY0A030	20	220
PY0A050	60	500
PY0A100	90	500
PY0A150	120	500

Calculating Regeneration Power

The formulas below may be used to calculate the amount of power generated by the moving load. There are separate formulas for horizontal moving loads and vertical loads.

P_M = Regeneration power	[W]
E_M = Total regeneration energy	[J]
E_{Hb} = Regeneration energy during deceleration	[J]
E_{VUb} = Regeneration energy during up decel	[J]
E_{VD} = Regeneration energy during down drive	[J]
E_{VDb} = Regeneration energy during down decel	[J]
K_E = Motor voltage constant	[V / RPM]
K_T = Motor torque constant	[Nm / A_{rms}]
N = Motor speed	[RPM]
T_b = Torque during acceleration	[Nm]

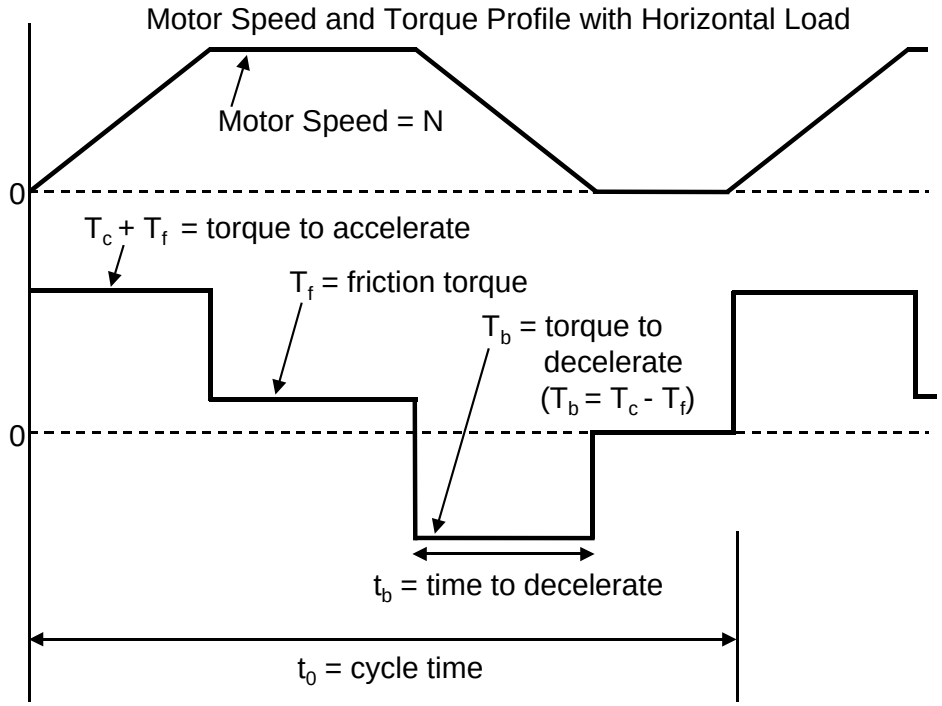
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T_{Ub} = Torque during up deceleration [Nm]
T_D = Torque during down drive [Nm]
T_{Db} = Torque during down deceleration [Nm]
R_ϕ = Armature resistance [Ohms]
t_b = Deceleration time [s]
t_{Ub} = Up deceleration time [s]
t_D = Down drive time [s]
t_{Db} = Down deceleration time [s]
t_0 = Cycle time [s]

Motor Model	K_T [Nm / A_{rms}]	K_E [V / RPM]	R_ϕ [Ohms]
P20B10150D	0.82	0.0292	0.67
P20B10250D	0.79	0.0276	0.31
P20B13300D	0.80	0.0280	0.19
P20B13500D	0.85	0.0297	0.11
P30B04010D	0.292	0.0102	4.30
P30B06040D	0.533	0.0186	1.40
P30B08075D	0.565	0.0197	0.52
P50N05020D	0.436	0.0152	3.4
P50N08100D	0.553	0.0193	0.41
P60B13150H	0.900	0.0314	0.27

Horizontal load

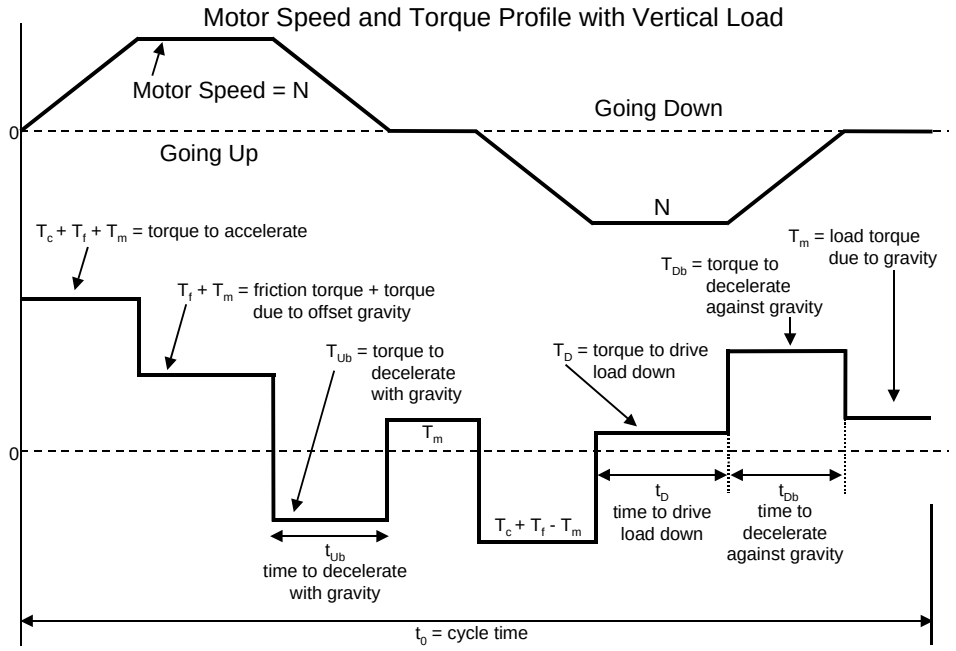


$$E_M = E_{Hb} = \frac{N \text{ x } 3 \text{ x } K_E \text{ x } T_b \text{ x } t_b}{2 \text{ x } K_T} - \left(\frac{T_b}{K_T} \right)^2 \text{ x } 3 \text{ x } R_\phi \text{ x } t_b \qquad P_M = \frac{E_M}{t_0}$$

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Vertical Load



$$E_M = E_{VUb} + E_{VD} + E_{VDb}$$

$$E_{VUb} = \frac{N \times 3 \times K_E \times T_{Ub} \times t_{Ub}}{2 \times K_T} - \left(\frac{T_{Ub}}{K_T}\right)^2 \times 3 \times R_\phi \times t_{Ub} \quad \text{for}\left(E_{VUb} \geq 0\right) \text{else}\, 0$$

$$E_{VD} = \frac{N \times 3 \times K_E \times T_D \times t_D}{K_T} - \left(\frac{T_D}{K_T}\right)^2 \times 3 \times R_\phi \times t_D \quad \text{for}\left(E_{VD} \geq 0\right) \text{else}\, 0$$

$$E_{VDb} = \frac{N \times 3 \times K_E \times T_{Db} \times t_{Db}}{2 \times K_T} - \left(\frac{T_{Db}}{K_T}\right)^2 \times 3 \times R_\phi \times t_{Db} \quad \text{for}\left(E_{VDb} \geq 0\right) \text{else}\, 0$$

$$P_M = \frac{E_M}{t_0}$$

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Selecting the Right External Regen Resistor

If the calculated regeneration power is greater than the capacity of the internal resistor, an external regeneration resistor is required. The table below provides details on the factory external regen options. There is a low, medium, and high power option for amplifiers up through 100A. There is a low and high option for the 150A amplifier. Select an option that has a higher power rating than P_M, calculated above.

Table 16: Regeneration Resistor Selection

		PY2A015 PY0A015	PY2A030 PY0A030	PY2A050 PY0A050	PY0A100	PY0A150
55w	Resistor					
	Part Number REGIST-	220W100B	220W50B			
	Quantity	1	1			
	Resistance [Ω]	100	50			
	Power [W]	55	55			
	Dimensions w, l, d [mm]	60, 230, 20	60, 230, 20			
	Connection Diagram	Type D	Type D			
110w	Resistor					
	Part Number REGIST-	220W50B	220W100B			
	Quantity	2	2			
	Resistance [Ω]	50	100			
	Power [W]	55	55			
	Dimensions w, l, d [mm]	60, 230, 20	60, 230, 20			
	Connection Diagram	Type S	Type P			
125W	Resistor					
	Part Number REGIST-			500W20B	500W10B	50W7B
	Quantity			1	1	1
	Resistance [Ω]			20	10	7
	Power [W]			125	125	125
	Dimensions w, l, d [mm]			80, 250, 40	80, 250, 40	80, 250, 40
	Connection Diagram			Type D	Type D	Type D
220w	Resistor					
	Part Number REGIST-	220W100B	220W50B			
	Quantity	4	4			
	Resistance [Ω]	100	50			
	Power [W]	55	55			
	Dimensions w, l, d [mm]	60, 230, 20	60, 230, 20			
	Connection Diagram	Type SP	Type SP			
250w	Resistor					
	Part Number REGIST-			500W10B	500W20B	
	Quantity			2	2	
	Resistance [Ω]			10	20	
	Power [W]			125	125	
	Dimensions w, l, d [mm]			80, 250, 40	80, 250, 40	
	Connection Diagram			Type S	Type P	
500w	Resistor					
	Part Number REGIST-			500W20B	500W10B	50W7B
	Quantity			4	4	4
	Resistance [Ω]			20	10	7
	Power [W]			125	125	125
	Dimensions w, l, d [mm]			80, 250, 40	80, 250, 40	80, 250, 40
	Connection Diagram			Type SP	Type SP	Type SP

Note:

- When using an external regen resistor, Func2 bit 4 of the remote operator must be set for external resistor.

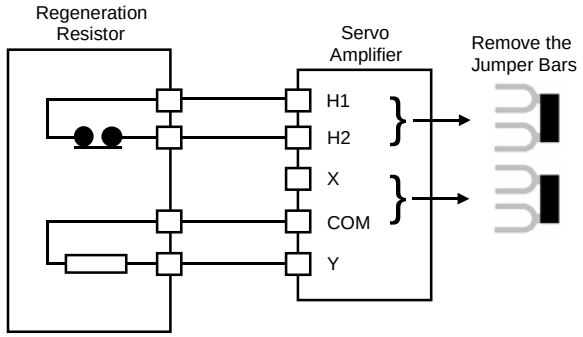
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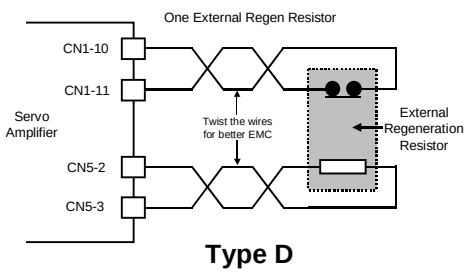
How to connect a Regen Resistor

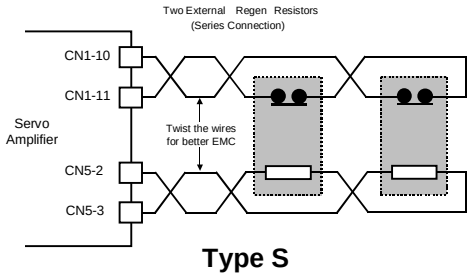
Disconnect the internal resistor from H1, H2, "X", and "COM" terminals and then connect according to diagram below. See figure below.

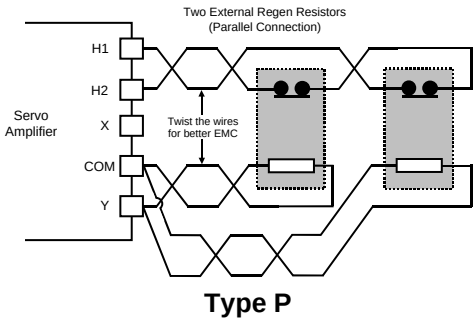
The PY2 (15A & 30A drives) has no shorting bars. For the PY2 (50A), disconnect the jumper bars from "P" and "X", then connect the leads of the regen resistor to "COM" and "Y". There is no connection for the thermostat.

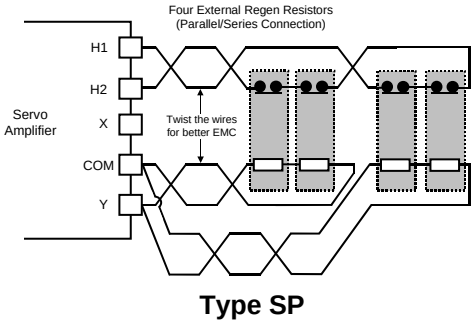


1. Using the Table 16: Regeneration Resistor Selection above, determine the proper circuit configuration, type D or S.









2. Make the connection wires as short as possible. Twist resistor leads together. Twist thermostat connection together.

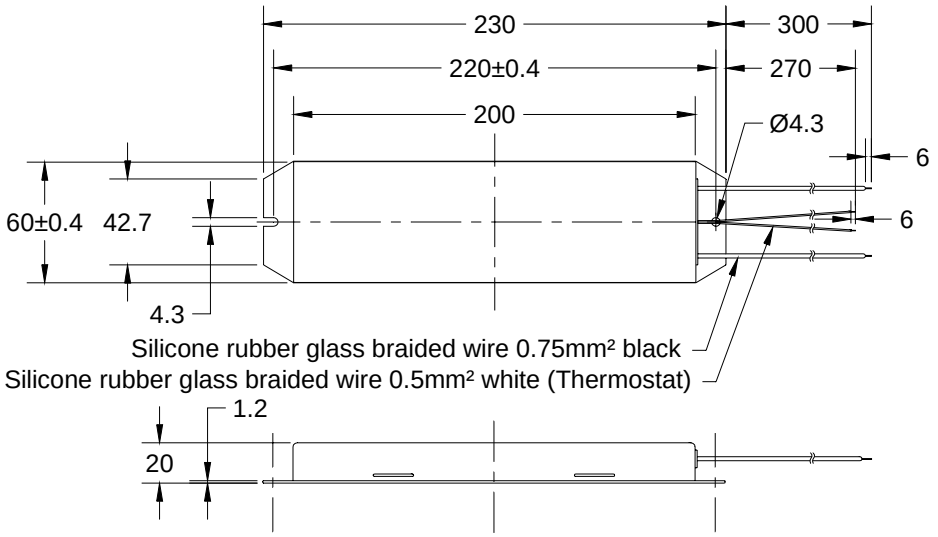
3. If possible, mount the resistor(s) above the amplifier. The resistors get hot so protect adjacent equipment from the heat generated by the regen resistors.

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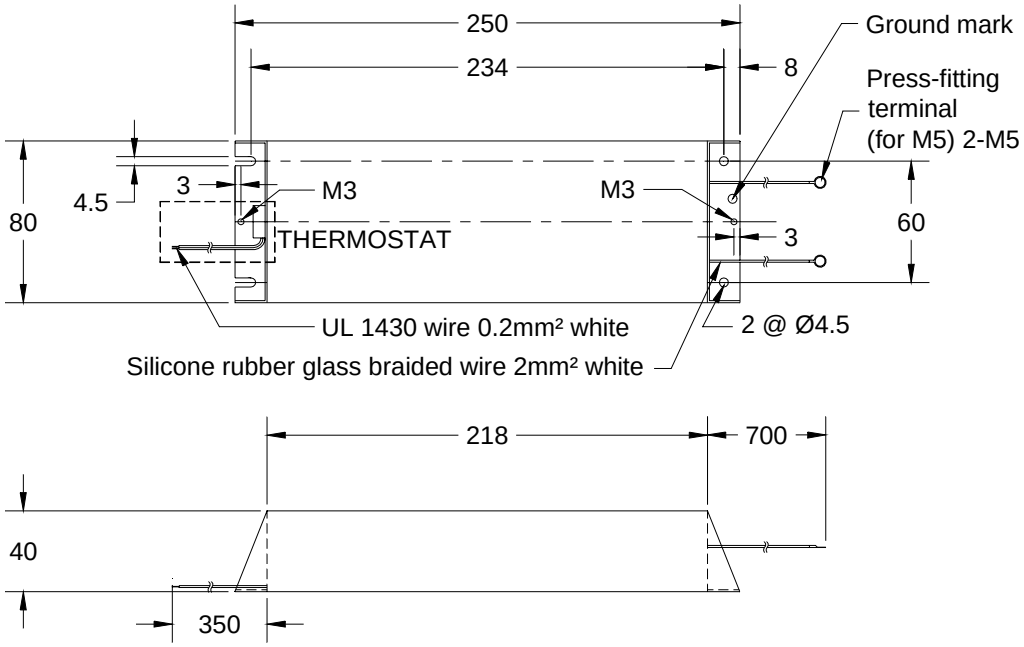
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Regeneration
Resistor Mounting

REGIST-220W100B and REGIST-220W50B (dimensions in mm)



REGIST-500W20B, REGIST-500W10B or REGIST-500W7B (dimensions in mm)



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Wiring Check List

- ☑ 1. The shortest possible factory-supplied cables have been used for motor power, encoder feedback, control signals and remote operator.
- ☑ 2. All local electrical and safety regulations have been satisfied.
- ☑ 3. All screw terminals are tight.
- ☑ 4. The motor power and motor encoder cables are routed separately.
- ☑ 5. All ground connections are secure.
- ☑ 6. The bus power (R, S, and T) voltage and control signal voltages are within specification.
- ☑ 7. If an external regeneration resistor is used, ensure that the internal resistor is disconnected from (H1 & H2—PY0, and X & COM—PY2).
- ☑ 8. If an external regeneration resistor is used, ensure that power leads are twisted together and the thermostat leads are twisted together.
- ☑ 9. Control wires are as short as possible. The command input is 3m or less and the other control wires are 50m or less.

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Operation

Chapter Overview

This chapter contains a guide for the operation of the amplifier. Included in this section are timing diagrams showing the state of inputs and outputs during normal and alarm operation.

Chapter Overview 54
Pre-Operation 55
Amplifier Status Display *55*
Power "On" Sequence 56
Stop Sequences 57
Stop and recovery due to loss of bus power (interlock) *57*
Stop and recovery due to an internal error *58*
Servo "OFF" Sequence 59
With 300mS Brake Delay *59*
With no Brake Delay *60*
Alarm Reset Sequence 61
Over-travel Sequence 62
Positive Over-Travel *62*
Negative Over-Travel *62*

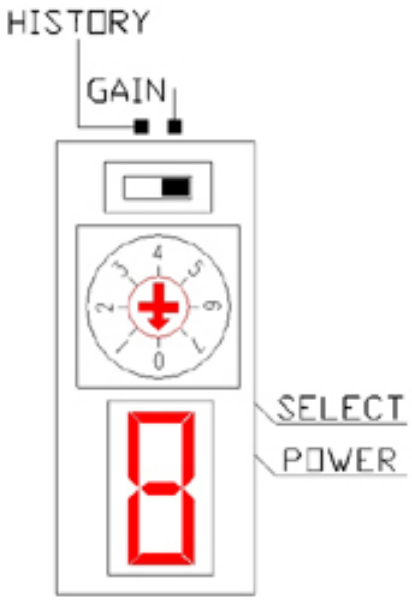
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Pre-Operation

Amplifier Status Display

The amplifier has a 7-segment display, a power LED and a Charge LED on the face that is used to indicate the operating status and alarm conditions. The display has two modes (History and Gain) that are selected by switching a DIP switch above the LED. When placed in History mode, the seven-position dial can be adjusted to see the current staus (0) or one of the last seven alarms (1-7).



In Gain Mode the current status is also displayed.

Table 17: Amplifier Status Display

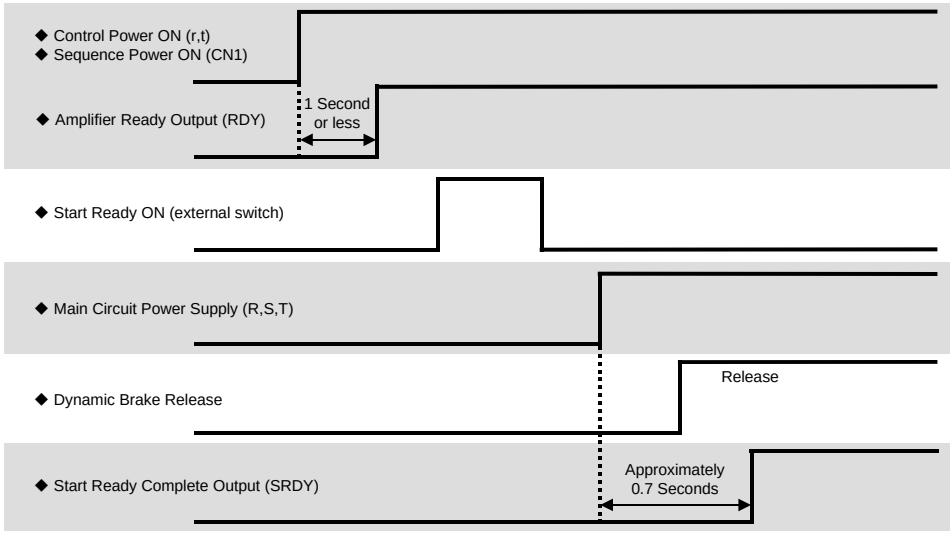
Display	Status
	Control power (r, t) is present and the amplifier-ready output (RDY) signal is ON.
	The bus power (R, S, and, T) is present but the start ready complete (SRDY) signal is OFF.
	The bus power (R, S, and, T) is present and the start ready complete (SRDY) signal is ON.
 Rotating in a figure 8	The Servo ON signal is ON.
	In the position/velocity control, the forward over-travel limit (PROT) input is active.
	In the position/velocity control, the reverse over-travel limit (NROT) input is active.
Power	The control power supply +5V is present.
Charge	The bus capacitors are charged. While this LED is ON be careful of high voltage.
Flashing Code	When an alarm occurs then the alarm code is flashed on the 7-segment display.

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Power “On” Sequence

The timing diagram and circuit diagram below details the proper sequence of operation for turning on the power to the amplifier.



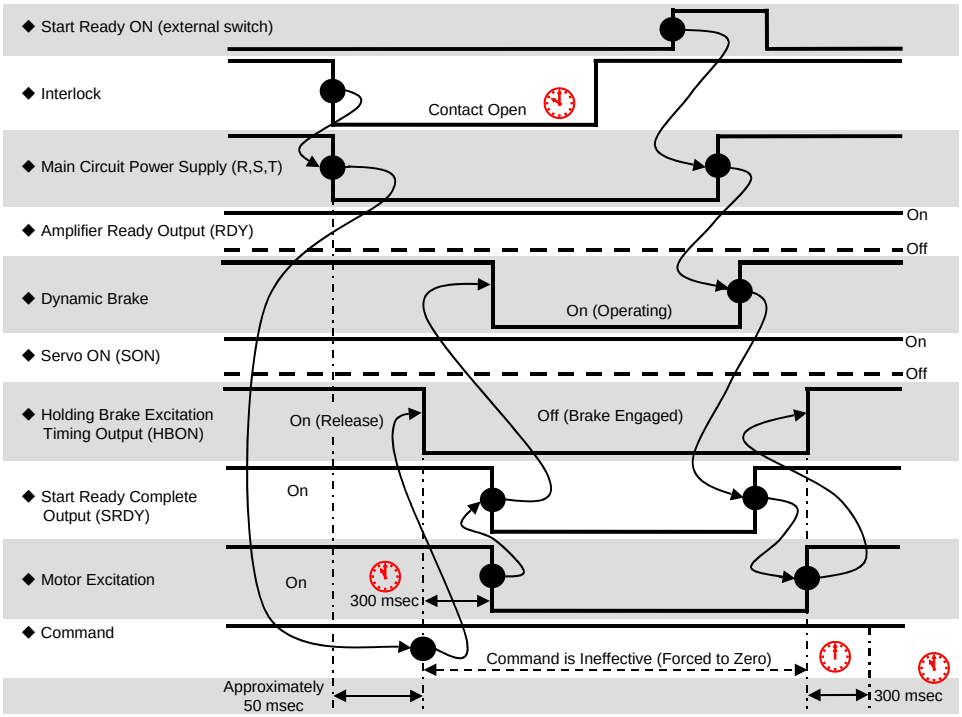
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Stop Sequences

Stop and recovery due to loss of bus power (interlock)

During normal operation, bus power (**R**, **S**, and **T**) may be removed from the amplifier without removing the control power (**r** and **t**). For example, this may be done to create a safe environment so the operator may remove a product sample mid-process for quality control or to clear a product jam. Since control power is not removed, the position of the motor continues to be tracked and alarm information remains available.



Notes:

1. Release the "interlock" before inputting the "start ready" input.

2. This value can be changed to 0mS by setting the "Holding Brake Excitation Timing" to "0" (Mode 1, Page 13). The current is limited by the sequence current limit value for 300mS. The default value for the sequence current limit (SILM) is 120%. It may be change in Mode 1, Page 12.

3. It is possible to force the command to 0 for 300mS after Servo "ON" (SON) by setting ZCLP. When in position mode, the command pulses continue to affect the deviation for 300mS. It is possible to make the command effective immediately after Servo ON (SON) by setting INH

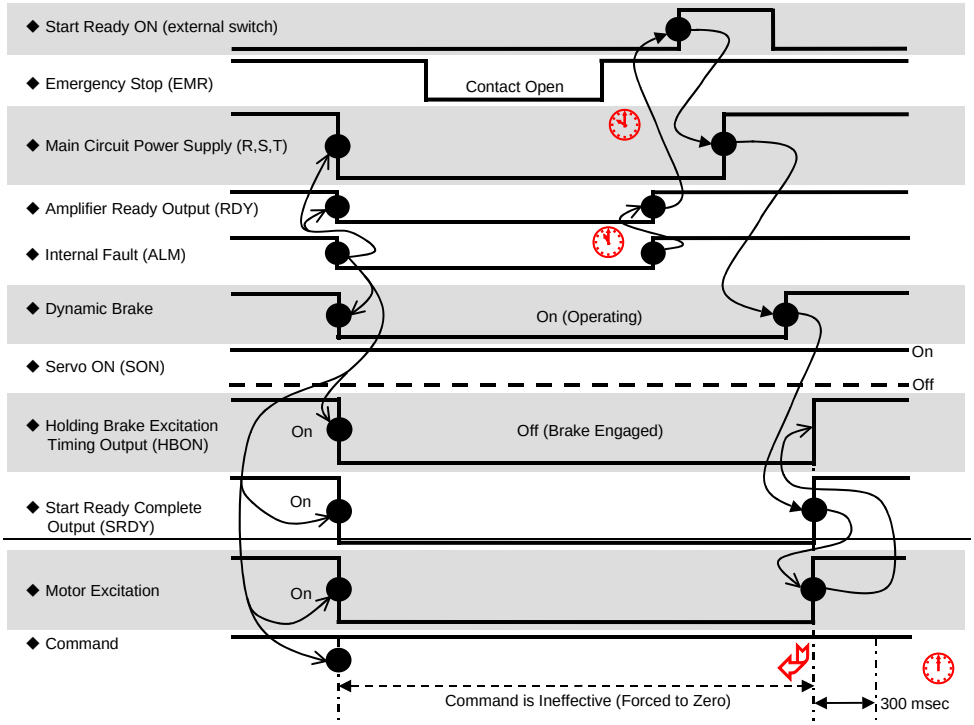
4. If an interlock condition occurs while moving a heavy load a Bus Circuit Power Error (MPE) alarm may occur.

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Stop and recovery due to an internal error

If an error occurs during operation, the amplifier signals the alarm and stops motion. When the cause of the alarm is corrected and the amplifier alarm is reset, normal operation can continue. The following timing diagram defines the sequence of operation during a stop following an alarm and the restart after it is reset.



Notes:

1. During an internal alarm condition, opening the “Interlock” has no effect. However, release it before inputting “Start Ready”.

2. This value can be changed to 0mS by setting the “Holding Brake Excitation Timing” to “0” (Mode 1, Page 13). The current is limited by the sequence current limit value for 300mS. The default value for the sequence current limit (SILM) is 120%. It may be change in Mode 1, Page 12.

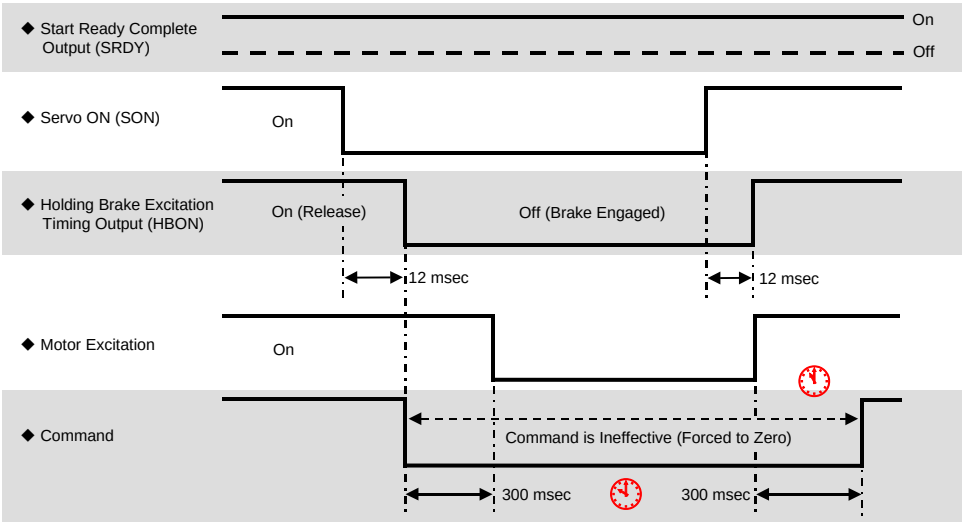
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Servo “OFF” Sequence

With 300mS Brake Delay

During normal operation, the Servo “ON” (SON) input may be used to enable and disable the amplifier. The timing diagram below defines the sequence of operation. In this configuration there is a 300mS delay from the time the brake is released and the motor excitation begins. This delay is present to allow mechanical delays in the actual release of the brake. During this time, the command is internally clamped to zero. If the amplifier is in position mode, the command pulses are counted during this 300mS delay and will be present as a position error when the motor is enabled. This 300mS delay may be eliminated by setting the “Holding Brake Excitation Timing” (Mode 1, Page 13) to “0”. Refer to the next section for more details.



Notes:

1. The current is limited by the sequence current limit value for 300mS. The default value for the sequence current limit (SILM) is 120%. It may be changed in Mode 1, Page 12.

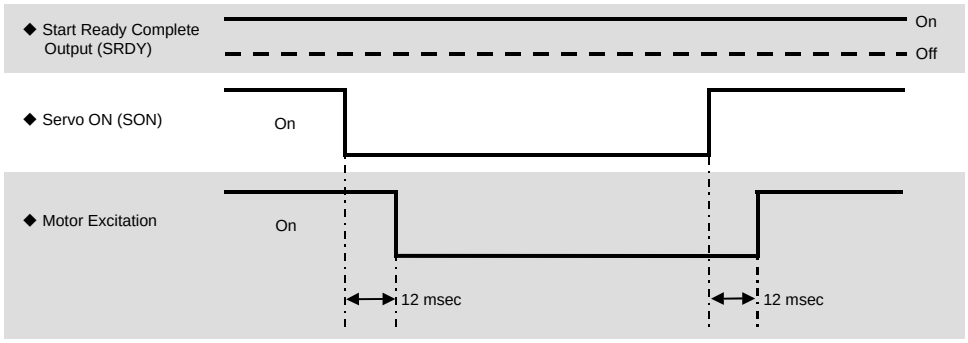
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With no Brake Delay

As noted in the section above, the standard amplifier configuration has a 300mS delay between the release of the brake and motor excitation. During this time, the command is internally clamped to 0, but position commands are still being counted. In the case where the load may force the motor to move during this short time, the motor will jump on motor excitation. The amplifier will attempt to move the motor back to the position it was in when the Holding Brake Excitation output (HBON) was turned "OFF". This condition is common with vertical loads.

To eliminate this "jump," the holding brake delay can be set to 0 by changing the "Holding Brake Excitation Timing", Mode 1, Page 12 to" 0". In this case, the motor excitation will occur before the brake is actually released. The drawback to this configuration is increased wear and strain on the holding brake. The timing diagram below defines the sequence of operation.

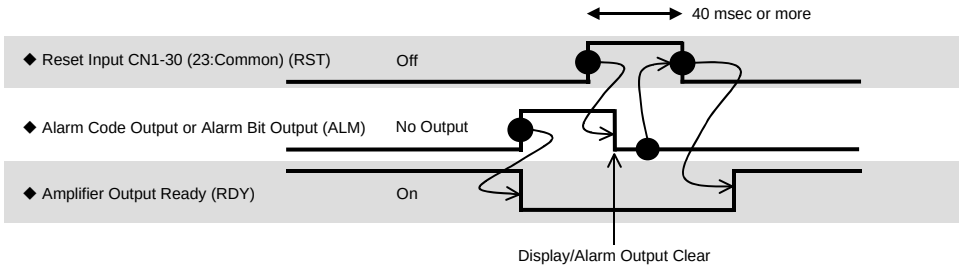


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Alarm Reset Sequence

Should an alarm occur, it must be reset before normal operation can continue. The timing diagram below defines the sequence of operation for an Alarm Reset.



Notes:

1. Turn “OFF” the Reset Input (RST) after checking that the Alarm Code Output (ALM) is “OFF”.

2. Sensor Error (DE), DSP Errors (DSPE), Memory Errors (MEME) and CPU Errors (CPUE) cannot be reset unless the control power is cycled “OFF” and back “ON”.

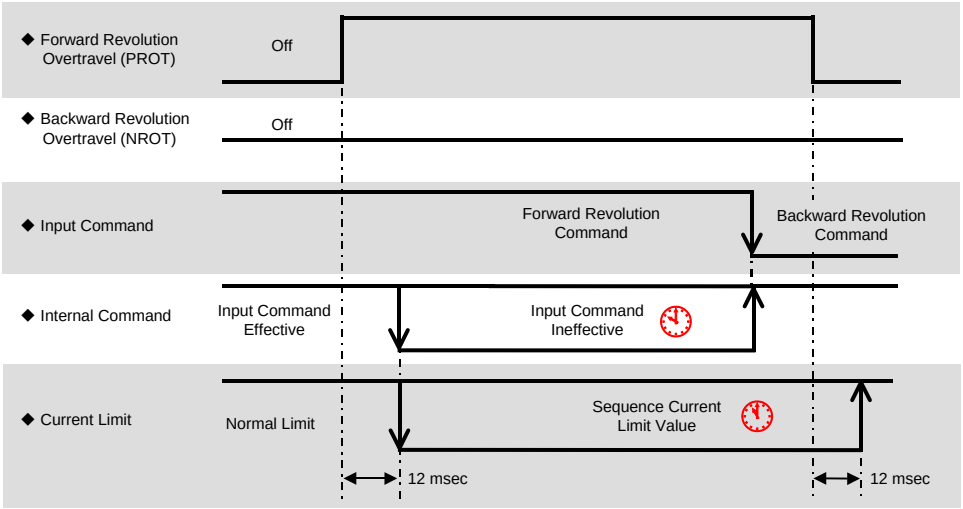
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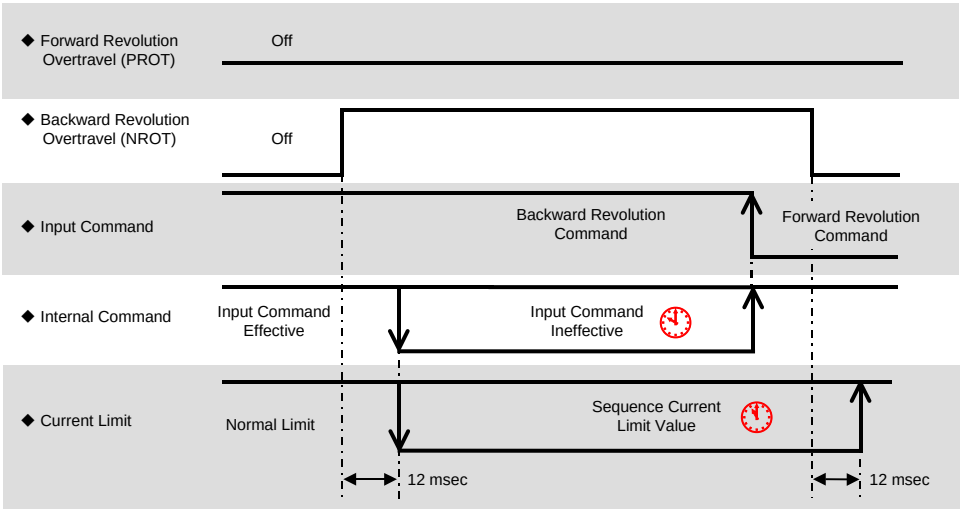
Over-travel Sequence

Over-travel limit inputs are provided on CN1. The positive rotation over-travel (PROT) limit input is on pin CN1-32 and the negative rotation over-travel (NROT) limit is on pin CN1-33. This condition is not an alarm. The timing diagrams below define the sequence of operation for over-travel conditions. Func0 (Mode 2, Bit 5), may be used to change the sense of the NROT and PROT.

Positive Over-Travel



Negative Over-Travel



Notes:

1. The operation of the command invalidation differs between position and velocity controls. For position controls, command pulses are inhibited, and for velocity controls, the command is forced to 0 (VCMD=0). These settings are valid when the acceleration/deceleration time (Tvac, Tvde) or low pass filter (VLPF) parameters are set.

2. Setting the Sequence Current Limit (SILM) parameter using the Remote Operator (Mode 1, Page 12) can change sequence current limit values.

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Drive Setup

Chapter Overview

In this chapter, you will be introduced to setting parameters, viewing alarm history, tuning and monitoring the amplifier with the Remote Operator and the PY Setup Software.

Chapter Overview 63
Using the Remote Operator 64
Overview 64
Remote Operator Modes Navigation 65
PY Setup Software 66
Overview 66
Getting Started 66
Online Connections 66
Offline Modifications 67
Amplifier Parameter Modifications 67
Saving Amplifier Parameter Values 67
Jogging Operations 68
Amplifier Tuning 71
Auto-Tuning 71
Manual Tuning 73
Monitor Screen 74
Remote Operator 74
PY Setup Software 74
Alarm Trace Screen 75
Remote Operator 75
PY Setup Software 75
Quick Setup 76

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Using the Remote Operator

Overview

The Remote Operator can be used to configure and test the amplifier. There are five modes of operation: Parameter Set, Parameter Select, Monitor, Alarm Trace, and Test.

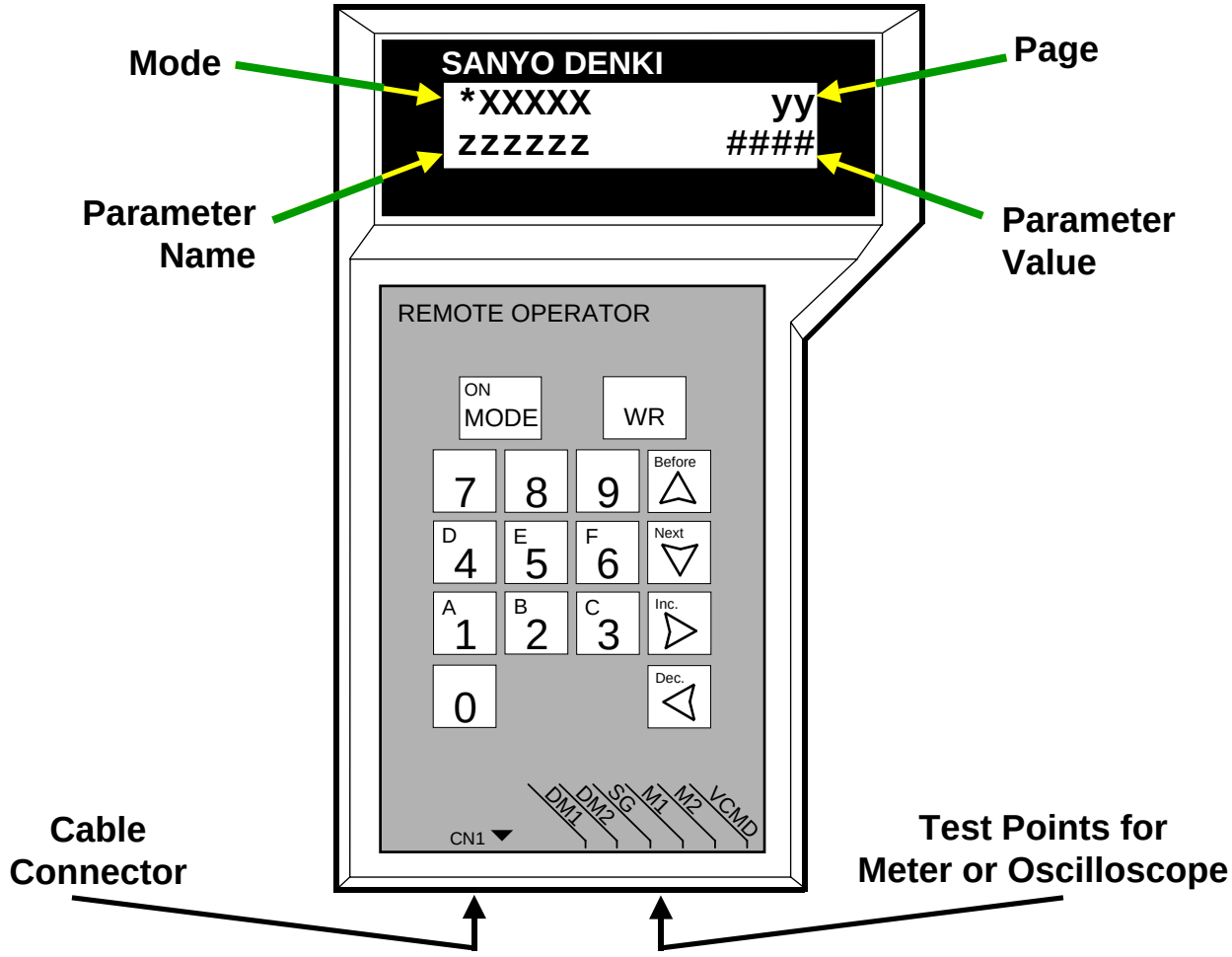
Para. Set The 4 parameters that allow the operator to enter a value are in this mode.

Para. Select There are 9 parameters where the operator can choose between several factory options. These parameters are contained in the parameter select mode.

Monitor The monitor mode is used to view internal values, and the state of inputs and outputs.

Alarm Trace In the Alarm Trace mode, the operator can review the current and previous 7 alarms.

Test In the test mode, the operator can jog the servomotor and run the auto-tuning algorithm.

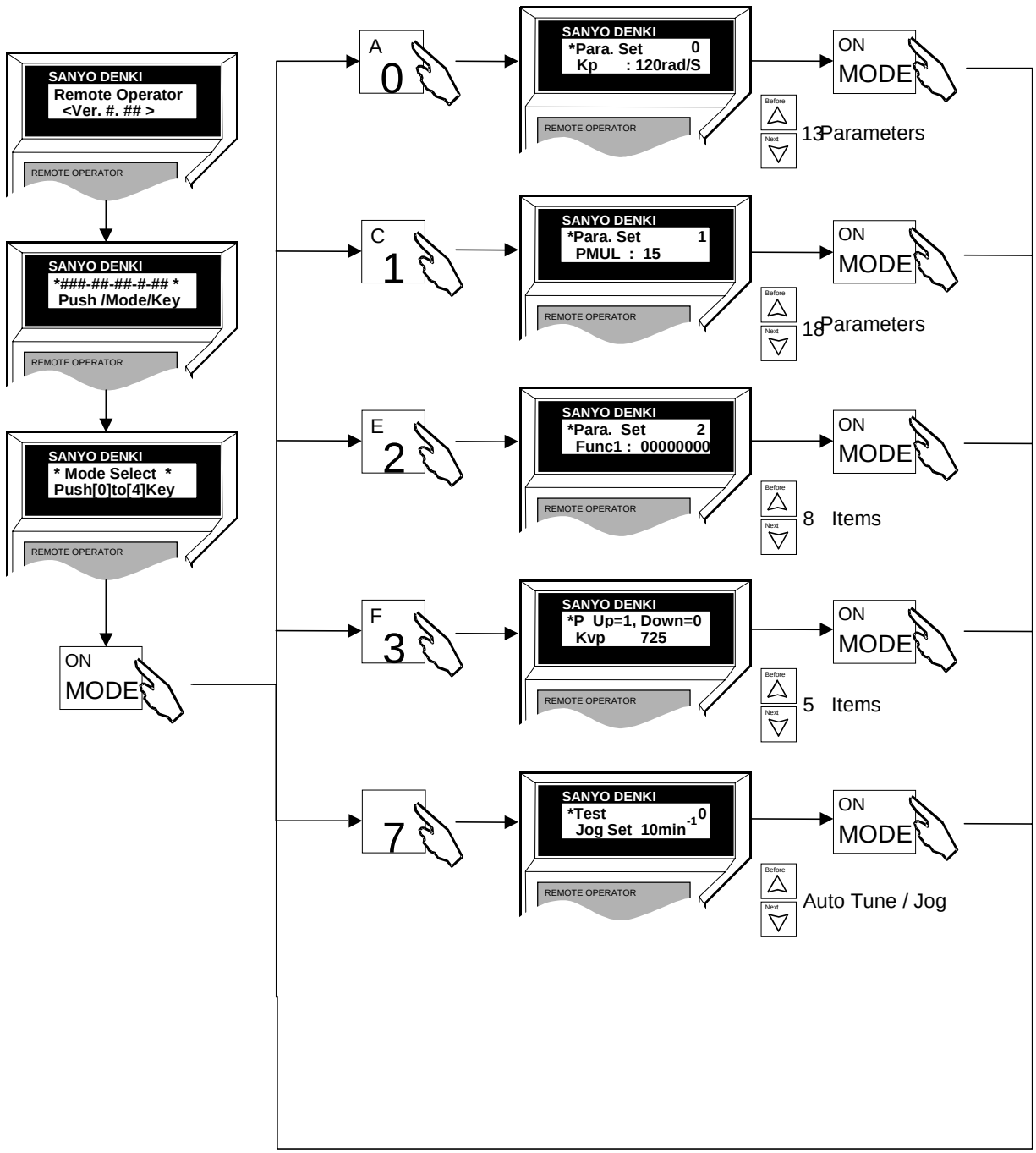


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Remote Operator Modes Navigation

The remote operator has seven (7) modes, Parameter Set 0, 1, 2, & 8 Parameter Select, Monitor, Alarm Trace, and Test. The diagram below shows how to navigate through these modes. The up and down arrows are used to scroll through the elements within a mode.



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PY Setup Software

Overview

Like the Remote Operator, PY Setup Software can be used to configure and test the amplifier. One advantage of the software is that it allows you to save a copy of your configuration for backup or for reuse as a later date.

The PY-PCSETUP Software Kit comes with a drive connection cable and software. This software uses COM1 or COM2 (9-Pin port) to connect to a PY0 or PY2 drive.

Getting Started

The PY Setup Software should be initialized as follows:

1) Install the software using the Setup program on the floppy disk.

2) Connect the PY Setup cable to the OP connector on the PY0 or PY2 drive for an online connection. A configuration file can also be opened offline without connecting to the drive. Insure that the drive is powered up if you wish to make an online connection.

3) Start the PY Setup Software program.

4) The initial screen will request that you to select either COM1 or COM2 for the online connection. Select the choice that matches your available online cable connection. If you intend to open a file offline, the choice does not matter.

5) The Main Menu will appear.

Online Connections

For an online connection, complete the following steps

1) After the Main Menu is displayed, click the ONLINE option under Communication.

2) Click the Yes button after you have confirmed that the drive is powered up and connected to the cable.

3) New choices will be available on the menu if the connection is successful.

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The following online options are available.

- Set Parameters – Allows access to parameter values for the drive. Current values can be viewed or modified.
- Digital Monitor – The Digital Monitor screen allows you to monitor servo status, CN1 I/O, torque, and miscellaneous feedback and command values.
- Alarm Trace – This screen shows the current error in addition to a history of the last seven errors.
- Test Mode – This screens provides commands for jogging the motor, tuning the motor, and adjusting the velocity or torque offset.

Offline Modifications

For offline use, complete the following steps

1) After the Main Menu is displayed, click the EDIT PARAMETER button.
2) Browse to the folder on your computer that contains the saved configuration.
3) Select the file and click on the LOAD button. Parameters for the selected configuration will be displayed.

Amplifier Parameter Modifications

Parameters are placed in six tabs labeled Mode 0-4 and Mode8. Current values for a parameter can be viewed by clicking on the required tab and using the scroll bars to find the desired parameter. Each row on the Mode tab has a Page assigned in the left column. This numbering system allows you to easily locate the parameter when it is referenced in the PY manual. The parameters are located in the same Mode areas as the Remote Operator.

To modify a parameter, click on the desired parameter to be modified. Its current value will be displayed in the Input Value window. This value can be changed to a different value. For parameters where one of a set number of choices is available, use the pull-down for the Input Value Window to select a different choice. If the Input Value Window requires a numeric value, type in a new value that is within the Setting Range displayed for the selected parameter. Once the value is changed, hit the "Set" button to send the new value to the drive.

Saving Amplifier Parameter Values

After you have made modifications to a configuration (offline or online), the software will prompt you to save your settings when you attempt to return to the Main Menu. Provide a file name and browse to a desired path to preserve the settings.

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Jogging Operations

The motor can be rotated forward and backward using the Remote Operator or PY Setup Software. The jogging speed may also be set during a jogging operation. Jogging is one of two operations that can be performed in the test mode. The other is auto-tuning.

Precautions

- Jogging is performed in the velocity control mode.
- If a load is attached to the motor, secure enough operating range before jogging the motor. In particular, when load inertia or jogging speed is high, consider the deceleration distance.
- During the JOG operation, current is limited by the sequence current limit value. The default value is 120%. It can be changed using the Remote Operator.
- During JOG operations, the overtravel limits are effective. For example, if a forward overtravel alarm occurs while jogging in the forward direction, the motor speed will reduce to zero and no forward motion will be permitted. The acceleration/ deceleration time setting is used when an overtravel limit alarm occurs. Therefore, consider the distance traveled during deceleration when setting these positions.
- Since a position loop deviation may remain after a JOG operation, be sure to perform a "deviation clear" before returning to normal operation.

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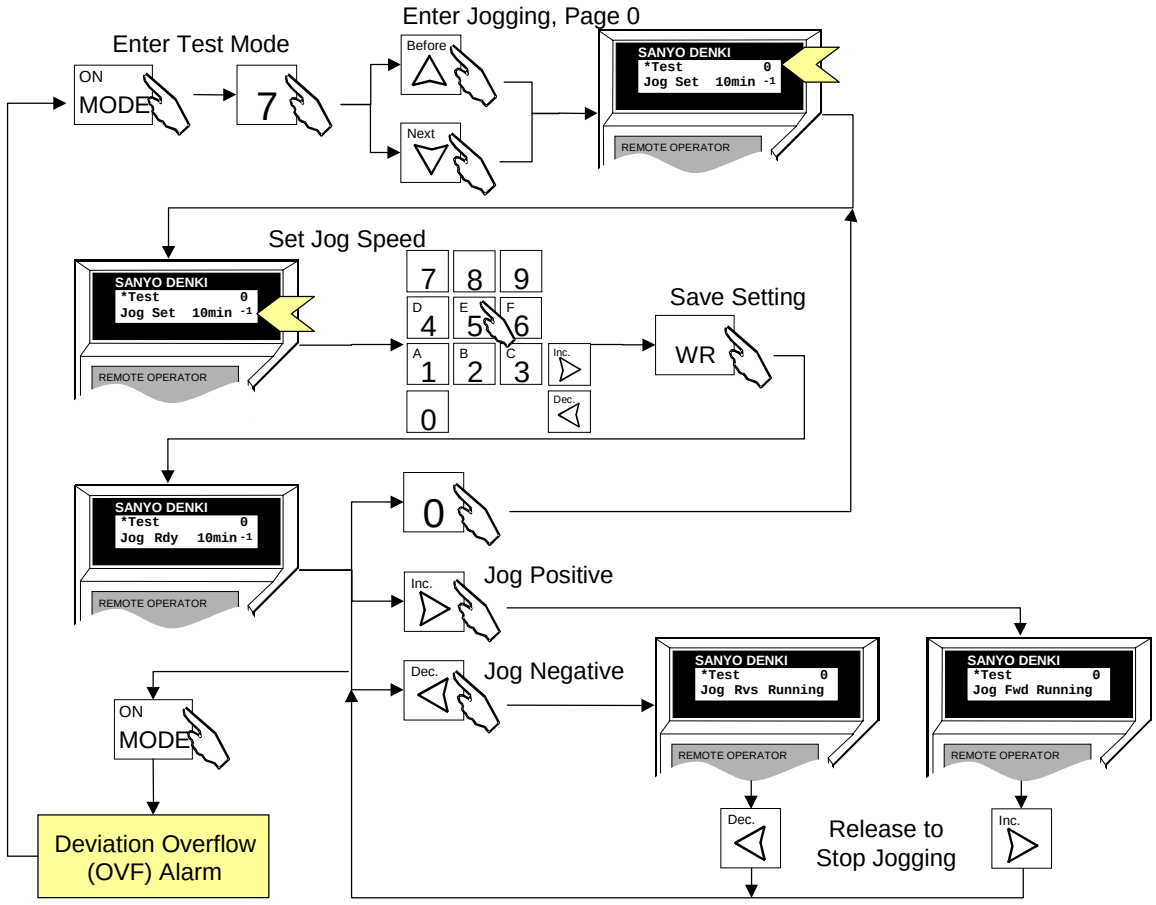
Jogging Operation Procedure with Remote Operator.

Operations before Entering the Test Mode

- Enable test mode operations by setting Func6 bit 6 in mode 2 on page 7 to "1".
- Set the command input to 0.
- The Remote Operator internally controls the Brake release.

Turn ON the bus power (r and t).

- Pressing the ► key performs Forward motion. "Fwd Running" is displayed when the motor revolves in the counter clockwise direction when looking at the motor shaft.
- Pressing the ◄ key performs Reverse motion. "Rvs Running" is displayed when the motor revolves in the clockwise direction when viewed looking at the motor shaft.



Jogging Operation Procedure with PY Setup Software.

Connect the computer to the drive and go online using the PY Setup Software. After reaching the Main Menu, complete the following actions.

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1) Click the TEST MODE button on the Main Menu screen.

2) Click the JOG OPERATION button on the Test Mode Screen.

3) You will be prompted whether or not an OFV (deviation) alarm should occur when jogging operations are completed. Select "yes" if you want an alarm generated (note that the amplifier is switched to velocity mode to accomplish the jogging operation). Otherwise select "no".

4) Once the Drive is ready, a prompt will appear for entry of a speed. Units are the speed are revolutions per minute. Keep in mind that this is revolutions of the motor shaft before entry to gearboxes, etc.

5) After entry of a speed, a new prompt will appear with CCW (Counter-Clockwise) and CW (Clockwise) buttons.

6) Press and hold the left mouse button on the desired direction button. Releasing the mouse will make the motor decelerate to a stop position.

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Amplifier Tuning

Auto-Tuning

General

The auto-tuning function operates the motor using the Remote Operator and estimates the load inertia by moving the load and measuring amplifier currents. With this information, the tuning parameters are automatically set. The four (4) parameters that are set include position loop gain (Kp), velocity loop gain (Kvp), velocity loop integration time constant (Tvi) and current command low pass filter (ILPF).

Precautions

- When auto-tuning is performed, a 60Hz peak torque command is applied for 0.5 seconds. This results in forward and backward motion of one or more turns depending on the load. Use this function only when motor vibrations will not damage the machine.
- If the motor starts vibrating before auto-tuning is performed, reduce the velocity loop gain (Kvp) and increase the integral time constant (Tvi).
- The presence of external current limits may adversely affect the auto-tuning results.

Best Results

Auto-tuning algorithms work best under the following conditions; under other conditions, manual tuning may be required.

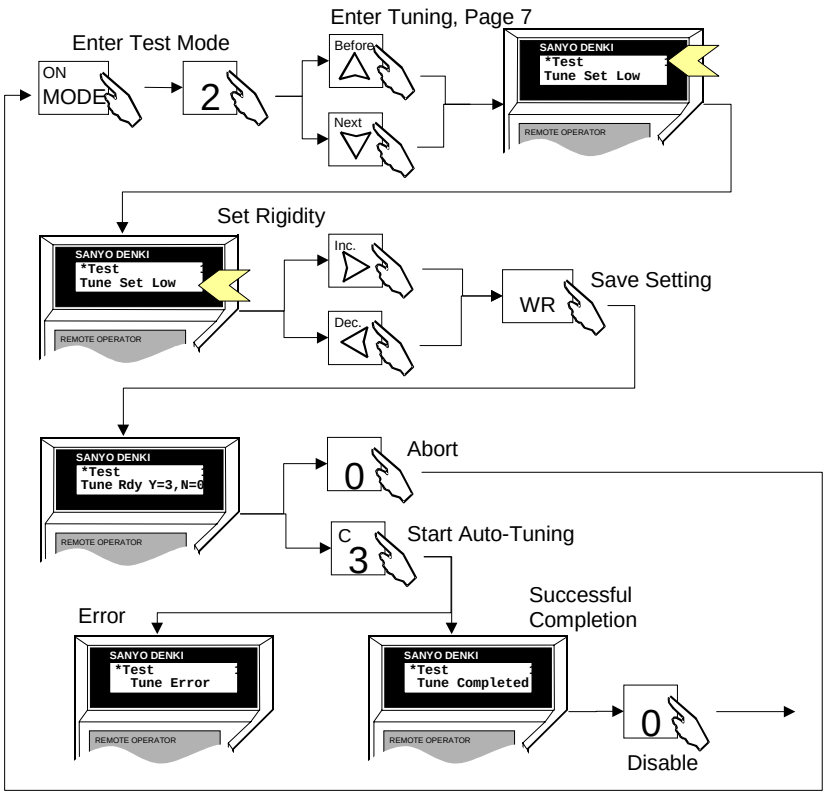
- The load inertia, reflected to the motor shaft, is similar to the inertia of the motor shaft.
- The variations in load inertia and friction are small, i.e., the load is not dynamic.
- The system backlash including motor coupling, gear reductions, ball screws, etc., is small. Backlash is typically measured in degrees and is the distance that the motor shaft can turn while the load is locked in position.
- Results are best when the mechanical system is rigid. Low rigidity systems, including the coupling, may cause mechanical resonance.

Auto-tuning operation with Remote Operator

1. Enable test mode operations by setting Func6 bit 6 in mode 2 on page 7 to “1”.
2. Set the command input to 0.
3. The remote operator internally controls the brake release.
4. Turn ON the bus power (R, S, and T).

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5. Enter test mode, press **[ON / Mode]** and then press 7.

6. On page 1, choose the desired level of performance: high, medium, or low. For the longest mechanical life, and quietest operation, choose the lowest performance setting that will still meet the application requirements. High performance settings require rigid mechanical systems and cause the highest stresses and strains to the mechanical components.

7. To abort auto-tuning, press 0. To start auto-tuning, press 3.

8. At the conclusion of auto-tuning, the proper parameter values are automatically stored into nonvolatile memory.

9. If an error occurs during auto-tuning, the word ERROR appears on the Remote Operator. Mechanical problems are the most common cause of an error during auto-tuning (drivetrain backlash or compliance).

Operations after Auto-Tuning with the Remote Operator

- Upon exiting the Test Mode, an OVF (Deviation Over) alarm occurs. However, this alarm is not entered into the alarm history.

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- If a position controller is being used, a position error in that controller may have accumulated during the jogging operation. This error results in a command signal from the position controller to the amplifier. Clear this position error before starting normal operation; otherwise, the amplifier will make a sudden move in the direction to eliminate the position error.

Auto-tuning operation with PY Setup Software

1. Select **Test Mode** on Main Menu.
2. Select **Offline Auto Tuning** on Test Mode Menu.
3. You will be prompted whether or not an OFV (deviation) alarm should occur on when tuning is completed. Select "yes" if you want an alarm generated (this could serve as an indication to your controller that the axis is no longer in position). Otherwise select "no".
4. Select **High**, **Medium**, or **Low** Tuning on Menu.
5. Select **Yes** for **Offline Tuning Start Okay**?
6. **Tuning Successful** window will appear showing tuning values.
7. Select **Cancel** to exit Tuning Mode Menu.

Manual Tuning

In applications where auto-tuning is not suitable, the servo loops may be tuned manually. If you are not familiar with the operation of PI (Proportional and Integral) controls, please review our *Handbook of AC Servo Systems* which is available as a PDF file from our website.

If you are in position mode, refer to the diagram on page 68 for a complete list of parameters that affect tuning. If you are using Velocity Control refer to page 79 for a complete list of parameters that affect tuning.

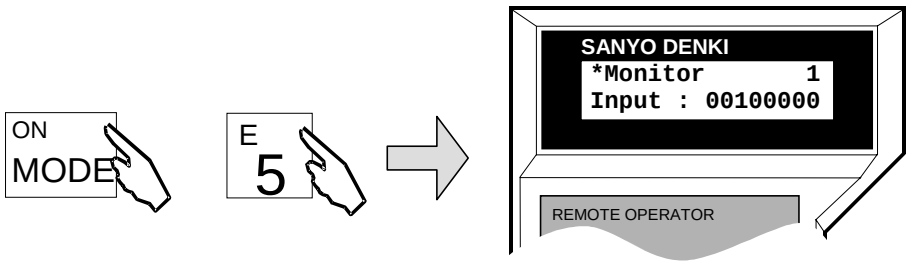
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Monitor Screen

Remote Operator

The Remote Operator may be used to monitor inputs, outputs, velocity, current, etc., of the servo amplifier. The monitor mode is mode 5.



PY Setup Software

The PY Setup Software Monitoring Mode can be reached by clicking the DIGITAL MONITOR button on the Main Menu Screen.

Table 18: Monitor Mode Page Descriptions

Page ▼▲	Abbrev	Description
0	STATUS	Indicates the internal status of the amplifier. Power OFF, Servo Ready, Servo ON, Alarms.
1	INPUT	Indicates the input status of CN1 inputs, [1=ON, 0=OFF] and setting status.
2	OUTPUT	Indicates the output status of CN1 outputs, [1=ON,0=OFF] and internal drive status.
3	VCMD	Indicates the commanded velocity [RPM]
4	VFBK	Indicates the actual velocity [RPM]
5	ICMD	Indicates the commanded current as a percent [IP/IR x 100%]
6	IFBK	Indicates the actual current as a percent [IP/IR x 100%]
7	POS. E	Indicates the position error deviation counter value [Pulses]
8	CSU	Indicates the electric angle of phase U [Degrees]
9	PCMD F	Indicates the position command frequency [Pulses/sec]
10	PS	Indicates the absolute position (Hexadecimal)
11	FCCNT	Indicates the position free-run counter value (Hexadecimal)
12	Trms	Indicates the effective torque (Trma/Tr x 100%)
13	KpM	Indicates the position loop gain (rad/s)
14	KvpM	Indicates the velocity loop proportional gain (Hz)
15	TviM	Indicates the velocity loop integral action time (ms)

Bit 7 6 5 4 3 2 1 0

Name	HOME	0	1	PROB2	PROB1	CW Limit	CCW Limit	EXOH
Pin	16	-	-	15	14	13	12	11

Bit 7 6 5 4 3 2 1 0

Name	0	0	0	0	0	0	OUT1	OUT2
Pin	-	-	-	-	-	-	19	17

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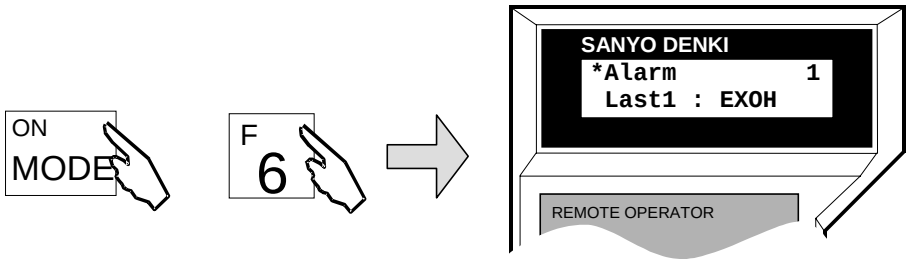
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Alarm Trace Screen

This mode permits you to view a history of the last eight faults that have occurred on the amplifier. Using the Remote Operator, you may view the current alarm and the previous 7 alarms. Refer to Maintenance and Troubleshooting on page 117, for assistance determining and correcting the conditions that led to the alarms.

Remote Operator

The monitor mode is mode 6.



PY Setup Software

For the PY Setup Software, click on the ALARM TRACE button on the Main Menu Screen to view alarm history.

Table 19: Alarm Mode Page Descriptions

Page ▼▲	Switch Position	Description
0	0	Current Status or Alarm
1	1	Previous Alarm
2	2	
3	3	
4	4	
5	5	
6	6	
7	7	Oldest Alarm

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Quick Setup

The amplifiers are factory configured for the most common applications. Therefore, no setup is required in most cases. The most common configuration changes include the following:

- The selection of an alternative command mode, such as position or torque mode.
- The selection of the proper motor purchased with your system.
- For optimal performance in your application, tuning may also need to be adjusted.

Table 20: Quick Setup Steps with Remote Operator

Step	Procedure
Select the proper motor and the desired control type. • Position Mode	1. Turn ON the control power, the 230Vac attached to the "r" and "t" terminals. • The Remote Operator screen should display the [Push Mode Key] screen and a beep should sound. 2. Enable System Parameter changes using the Remote Operator. • Press [ON / Mode] and 2 to enter the parameter set mode. • Press the ▼ key until you have switched to page 7 where you can set the Func6 parameters. • Press the 1 key to change bit 7 to a 1. • Press the [WR] key to save the change. 3. Select the proper motor. • Press [ON / Mode] and 4 to enter the parameter select mode. • Press the ▼ key until you have switched to page 6 where you can set the motor type parameter. • Press the ◄ and ► keys to change to the proper motor type. • Press the [WR] key to save the change. • Cycle the control power OFF and back ON
Adjust Tuning	In many cases, the default tuning will provide exceptional performance. With large motor-to-load inertia mismatches or in cases where very high performance is desired, servo loop tuning is required. This can be accomplished using the amplifiers internal auto-tuning algorithms or manual tuning.

For the PY Setup Software, the Control Mode can be accessed in SET PARAMETERS. Go to Mode 4 on the tabs. Control Mode will be on Page 4 (4th item in list). The motor type is on Page 6 on the same Mode tab (6th item in list).

In addition to these fundamental setup features, the remote allows configuration for external regen resistor. Please refer to the function lists in the following section.

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Amplifier Parameters

Chapter Overview

In this chapter, you see a list of all Amplifier Parameters. A description, range of valid values, and default value is provided.

Chapter Overview 77
Summary *77*
Position Control *78*
Velocity Control *79*
Current Limiting *79*
Parameter Summary, by Mode and Page 80
Detailed Description of Parameters 83

Summary

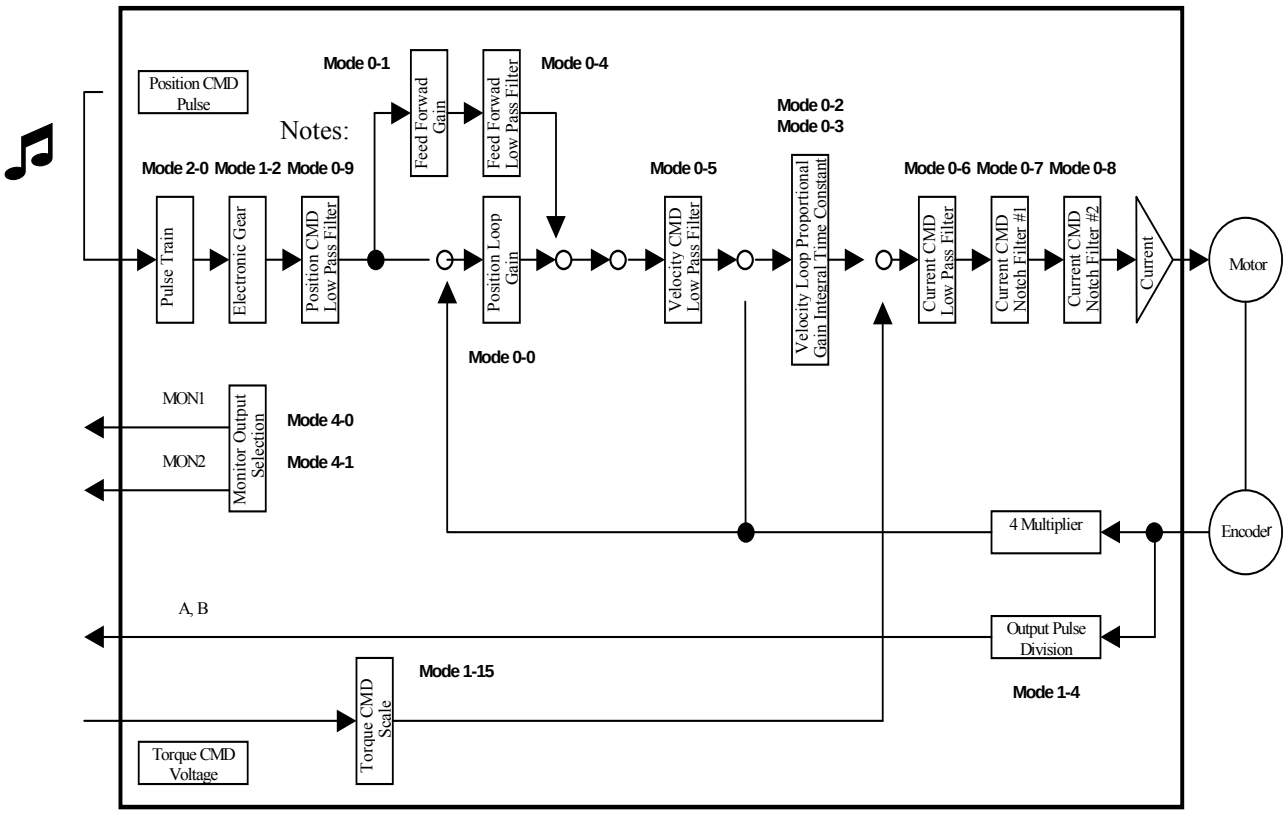
The PY Amplifier family has many features and functions. The behavior of those functions are controlled and configured by amplifier parameters. The descriptions of these parameters have been arranged in several ways for easy reference. The Remote Operator or PY Software can access the amplifier parameters.

Position Loop See page 78	Pictorial reference of all the parameters associated with tuning a controller that is configured for position control.
Velocity Loop See page 79	Pictorial reference of all the parameters associated with tuning a controller that is configured for velocity control.
Sorted by Mode and Page See page 80	A table of all the parameters sorted by Remote Operator Mode and Page. For example, Kvp which is the symbol for Velocity Loop Proportional Gain is in mode 0 on page 2.
Detailed Description of Parameters See page 83	A detailed description of each parameters, including limits.

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Position Control Position Loop Parameter Block Diagram

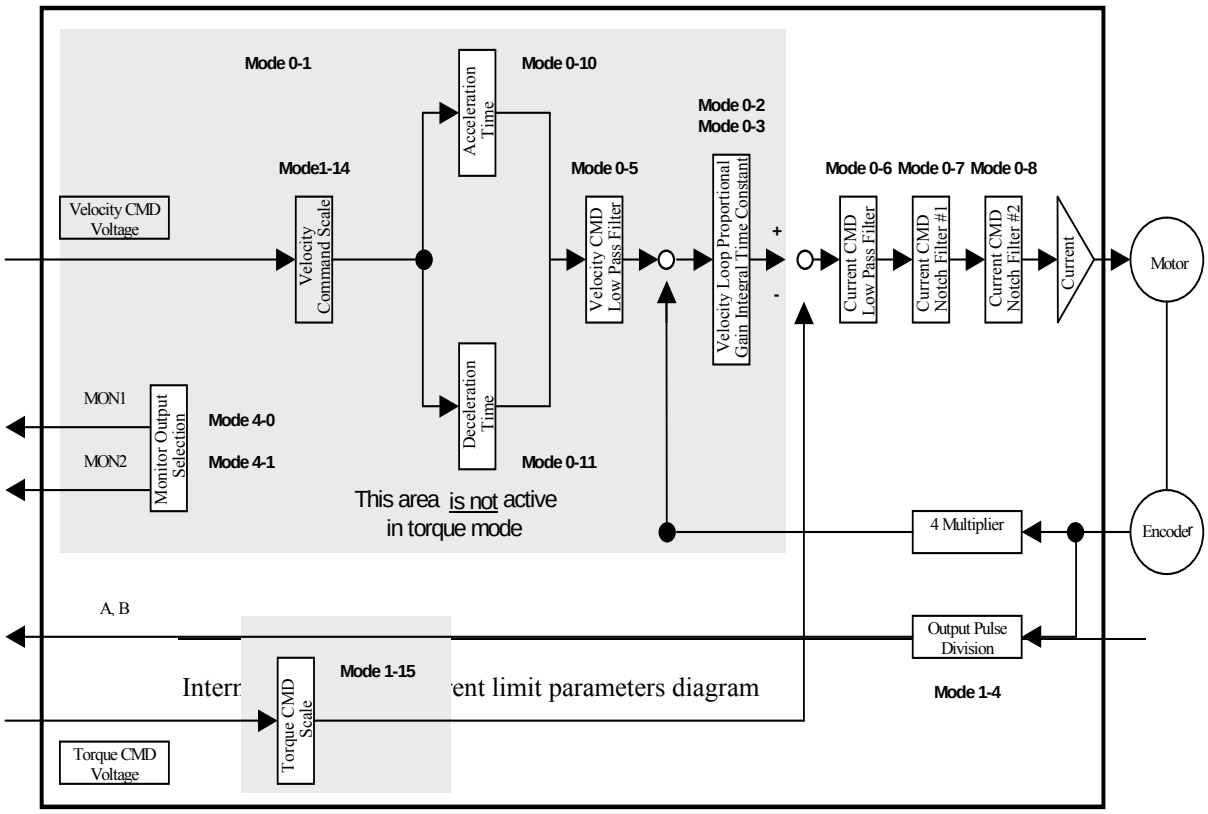


- Each low pass or notch filter is disabled when set to 1000 Hz.

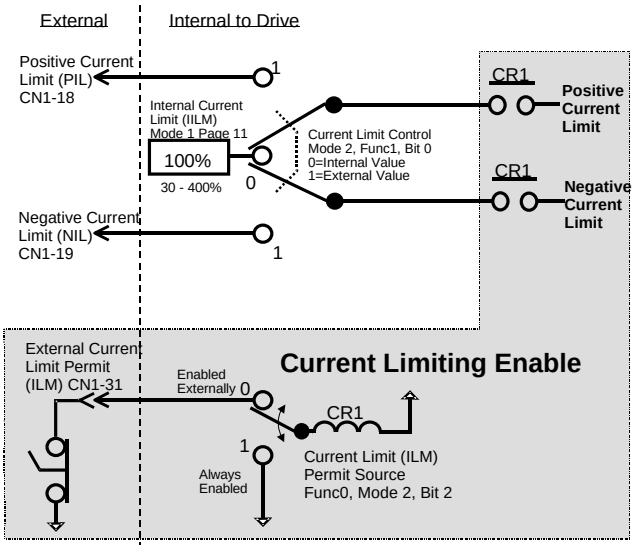
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Velocity Control Velocity Loop Parameter Block Diagram



Current Limiting



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Parameter Summary, by Mode and Page

The table below contains a list of all the amplifier parameters arranged by mode and page as they appear in the remote operator. Detailed descriptions of the parameters follow this table. Values in parentheses on the table are applicable to motors other than P3 and P5 series.

Name	Abbrev	Range	Default	Units	Mode-Page
Position Loop Gain	Kp	1 to 1000	45 (30)	rad/S	0-0
Feed Forward Gain	Kff	0 to 100	0	%	0-1
Velocity Loop, Proportional Gain	Kvp	10 to 3000	100 (70)	Hz	0-2
Velocity Loop, Integral Time Constant	Tvi	1 to 1000	15 (20)	mS	0-3
Feed Forward Low Pass Filter	FLPF	1 to 1000	1000	Hz	0-4
Velocity Command Low Pass Filter	VLPF	1 to 1000	1000	Hz	0-5
Current Command Low Pass Filter	ILPF	1 to 1000	450	Hz	0-6
Current Command, Band Eliminate Filter #1	IBF1	200 to 1000	1000	Hz	0-7
Current Command, Band Eliminate Filter #2	IBF2	IBF1 to 1000	1000	Hz	0-8
Position Command, Low Pass Filter Time Constant	Tpcm	0 to 4000	0	mS	0-9
Velocity Command, Acceleration Time	Tvac	0 to 9999	0	mS	0-10
Velocity Command, Deceleration Time	Tvde	0 to 9999	0	mS	0-11
Velocity Loop, Proportional Gain Addition	KvpA	0 to 255	0	Hz	0-12

Name	Abbrev	Range	Default	Units	Mode-Page
Positioning Complete Signal Width	INP	1 To 32767	64	P(+/-)	1-0
Excessive Deviation Value	OVF	1 To 32767	256	x256P	1-1
Electronic Gear Ratio	EGER	1/32767 To 32767	4/1	-	1-2
Command Pulse Multiplier	PMUL	1To 63	1	-	1-3
Output Pulse Division Ratio	ENCR	1 To 1/8192	1/1	-	1-4
Low Speed	LTG	0 to 32767	50	min^{-1}	1-5
High Speed	HTG	0 to 32767	1000	min^{-1}	1-6
Velocity Matching Width	SPE	0 to 32767	50	min^{-1}	1-7
Internal Velocity, Command Value #1	VCI1	0 to 32767	500	min^{-1}	1-8
Internal Velocity, Command Value #2	VCI2	0 to 32767	1000	min^{-1}	1-9

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Name	Abbrev	Range	Default	Units	Mode-Page
Internal Velocity, Command Value #3	VCI3	0 to 32767	1500	min^{-1}	1-10
Internal Current Limit Value	IILM	30 To (IP/IR) x 100	100	%	1-11
Sequence Current Limit Value	SILM	30 To (IP/IR) x 100	120	%	1-12
Holding Brake Timing	THB	0 To 1000	300	mS	1-13
Velocity Command Scale	VCMS	0 To 3000	500	min^{-1}/V	1-14
Torque Command Scale	TCMS	0 To 400	50	%/V	1-15
Motor Encoder Pulse Number	MENP	500 to 65535	$$$$	P/R	1-16
Full Close Encoder Pulse Number	EENP*	500 To 65535	$$$$	P/R	1-17

Name	Abbrev	Range	Default	Units	Mode-Page
Command Pulse Train Form	PMOD	0, 1	00000000	Bit	2-0
Amplifier Function Select #0	Func0	0, 1	00000000	Bit	2-1
Amplifier Function Select #1	Func1	0, 1	00000000	Bit	2-2
Amplifier Function Select #2	Func2	0, 1	00100000	Bit	2-3
Amplifier Function Select #3	Func3	0, 1	00000001	Bit	2-4
Amplifier Function Select #4	Func4	0, 1	00000001	Bit	2-5
Amplifier Function Select #5	Func5	0, 1	00000000	Bit	2-6
Amplifier Function Select #6	Func6	0, 1	00000000	Bit	2-7

Name	Abbrev	Range	Default	Units	Mode-Page
Position Loop, Gain	Kp	1 To 1000	45 (30)	rad/S	3-0
Velocity Loop, Proportional Gain	Kvp	10 To 3000	100 (70)	Hz	3-1
Velocity Loop, Integral Time Constant	Tvi	1 To 1000	15 (20)	mSec	3-2
Zero Adjustment of Velocity Command	Vzero	+/-16383	$$$$		3-3
Zero Adjustment of Torque Command	Tzero	+/-16383	$$$$		3-4

Name	Abbrev	Range	Default	Units	Mode-Page
Monitor #1 Output	M1	12 Ranges	Vm2mV/min^{-1}		4-0
Monitor #2 Output	M2	12 Ranges	Ic2v/IR		4-1
Gain Select (older models only)	GAIN	2 Ranges	Fix		4-2
Servo Function Choice (newer models)	Func	4 Ranges	Normal		4-2
Control Mode	TYPE	6 Ranges	$$$$		4-3
Encoder Type	ENKD	3 Ranges	$$$$		4-4

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Name	Abbrev	Range	Default	Units	Mode-Page
ABS Sensor Format	ABSF	11 Ranges	$$$$		4-5
Motor Type	MOT.	For P1, P2, P3, P5, P6, and P8 motors	$$$$		4-6
Motor Configuration	MOKD	Rotary (Can not be changed)	Rotary		4-7
Power Supply Type	PSKD	2 Ranges	AC 200V 1P		4-8
Regenerative	RGKD	2 Ranges	Built in R		4-9

Name	Abbrev	Range	Default	Units	Mode-Page
Position Loop, Gain #2	Kp2	1 To 1000	45 (30)	rad/S	8-0
Velocity Loop, Proportional Gain #2	Kvp2	10 To 3000	100 (70)	Hz	8-1
Velocity Loop, Integral Time Constant #2	Tvi2	1 To 1000	15 (20)	mS	8-2
Current Command Value with Automatic Notch Filter Tuning	Tn_F	30 to (IP/IR) X 100	100	%	8-3
Observer – load Inertia Ratio	O_JL	0 to 3000	100	%	8-4

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Detailed Description of Parameters

Following is a detailed description of the amplifier parameters arranged by mode number.

Position Loop Gain — *Kp*

Remote Operator Mode: 0 **Page:** 0 **Default Value:** 45 (30) rad/s

Function: Tune **Setting Range:** 1 to 1000 rad/s

Description:

- Proportional gain of the position controller

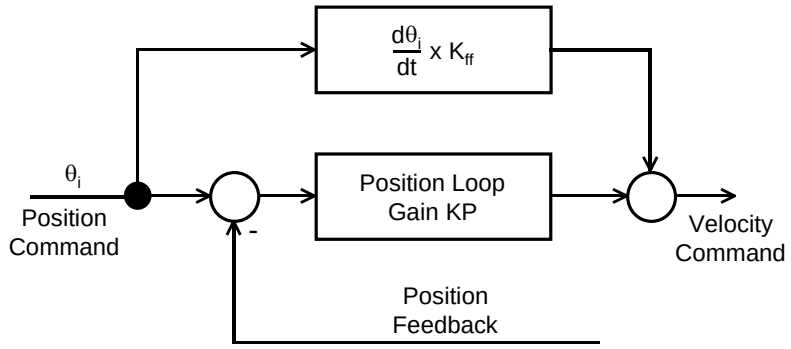
Feed Forward Gain — *Kff*

Remote Operator Mode: 0 **Page:** 1 **Default Value:** 0 %

Function: Tune **Setting Range:** 0 to 100%

Description:

- When set to 100%, the following error becomes "0" when a constant speed is commanded.
- Higher values of Kff reduce the following error of the position loop. However, too high of a value may cause the system to become unstable and vibrate.



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Velocity Loop, Proportional Gain — *Kvp*

Remote Operator Mode: 0 **Page:** 2 **Default Value:** 100 (70) Hz
Function: Tune **Setting Range:** 10 to 3,000 Hz

Description:

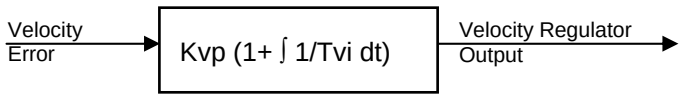
- Proportional gain of the velocity controller (PI control).
- The setting indicates the value when the load inertia is 0.

Velocity Loop, Integral Time Constant — *Tvi*

Remote Operator Mode: 0 **Page:** 3 **Default Value:** 15 (20) ms
Function: Tune **Setting Range:** 1 to 1000 ms

Description:

- Integration time constant of the velocity controller (PI control) .



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Feed Forward, Low Pass Filter *FLPF*

Remote Operator Mode: 0 **Page:** 4 **Default Value:** 1000 Hz
Function: Tune **Setting Range:** 1 to 1000 Hz

Description:

- The cut-off frequency of the low-pass filter is set for the feed-forward command of the position loop.

Velocity Command, Low Pass Filter *VLPF*

Remote Operator Mode: 0 **Page:** 5 **Default Value:** 1000 Hz
Function: Tune **Setting Range:** 1 to 1000 Hz

Description:

- The cut-off frequency of the velocity command low-pass filter.

Current Command, Low Pass Filter *ILPF*

Remote Operator Mode: 0 **Page:** 6 **Default Value:** 450 Hz
Function: Tune **Setting Range:** 1 to 1000 Hz

Description:

- The cut-off frequency of the current command low-pass filter.

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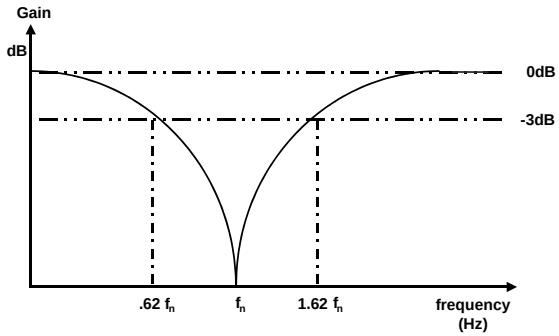
Current Command, Band Eliminate Filter #1 (Notch Filter) — *IBEF*

Remote Operator Mode: 0 **Page:** 7 **Default Value:** 1000 Hz

Function: Tune **Setting Range:** 200 to 1000 Hz

Description:

- The center frequency of the notch filter with the characteristics shown in the following figure is set for the current command in the velocity loop.



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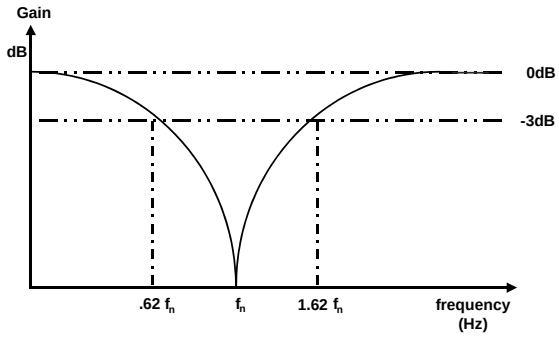
Current Command, Band Eliminate Filter #2 Notch Filter) *IBEF*

Remote Operator Mode: 0 **Page:** 8 **Default Value:** 1000 Hz

Function: Tune **Setting Range:** IBF1 to 1000 Hz

Description:

- The center frequency of the notch filter with the characteristics shown in the following figure is set for the current command in the velocity loop.
- This parameter must satisfy the following requirement: IBF1 ≤ IBF2.



Position Command, Low Pass Filter Time Constant *Tpcm*

Remote Operator Mode: 0 **Page:** 9 **Default Value:** 0 ms

Function: Tune **Setting Range:** 0 to 4000 ms

Description:

- The time constant for the position loop low-pass filter. When it is set to "0 ms", no filter is inserted.

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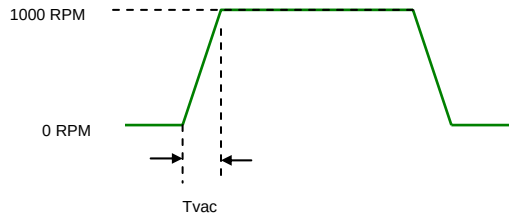
Acceleration Time — *Tvac*

Remote Operator Mode: 0 **Page:** 10 **Default Value:** 0 ms

Function: CMD **Setting Range:** 0 to 9999 ms

Description:

- This parameter is used for limiting the acceleration time in the velocity control mode. The setting represents the minimum time over which the motor velocity can accelerate by 1000 min^{-1} (rpm per minute).
- Even if the velocity command voltage suddenly changes, the velocity command inside the servo amplifier is limited so that the acceleration is equal to that determined by this time.



Note:

- This parameter is effective in the velocity control type. Using this when an external closed loop position controller is used introduces a phase delay that may cause instability and vibration.

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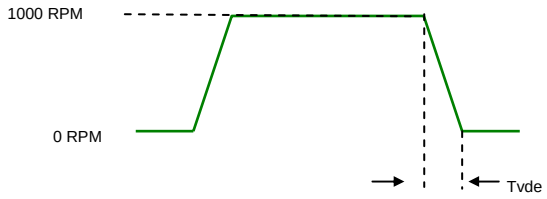
Deceleration Time — *Tvde*

Remote Operator Mode: 0 **Page:** 11 **Default Value:** 0 ms

Function: CMD **Setting Range:** 0 to 9999 ms

Description:

- This parameter is used for limiting the deceleration time in the velocity command mode. The setting represents the minimum time over which the motor velocity can decelerate by 1000 min^{-1} (rpm per minute).
- Even if the velocity command voltage suddenly changes, the velocity command inside the servo amplifier is limited so that the acceleration/deceleration is equal to that determined by this time.



Note:

- This parameter is effective in the velocity control type. Using this when an external closed loop position controller is used introduces a phase delay that may cause instability and vibration.
- This parameter determines the rate of deceleration when an over-travel limit is reached.

Velocity Loop Proportional Gain Addition — *KvpA*

Remote Operator Mode: 0 **Page:** 12 **Default Value:** 0 Hz

Function: Alarm **Setting Range:** 0 to 255 Hz

Description:

- The actual velocity loop proportional gain is:
  Kvp + (KvpA x RSW)
  When Gain Switching is active, it will be:
  Kvp2 + (KvpA x RSW)
- RSW: A value set on the rotary switch.
- Moving the switch on front of the drive to the side labeled “GAIN” enables this.

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In-Position Window — *INP*

Remote Operator Mode: 1 **Page:** 0 **Default Value:** 64 pulse

Function: Alarm **Setting Range:** 1 to 32767 pulses

Description:

- When the absolute value of the difference between the command position and the actual position is less than the In-Position Window (INP) the In-Position Output (CN1-39) is turned ON.
- The standard value is the encoder pulse multiplied by 4, irrespective of the electronic gear function, encoder dividing ratio, or the command multiplier setting.

  (Example)

  When the parameter is set to 64 with a 2,000 pulse encoder, the positioning complete signal is output when the value falls towards the target position in the following range:

$$64 \times \frac{1}{2000 \times 4} \times 360 = \pm 2.88 \text{ Degrees}$$

Following Error Limit — *OVF*

Remote Operator Mode: 1 **Page:** 1 **Default Value:** 256

Function: Alarm **Units:** x256 pulses

Setting Range: 1 to 32767 pulses

Description:

- The following error limit is the absolute difference between the commanded position and the actual position. If the following limit is exceeded an OVF alarm occurs.
- A setting of 10 would equal the following error limit of 2,560 (10 x 256) encoder pulses.

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Electronic Gear Ratio — *EGER*

Remote Operator Mode: 1 **Page:** 2 **Default Value:** 4/1
Function: CMD **Setting Range:** 1/32767 to 32767

Description:

- Electronic gear ratio is applied to incoming position commands.

F_{in} = Frequency into the amplifier
F_{out} = Frequency out of the gear function

EGER = N / D N (1 to 32767)
D (1 to 32767)

$F_{out} = F_{in} \times (N / D)$
$1 / 32767 \leq N / D \leq 32767$

Note:

- Since the electronic gear ratio is for changing the magnification ratio of the command pulses, changing this setting does not change the resolution of the position feedback.
- The encoder in use determines the minimum positioning resolution.

Position Command, Pulse Multiplier — *PMUL*

Remote Operator Mode: 1 **Page:** 3 **Default Value:** 1
Function: CMD **Setting Range:** 1 to 63

Description:

- A multiplier for the position command pulse can be selected from 1 to 63.
- This multiplier is used when the PMUL input terminal is selected by the Func3 parameter.

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Output Pulse Divide Ratio — *ENCR*

Remote Operator Mode: 1 **Page:** 4 **Default Value:** 1/1

Function: Monitor **Setting Range:** 1 to 1/8192

Description:

- Defines the ratio of encoder pulses (CN2) to control feedback pulses.

F_{in} Frequency in from the motor encoder

F_{out} Frequency out to a position controller

$$ENCR := \left(\frac{\beta}{\alpha}\right)$$

α = 1 to 64 or 8192
β = 1 (when α=1 to 64)
= 2 (when α=3 to 64)
= 1 to 8191 (when α= 8192)

$$F_{out} := F_{in} \cdot \left(\frac{\beta}{\alpha}\right)$$

Low Speed — *LTG*

Remote Operator Mode: 1 **Page:** 5 **Default Value:** 50 min^{-1}

Function: Monitor **Setting Range:** 0 to 32767 min^{-1}

Description:

- Low Speed: When the speed decreases below this set level the “low speed” (LTG) status is turned ON if enabled.
- The LTG status can be output to CN1-39 or CN1-40 by setting Function Switch 4.

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High Speed — *HTG*

Remote Operator Mode: 1 **Page:** 6 **Default Value:** 1000 min^{-1}

Function: Monitor **Setting Range:** 0 to 32767 min^{-1}

Description:

- High speed: When the speed exceeds this set level the “high speed” (HTG) status is turned ON (CN1-39) if enabled.
- The LTG status can be output to CN1-39 or CN1-40 by setting Function Switch 4.
- The following switching (control mode) enables a speed limit to be set in the torque control mode:

  Velocity ⟷ Torque

  Position ⟷ Torque

Speed Matching Width — *SPE*

Remote Operator Mode: 1 **Page:** 7 **Default Value:** 50 min^{-1}

Function: **Setting Range:** 0 to 32767 min^{-1}

Description:

- When the difference between the velocity command and the velocity feedback is smaller than the specified value, the SPE status is turned on if enabled.
- The LTG status can be output to CN1-39 or CN1-40 by setting Function Switch 4.

Internal Velocity Command Value #1 — *VCI1*

Remote Operator Mode: 1 **Page:** 8 **Default Value:** 500 min^{-1}

Function: **Setting Range:** 0 to 32767 min^{-1}

Description:

- Sets a velocity command value.
- It is enabled by setting the Func3 parameter bits 3, 2, 1, and 0 to “1010” respectively, and turn the CN1-36 pin “ON” and CN1-35 pin “OFF”.
- The drive must be configured for velocity mode operation.

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Internal Velocity Command Value #2 — *VCI2*

Remote Operator Mode: 1 **Page:** 9 **Default Value:** 1000 min^{-1}

Function: **Setting Range:** 0 to 32767 min^{-1}

Description:

- Set a velocity command value.
- It is enabled by setting the Func3 parameter bits 3, 2, 1, and 0 to "1010" respectively, and turning the CN1-35 pin "ON" and the CN1-36 pin "OFF".
- The drive must be configured for velocity mode operation.

Internal Velocity Command Value #3 — *VCI3*

Remote Operator Mode: 1 **Page:** 10 **Default Value:** 1500 min^{-1}

Function: **Setting Range:** 0 to 32767 min^{-1}

Description:

- Sets a velocity command value.
- It is enabled by setting the Func3 parameter bits 3, 2, 1, and 0 to "1010" respectively, and simultaneously turning both the CN1-35 pin and the CN1-36 pins "ON".
- The drive must be configured for velocity mode operation.

Current Limit, Internal Value — *IILM*

Remote Operator Mode: 1 **Page:** 11 **Default Value:** 100 %

Function: Current Limit **Setting Range:** 30 to (IP/IR) x 100

Description:

- By setting Func1, Bit 0 to "0" and turning "ON" pin ILM (CN1-31 pin), the current is clamped at the above set value. However, it is impossible to set the value higher than the IP value.
- This parameter can be set within the range from 30% to (IP/IR x 100)%.

  IP: Peak armature current.

  IR: Rated armature current.

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Current Limit, Sequence — *SILM*

Remote Operator Mode: 1 **Page:** 12 **Default Value:** 120 %

Function: Current Limit **Setting Range:** 30 to (IP/IR) x 100

Description:

- This current limit applies under the following conditions: holding brake sequence, over-travel, and while jogging.
- Even if this parameter is set to a value larger than the peak current, the actual current will be limited to the peak current.
- Changes to this parameter do not take affect until the control power is cycled "OFF" and back "ON".
- The setting is a percentage of rated current (IR).

Holding Brake Excitation Timing — *THB*

Remote Operator Mode: 1 **Page:** 13 **Default Value:** 300 ms

Function: **Setting Range:** 0 to 1000 ms

Description:

- Sets the holding brake excitation timing.
- Select "0" when this function is not used.

Velocity Command, Scale Adjustment — *VCMS*

Remote Operator Mode: 1 **Page:** 14 **Default Value:** 500 min^{-1}/V

Function: **Setting Range:** 0 to 3000 min^{-1}/V

Description:

- Sets a velocity command scale corresponding to 1V of the command voltage.

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Torque Command, Scale Adjustment — *TCMS*

Remote Operator Mode: 1 **Page:** 15 **Default Value:** 50 %/V
Function: **Setting Range:** 0 to 400 %/V

Description:

- Sets a torque command scale corresponding to 1V of the command voltage.

Motor Encoder Pulse Number — *MENP*

Remote Operator Mode: 1 **Page:** 16 **Default Value:** 2000 P/R
Function: Motor **Setting Range:** 500 to 65535 P/R

Description:

- Sets the number of pulses of the encoder used.
- The following shows the number of encoder pulses for the standard combinations:
  "Wire-Saving" Incremental encoder—2000 P/R
  Absolute Encoder—2048 P/R
- Changes to this parameter do not take affect until the control power is cycled "OFF" and back "ON".
- When changing this setting, set Func6 Bit 7 to "1" from Mode 2 prior to the change.

Number of Pulses of Fully Closed Encoder — *EENP*

Remote Operator Mode: 1 **Page:** 17 **Default Value:** 2000 P/R
Function: **Setting Range:** 500 to 65535 P/R

Description:

- Sets the number of pulses of the encoder used in terms of the motor shaft.
- This parameter is usable only on the servo system that supports the fully closed design.
- Changes to this parameter do not take affect until the control power is cycled "OFF" and back "ON".
- When changing this setting, set Func6 Bit 7 to "1" from Mode 2 prior to the change.

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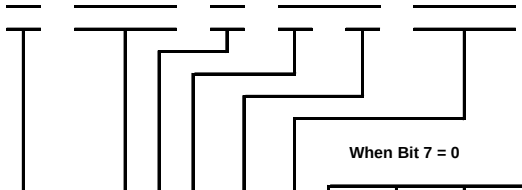
Position Command, Pulse Train Pattern — *PMOD*

Remote Operator Mode: 2 **Page:** 0 **Default Value:** 00000000 Bit

Function: CMD **Setting Range:** 0,1

Description:

- The position command pulse train can be entered in 3 forms: Forward & Backward Revolution Pulse Train, Code & Pulse Train, 90º Phase Difference Two-Phase Pulse Train
- The rising/falling edge command, the revolution direction, and digital filter clock can be specified here.



When Bit 7 = 0

Bit 1	Bit 0	Digital Filter for Command Pulse Input	
		Maximum Frequency	Minimum Pulse Width
0	0	666 kpulse/S	750 nS
0	1	2.6 Mpulse/S	187.5 nS
1	0	1.3 Mpulse/S	375 nS
1	1	333 kpulse/S	1.5 uS

When Bit 7 = 1

Bit 1	Bit 0	Digital Filter for Command Pulse Input	
		Maximum Frequency	Minimum Pulse Width
0	0	166 kpulse/S	3.0 uS
0	1	666 kpulse/S	750 nS
1	0	333 kpulse/S	1.5 uS
1	1	83.3 kpulse/S	6.0 uS

CCWP Input Polarity Switching	
0	Counts at the Rising Edge
1	Counts at the Falling Edge

CWP Input Polarity Switching	
0	Counts at the Rising Edge
1	Counts at the Falling Edge

Selection of Revolution Direction	
0	Standard
1	Backward Revolution

Bit 5	Bit 6	Command Pulse Form
0	0	Forward & Backward Revolution
0	1	Code & Pulse
1	0	90 Degree Phase Difference
1	1	Prohibited

Switching of Digital Filter	
0	High Speed
1	Low Speed (1/4)

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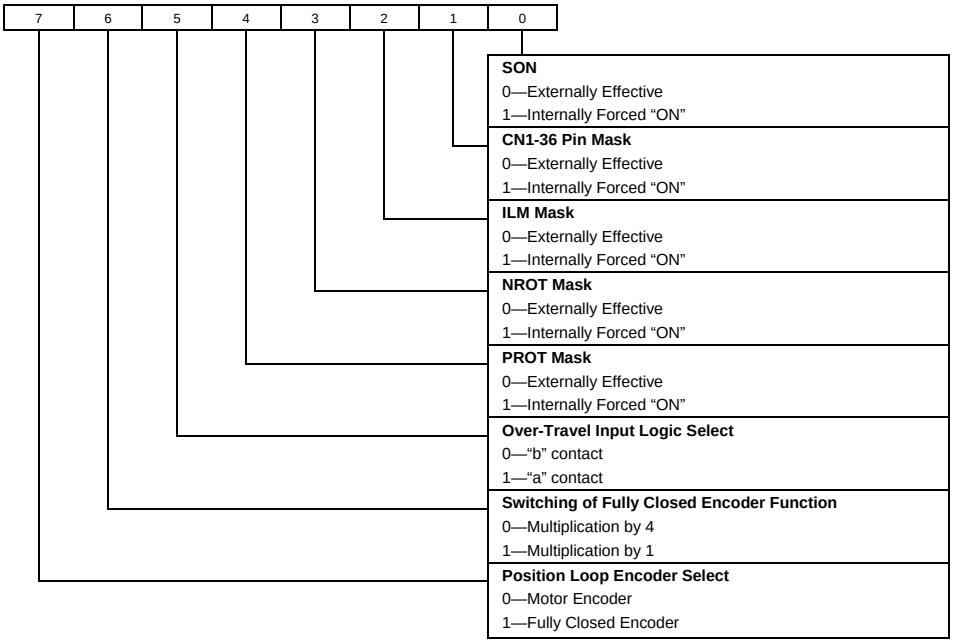
Function Switch 0 — *Func0*

Remote Operator Mode: 2 **Page:** 1 **Default Value:** 00000000 Bit

Function: I/O **Setting Range:** 0,1

Description:

- This parameter selects whether external signals are made effective or are forced "ON" internally. It also selects the overt-travel input logic, the encoder used (between motor or fully enclosed-external-encoder), and the multiplication factor of the encoder.



- Bits 6 and 7 are only available with servo systems that support the fully closed design.
- Selecting a fully closed encoder does not change the divided output. Thus, when you need a divided output for the fully closed encoder, set Func5, Bit 4 to "1".
- When over-travel bits 3 and 4 are internally turned "ON", they become ineffective if the over-travel input logic is "b" contact. Also, bits 3 and 4 are always in over-travel status if the over-travel input logic is "a" contact.
- When changing the setting of Bit 7 or 6, you must turn the control power "OFF" once prior to making the change.

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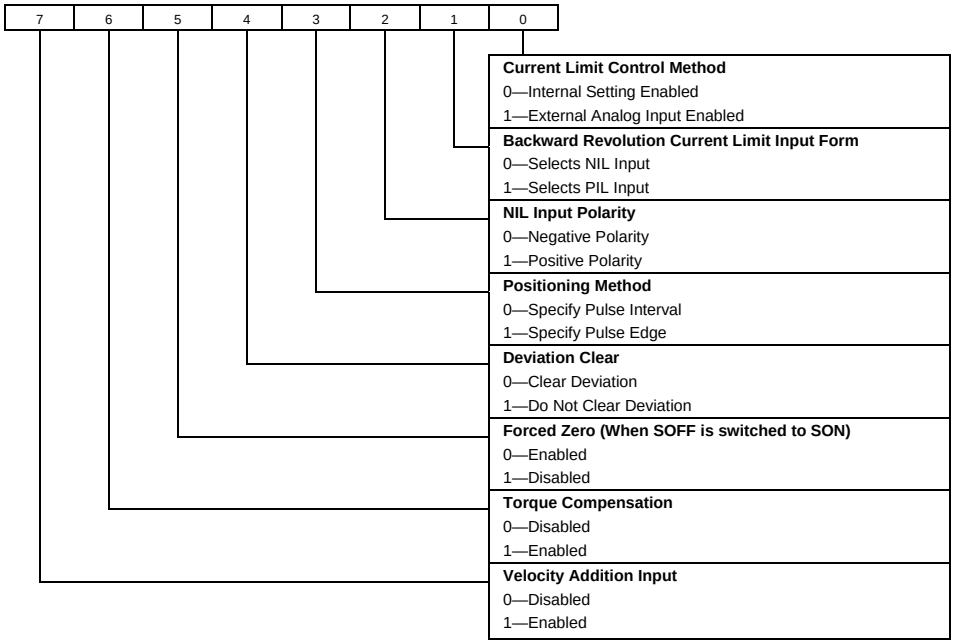
Function Switch 1 — *Func1*

Remote Operator Mode: 2 **Page:** 2 **Default Value:** 00000000 Bit

Function: I/O **Setting Range:** 0,1

Description:

- A desired function can be set from the digital switch



- Bit 7 is effective in the position control mode.
- Bit 6 is effective in both the position and velocity control modes.
- When Bit 4 is set to "1", the position deviation is not cleared upon the occurrence of an alarm. Therefore, be sure to clear the deviation before clearing the alarm.
- The current limit is enabled only after the CN1-31 pins are turned on.

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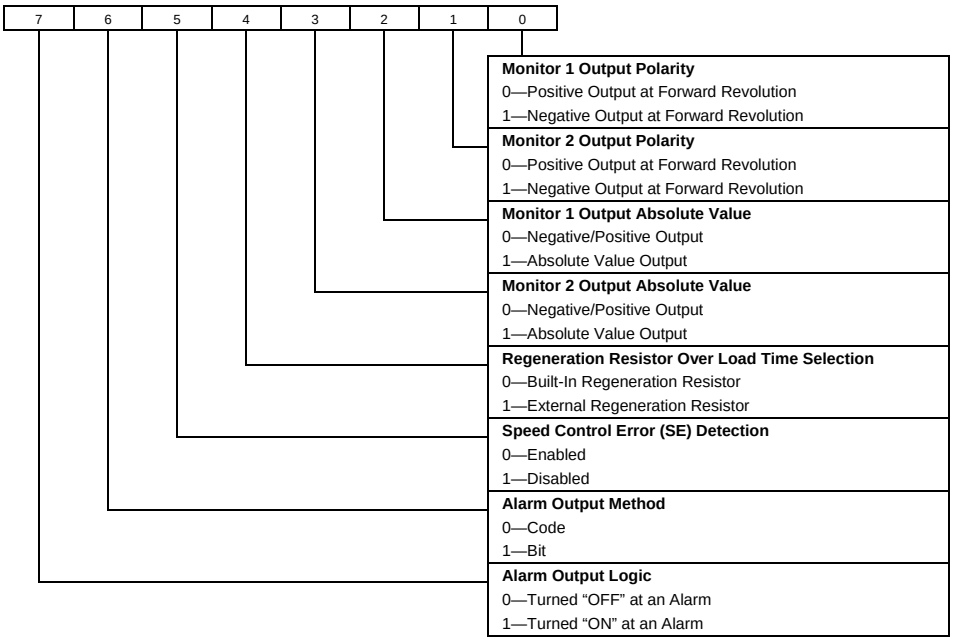
Function Switch 2 — *Func2*

Remote Operator Mode: 2 **Page:** 3 **Default Value:** 00100000 Bit

Function: I/O **Setting Range:** 0,1

Description:

- A desired monitor output method or regeneration resistor “over-load” time can ce selected.



- Changes to bit 4 do not take affect until the control power supply is cycled “OFF” and back “ON”.
- If Bit 7 is set at “1”, and alarm will not be indicated for a CPU error.
- Bit 4 cannot be changed unless the control power is turned “OFF”.
- Forward revolution refers to the counterclockwise revolution when viewed from the load (motor shaft) side.

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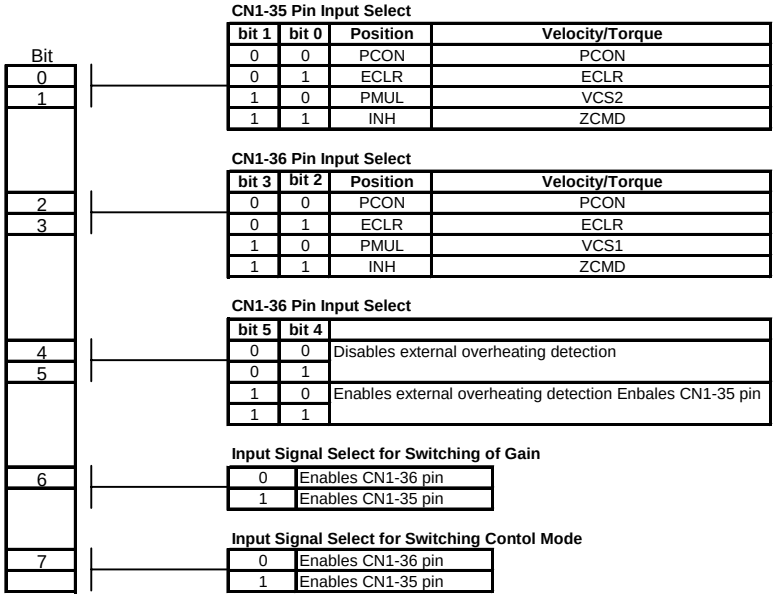
Function Switch 3 — *Func3*

Remote Operator Mode: 2 **Page:** 4 **Default Value:** 00000000 Bit

Function: I/O **Setting Range:** 0,1

Description:

- This parameter allows you to set the CN1-35 and CN1-36 pins to the desired terminals. It also allows you to select the input signal for switching the control mode or gain.



CN1-35 Pin Input Select

bit 1	bit 0	Position	Velocity/Torque
0	0	PCON	PCON
0	1	ECLR	ECLR
1	0	PMUL	VCS2
1	1	INH	ZCMD

CN1-36 Pin Input Select

bit 3	bit 2	Position	Velocity/Torque
0	0	PCON	PCON
0	1	ECLR	ECLR
1	0	PMUL	VCS1
1	1	INH	ZCMD

CN1-36 Pin Input Select

bit 5	bit 4	
0	0	Disables external overheating detection
0	1	
1	0	Enables external overheating detection Enbales CN1-35 pin
1	1	

Input Signal Select for Switching of Gain

0	Enables CN1-36 pin
1	Enables CN1-35 pin

Input Signal Select for Switching Contol Mode

0	Enables CN1-36 pin
1	Enables CN1-35 pin

- Bit 7 is enabled when the switching mode is selected for the control mode.
- Bit 6 is enabled when the gain-switching mode is selected.
- Setting bits 3, 2, 1, and 0 to “1010” in the velocity control mode enables the internal velocity command. Setting bits 3 and 2 “ON”, or 1 and 0 alone does not make this command valid.
- As long as the input signal for control mode or gain switching is assigned to the CN1-35 pin, input signal selection with Func3 Bits 1 and 0 is disabled except for the internal velocity select function. When the input signal for control mode or gain switching is assigned to the CN1-36 pin, input signal selection with Func3 bits 3 and 2 is disabled except for the internal velocity select function. If the internal velocity select function is enabled (Func3, Bits 2 and 0 are set at “1010”), the internally velocity set with the CN1-35 and CN1-36 pins are enabled. At the same time, control mode and gain switching are made valid. This, however, is only effective when the velocity control mode including the control mode-switching mode is selected.
- When the same signal is selected for CN1-35 and CN1-36 pins, the 36 pin take precedence.

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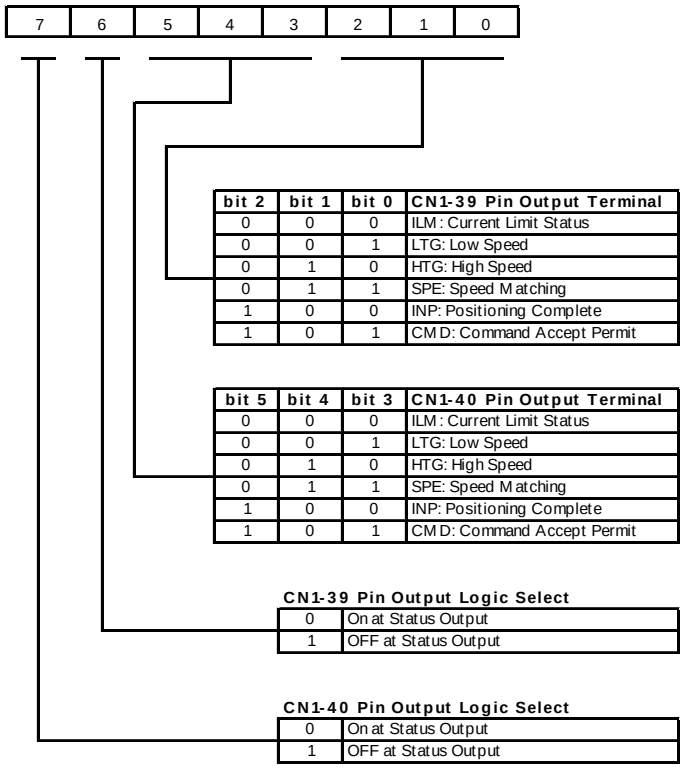
Function Switch 4 — *Func4*

Remote Operator Mode: 2 **Page:** 5 **Default Value:** 00000001 Bit

Function: I/O **Setting Range:** 0,1

Description:

- This parameter allows you to set the CN1-39 and CN1-40 pins to the desired terminals.



bit 2	bit 1	bit 0	CN1-39 Pin Output Terminal
0	0	0	ILM: Current Limit Status
0	0	1	LTG: Low Speed
0	1	0	HTG: High Speed
0	1	1	SPE: Speed Matching
1	0	0	INP: Positioning Complete
1	0	1	CMD: Command Accept Permit

bit 5	bit 4	bit 3	CN1-40 Pin Output Terminal
0	0	0	ILM: Current Limit Status
0	0	1	LTG: Low Speed
0	1	0	HTG: High Speed
0	1	1	SPE: Speed Matching
1	0	0	INP: Positioning Complete
1	0	1	CMD: Command Accept Permit

CN1-39 Pin Output Logic Select

0	On at Status Output
1	OFF at Status Output

CN1-40 Pin Output Logic Select

0	On at Status Output
1	OFF at Status Output

- The standard value is set at 00000100 in the position control mode.

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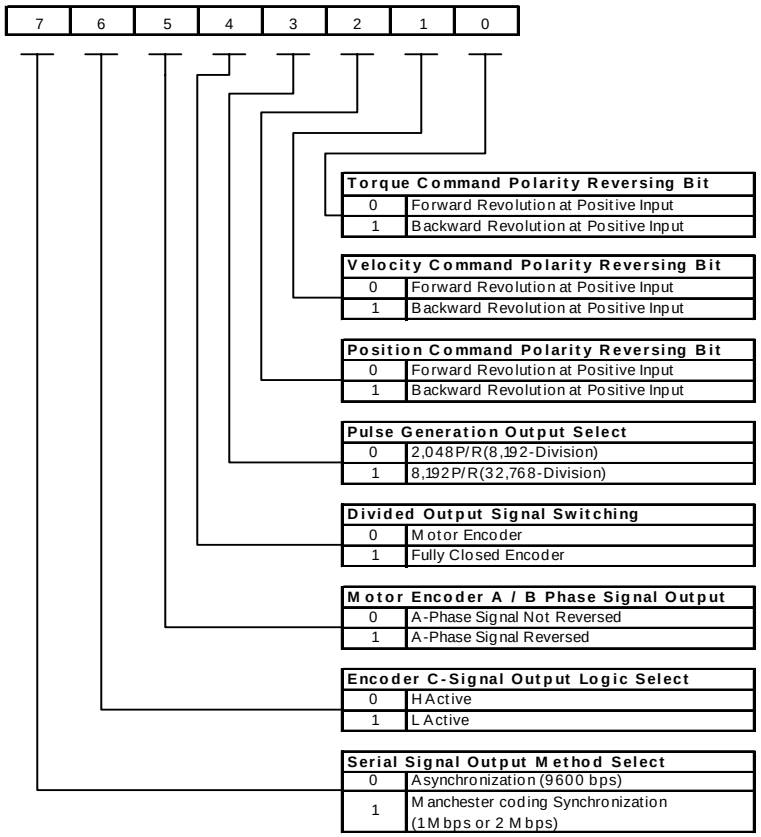
Function Switch 5 — *Func5*

Remote Operator Mode: 2 **Page:** 6 **Default Value:** 00000000 Bit

Function: I/O **Setting Range:** 0,1

Description:

- This parameter is used select the encoder output format or the command input polarity.



- Even if you choose the fully closed encoder using the Func0, Bit 7 parameter, the divided output remains the same.
- The “Fully Closed Encoder” setting can be used only on a servo system that supports the fully closed design.
- Before changing the settings of bits 7, 6, 5, and 4, you must turn off the control power once.
- Forward revolution means counterclockwise revolution as viewed from the load (motor shaft) side.
- Bit 3 is enabled when the ABS-RII absolute sensor is used. The number of incremental pulses to be outputted from CN1-3 to 8 pins can be selected
- Bit 2 of Func5 and Bit 4 of PMOD both function the same. When 1 is set to both bits, the system is rotated forward at the positive input.

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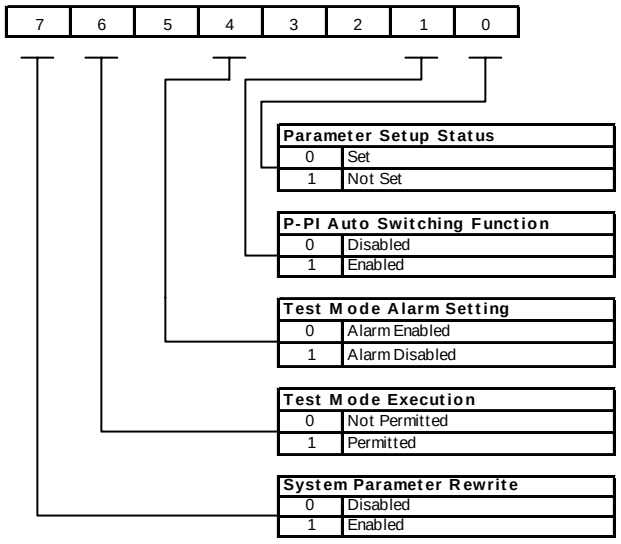
Function Switch 6 — *Func6*

Remote Operator Mode: 2 **Page:** 7 **Default Value:** 00000000 Bit

Function: I/O **Setting Range:** 0,1

Description:

- This parameter is used for changing the contents of parameters or permiting execution of the test mode.



- After operation, Bits 7 and 6 must be set at “0” again.
- Turning “OFF” the control power returns bits 7, 6, and 4 back to “0”.
- If Bit 0 is set to “1”, and alarm (memory error) will be indicated. After the necessary parameter setting is completed, set Bit 0 to “0”, then turn power “ON”.

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Position Loop Gain — *Kp*

Remote Operator Mode: 3 **Page:** 0 **Default Value:** 45 (30) rad/s

Function: Tune **Setting Range:** 1 to 1000 rad/s

Description:

- Proportional gain of the position controller.
- Parameter can also be changed from Mode 0 Page 0.

Velocity Loop, Proportional Gain — *Kvp*

Remote Operator Mode: 3 **Page:** 1 **Default Value:** 100 (70) Hz

Function: Tune **Setting Range:** 10 to 3,000 Hz

Description:

- Proportional gain of the velocity controller (PI control).
- The setting indicates the value when the load inertia is 0.
- Parameter can also be changed from Mode 0 Page 2.

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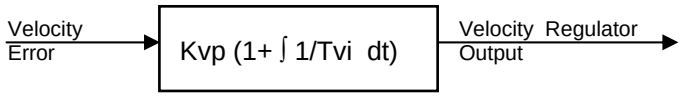
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Velocity Loop, Integral Time Constant — *Tvi*

Remote Operator Mode: 3 **Page:** 2 **Default Value:** 15 (20) ms
Function: Tune **Setting Range:** 1 to 1000 ms

Description:

- Integration time constant of the velocity controller (PI control).



- Parameter can also be changed from Mode 0, Page 3
- If you specify 1000 ms, proportional control is selected.

Velocity Command Zero Adjustment — *Vzero*

Remote Operator Mode: 3 **Page:** 3 **Default Value:** $$$$
Function: Tune **Setting Range:** +/- 16383

Description:

- Offset of the velocity command (adjustment).
- The value varies according to the adjustments done at shipment. You can change the setting by executing offset adjustment of the test mode (Page 2 and 3).

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Torque Command Zero Adjustment — *Tzero*

Remote Operator Mode: 3 **Page:** 4 **Default Value:** $$$$

Function: Tune **Setting Range:** +/-16383

Description:

- Offset of the torque command (adjustment).
- The value varies according to the adjustments done at shipment. You can change the setting by executing offset adjustment of the test mode (Page 2 and 3).

Monitor Output Select #1 — *M1*

Remote Operator Mode: 4 **Page:** 0 **Default Value:** Vm2mV/min^{-1}

Function: **Setting Range:** 17 types

Description:

- This parameter allows you to specify a desired output from 17 types of data from the monitor 1 output (CN1-15 pin and check pin M1) as shown below.

Indication	Contents	
Im 2V/IR	Current Monitor	2 V/IR Peak
Ic 2V/IR	Current Command	2 V/IR Peak
Vm 2mV/min-1	Velocity Monitor	2 mV/min^{-1}
Vm 1mV/min-1	Velocity Monitor	1 mV/min^{-1}
Vm 3mV/min-1	Velocity Monitor	3 mV/min^{-1}
Vc 2mV/min-1	Velocity Command	2 mV/min^{-1}
Vc 1mV/min-1	Velocity Command	1 mV/min^{-1}
Vc 3mV/min-1	Velocity Command	3 mV/min^{-1}
Per 50mV/P	Position Deviation	50 mV/1 Pulse
Per 20mV/P	Position Deviation	20 mV/1 Pulse
Per 10mV/P	Position Deviation	10 mV/1 Pulse
Rm 0.3V/Full	Regenerative Load Factor	0.3 V/Full
Im 0.5 V/IR	Current Monitor	Im0.5V/IR
Ic 0.5 V/IR	Current Command	Ic0.5V/IR
Vm 0.5 mV/min^{-1}	Velocity Monitor	Vm0.5V/min^{-1}
Vc 0.5 mV/min^{-1}	Velocity Command	Vc0.5V/min^{-1}
Per 5 mV/P	Position Deviation	Per5mV/P

- IR is the “Rated Armature Current”.
- Full is the “allowable power of the built-in regenerative resistor”.

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Monitor Output Select #2 — *M2*

Remote Operator Mode: 4 **Page:** 1 **Default Value:** Ic2V/IR

Function: **Setting Range:** 17 Types

Description:

This parameter allows you to specify a desired output from 17 types of data for the monitor 2 output (CN1-16 pin and check pin M2) as shown above.

Gain Switching Select (older models only) — *GAIN*

Remote Operator Mode: 4 **Page:** 2 **Default Value:** Fix

Function: **Setting Range:** 2 Choices

Description:

- Enables gain switching by an external input.

Indication	Contents
Fix	Gain Switching Disabled
Select	Gain Switching Enabled

- Choosing “Select” allows you to switch between Kp, Kvp, and Tvi from screen Mode 8 (use CN1-36 or CN1-35 pin for switching).

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Servo function choice (newer models only) *Func*

Remote Operator Mode: 4 **Page:** 2 **Default Value:** Normal
Function: **Setting Range:** 4 Choices

Description:

- Enable for Gain Switch and automatic tuning.

Indication	Contents
Normal	Gain Switching Disabled. Real time automatic tuning disabled
Gain_Sel.	Gain Switching Enabled. Real time automatic tuning disabled
Gain_Tun	Gain Switching Disabled. Real time automatic tuning enabled
Gsel&Gtun	Gain Switching Enabled. Real time automatic tuning enabled

- Choosing options other than "Normal" allows you to switch between Kp, Kvp, and Tvi from screen Mode 8 (use CN1-36 or CN1-35 pin for switching).
- For Func = "Gain_Sel" with Gain Switch input = OFF

Description	**Parameter**	Mode - Page
Position loop gain	Kp	0-0
Velocity loop proportional gain	Kvp	0-2
Velocity loop integral time constant	Tvi	0-3
Current command LPF	ILPF	0-6

- For Func = "Gain_Sel" with Gain Switch input = ON

Description	**Parameter**	Mode - Page
Position loop gain	Kp2	8-0
Velocity loop proportional gain	Kvp2	8-2
Velocity loop integral time constant	Tvi2	8-3
Current command LPF	ILPF	0-6

- For Func = "Gsel&Gtun" with Gain Switch input = OFF

Description	Parameter	Mode - Page
Position loop gain	Kp	0-0
Velocity loop proportional gain	Kvp	Value of real time automatic tuning result
Velocity loop integral time constant	Tvi	Value of real time automatic tuning result
Current command LPF	ILPF	Value of real time automatic tuning result

- For Func = "Gsel&Gtun" with Gain Switch input = ON

Description	**Parameter**	Mode - Page
Position loop gain	Kp2	8-0
Velocity loop proportional gain	Kvp2	8-2
Velocity loop integral time constant	Tvi2	8-3
Current command LPF	ILPF	0-6

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Control Mode — *TYPE*

Remote Operator Mode: 4 **Page:** 3 **Default Value:** $$$$

Function: **Setting Range:** 6 choices

Description:

- Allows you to choose a desired control mode (position, velocity, and torque).

Indication	Contents
Position	Position Control Type
Velocity	Velocity Control Type
Torque	Torque Control Type
Velocity / Torque	Velocity-to-Torque "Switch-On-the-Fly"
Position / Torque	Position-to-Torque "Switch-On-the-Fly"
Position / Velocity	Position-to-Velocity "Switch-On-the-Fly"

- You can specify a desired control mode from CN1-36 and CN1-35 pins. When Func3, Bit 7 is “0”, pin CN1-36 is enabled. When Bit 7 is “1”, pin CN1-35 is enabled.
- Parameter can also be changed from Mode 0, Page 3.

Encoder Type — *ENKD*

Remote Operator Mode: 4 **Page:** 4 **Default Value:** $$$$

Function: **Setting Range:** 3 types

Description:

- Allows the selection of encoder type used.

Indication	Contents
INC.E	Incremental Encoder with Reduced Wiring
ABS.E (1M)	Absolute Encoder (1 Mbps)
ABS.E (2M)	Absolute Encoder (2 Mbps)

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ABS Sensor Format *ABSF*

Remote Operator Mode: 4 **Page:** 5 **Default Value:** $$$$

Function: **Setting Range:** 11 Formats

Description:

- A desired format can be selected from the following.

2048 FMT
4096 FMT
8192 FMT
16384 FMT
32768 FMT
65536 FMT
131072 FMT
262144 FMT
524288 FMT
1048576 FMT
2097152 FMT

- You must turn “OFF” the control power before making the change.
- Your change is effective only after Func6, Bit 7 has been set a “1”.
- If the above operation (Func6, Bit 7 to “1”) is ignored, the parameter change is invalid, thus, does not take place.

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Motor Type *MOT.*

Remote Operator Mode: 4 **Page:** 6 **Default Value:** $$$$

Function: **Setting Range:** A motor from the P1, P2, P3, P5, P6, and P8 series.

Description:

- Selects the motor used (in each series).
- Selectable motor types vary with the amplifier capacity.

Motor Configuration *MOKD*

Remote Operator Mode: 4 **Page:** 7 **Default Value:** Rotary

Function: **Setting Range:** Rotary

Description:

- This parameter value can not be changed.

Power Supply Type *PSKD*

Remote Operator Mode: 4 **Page:** 8 **Default Value:** AC 200V 1P

Function: **Setting Range:** AC 200V 3P
AC 200V 1P

Description:

- Selects the type of power supply for user connection.

Setting	Description
AC 200V 3P	200-240 VAC, 3 Phase
AC 200V 1P	200-240 VAC, 1 Phase

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Regenerative — *RGKD*

Remote Operator Mode: 4 **Page:** 9 **Default Value:** Built in R

Function: **Setting Range:** Built in R
None/ Ext. R

Description:

- Selects regenerative resistor to use.

Setting	Description
None/ Ext. R	Regenerative resistor is not connected, or external regenerative resistor is used.
Built in R	Built in regenerative resistor is used.

- It is important that the resistor type be set correctly. Overload protection is adjusted based on this setting. Failure to correctly set this value can cause damage to the amplifier.

Position Loop Gain #2 — *Kp2*

Remote Operator Mode: 8 **Page:** 0 **Default Value:** 45 (30) rad/S

Function: **Setting Range:** 1 to 1000 rad/S

Description:

- Proportional gain of the position controller
- Enabled during gain switching

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Velocity Loop Proportional Gain #2 — *Kvp2*

Remote Operator Mode: 8 **Page:** 1 **Default Value:** 100 (70) Hz
Function: **Setting Range:** 10 to 3000 Hz

Description:

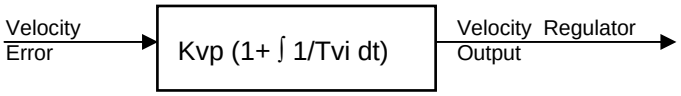
- Proportional gain of the velocity controller
- Enabled during gain switching

Velocity Loop Integral Time Constant #2 — *Tvi2*

Remote Operator Mode: 8 **Page:** 2 **Default Value:** 15 (20) ms
Function: **Setting Range:** 1 to 1000 ms

Description:

- Integration time constant of the velocity controller (proportional integral controller).



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Current Command with Automatic Notch Filter Tuning — *Tn_F*

Remote Operator Mode:	8	**Page:**	3	**Default Value:**	100 %
Function:				**Setting Range:**	30 to (IP/IR) X 100 %

Description:

- User setting value of current command when executing automatic notch filter tuning in test mode.
- Selecting lc=lst on Tune IBEF setting screen enables automatic notch tuning execution at current command of this setting value

Observer – Load Inertia Ratio — *O_JL*

Remote Operator Mode:	8	**Page:**	4	**Default Value:**	100 %
Function:				**Setting Range:**	0 to 3000 %

Description:

- This parameter estimates load torque used for real time automatic tuning processor
- O_JL (%) = load inertia JL / motor inertia JM * 100

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Maintenance and Troubleshooting

Chapter Overview

This chapter contains a maintenance and troubleshooting guide for installation of amplifiers and matching motors.

Chapter Overview 117
Maintenance 118
Troubleshooting 118
Power Element Error *119*
Overload *120*
Amplifier Overheating *120*
Overvoltage *121*
Overspeed *121*
Control Power Supply Error *122*
Sensor Error *122*
Bus Power (R, S, and T) Supply Failure *123*
Bus Power (R, S, and T) Phase Missing *123*
Velocity Control Error *124*
Deviation Overflow (Position) *124*
External (Regeneration Resistor) Overheating *125*
DSP Error *125*
Internal Regeneration Resistor Overheating *126*
Regeneration Error *126*
Memory Error *127*
Absolute Encoder Battery Alarm (not available at this time) *127*
CPU Error *127*
Chapter Overview 128
Acceleration and Deceleration Time 129
Dynamic Brake 130
Stopping Time *130*
Miscellaneous Servo Motor Specifications 132
Direction of Rotation *132*
Holding Brake Specification *132*

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Maintenance

- Normally, the only maintenance required is the removal of superficial dust and dirt from the amplifier. To clean the amplifier, use low-pressure, oil-free compressed air.
- Periodically inspect all cables, verifying they are free from damage and ensuring that the connections to the amplifier are tight.
- Investigate any unusual vibrations or noises immediately.

Troubleshooting

Upon the occurrence of an alarm, the 7-segment display on the amplifier will flash an alarm code. The alarm code or bit will also be set on the output pins on CN1-43, 44, 45, 46 and reported in the alarm trace mode of the Remote Operator and PY Software. Table 21 shows the alarm codes that may appear on a drive or monitoring device.

Table 21: Amplifier Alarm Codes

7-Segment	Abbreviation	Description
1	OC	Overcurrent
2	OL	Overload
3	AOH	Amplifier Overheating
5	OV	Overvoltage
6	OS	Overspeed
7	PE	Control Power Supply Error
8	DE	Detector Error – Encoder Error
9	MPE	Bus power (R, S, and T) Error
A	FP	Fail Phase - bus power (R, S, and T) is missing a phase
C	SE	Speed Control Error
D	OVF	Position Deviation Overflow
E	EXOH	External Regen Resistor Overheating
F	DSPE	DSP Error
H	RGOH	Internal Regen Resistor Overheating
J	RGOL	Resistor Overload
P	MEME	Memory Error
U	AEE	Absolute Encoder Error (Not available at this time)
No Light	CPUE	CPU Error

The table below outlines possible causes and corrective actions for each alarm.

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Power Element Error		
Symbol	**7-Segment Display**	**Alarm code CN1- [46,45,44,43]**
OC	1	0001
Operating Condition	**Cause**	**Corrective Action**
Alarm occurs when the control power supply is turned ON	• Faulty PC board	• Replace the servo amplifier
Alarm occurs when the Start Ready Complete output (SRDY, CN1-41) turns ON, after turning ON the bus power (R, S, and T)	• Faulty PC board	• Replace the servo amplifier
Alarm occurs when Servo On input (SON, CN1-37) turns ON	• Faulty motor ground	• Check ground circuits • Replace motor
	• Faulty Power Module • Faulty current feedback circuit	• Replace the servo amplifier
	• Incorrect motor power wiring	• Check and correct motor wiring
Alarm occurs when the motor starts or stops	• Improper combination of motor and amplifier	• Use the Remote Operator to check and set parameter MOT.

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Overload		
Symbol	**7-Segment Display**	**Alarm code CN1- [46,45,44,43]**
OL	2	0010
Operating Condition	**Cause**	**Corrective Action**
Alarm occurs when the control power supply is turned ON	• Faulty PC board	• Replace servo amplifier
Alarm occurs while the motor is in operation	• The motor is operating over the rated torque	• Review the load requirements and the motor specifications
	• The holding brake is not released	• Release the brake
The motor turns but has very little torque or the Alarm occurs after the motor is operated for a while	• Incorrect wiring of the motor power circuit • Intermittent failure in motor power circuit	• Correct the wiring
	• Improper combination of motor and amplifier	• Use the Remote Operator to check and set parameter MOT.
Load conditions have been verified to be under rated conditions and the alarm occurs	• Faulty PC board	• Replace the servo amplifier
	• Faulty motor encoder	• Replace servo motor

Amplifier Overheating		
Symbol	**7-Segment Display**	**Alarm code CN-1 [46,45,44,43]**
AOH	3	0011
Operating Condition	**Cause**	**Corrective Action**
Alarm occurs when the control power supply is turned ON	• Faulty temperature sensor on PC board	• Replace servo amplifier
Alarm occurs while the motor is in operation	• The ambient temperature of the servo amplifier is greater than 55C	• Take measures to lower the ambient temperature
	• Excess heat generated due to an amplifier failure	• Replace servo amplifier

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Overvoltage

Symbol	7-Segment Display	Alarm code CN1- [46,45,44,43]
OV	5	0101
Operating Condition	**Cause**	**Corrective Action**
Alarm occurs when the control power supply is turned ON	• Faulty PC board	• Replace servo amplifier
Alarm occurs after the bus power (R, S, and T) supply is turned ON for a while	• The input power voltage is high (high-line) • The input power waveform is distorted	• Lower the line voltage below the specification
Alarm occurs while the motor is in operation	• The load inertia is too large for the existing regeneration resistor	• Lower the load inertia • Add or increase the size of the external regen resistor.

Overspeed

Symbol	7-Segment Display	Alarm code CN1- [46,45,44,43]
OS	6	0110
Operating Condition	**Cause**	**Corrective Action**
Alarm occurs when the control power supply is turned ON	• Faulty PC board	• Replace servo amplifier
	• Faulty motor encoder	• Replace servo motor
Alarm occurs while the motor is in operation	• Improper velocity scale setting	• Reset the velocity scale
	• The velocity command is too high	• Reduce the command below the system specification
	• Incorrect encoder wiring	• Correct encoder wiring
	• Faulty encoder	• Replace servo motor
Alarm occurs when the motor starts	• Velocity overshoot is excessive	• Reset servo tuning • Increase the acceleration time

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Control Power Supply Error		
Symbol	**7-Segment Display**	**Alarm code CN1- [46,45,44,43]**
PE	7	0111
Operating Condition	**Cause**	**Corrective Action**
Alarm occurs when the control power supply is turned ON	• The input power supply is below 170VAC	• Raise the line voltage to within the specification
	• The ±15V power is abnormal	• Replace servo amplifier
Alarm occurs while the motor is in operation	• Too large of an input power variation	• Bring input power within specification

Sensor Error		
Symbol	**7-Segment Display**	**Alarm code CN1- [46,45,44,43]**
DE	8	1000
Operating Condition	**Cause**	**Corrective Action**
Alarm occurs when the control power supply is turned ON	• Faulty Encoder	• Replace servo motor
	• Faulty PC board	• Replace servo amplifier
	• Incorrect or disconnected encoder wiring	• Correct encoder wiring
	• Incorrect parameter setting of encoder type	• Use the Remote Operator to check and set parameter ENKD
Alarm occurs after the motor has moved slightly	• Faulty encoder	• Replace servo motor
	• Incorrect or disconnected encoder wiring	• Correct encoder wiring

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Bus Power (R, S, and T) Supply Failure		
Symbol	**7-Segment Display**	**Alarm code CN1- [46,45,44,43]**
MPE	9	1001
Operating Condition	**Cause**	**Corrective Action**
Alarm occurs when the control power supply is turned ON	• Faulty PC board	• Replace servo amplifier
Alarm occurs when the bus power (R, S, and T) supply is turned ON	• The bus power (R, S, and T) voltage is too low	• Bring input power within specification
	• The internal bridge rectifier or fuse is damaged	• Replace servo amplifier
Alarm occurs while the motor is in operation	• Too large of a input power variation	• Bring input power within specification
	• Faulty PC board	• Replace servo amplifier

Bus Power (R, S, and T) Phase Missing		
Symbol	**7-Segment Display**	**Alarm code CN1- [46,45,44,43]**
FP	A	1010
Operating Condition	**Cause**	**Corrective Action**
Alarm occurs when the control power supply is turned ON	• Faulty PC board	• Replace servo amplifier
Alarm occurs when the bus power (R, S, and T) is turned ON	• The three phase power has a phase missing	• Bring input power within specification
	• Bus power (R, S, and T) connections are not tight	• Tighten terminals R, S, and, T on main terminal strip

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Velocity Control Error		
Symbol	**7-Segment Display**	**Alarm code CN1- [46,45,44,43]**
SE	C	1100
Operating Condition	**Cause**	**Corrective Action**
Alarm occurs when the control power supply is turned ON	• Faulty PC board	• Replace servo amplifier
Alarm occurs with Servo ON	• The motor oscillates (vibrates)	• Perform servo tuning • Replace servo amplifier • Replace servo motor
Alarm occurs when a velocity command is entered	• Incorrect motor power wiring	• Correct motor power wiring

Deviation Overflow (Position)		
Symbol	**7-Segment Display**	**Alarm code CN1- [46,45,44,43]**
OVF	d	1101
Operating Condition	**Cause**	**Corrective Action**
Alarm occurs when the control power supply is turned ON	• Faulty PC board	• Replace servo amplifier
	• Command pulses are being sent before the amplifier is ready	• Stop inputting command pulses and enter deviation clear
Alarm occurs during motor operation	• The maximum deviation value is set too low	• Review the deviation over value and position loop gain
	• The load inertia is too large	• Lower the load inertia
	• The holding brake is not released	• Release the brake
	• Incorrect encoder wiring	• Correct encoder wiring
	• High command pulse frequency, resulting in high acceleration rate	• Lower the frequency within specification • Make the commanded velocity lower

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External (Regeneration Resistor) Overheating		
Symbol	**7-Segment Display**	**Alarm code CN1- [46,45,44,43]**
EXOH	E	0011
Operating Condition	**Cause**	**Corrective Action**
Alarm occurs when the control power supply is turned ON	• Faulty PC board	• Replace servo amplifier
	• The H1 and H2 terminals are open	• Correct wiring
	• Faulty external regeneration resistor thermostat	• Replace external regeneration resistor
Alarm occurs during motor operation	• External regeneration resistor thermostat open	• Review working condition
	• Capacity of the external regeneration resistor is too small	• Review application requirements and regeneration resistor sizing.

DSP Error		
Symbol	**7-Segment Display**	**Alarm code CN1- [46,45,44,43]**
DSPE	F	1111
Operating Condition	**Cause**	**Corrective Action**
Alarm occurs when the control power supply is turned ON	• Faulty PC board • The 5V power supply is low • The DSP is malfunctioning	• Replace servo amplifier
Alarm occurs during motor operation	• The 5V power supply is low • The DSP is malfunctioning	• Replace servo amplifier

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Internal Regeneration Resistor Overheating		
Symbol	**7-Segment Display**	**Alarm code CN1- [46,45,44,43]**
RGOH	H	0101
Operating Condition	**Cause**	**Corrective Action**
Alarm occurs when the control power supply is turned ON	• Faulty PC board	• Replace servo amplifier
	• Faulty Thermostat	• Replace servo amplifier
Alarm occurs during motor operation	• Capacity of the internal regeneration resistor is too small	• Review application requirements and regeneration resistor sizing
	• Faulty Thermostat	• Replace servo amplifier

Regeneration Error		
Symbol	**7-Segment Display**	**Alarm code CN1- [46,45,44,43]**
RGOL	J	0101
Operating Condition	**Cause**	**Corrective Action**
Alarm occurs when the control power supply is turned ON	• Faulty PC board	• Replace servo amplifier
Alarm occurs after the bus power (R, S, and T) is turned ON	• Faulty regeneration transistor	• Replace servo amplifier
Alarm occurs during motor operation	• The regeneration capacity is exceeded	• Install an external regeneration resistor
	• The load inertia is too large	• Reduce the load inertia within specification • Make the deceleration time longer • If possible, lower the current limit

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Memory Error		
Symbol	**7-Segment Display**	**Alarm code CN1- [46,45,44,43]**
MEME	P	1111
Operating Condition	**Cause**	**Corrective Action**
Alarm occurs when the control power supply is turned ON	• Faulty PC board • Memory IC failure	• Replace servo amplifier
	• Improper combination of motor and amplifier	• Use the Remote Operator to check and set parameter Func6, Bit 0 to "0"

Absolute Encoder Battery Alarm (not available at this time)		
Symbol	**7-Segment Display**	**Alarm code CN1- [46,45,44,43]**
AEE	U	1000
Operating Condition	**Cause**	**Corrective Action**
Alarm occurs when the control power supply is turned ON	• The battery has less than 20 hours of operation remaining and the absolute encoder position is unreliable	• Replace battery
	• Faulty PC board	• Replace servo amplifier

CPU Error		
Symbol	**7-Segment Display**	**Alarm code CN1- [46,45,44,43]**
CPUE	No Lights	1111
Operating Condition	**Cause**	**Corrective Action**
Light remains OFF after the control power is applied	• The CPU has failed • The 5V power supply is low • Faulty PC board	• Replace servo amplifier
Lights go off during motor operation	• The CPU has failed • The 5V power supply is low	• Replace servo amplifier

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Specifications

Chapter Overview

This chapter contains specifications for the system, amplifiers and motors that are not in the *Product Catalog and Business Policies*.

Chapter Overview 128
Acceleration and Deceleration Time 129
Dynamic Brake 130
Stopping Time *130*
Miscellaneous Servo Motor Specifications 132
Direction of Rotation *132*
Holding Brake Specification *132*

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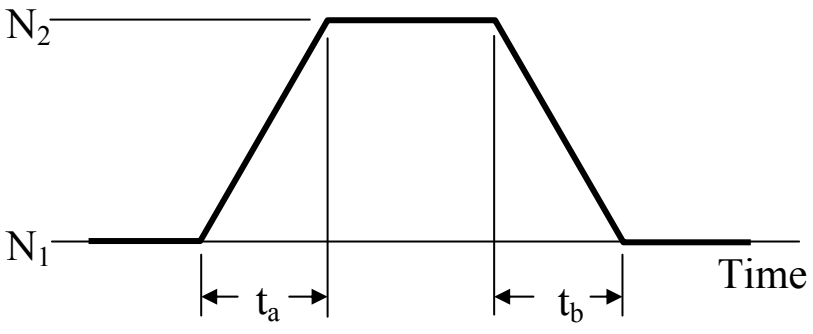
Acceleration and Deceleration Time

The acceleration time (t_a) and deceleration time (t_d) of the motor under certain conditions are calculated by the following expressions. These expressions are for rated speed (or less). Ignore viscosity torque and friction torque(s) of the motor.

Acceleration time $$t_a := \left(J_M + J_L\right) \cdot \frac{(2\pi)}{60} \cdot \frac{N_2 - N_1}{T_P - T_L}$$

Deceleration Time $$t_d := \left(J_M + J_L\right) \cdot \frac{(2\pi)}{60} \cdot \frac{N_2 - N_1}{T_P + T_L}$$

t_a	Acceleration Time [sec]
t_b	Deceleration Time [sec]
N_1	Initial Speed [RPM]
N_2	Final Speed [RPM]
T_P	Maximum Stall Torque [Nm]
T_L	Load Torque [Nm]
J_M	Motor Inertia [kg m^2]
J_L	Load Inertia [kg m^2]



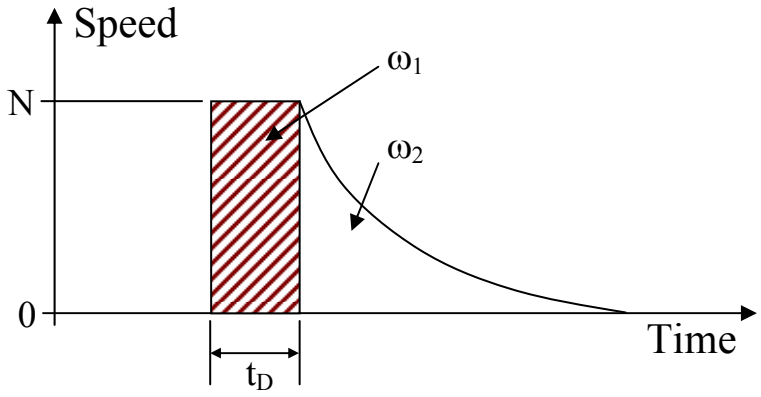
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Dynamic Brake

The PY servo amplifier is designed with an internal dynamic brake for stopping. The brake is activated when an alarm is detected. The following explains the dynamic brake characteristics and allowable operating frequency.

Stopping Time



$$\omega_1 := \frac{2\pi \cdot N \cdot t_D}{60} \qquad \omega_2 := \left(J_M + J_L\right) \cdot \left(\alpha \cdot N + \beta \cdot N^3\right) \qquad \omega_3 := \left(\frac{J_M + J_L}{2 \cdot T_L}\right) \cdot \left(\frac{2 \cdot \pi \cdot N}{60}\right)^2$$

No Load Torque

$$\omega_{t1} := \omega_1 + \omega_2$$

With Load Torque

$$\omega_{t2} := \omega_1 + \frac{\omega_2 \cdot \omega_3}{\left(\omega_2 + \omega_3\right)}$$

N	Motor speed [RPM]
J_M	Motor inertia [kg m^2]
J_L	Load inertia [kg m^2]
T_L	Load torque, acting to slow the motor [N m]
ω_1	Distance traveled during processing delay (assume T_L=0)
ω_2	Distance travel while slowing from N to a stop (assume T_L=0)
ω_3	Reduction in distance traveled as a result of a load torque T_L
ω_{t1} ω_{t2}	Total distance traveled [revolutions]
α	Motor Constant
β	Motor Constant

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Drive Model	Motor Model	t_D [sec]	Dynamic Brake Constants		
			α	β	J_M [kg m^2]
PY2A015	P30B04010D	0.0100	25	12.2×10^{-7}	0.051×10^{-4}
PY2A015	P50N05020D	0.0100	9.78	3.86×10^{-7}	0.173×10^{-4}
PY2A030	P30B06040D	0.0100	4.32	6.8×10^{-7}	0.255×10^{-4}
PY2A030	P30B08075D	0.0100	2.97	3.68×10^{-7}	0.635×10^{-4}
PY2A050	P50N08100D	0.0100	2.99	0.30×10^{-7}	2.66×10^{-4}
PY2A050	P60B13150H	0.0100	1.08	0.60×10^{-7}	8.30×10^{-4}
PY2A050	P20B10150D	0.0240	2.19	1.05×10^{-7}	2.04×10^{-4}
PY0A015	P30B04010D	0.0065	25	12.2×10^{-7}	0.051×10^{-4}
PY0A015	P50N05020D	0.0065	9.78	3.86×10^{-7}	0.173×10^{-4}
PY0A030	P30B06040D	0.0065	4.32	6.8×10^{-7}	0.255×10^{-4}
PY0A030	P30B08075D	0.0065	2.97	3.68×10^{-7}	0.635×10^{-4}
PY0A050	P50N08100D	0.0100	2.99	0.30×10^{-7}	2.66×10^{-4}
PY0A050	P60B13150H	0.0100	1.08	0.60×10^{-7}	8.30×10^{-4}
PY0A050	P20B10150D	0.0240	2.19	1.05×10^{-7}	2.04×10^{-4}
PY0A100	P20B10250D	0.0240	2.87	0.26×10^{-7}	3.71×10^{-4}
PY0A100	P20B13300D	0.0240	2.02	0.25×10^{-7}	7.14×10^{-4}
PY0A150	P20B13500D	0.0240	1.54	0.07×10^{-7}	12.58×10^{-4}

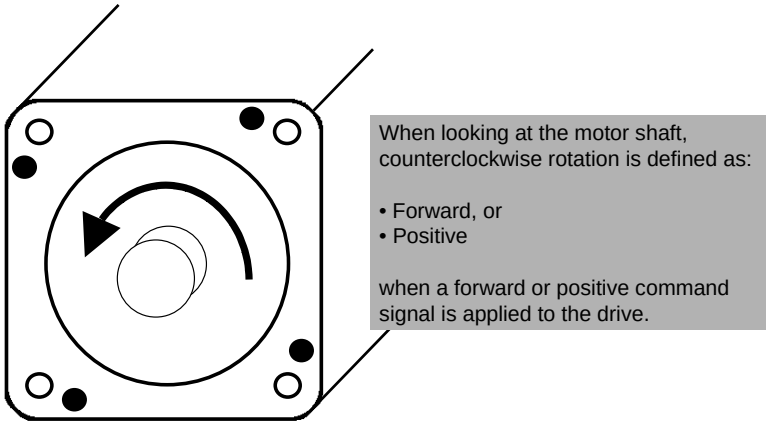
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Miscellaneous Servo Motor Specifications

Direction of Rotation

For the standard setting, the servomotor revolves counterclockwise, as viewed from the shaft when a positive velocity command or forward position (pulse) command is applied. By changing parameters with the Remote Operator, the direction of rotation with the same positive command can be reversed (Func5, Bit 1 for Velocity Command. Func5, Bit 2 for Position Command).



Holding Brake Specification

The optional brake is for holding only and should not be used to stop the motor. Turn "ON" and "OFF" the brake using the holding brake signal output HBON, CN1-42. The specifications for the holding brake are in the table below.

Table 22: Holding Brake Specifications

Motor Model	Static friction Torque [N m]	Release time varistor (diode) [mS]	Set Time [mS]
P60B13150H	9.0	30 (140)	100
P50N05020D	0.353	10 (100)	15
P50N08100D	2.94	20 (200)	30
P30B04010D	0.32	15 (100)	25
P30B06040D	1.274	20 (120)	30
P30B08075D	2.38	20 (200)	40
P20B10150D	7.84	50 (200)	60
P20B10250D	9.4	30 (140)	100
P20B13300D	11.4	30 (140)	100
P20B13500D	18.1	50 (150)	120

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Index

7

7-Segment Display 55

A

A Encoder Input CN2-3 45
A Encoder Output CN1-3 41
ABS Sensor Format 111
ABSF Parameter 111
Absolute Encoder Battery Alarm 127
AC Power ..... *See* Bus Power
Acceleration Time 88
Acceleration/Deceleration Time 129
AEE Error Code 127
Alarm
- 7-Segment Display 118
- Codes 118
- History Trace Screen 75
- Output 44
- Output Active High or Low 98, 99
- Output Bit 98, 99
- Output Code 98, 99
- Reset 42
- Troubleshooting 118

Alarm Reset Sequence 61
ALOG Bit Parameter 98, 99
AMOD Bit Parameter 98, 99
Amplifier
- Clearance Requirements 16
- Enclosure Size 19
- Environmental Requirements 18
- Humidity 18
- Input Power 33
- Installation 15
- Leakage Current 33
- Maintenance 118
- Overheating 120
- Parameters 77
- Power Dissipation 18
- Shock 18
- Status Display 55
- Temperature 18
- Tuning 71
- Vibration 18

AOH Error Code 120

B

B Encoder Input CN2-5 45
Bus Power (CN3-1 and CN3-2)
- TB Connections 38

Bus Power (R, S, and T)
- Capacity Requirements 33
- Phase Missing 123
- Supply Failure 123
- Wire Size 32

C

C Encoder Input CN2-7 45
Cable Routing
- Orientation 23

Cables 12
Clear Deviation Error 43
Clearance Requirements 16
CN1-35 Program 101, 102, 103, 104
CN1-36 Program 101, 102, 103, 104
CN3 Terminal Board Connector 38
CN4 Terminal Board Connector 38
CN5 Terminal Board Connector 38
Combustible Gas Environment 15
Command Direction 97
Connection Diagram
- Drive with P2 Motor 36

Connectors
- Bus Power (R, S, and T) 38
- CN1 Control Connector 41
- CN1 Internal Circuits 40
- CN2 Motor Encoder 45
- Control Power 38
- Motor Connector Orientation 23
- Motor Power 38
- Regen Resistor 38
- Remote Operator Terminal 46
- TB Connector 38

Control Mode 110
Control Power
- Supply Error 122
- TB Connections 38
- Wire Size 32

Corrosive Gas Environment 15
CPU Error 127
CPUE Error Code 127
Current Command
- *Band Eliminate Filter* 86, 87

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BEF Enable 98, 99
Low Pass Filter 85
Current Limit
Control Source 98, 99
Internal Value 94
Negative Input, Analog 42
Parameters 79
Permit 42
Positive Input, Analog 42
Sequence 95

D

DE Error Code 122
Deceleration Time 89
Deviation, Position
Clear 98, 99
Error 43
Overflow 124
DFC0 Bit Parameter 97
DFC1 Bit Parameter 97
Direction of Rotation 132
Drive ..... *See* Amplifier
Drive Systems, Valid Combination 11
DSP Error 125
DSPE Error Code 125
Dust And Oil Environments 15
Dynamic Brake 130

E

ECLR Bit Parameter 101, 102, 103, 104
EENP Parameter 96
EGER Parameter 91
Electrical Noise Environments 15
Electronic Gear Ratio 91
Enable System Parameter Changes 101, 102, 103, 104
Enclosure Size 19
Encoder
5 Volt Power 45
C Channel Open Collector Output 41
CN2 Connector 45
Preventing Damage 25
Pulse Number 96
Encoder Type 110
ENCR Parameter 92
ENKD Parameter 110
Environmental Requirements 18
EXOH Error Code 125
Explosive Gas Environment 15
External (Regeneration Resistor)
Overheating 125

F

Feed Forward Gain 83
Feed Forward, Low Pass Filter 85
FLPF Parameter 85
Fluids, Prevention Against 23
Following Error Limit 90
FP Error Code 123
Func0 Parameter 98
Func1 Parameter 99
Func2 Parameter 100
Func3 Parameter 101
Func4 Parameter 102
Func5 Parameter 103
Func6 Parameter 104
Function Switch 0 98
Function Switch 1 99
Function Switch 2 100
Function Switch 3 101
Function Switch 4 102
Function Switch 5 103
Function Switch 6 104

G

GAIN Parameter 108
Gain Switching Select 108
Gearbox 24
Gears and Pulleys 25

H

High Speed 93
HOFF Bit Parameter 100
Holding Brake
Output 44
Specification 132
Time 100
Holding Brake Excitation Timing 95
HTG Parameter 93

I

IBEF Bit Parameter 98, 99
IBEF Parameter 86, 87
IILM Parameter 94
ILPF Parameter 85
IMOD Bit Parameter 98, 99
INH Bit Parameter 101, 102, 103, 104
INP Parameter 90
In-Position Window 90
Input Power 33
Input sequence power supply 42
In-Rush Current 33
Inspection Procedure 14
Installation
Drive 15
Motor 20
Interface Circuits 40
Internal Regeneration Resistor Overheating 126
Internal Velocity Command Value #1 93
Internal Velocity Command Value #2 94
Internal Velocity Command Value #3 94
IP Rating 23

J

Jogging 69

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K

KAO Bit Parameter 98, 99
Kff Parameter 83
Kp Parameter 83, 105
Kvp Parameter 84, 105
KvpA Parameter 89

L

Leakage Current 33
List of Tables 4
Low Speed 92
LTG Parameter 92

M

M1 Bit Parameter 100
M1 Parameter 107
M1R Bit Parameter 100
M2 Bit Parameter 100
M2 Parameter 107
M2R Bit Parameter 100
Maintenance 118
Manual Tuning 73
MEME Error Code 127
Memory Error 127
MENP Parameter 96
MON2 Output CN1-16 41
Monitor
  Output 1 41
  Output 1 Absolute Value 100
  Output 1 Polarity 100
  Output 2 41
  Output 2 Absolute Value 100
  Output 2 Polarity 100
  Remote Operator Screen 74
Monitor Output Select #1 107
Monitor Output Select #2 107
MOT Parameter 112, 113
Motor
  Ambient Temperature 20
  Bearing Specifications 26
  Connecting the Load 24
  Couplings 24
  Encoder ..... *See* Encoder
  Environmental Requirements 20
  Humidity 20
  Installation 20
  IP Rating 23
  Leakage Current 33
  Maintenance 118
  Orientation 23
  P2 Mounting Dimensions 21, 22
  P3 Mounting Dimensions 21
  Power Connection 38
  Radial and Thrust Loads 26
Motor Power
  Wire Size 32
Motor Type 112, 113
MPE Error Code 123

N

National Electric Code 31
Negative Current Limit Input 42
Negative Pulse Command 42
Negative Rotation Overtravel 43
NOB Bit Parameter 98, 99
NPC Bit Parameter 97
Number of Pulses of Fully Closed Encoder 96

O

OC Error Code 119
Oil And Dust Environments 15
OL Error Code 120
OS Error Code 121
Output Pulse Divide Ratio 92
Output sequence power common 42
Output Sequence Power Supply 43
OV Error Code 121
Overload 120
Overspeed 121
Overtravel
  Negative Rotation 43
  Positive Rotation 43
Overvoltage 121
OVF Error Code 124
OVF Parameter 90

P

PCON Bit Parameter 101, 102, 103, 104
PE Error Code 122
PM1 Bit Parameter 97
PM2 Bit Parameter 97
PMOD Parameter 97
PMUL Bit Parameter 101, 102, 103, 104
PMUL Parameter 91
Position Command
  Edge or Level Sensitive 98, 99
  Low Pass Filter Time Constant 87
  Pulse Multiplier 91
  Pulse Train Pattern 97
  Type 97
Position Loop
  Gain 83, 105
Positive Current Limit Input 42
Positive Pulse Command 42
Positive Rotation Overtravel 43
Power Dissipation 18
Power Element Error 119
Power On Sequence 56
PPC Bit Parameter 97
Product Support ..... *See* Technical Support
Proportional Control Input 43
Pulleys and Gears 25

R

Radial Load Limits 26
Regeneration Resistor

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Connections 51
Error 126
Mounting 52
Over Load time selection 100
Power Connections 38
Selection 50
Thermostat Wire Size 32
Regeneration Resistors
External 47
Remote Operator 11
Modes 65
Operation 64
Remote Operator Terminal 46
REV Bit Parameter 98, 99
RGOH Error Code 126
RGOL Bit Parameter 100
RGOL Error Code 126
RV Bit Parameter 97

S

Safety 7
SE Error Code 124
SEIH Bit Parameter 100
Sensor Error 122
Servo OFF Sequence 59
Servo ON 43
SILM Parameter 95
SPC Bit Parameter 101, 102, 103, 104
Speed control Error (SE) Detection 100
Speed Matching Width 93
Start Ready Complete Output 44
Status Display 55
Step and Direction Command Type 97
Stop Sequences 57
Support ..... *See* Technical Support
Syntax, Manual 6

T

TCMS Parameter 96
TCOP Bit Parameter 100
Technical Support
E-Mail Support 9
Field Service 9
Online Support 9
Telephone Support 9
TEST Bit Parameter 101, 102, 103, 104
Test Mode Enable 101, 102, 103, 104
THB Parameter 95
Thrust Load Limits 26
Torque Command 42
Polarity 98, 99
Scale Adjustment 96
Torque Comp Input (CN1-22) effectiveness 100
Torque Compensation 42
Torque Loop
Zero Adjustment 106
Tpcm Parameter 87
Transformer Size 33
Troubleshooting 118
Tuning 71
Auto 71, 74, 75
Manual 73
Tvac Parameter 88
Tvde Parameter 89
Tvi Parameter 84, 105
Tvi2 Parameter 113, 114, 115
TYPE Parameter 110
Typefaces 6
Tzero Parameter 106

U

Unpacking 14

V

Valid Drive Systems 11
VCI1 Parameter 93
VCI2 Parameter 94
VCI3 Parameter 94
VCMS Parameter 95
Velocity Clamp 101, 102, 103, 104
Velocity Command 42
Clamp 101, 102, 103, 104
Low Pass Filter 85
Low Pass Filter Enable 98, 99
Polarity 98, 99
Scale Adjustment 95
Velocity Control Error 124
Velocity Control Parameters 78, 79
Velocity Loop
Integral Time Constant 84, 105
Integral Time Constant #2 .. 113, 114, 115
Proportional Gain 84, 105
Proportional Gain Addition 89
Zero Adjustment 106
VLPF Bit Parameter 98, 99
VLPF Parameter 85
Vzero Parameter 106

W

Wire Sizes 32

X

XE Parameter 93

Z

ZCLP Bit Parameter 101, 102, 103, 104

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