



Operating Guide

VLT[®] Midi Drive FC 280



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1 Introduction

1.1 Purpose of the Manual

This operating guide provides information for safe installation and commissioning of the VLT® Midi Drive FC 280 frequency converter.

The operating guide is intended for use by qualified personnel.

To use the frequency converter safely and professionally, read and follow the operating guide. Pay particular attention to the safety instructions and general warnings. Always keep this operating guide with the frequency converter.

VLT® is a registered trademark.

1.2 Additional Resources

Resources available to understand advanced frequency converter functions, programming, and maintenance:

- *VLT® Midi Drive FC 280 Design Guide*, provides detailed information about the design and applications of the frequency converter.
- *VLT® Midi Drive FC 280 Programming Guide*, provides information on how to program and includes complete parameter descriptions.

Supplementary publications and manuals are available from Danfoss. See drives.danfoss.com/knowledge-center/technical-documentation/ for listings.

1.3 Document and Software Version

This manual is regularly reviewed and updated. All suggestions for improvement are welcome. *Table 1.1* shows the document version and the corresponding software version.

Edition	Remarks	Software version
MG07A4	Software update and more information for POWERLINK.	1.4

Table 1.1 Document and Software Version

1.4 Product Overview

1.4.1 Intended Use

The frequency converter is an electronic motor controller intended for:

- Regulation of motor speed in response to system feedback or to remote commands from external controllers. A power drive system consists of the frequency converter, the motor, and equipment driven by the motor.
- System and motor status surveillance.

The frequency converter can also be used for motor overload protection.

Depending on configuration, the frequency converter can be used in standalone applications or form part of a larger appliance or installation.

The frequency converter is allowed for use in residential, industrial, and commercial environments in accordance with local laws and standards.

NOTICE

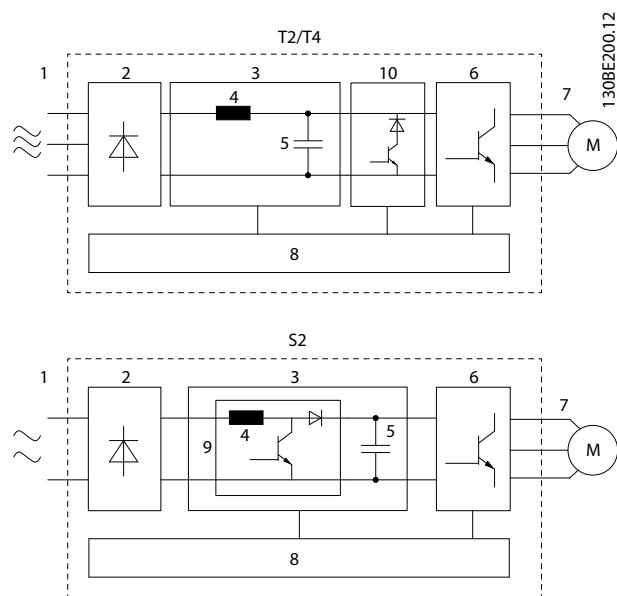
In a residential environment, this product can cause radio interference, in which case supplementary mitigation measures may be required.

Foreseeable misuse

Do not use the frequency converter in applications which are non-compliant with specified operating conditions and environments. Ensure compliance with the conditions specified in *chapter 9 Specifications*.

1.4.2 Block Diagram of the Frequency Converter

Illustration 1.1 is a block diagram of the internal components of the frequency converter.



Area	Component	Functions
1	Mains input	AC mains supply to the frequency converter.
2	Rectifier	The rectifier bridge converts the AC input to DC current to supply inverter power.
3	DC bus	Intermediate DC-bus circuit handles the DC current.
4	DC reactor	- Filters the intermediate DC circuit current. - Provides mains transient protection. - Reduces the root mean square (RMS) current. - Raises the power factor reflected back to the line. - Reduces harmonics on the AC input.
5	Capacitor bank	- Stores the DC power. - Provides ride-through protection for short power losses.
6	Inverter	Converts the DC into a controlled PWM AC waveform for a controlled variable output to the motor.

Area	Component	Functions
7	Output to motor	Regulated 3-phase output power to the motor.
8	Control circuitry	- Input power, internal processing, output, and motor current are monitored to provide efficient operation and control. - User interface and external commands are monitored and performed. - Status output and control can be provided.
9	PFC	Power factor correction changes the waveform of current which is drawn by the frequency converter to improve the power factor.
10	Brake chopper	Brake chopper is used in the DC intermediate circuit to control DC voltage when the load feeds energy back.

Illustration 1.1 Example of Block Diagram for a Frequency Converter

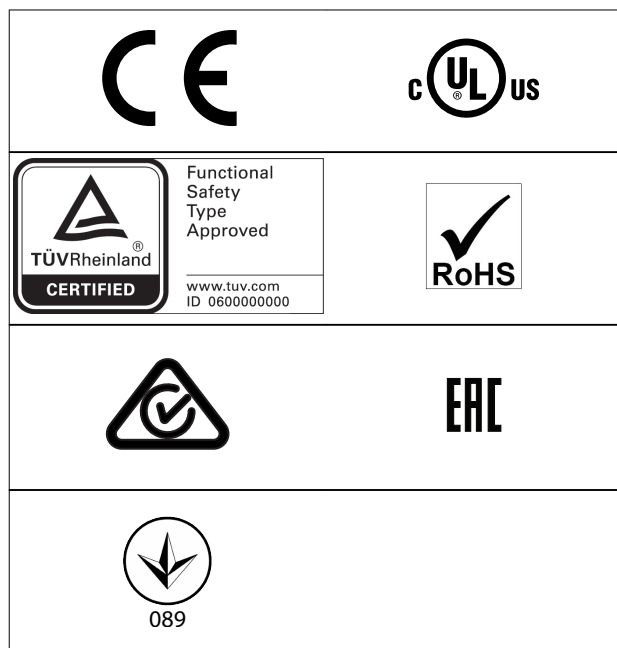
1.4.3 Enclosure Sizes and Power Ratings

For enclosure sizes and power ratings of the frequency converters, refer to *chapter 9.9 Enclosure Sizes, Power Ratings, and Dimensions*.

1.4.4 Safe Torque Off (STO)

The VLT® Midi Drive FC 280 frequency converter supports Safe Torque Off (STO). See *chapter 6 Safe Torque Off (STO)* for details about the installation, commissioning, maintenance, and technical data of STO.

1.5 Approvals and Certifications



For compliance with the European Agreement concerning International Carriage of Dangerous Goods by Inland Waterways (ADN), refer to the *chapter ADN-compliant Installation* in the *VLT® Midi Drive FC 280 Design Guide*.

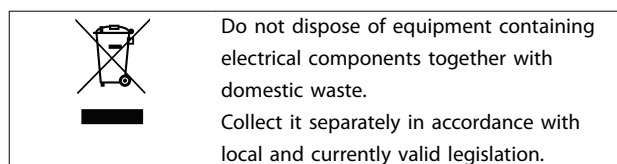
The frequency converter complies with UL 508C thermal memory retention requirements. For more information, refer to the *chapter Motor Thermal Protection* in the *VLT® Midi Drive FC 280 Design Guide*.

Applied standards and compliance for STO

Using STO on terminals 37 and 38 requires fulfillment of all provisions for safety including relevant laws, regulations, and guidelines. The integrated STO function complies with the following standards:

- IEC/EN 61508:2010, SIL2
- IEC/EN 61800-5-2:2007, SIL2
- IEC/EN 62061:2015, SILCL of SIL2
- EN ISO 13849-1:2015, Category 3 PL d

1.6 Disposal



2 Safety

2.1 Safety Symbols

The following symbols are used in this document:

⚠ WARNING

Indicates a potentially hazardous situation that could result in death or serious injury.

⚠ CAUTION

Indicates a potentially hazardous situation that could result in minor or moderate injury. It can also be used to alert against unsafe practices.

NOTICE

Indicates important information, including situations that can result in damage to equipment or property.

2.2 Qualified Personnel

Correct and reliable transport, storage, installation, operation, and maintenance are required for the trouble-free and safe operation of the frequency converter. Only qualified personnel are allowed to install or operate this equipment.

Qualified personnel are defined as trained staff, who are authorized to install, commission, and maintain equipment, systems, and circuits in accordance with pertinent laws and regulations. Also, the personnel must be familiar with the instructions and safety measures described in this guide.

2.3 Safety Precautions

⚠ WARNING

HIGH VOLTAGE

Frequency converters contain high voltage when connected to AC mains input, DC supply, or load sharing. Failure to perform installation, start-up, and maintenance by qualified personnel can result in death or serious injury.

- Only qualified personnel must perform installation, start-up, and maintenance.
- Before performing any service or repair work, use an appropriate voltage measuring device to make sure that there is no remaining voltage on the drive.

⚠ WARNING

UNINTENDED START

When the frequency converter is connected to AC mains, DC supply, or load sharing, the motor may start at any time. Unintended start during programming, service, or repair work can result in death, serious injury, or property damage. The motor can start with an external switch, a fieldbus command, an input reference signal from the LCP, via remote operation using MCT 10 Set-up Software, or after a cleared fault condition.

To prevent unintended motor start:

- Disconnect the frequency converter from the mains.
- Press [Off/Reset] on the LCP before programming parameters.
- Completely wire and assemble the frequency converter, motor, and any driven equipment before connecting the frequency converter to AC mains, DC supply, or load sharing.

⚠ WARNING

DISCHARGE TIME

The frequency converter contains DC-link capacitors, which can remain charged even when the frequency converter is not powered. High voltage can be present even when the warning LED indicator lights are off. Failure to wait the specified time after power has been removed before performing service or repair work can result in death or serious injury.

- Stop the motor.
- Disconnect AC mains and remote DC-link supplies, including battery back-ups, UPS, and DC-link connections to other frequency converters.
- Disconnect or lock PM motor.
- Wait for the capacitors to discharge fully. The minimum waiting time is specified in *Table 2.1*.
- Before performing any service or repair work, use an appropriate voltage measuring device to make sure that the capacitors are fully discharged.

Voltage [V]	Power range [kW (hp)]	Minimum waiting time (minutes)
200–240	0.37–3.7 (0.5–5)	4
380–480	0.37–7.5 (0.5–10)	4
	11–22 (15–30)	15

Table 2.1 Discharge Time

⚠ WARNING

LEAKAGE CURRENT HAZARD

Leakage currents exceed 3.5 mA. Failure to ground the frequency converter properly can result in death or serious injury.

- Ensure the correct grounding of the equipment by a certified electrical installer.

⚠ WARNING

EQUIPMENT HAZARD

Contact with rotating shafts and electrical equipment can result in death or serious injury.

- Ensure that only trained and qualified personnel perform installation, start-up, and maintenance.
- Ensure that electrical work conforms to national and local electrical codes.
- Follow the procedures in this guide.

⚠ CAUTION

INTERNAL FAILURE HAZARD

An internal failure in the frequency converter can result in serious injury when the frequency converter is not properly closed.

- Ensure that all safety covers are in place and securely fastened before applying power.

3 Mechanical Installation

3.1 Unpacking

3.1.1 Items Supplied

Items supplied may vary according to product configuration.

- Make sure that the items supplied and the information on the nameplate correspond to the order confirmation.
- Check the packaging and the frequency converter visually for damage caused by inappropriate handling during shipment. File any claim for damage with the carrier. Retain damaged parts for clarification.



1	Product logo
2	Product name
3	Disposal
4	CE mark
5	Serial number
6	TÜV logo
7	UkrSEPRO logo
8	Barcode
9	Country of origin
10	Reference to enclosure type
11	EAC logo
12	RCM logo
13	UL reference
14	Warning specifications
15	UL logo
16	IP rating
17	Output voltage, frequency, and current (at low/high voltages)
18	Input voltage, frequency, and current (at low/high voltages)
19	Power rating
20	Ordering number
21	Type code

Illustration 3.1 Product Nameplate (Example)

NOTICE

Do not remove the nameplate from the frequency converter (loss of warranty).

For more information of the type code, refer to the chapter Type Code in the VLT® Midi Drive FC 280 Design Guide.

3.1.2 Storage

Ensure that requirements for storage are fulfilled. Refer to *chapter 9.4 Ambient Conditions* for further details.

3.2 Installation Environment

NOTICE

In environments with airborne liquids, particles, or corrosive gases, ensure that the IP/Type rating of the equipment matches the installation environment. Failure to meet requirements for ambient conditions can reduce lifetime of the frequency converter. Ensure that requirements for air humidity, temperature, and altitude are met.

Vibration and shock

The frequency converter complies with requirements for units mounted on the walls and floors of production premises, and in panels bolted to walls or floors.

For detailed ambient conditions specifications, refer to *chapter 9.4 Ambient Conditions*.

3.3 Mounting

NOTICE

Improper mounting can result in overheating and reduced performance.

Cooling

- Ensure 100 mm (3.9 in) of top and bottom clearance for air cooling.

Lifting

- To determine a safe lifting method, check the weight of the unit, see *chapter 9.9 Enclosure Sizes, Power Ratings, and Dimensions*.
- Ensure that the lifting device is suitable for the task.
- If necessary, plan for a hoist, crane, or forklift with the appropriate rating to move the unit.
- For lifting, use hoist rings on the unit, when provided.

Mounting

To adapt the mounting holes of VLT® Midi Drive FC 280, contact the local Danfoss supplier to order a separate backplate.

To mount the frequency converter:

1. Ensure that the mounting location is strong enough to support the unit weight. The frequency converter allows side-by-side installation.
2. Place the unit as close to the motor as possible. Keep the motor cables as short as possible.

3. Mount the unit vertically to a solid flat surface or to the optional backplate to provide cooling airflow.
4. When provided, use the slotted mounting holes on the unit for wall mounting.

NOTICE

For dimensions of mounting holes, see *chapter 9.9 Enclosure Sizes, Power Ratings, and Dimensions*.

3.3.1 Side-by-side Installation

Side-by-side installation

All VLT® Midi Drive FC 280 units can be installed side by side in vertical or horizontal position. The units do not require extra ventilation on the side.

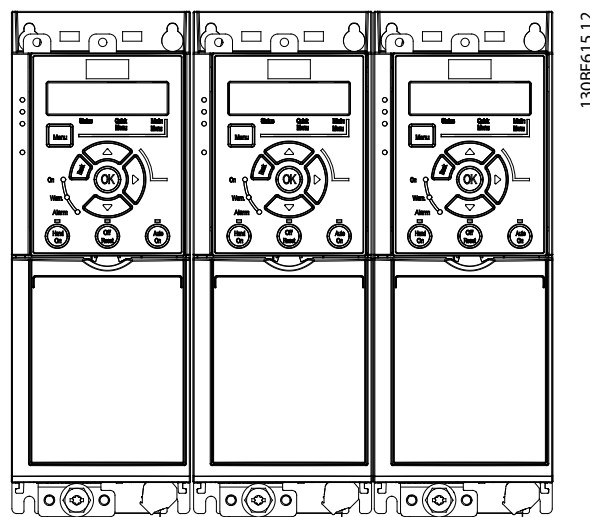


Illustration 3.2 Side-by-side Installation

NOTICE

RISK OF OVERHEATING

If IP21 conversion kit is used, mounting the units side by side could lead to overheating and damage to the unit.

- Avoid mounting the units side by side if IP21 conversion kit is used.

3.3.2 Horizontal Mounting

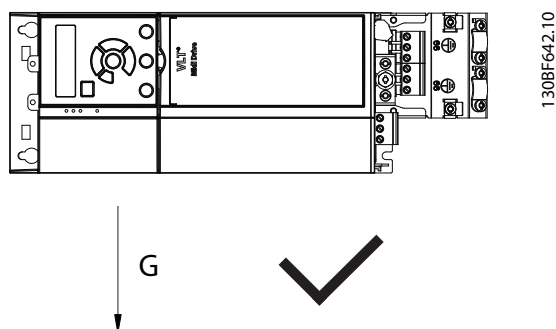


Illustration 3.3 Right Way of Horizontal Mounting (Left Side Downwards)

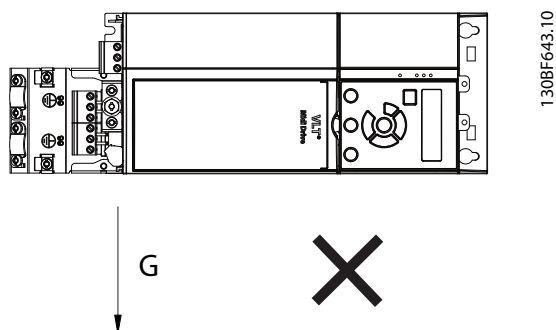


Illustration 3.4 Wrong Way of Horizontal Mounting (Right Side Downwards)

3.3.3 Bus Decoupling Kit

The bus decoupling kit ensures mechanical fixation and electrical shielding of cables for the following control cassette variants:

- Control cassette with PROFIBUS.
- Control cassette with PROFINET.
- Control cassette with CANopen.
- Control cassette with Ethernet.
- Control cassette with POWERLINK.

Each bus decoupling kit contains 1 horizontal decoupling plate and 1 vertical decoupling plate. Mounting the vertical decoupling plate is optional. The vertical decoupling plate provides better mechanical support for PROFINET, Ethernet, and POWERLINK connectors and cables.

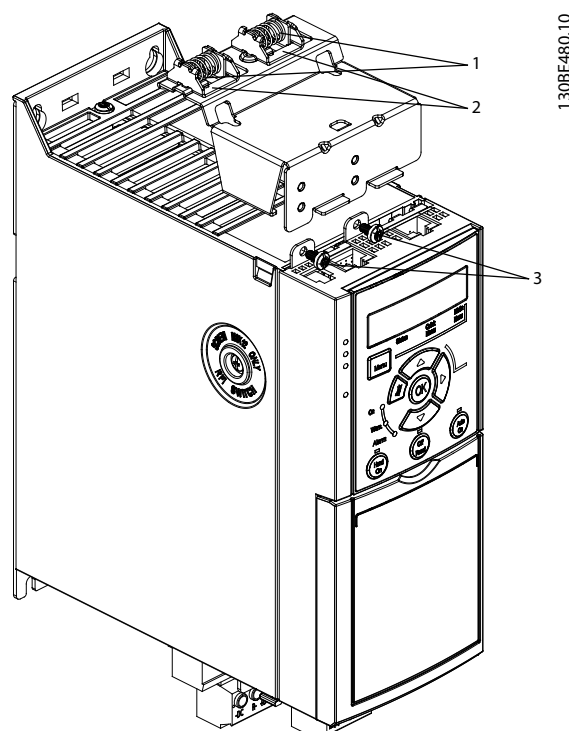
3.3.4 Mounting

To mount the bus decoupling kit:

1. Place the horizontal decoupling plate on the control cassette mounted on the frequency converter and fasten the plate using 2 screws as shown in *Illustration 3.5*. Tightening torque is 0.7–1.0 Nm (6.2–8.9 in-lb).
2. Optional: Mount the vertical decoupling plate as follows:
 - 2a Remove the 2 mechanical springs and 2 metal clamps from the horizontal plate.
 - 2b Mount the mechanical springs and metal clamps on the vertical plate.
 - 2c Fasten the plate with 2 screws as shown in *Illustration 3.6*. Tightening torque is 0.7–1.0 Nm (6.2–8.9 in-lb).

NOTICE

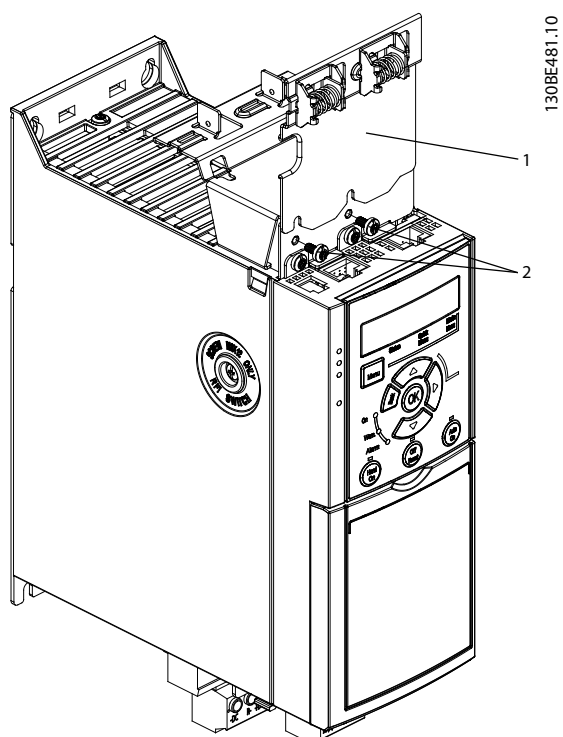
If the IP21 top cover is used, do not mount the vertical decoupling plate, because its height affects the proper installation of the IP21 top cover.



1	Mechanical springs
2	Metal clamps
3	Screws

Illustration 3.5 Fasten the Horizontal Decoupling Plate with Screws

3



1	Vertical decoupling plate
2	Screws

Illustration 3.6 Fasten the Vertical Decoupling Plate with Screws

Both *Illustration 3.5* and *Illustration 3.6* show Ethernet based connectors (RJ45). The actual connector type depends on the selected fieldbus variant of the frequency converter.

3. Ensure proper wiring of the fieldbus cables (PROFIBUS/CANopen) or push the cable connectors (RJ45 for PROFINET/POWERLINK/Ethernet/IP) into the sockets in the control cassette.
4.
 - 4a Place the PROFIBUS/CANopen cables between the spring-loaded metal clamps to establish mechanical fixation and electrical contact between the shielded sections of the cables and the clamps.
 - 4b Place the PROFINET/POWERLINK/Ethernet/IP cables between the spring-loaded metal clamps to establish mechanical fixation between the cables and the clamps.

4 Electrical Installation

4.1 Safety Instructions

See *chapter 2 Safety* for general safety instructions.

⚠ WARNING

INDUCED VOLTAGE

Induced voltage from output motor cables of different frequency converters that run together can charge equipment capacitors even with the equipment turned off and locked out. Failure to run output motor cables separately or use shielded cables could result in death or serious injury.

- Run output motor cables separately.
- Use shielded cables.
- Lock out all the frequency converters simultaneously.

⚠ WARNING

SHOCK HAZARD

The frequency converter can cause a DC current in the PE conductor and hence result in death or serious injury.

- When a residual current-operated protective device (RCD) is used for protection against electrical shock, only an RCD of Type B is allowed on the supply side.

Failure to follow the recommendation means that the RCD cannot provide the intended protection.

Overcurrent protection

- Extra protective equipment such as short-circuit protection or motor thermal protection between frequency converter and motor is required for applications with multiple motors.
- Input fusing is required to provide protection against short circuit and overcurrent. If fuses are not factory-supplied, the installer must provide them. See maximum fuse ratings in *chapter 9.8 Fuses and Circuit Breakers*.

Wire type and ratings

- All wiring must comply with local and national regulations regarding cross-section and ambient temperature requirements.
- Power connection wire recommendation:
Minimum 75 °C (167 °F) rated copper wire.

See *chapter 9.5 Cable Specifications* for recommended wire sizes and types.

4.2 EMC-compliant Installation

To obtain an EMC-compliant installation, follow the instructions provided in *chapter 4.3 Grounding*, *chapter 4.4 Wiring Schematic*, *chapter 4.6 Motor Connection*, and *chapter 4.8 Control Wiring*.

4.3 Grounding

⚠ WARNING

LEAKAGE CURRENT HAZARD

Leakage currents exceed 3.5 mA. Failure to ground the frequency converter properly could result in death or serious injury.

- Ensure the correct grounding of the equipment by a certified electrical installer.

For electrical safety

- Ground the frequency converter in accordance with applicable standards and directives.
- Use a dedicated ground wire for input power, motor power, and control wiring.
- Do not ground 1 frequency converter to another in a daisy-chain fashion (see *Illustration 4.1*).
- Keep the ground wire connections as short as possible.
- Follow motor manufacturer wiring requirements.
- Minimum cable cross-section for the ground wires:
 - Same diameter as the mains cable for mains cable cross-section up to 16 mm² (6 AWG)
 - 16 mm² (6 AWG) for mains cable cross-section between 16 mm² (6 AWG) and 35 mm² (1 AWG)
 - Half the diameter of the mains cable for mains cable cross-section bigger than 35 mm² (1 AWG).

Separately terminate individual ground wires, both complying with the dimension requirements.

4

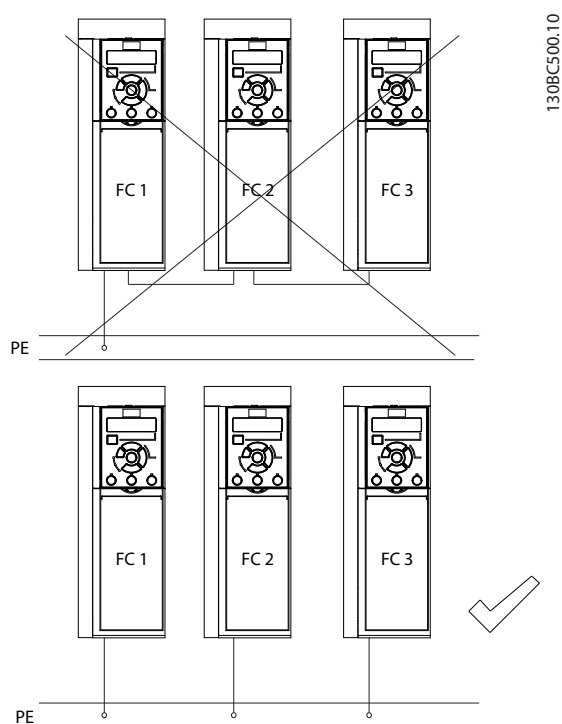


Illustration 4.1 Grounding Principle

For EMC-compliant installation

- Establish electrical contact between the cable shield and the frequency converter enclosure by using metal cable glands or by using the clamps provided on the equipment (see *chapter 4.6 Motor Connection*).
- Use high-strand wire to reduce burst transient.
- Do not use pigtails.

NOTICE

POTENTIAL EQUALIZATION

Risk of burst transient when the ground potential between the frequency converter and the control system is different. Install equalizing cables between the system components. Recommended cable cross-section: 16 mm² (6 AWG).

4.4 Wiring Schematic

This section describes how to wire the frequency converter.

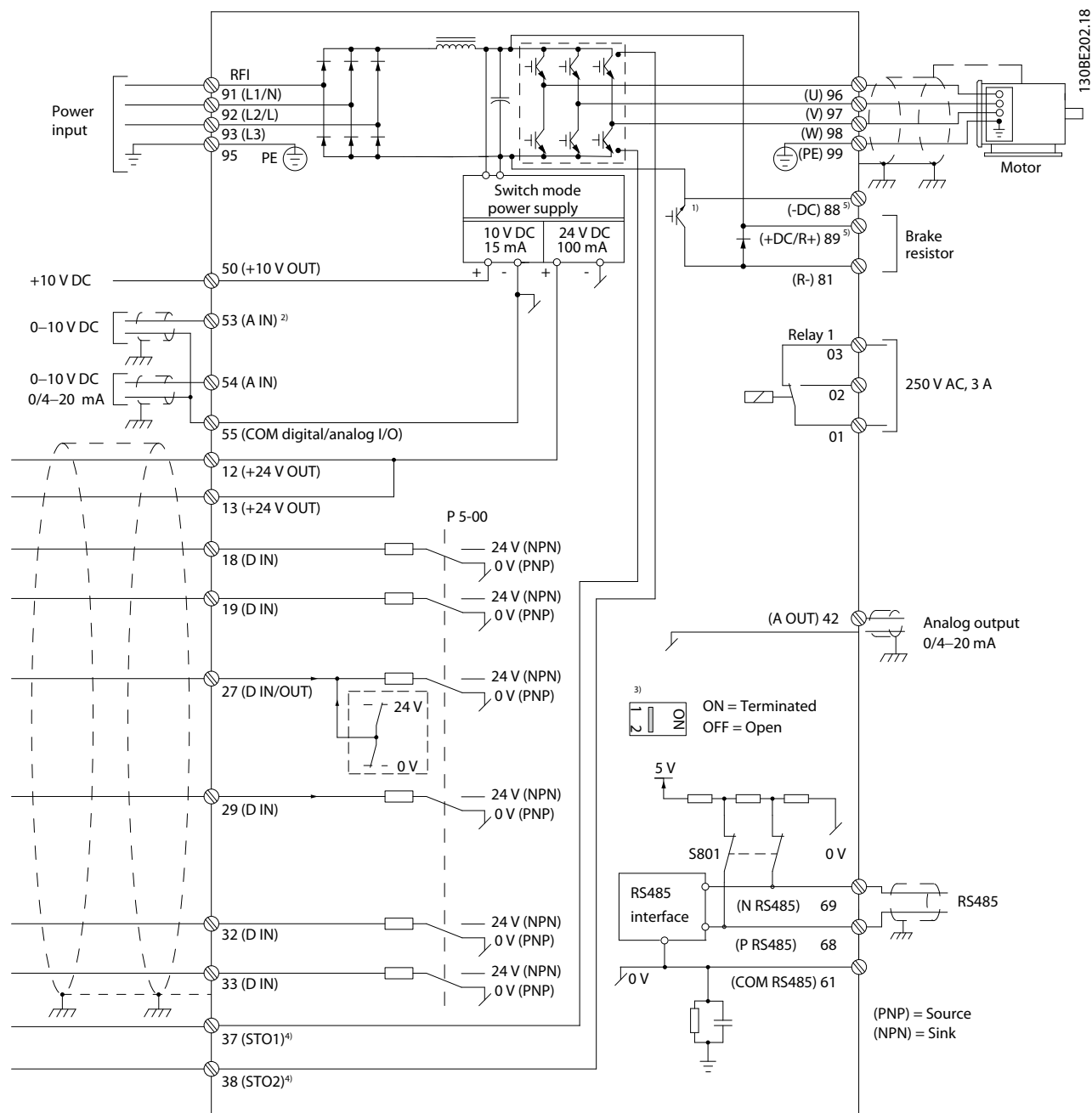


Illustration 4.2 Basic Wiring Schematic Drawing

A=Analog, D=Digital

1) Built-in brake chopper is only available on 3-phase units.

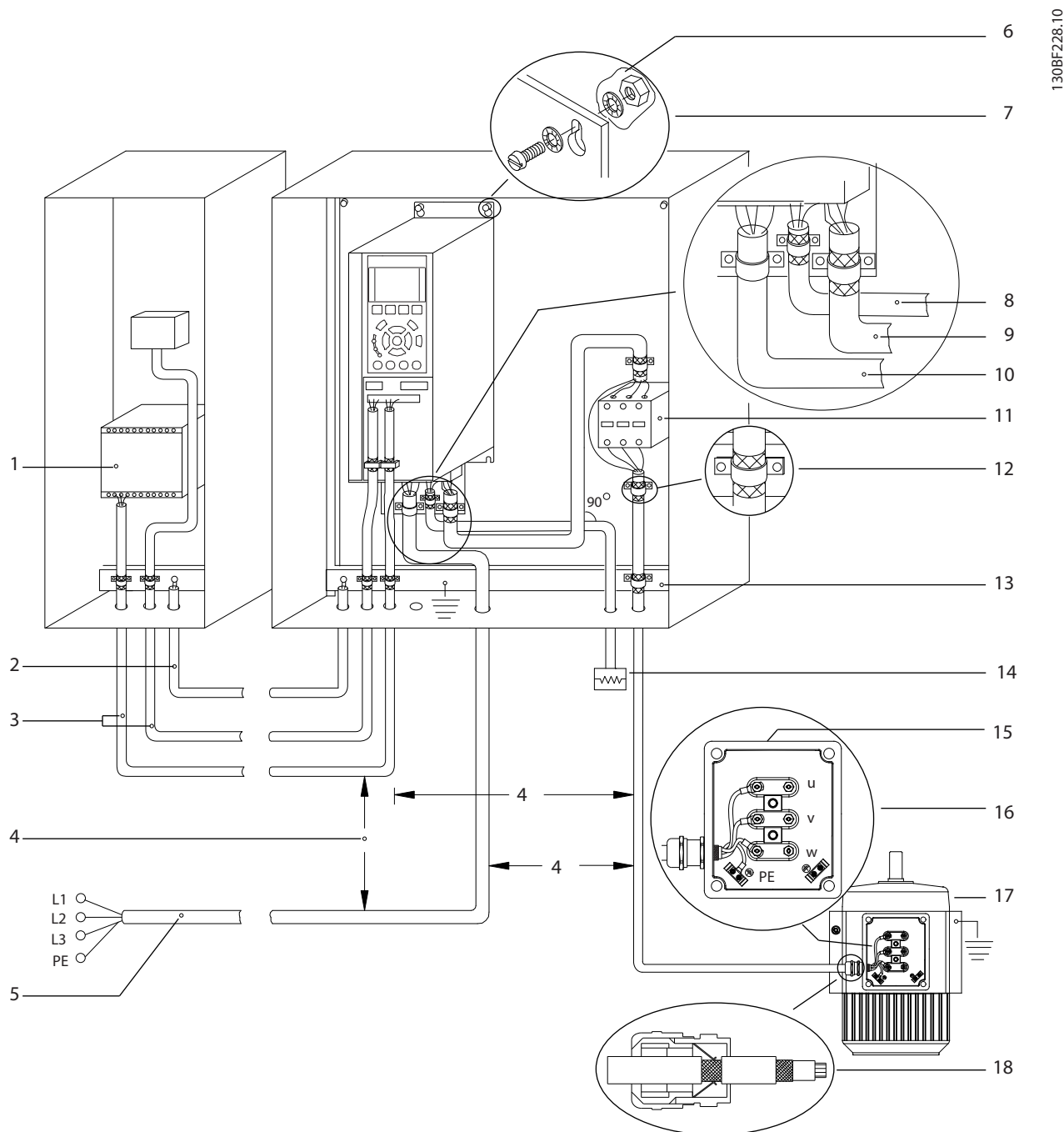
2) Terminal 53 can also be used as digital input.

3) Switch S801 (bus terminal) can be used to enable termination on the RS485 port (terminals 68 and 69).

4) Refer to chapter 6 Safe Torque Off (STO) for the correct STO wiring.

5) The S2 (single-phase 200–240 V) frequency converter does not support load sharing application.

4

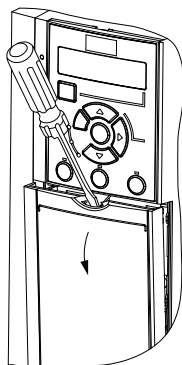


1	PLC	10	Mains cable (unshielded)
2	Minimum 16 mm ² (6 AWG) equalizing cable	11	Output contactor, and more.
3	Control cables	12	Cable insulation stripped
4	Minimum 200 mm (7.87 in) between control cables, motor cables, and mains cables.	13	Common ground busbar. Follow local and national requirements for cabinet grounding.
5	Mains supply	14	Brake resistor
6	Bare (unpainted) surface	15	Metal box
7	Star washers	16	Connection to motor
8	Brake cable (shielded)	17	Motor
9	Motor cable (shielded)	18	EMC cable gland

Illustration 4.3 Typical Electrical Connection

4.5 Access

- Remove the cover plate with a screwdriver. See *Illustration 4.4*.



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Illustration 4.4 Control Wiring Access

4.6 Motor Connection

⚠ WARNING

INDUCED VOLTAGE

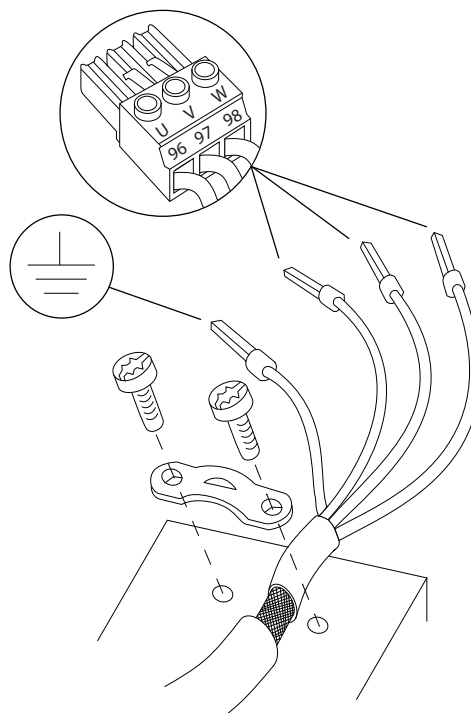
Induced voltage from output motor cables that run together can charge equipment capacitors, even when the equipment is turned off and locked out. Failure to run output motor cables separately or use shielded cables could result in death or serious injury.

- Run output motor cables separately.
- Use shielded cables.
- Comply with local and national electrical codes for cable sizes. For maximum cable sizes, see *chapter 9.1 Electrical Data*.
- Follow motor manufacturer wiring requirements.
- Motor wiring knockouts or access panels are provided at the base of IP21/Type 1 units.
- Do not wire a starting or pole-changing device (for example, Dahlander motor or slip ring induction motor) between the frequency converter and the motor.

Procedure

- Strip a section of the outer cable insulation.
- Position the stripped cable under the cable clamp to establish mechanical fixation and electrical contact between the cable shield and ground.
- Connect the ground cable to the nearest grounding terminal in accordance with the grounding instructions provided in *chapter 4.3 Grounding*. See *Illustration 4.5*.
- Connect the 3-phase motor wiring to terminals 96 (U), 97 (V), and 98 (W), as shown in *Illustration 4.5*.

- Tighten the terminals in accordance with the information provided in *chapter 9.7 Connection Tightening Torques*.



1308D531.10

Illustration 4.5 Motor Connection

The mains, motor, and grounding connection for single-phase and 3-phase frequency converters are shown in *Illustration 4.6*, *Illustration 4.7*, and *Illustration 4.8* respectively. Actual configurations vary with unit types and optional equipment.

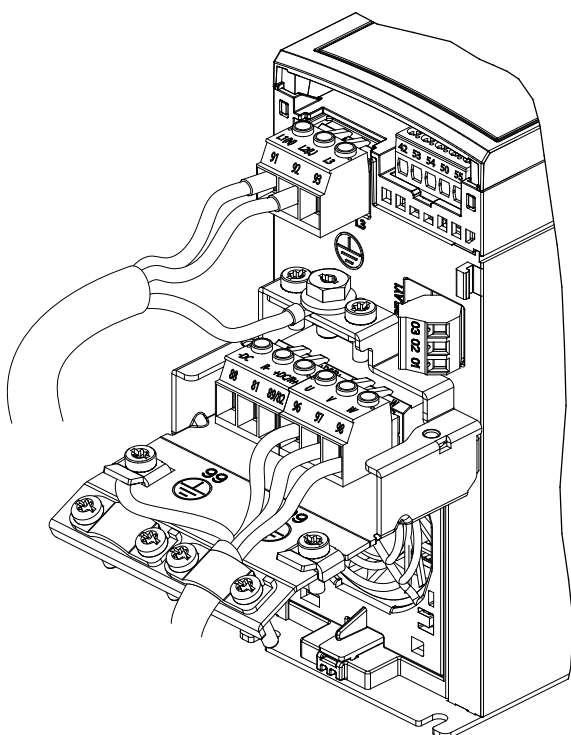


Illustration 4.6 Mains, Motor, and Grounding Connection for Single-phase Units

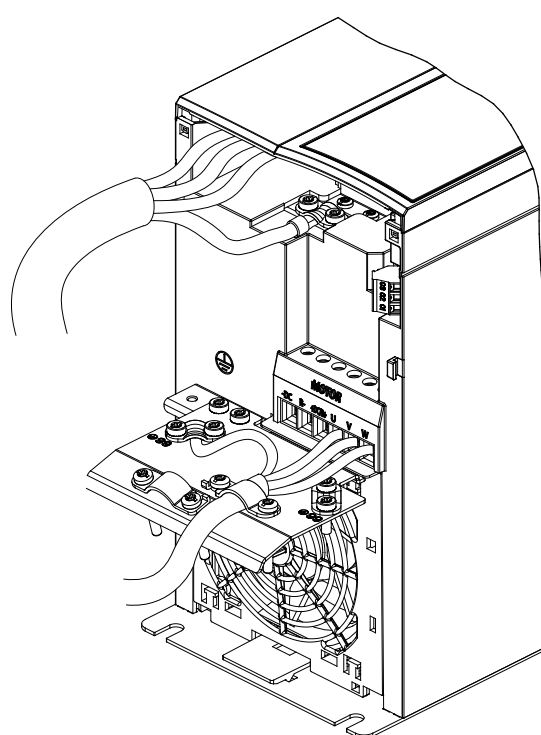


Illustration 4.8 Mains, Motor, and Grounding Connection for 3-phase Units (K4, K5)

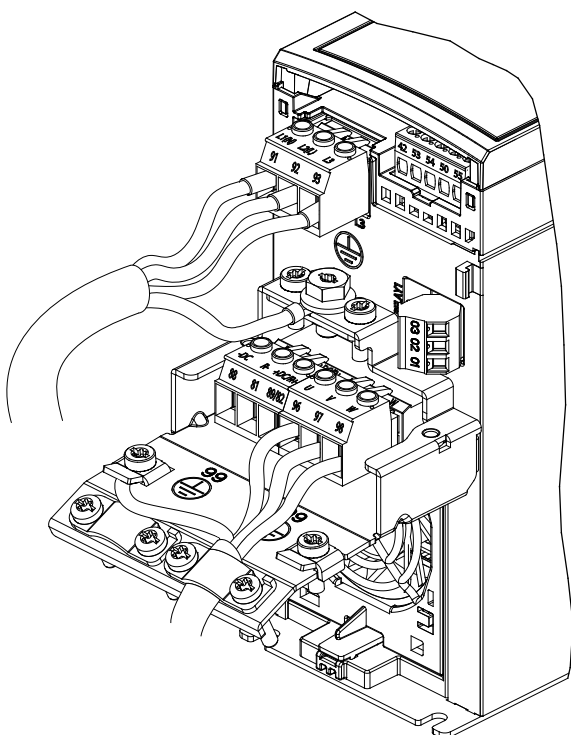


Illustration 4.7 Mains, Motor, and Grounding Connection for 3-phase Units (K1, K2, K3)

4.7 AC Mains Connection

- Size the wiring based on the input current of the frequency converter. For maximum wire sizes, see *chapter 9.1 Electrical Data*.
- Comply with local and national electrical codes for cable sizes.

Procedure

1. Connect the AC input power cables to terminals N and L for single-phase units (see *Illustration 4.6*), or to terminals L1, L2, and L3 for 3-phase units (see *Illustration 4.7*).
2. Depending on the configuration of the equipment, connect the input power to the mains input terminals or the input disconnect.
3. Ground the cable in accordance with the grounding instructions in *chapter 4.3 Grounding*.
4. When supplied from an isolated mains source (IT mains or floating delta) or TT/TN-S mains with a grounded leg (grounded delta), ensure that the RFI filter screw is removed. Removing the RFI screw prevents damage to the DC link and reduces ground capacity currents in accordance with IEC 61800-3 (see *Illustration 9.2*, the RFI screw is on the side of the frequency converter).

4.8 Control Wiring

4.8.1 Control Terminal Types

Illustration 4.9 shows the removable frequency converter connectors. Terminal functions and default settings are summarized in Table 4.1 and Table 4.2.

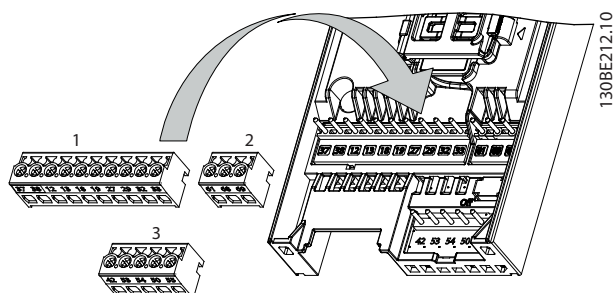


Illustration 4.9 Control Terminal Locations

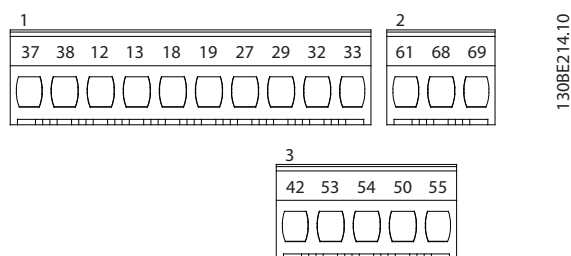


Illustration 4.10 Terminal Numbers

See chapter 9.6 Control Input/Output and Control Data for terminal ratings details.

Terminal	Parameter	Default setting	Description
Digital I/O, pulse I/O, encoder			
12, 13	–	+24 V DC	24 V DC supply voltage. Maximum output current is 100 mA for all 24 V loads.
18	Parameter 5-10 Terminal 18 Digital Input	[8] Start	Digital inputs.
19	Parameter 5-11 Terminal 19 Digital Input	[10] Reversing	

Terminal	Parameter	Default setting	Description
27	Parameter 5-01 Terminal 27 Mode Parameter 5-12 Terminal 27 Digital Input Parameter 5-30 Terminal 27 Digital Output	DI [2] Coast inverse DO [0] No operation	Selectable for either digital input, digital output, or pulse output. The default setting is digital input.
29	Parameter 5-13 Terminal 29 Digital Input	[14] Jog	Digital input.
32	Parameter 5-14 Terminal 32 Digital Input	[0] No operation	Digital input, 24 V encoder. Terminal 33 can be used for pulse input.
33	Parameter 5-15 Terminal 33 Digital Input	[0] No operation	
37, 38	–	STO	Functional safety inputs.
Analog inputs/outputs			
42	Parameter 6-91 Terminal 42 Analog Output	[0] No operation	Programmable analog output. The analog signal is 0–20 mA or 4–20 mA at a maximum of 500 Ω. Can also be configured as digital outputs.
50	–	+10 V DC	10 V DC analog supply voltage. 15 mA maximum commonly used for potentiometer or thermistor.
53	Parameter group 6-1* Analog input 53	–	Analog input. Only voltage mode is supported. It can also be used as digital input.
54	Parameter group 6-2* Analog input 54	–	Analog input. Selectable between voltage or current mode.
55	–	–	Common for digital and analog inputs.

Table 4.1 Terminal Descriptions - Digital Inputs/Outputs, Analog Inputs/Outputs

Terminal	Parameter	Default setting	Description
Serial communication			
61	–	–	Integrated RC filter for cable shield. ONLY for connecting the shield when experiencing EMC problems.
68 (+)	Parameter group 8-3* FC port settings	–	RS485 interface. A control card switch is provided for termination resistance.
69 (-)	Parameter group 8-3* FC port settings	–	
Relays			
01, 02, 03	Parameter 5-40 Function Relay	[1] Control Ready	Form C relay output. These relays are in various locations depending on the frequency converter configuration and size. Usable for AC or DC voltage and resistive or inductive loads.

Table 4.2 Terminal Descriptions - Serial Communication

4.8.2 Wiring to Control Terminals

Control terminal connectors can be unplugged from the frequency converter for ease of installation, as shown in *Illustration 4.9*.

For details about STO wiring, refer to *chapter 6 Safe Torque Off (STO)*.

NOTICE

Keep control cables as short as possible and separate them from high-power cables to minimize interference.

1. Loosen the screws for the terminals.
2. Insert sleeved control cables into the slots.
3. Fasten the screws for the terminals.
4. Ensure that the contact is firmly established and not loose. Loose control wiring can be the source of equipment faults or less than optimal operation.

See *chapter 9.5 Cable Specifications* for control terminal cable sizes and *chapter 7 Application Examples* for typical control cable connections.

4.8.3 Enabling Motor Operation (Terminal 27)

A jumper wire is required between terminal 12 (or 13) and terminal 27 for the frequency converter to operate when using factory default programming values.

- Digital input terminal 27 is designed to receive 24 V DC external interlock command.
- When no interlock device is used, wire a jumper between control terminal 12 (recommended) or 13 to terminal 27. The jumper provides an internal 24 V signal on terminal 27.
- Only for GLCP: When the status line at the bottom of the LCP reads *AUTO REMOTE COAST*, it indicates that the unit is ready to operate but is missing an input signal on terminal 27.

NOTICE

UNABLE TO START

The frequency converter cannot operate without a signal on terminal 27, unless terminal 27 is reprogrammed.

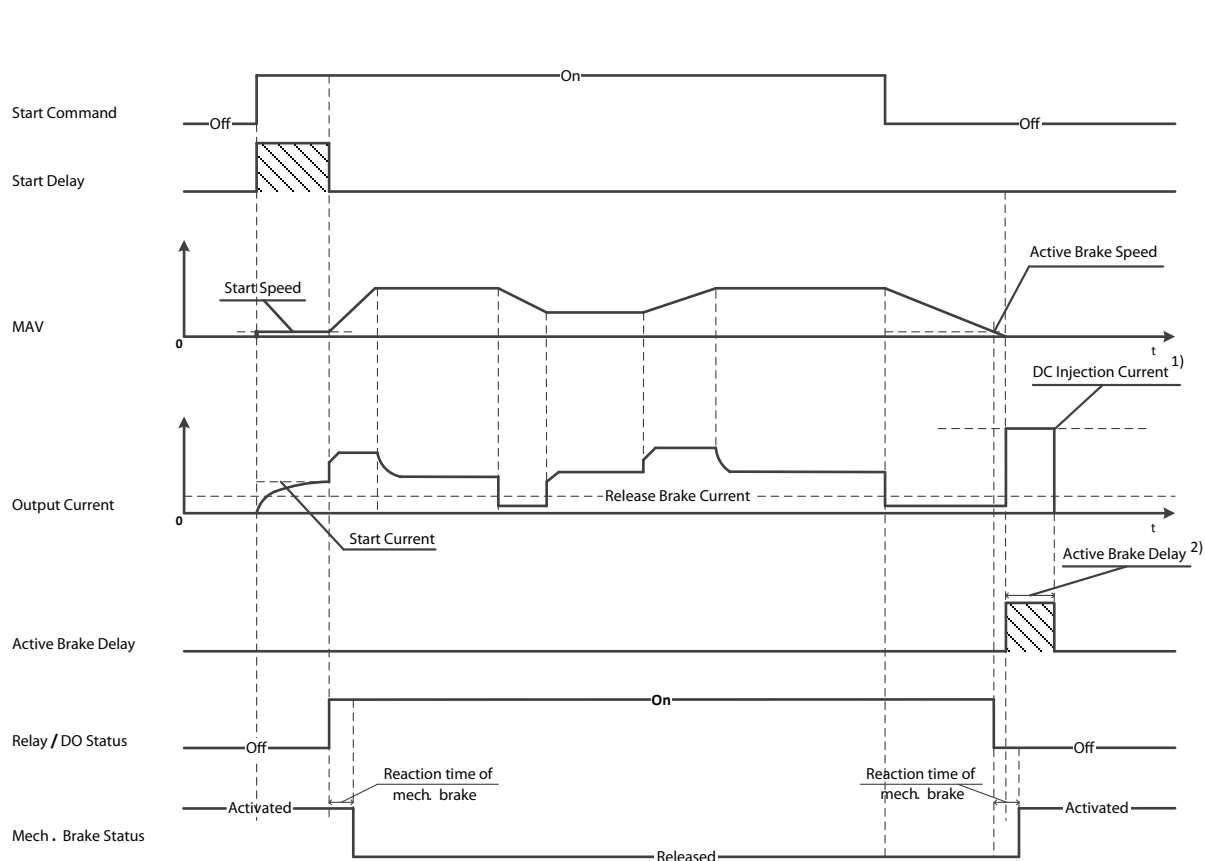
4.8.4 Mechanical Brake Control

In hoisting/lowering applications, it is necessary to control an electro-mechanical brake.

- Control the brake using any relay output or digital output (terminal 27).
- Keep the output closed (voltage-free) as long as the frequency converter is unable to keep the motor at standstill, for example due to the load being too heavy.
- Select [32] *Mechanical brake control* in parameter group 5-4* *Relays* for applications with an electro-mechanical brake.
- The brake is released when the motor current exceeds the preset value in parameter 2-20 *Release Brake Current*.
- The brake is engaged when the output frequency is less than the frequency set in parameter 2-22 *Activate Brake Speed [Hz]*, and only if the frequency converter carries out a stop command.

If the frequency converter is in 1 of the following situations, the mechanical brake immediately closes.

- In alarm mode.
- In an overvoltage situation.
- STO is activated.
- Coast command is given.



Note: 1) DC injection current during "Active Brake Delay" after MAV reduced to "0". Only support in some products.

2) Only support in some products.

Illustration 4.11 Mechanical Brake

The frequency converter is not a safety device. It is the responsibility of the system designer to integrate safety devices according to relevant national crane/lift regulations.

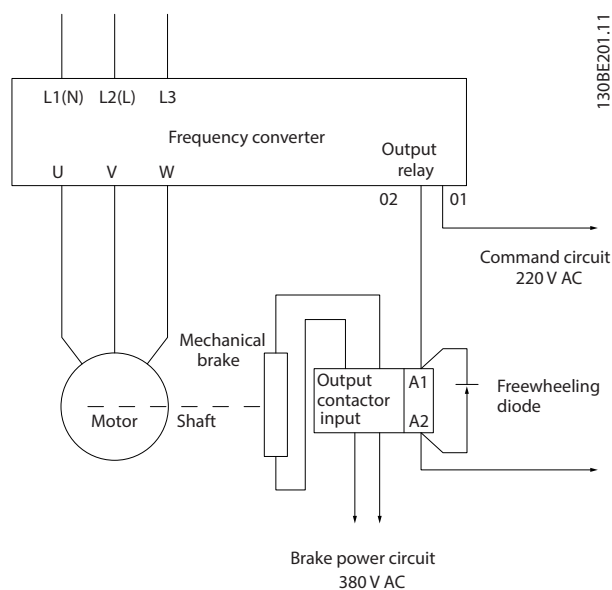
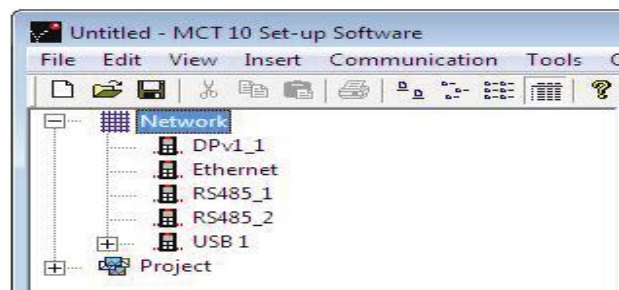


Illustration 4.12 Connecting the Mechanical Brake to the Frequency Converter

4.8.5 USB Data Communication



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Illustration 4.13 Network Bus List

When the USB cable is disconnected, the frequency converter connected via the USB port is removed from the *Network* bus list.

NOTICE

A USB bus has no address-setting capacity and no bus name to configure. If connecting more than 1 frequency converter through USB, the bus name is auto-incremented in the MCT 10 Set-up Software Network bus list.

Connecting more than 1 frequency converter through a USB cable often causes computers installed with Windows XP to throw an exception and crash. Therefore it is advised only to connect 1 frequency converter via USB to the PC.

4.8.6 RS485 Serial Communication

Connect RS485 serial communication wiring to terminals (+)68 and (-)69.

- Shielded serial communication cable is recommended.
- See chapter 4.3 Grounding for proper grounding.

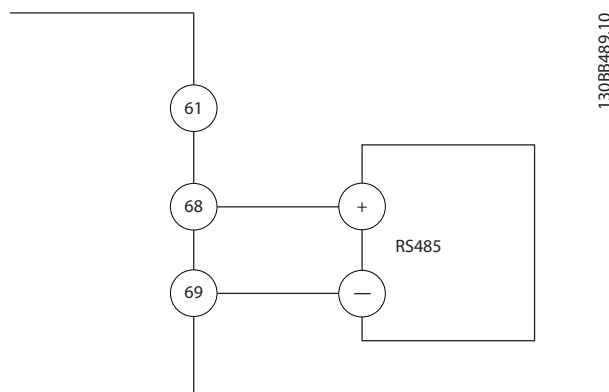


Illustration 4.14 Serial Communication Wiring Diagram

For basic serial communication set-up, select the following:

1. Protocol type in *parameter 8-30 Protocol*.
2. Frequency converter address in *parameter 8-31 Address*.
3. Baud rate in *parameter 8-32 Baud Rate*.

Two communication protocols are internal to the frequency converter. Follow motor manufacturer wiring requirements.

- Danfoss FC
- Modbus RTU

Functions can be programmed remotely using the protocol software and RS485 connection, or in *parameter group 8-** Communications and Options*.

Selecting a specific communication protocol changes various default parameter settings to match the specifications of the protocol and makes extra protocol-specific parameters available.

4.9 Installation Checklist

Before completing installation of the unit, inspect the entire installation as detailed in *Table 4.3*. Check and mark the items when completed.

Inspect for	Description	☑
Auxiliary equipment	- Look for auxiliary equipment, switches, disconnects, or input fuses/circuit breakers, which may reside on the input power side of the frequency converter or output side to the motor. Ensure that they are ready for full-speed operation. - Check the function and installation of any sensors used for feedback to the frequency converter. - Remove any power factor correction capacitors on the motor(s). - Adjust any power factor correction capacitors on the mains side and ensure that they are dampened.	
Cable routing	Ensure that the motor wiring and control wiring are separated, shielded, or in 3 separate metallic conduits for high frequency interference isolation.	
Control wiring	- Check for broken or damaged wires and loose connections. - Check that the control wiring is isolated from power and motor wiring for noise immunity. - Check the voltage source of the signals, if necessary. The use of shielded cable or twisted pair is recommended. Ensure that the shield is terminated correctly.	
Cooling clearance	Ensure that the top and bottom clearance is adequate to ensure proper airflow for cooling, see <i>chapter 3.3 Mounting</i>.	
Ambient conditions	Check that requirements for ambient conditions are met.	
Fusing and circuit breakers	- Check for proper fusing or circuit breakers. - Check that all fuses are inserted firmly and are in operational condition and that all circuit breakers are in the open position.	
Grounding	- Check for sufficient ground connections and ensure that they are tight and free of oxidation. - Do not ground to conduit, or mount the back panel to a metal surface.	
Input and output power wiring	- Check for loose connections. - Check that the motor and mains cables are in separate conduit or separated shielded cables.	
Panel interior	- Inspect that the unit interior is free of dirt, metal chips, moisture, and corrosion. - Check that the unit is mounted on an unpainted, metal surface.	
Switches	Ensure that all switch and disconnect settings are in the proper positions.	
Vibration	- Check that the unit is mounted solidly, or that shock mounts are used, as necessary. - Check for an unusual amount of vibration.	

Table 4.3 Installation Check List

⚠ CAUTION

POTENTIAL HAZARD IN THE EVENT OF INTERNAL FAILURE

Risk of personal injury if the frequency converter is not properly closed.

- Before applying power, ensure that all safety covers are in place and securely fastened.

5 Commissioning

5.1 Safety Instructions

See *chapter 2 Safety* for general safety instructions.

⚠ WARNING

HIGH VOLTAGE

Frequency converters contain high voltage when connected to AC mains input power. Failure to perform installation, start-up, and maintenance by qualified personnel could result in death or serious injury.

- Installation, start-up, and maintenance must be performed by qualified personnel only.

Before applying power:

1. Close the cover properly.
2. Check that all cable glands are firmly tightened.
3. Ensure that input power to the unit is off and locked out. Do not rely on the frequency converter disconnect switches for input power isolation.
4. Verify that there is no voltage on input terminals L1 (91), L2 (92), and L3 (93), phase-to-phase, and phase-to-ground.
5. Verify that there is no voltage on output terminals 96 (U), 97 (V), and 98 (W), phase-to-phase, and phase-to-ground.
6. Confirm continuity of the motor by measuring Ω values on U–V (96–97), V–W (97–98), and W–U (98–96).
7. Check for proper grounding of the frequency converter and the motor.
8. Inspect the frequency converter for loose connections on the terminals.
9. Confirm that the supply voltage matches the voltage of the frequency converter and the motor.

5.2 Applying Power

Apply power to the frequency converter using the following steps:

1. Confirm that the input voltage is balanced within 3%. If not, correct the input voltage imbalance before proceeding. Repeat this procedure after the voltage correction.
2. Ensure that any optional equipment wiring matches the installation application.
3. Ensure that all operator devices are in the OFF position. Panel doors must be closed and covers securely fastened.
4. Apply power to the unit. Do not start the frequency converter now. For units with a disconnect switch, turn it to the ON position to apply power to the frequency converter.

5.3 Local Control Panel Operation

The frequency converter supports numerical local control panel (NLCP), graphic local control panel (GLCP), and blind cover. This section describes the operations with NLCP and GLCP.

NOTICE

The frequency converter can also be programmed from the MCT 10 Set-up Software on PC via RS485 communication port or USB port. This software can be ordered using ordering number 130B1000 or downloaded from the Danfoss website: drives.danfoss.com/downloads/pc-tools/#/.

5.3.1 Numeric Local Control Panel (NLCP)

The numerical local control panel (NLCP) is divided into 4 functional sections.

- A. Numeric display.
- B. Menu key.
- C. Navigation keys and indicator lights (LEDs).
- D. Operation keys and indicator lights (LEDs).

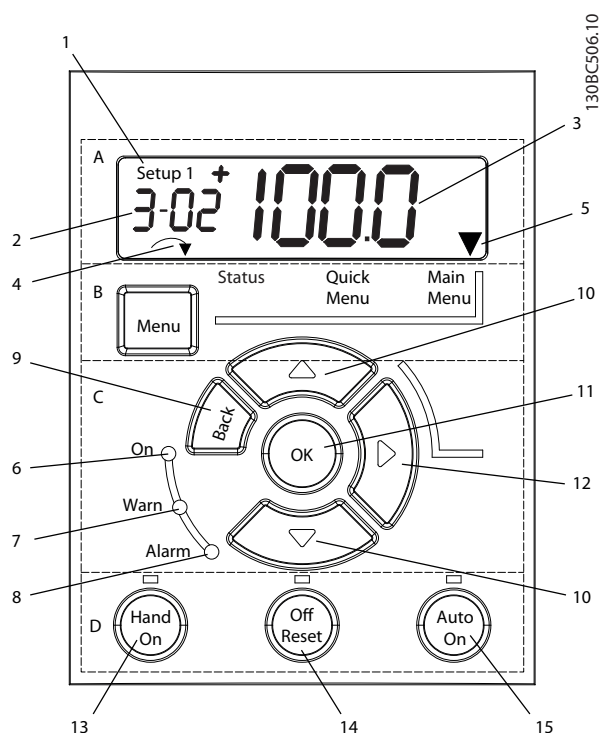


Illustration 5.1 View of the NLCP

A. Numeric display

The LCD display is backlit with 1 numeric line. All data is shown in the NLCP.

1	The set-up number shows the active set-up and the edit set-up. If the same set-up acts as both active and edit set-up, only that set-up number is shown (factory setting). When active and edit set-up differ, both numbers are shown in the display (for example set-up 12). The number flashing indicates the edit set-up.
2	Parameter number.
3	Parameter value.
4	Motor direction is shown at the bottom left of the display. A small arrow indicates the direction.
5	The triangle indicates whether the LCP is in Status, Quick Menu, or Main Menu.

Table 5.1 Legend to Illustration 5.1, Section A



Illustration 5.2 Display Information

B. Menu key

To select between Status, Quick Menu, or Main Menu, press [Menu].

C. Indicator lights (LEDs) and navigation keys

	Indicator	Light	Function
6	On	Green	ON turns on when the frequency converter receives power from the mains voltage, a DC bus terminal, or a 24 V external supply.
7	Warn	Yellow	When warning conditions are met, the yellow WARN LED turns on, and text appears in the display area identifying the problem.
8	Alarm	Red	A fault condition causes the red alarm LED to flash and an alarm text is shown.

Table 5.2 Legend to Illustration 5.1, Indicator Lights (LEDs)

	Key	Function
9	[Back]	For moving to the previous step or layer in the navigation structure.
10	[▲] [▼]	For switching between parameter groups, parameters, and within parameters, or increasing/decreasing parameter values. Arrows can also be used for setting local reference.
11	[OK]	Press to access parameter groups or to enable a selection.
12	[▶]	Press to move from left to right within the parameter value to change each digit individually.

Table 5.3 Legend to Illustration 5.1, Navigation Keys

D. Operation keys and indicator lights (LEDs)

	Key	Function
13	Hand On	Starts the frequency converter in local control. An external stop signal by control input or serial communication overrides the local hand on.
14	Off/Reset	Stops the motor but does not remove power to the frequency converter or resets the frequency converter manually after a fault has been cleared. If in alarm mode, the alarm is reset if the alarm condition is removed.
15	Auto On	Puts the system in remote operational mode. Responds to an external start command by control terminals or serial communication.

Table 5.4 Legend to *Illustration 5.1*, Section D

⚠ WARNING

ELECTRICAL HAZARD

Even after pressing the [Off/Reset] key, voltage is present at the terminals of the frequency converter. Pressing the [Off/Reset] key does not disconnect the frequency converter from mains. Touching live parts can result in death or serious injury.

- Do not touch any live parts.

5.3.2 The Right-key Function on NLCP

Press [▶] to edit any of the 4 digits on the display individually. When pressing [▶] once, the cursor moves to the first digit, and the digit starts flashing as shown in *Illustration 5.3*. Press the [▲] [▼] to change the value. Pressing [▶] does not change the value of the digits, or move the decimal point.

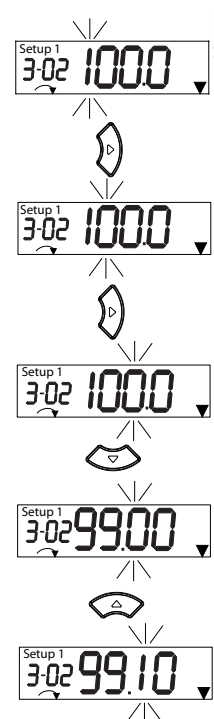


Illustration 5.3 Right-key Function

[▶] can also be used for moving between parameter groups. When in *Main Menu*, press [▶] to move to the first parameter in the next parameter group (for example, move from *parameter 0-03 Regional Settings [0] International* to *parameter 1-00 Configuration Mode [0] Open loop*).

NOTICE

During start-up, the LCP shows the message *INITIALISING*. When this message is no longer shown, the frequency converter is ready for operation. Adding or removing options can extend the duration of start-up.

5.3.3 Quick Menu on NLCP

The *Quick Menu* gives easy access to the most frequently used parameters.

- To enter *Quick Menu*, press [Menu] until the indicator in the display is placed above *Quick Menu*.
- Press [▲] [▼] to select either QM1 or QM2, then press [OK].
- Press [▲] [▼] to browse through the parameters in *Quick Menu*.
- Press [OK] to select a parameter.
- Press [▲] [▼] to change the value of a parameter setting.
- Press [OK] to accept the change.

7. To exit, press either [Back] twice (or 3 times if in QM2 and QM3) to enter *Status*, or press [Menu] once to enter *Main Menu*.

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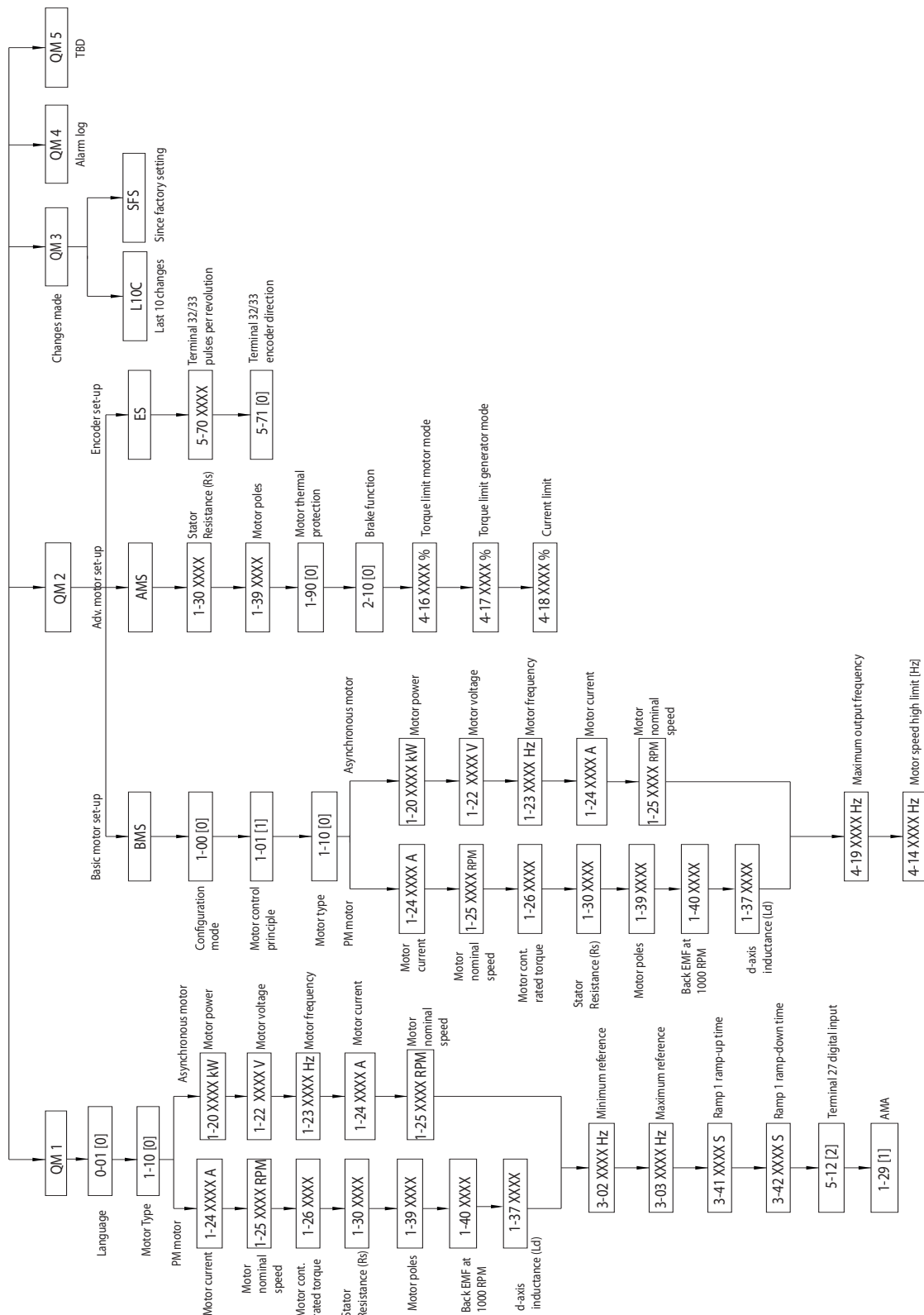


Illustration 5.4 Quick Menu Structure

5.3.4 Main Menu on NLCP

The *Main Menu* gives access to all parameters.

1. To enter *Main Menu*, press [Menu] until the indicator in the display is placed above *Main Menu*.
2. [▲] [▼]: Browse through the parameter groups.
3. Press [OK] to select a parameter group.
4. [▲] [▼]: Browse through the parameters in the specific group.
5. Press [OK] to select the parameter.
6. [▶] and [▲] / [▼]: Set/change the parameter value.
7. Press [OK] to accept the value.
8. To exit, press either [Back] twice (or 3 times for array parameters) to enter *Main Menu*, or press [Menu] once to enter *Status*.

See *Illustration 5.5*, *Illustration 5.6*, and *Illustration 5.7* for the principles of changing the value of continuous, enumerated, and array parameters, respectively. The actions in the illustrations are described in *Table 5.5*, *Table 5.6*, and *Table 5.7*.

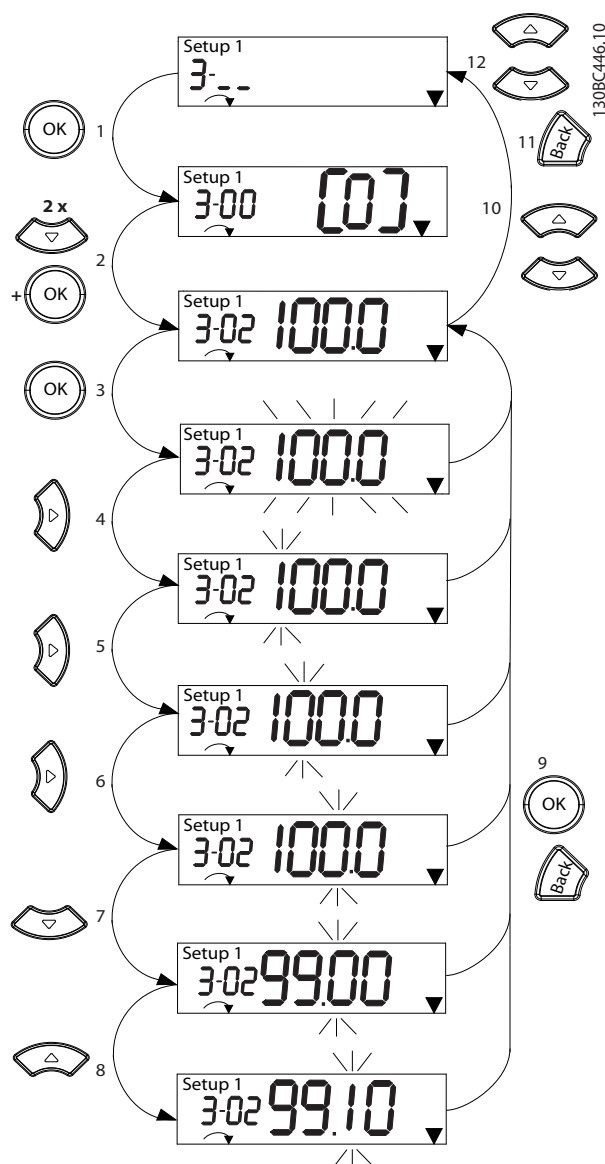


Illustration 5.5 Main Menu Interactions - Continuous Parameters

1	[OK]: The first parameter in the group is shown.
2	Press [▼] repeatedly to move down to the parameter.
3	Press [OK] to start editing.
4	[►]: First digit flashing (can be edited).
5	[►]: Second digit flashing (can be edited).
6	[►]: Third digit flashing (can be edited).
7	[▼]: Decrease the parameter value, the decimal point changes automatically.
8	[▲]: Increase the parameter value.
9	[Back]: Cancel changes, return to 2. [OK]: Accept changes, return to 2.
10	[▲][▼]: Select parameter within the group.
11	[Back]: Remove the value and show the parameter group.
12	[▲][▼]: Select group.

Table 5.5 Changing Values in Continuous Parameters

For enumerated parameters, the interaction is similar, but the parameter value is shown in brackets because of the digits limitation (4 large digits) on the NLCP, and the enum can be greater than 99. When the enum value is greater than 99, the LCP can only show the first part of the bracket.

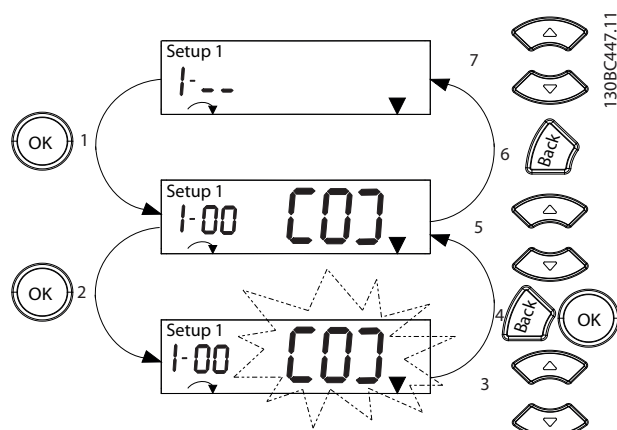


Illustration 5.6 Main Menu Interactions - Enumerated Parameters

1	[OK]: The first parameter in the group is shown.
2	Press [OK] to start editing.
3	[▲][▼]: Change parameter value (flashing).
4	Press [Back] to cancel changes or [OK] to accept changes (return to screen 2).
5	[▲][▼]: Select a parameter within the group.
6	[Back]: Remove the value and show the parameter group.
7	[▲][▼]: Select a group.

Table 5.6 Changing Values in Enumerated Parameters

Array parameters function as follows:

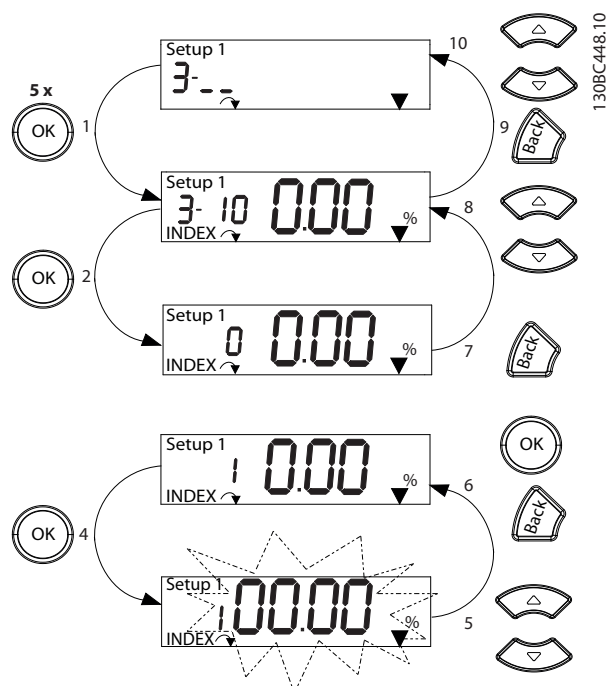


Illustration 5.7 Main Menu Interactions - Array Parameters

1	[OK]: Show parameter numbers and the value in the first index.
2	[OK]: Index can be selected.
3	[▲][▼]: Select index.
4	[OK]: Value can be edited.
5	[▲][▼]: Change parameter value (flashing).
6	[Back]: Cancel changes. [OK]: Accept changes.
7	[Back]: Cancel editing index, select a new parameter.
8	[▲][▼]: Select parameter within the group.
9	[Back]: Remove parameter index value and show the parameter group.
10	[▲][▼]: Select group.

Table 5.7 Changing Values in Array Parameters

5.3.5 Graphic Local Control Panel (GLCP)

The GLCP is divided into 4 functional groups (see *Illustration 5.8*).

- A. Display area.
- B. Display menu keys.
- C. Navigation keys and indicator lights (LEDs).
- D. Operation keys and reset.

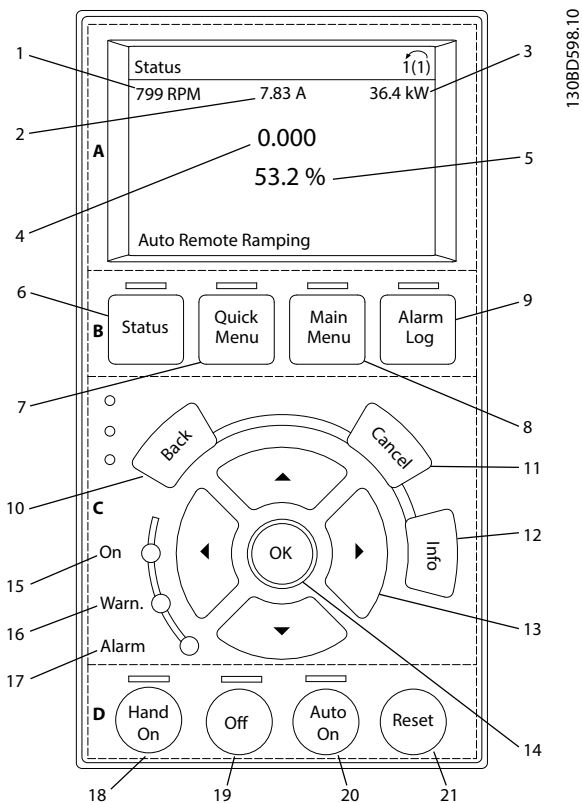


Illustration 5.8 Graphic Local Control Panel (GLCP)

A. Display area

The display area is activated when the frequency converter receives power from the mains voltage, a DC bus terminal, or a 24 V DC external supply.

The information shown on the LCP can be customized for user applications. Select options in the *Quick Menu Q3-13 Display Settings*.

Display	Parameter number	Default setting
1	0-20	[1602] Reference [%]
2	0-21	[1614] Motor Current
3	0-22	[1610] Power [kW]
4	0-23	[1613] Frequency
5	0-24	[1502] kWh Counter

Table 5.8 Legend to *Illustration 5.8*, Display Area

B. Display menu keys

Menu keys are used for menu access for parameter set-up, toggling through status display modes during normal operation, and viewing fault log data.

	Key	Function
6	Status	Shows operational information.
7	Quick Menu	Allows access to programming parameters for initial set-up instructions and many detailed application instructions.
8	Main Menu	Allows access to all programming parameters.
9	Alarm Log	Shows a list of current warnings, the last 10 alarms, and the maintenance log.

Table 5.9 Legend to *Illustration 5.8*, Display Menu Keys

C. Navigation keys and indicator lights (LEDs)

Navigation keys are used for programming functions and moving the display cursor. The navigation keys also provide speed control in local operation. There are also 3 frequency converter status indicator lights in this area.

	Key	Function
10	Back	Reverts to the previous step or list in the menu structure.
11	Cancel	Cancels the last change or command as long as the display mode has not changed.
12	Info	Press for a definition of the function being shown.
13	Navigation keys	To move between items in the menu, use the 4 navigation keys.
14	OK	Press to access parameter groups or to enable a selection.

Table 5.10 Legend to *Illustration 5.8*, Navigation Keys

	Indicator	Light	Function
15	On	Green	ON turns on when the frequency converter receives power from the mains voltage, a DC bus terminal, or a 24 V external supply.
16	Warn	Yellow	When warning conditions are met, the yellow WARN LED turns on, and text appears in the display area identifying the problem.
17	Alarm	Red	A fault condition causes the red alarm LED to flash, and an alarm text is shown.

Table 5.11 Legend to *Illustration 5.8*, Indicator Lights (LEDs)

D. Operation keys and reset

Operation keys are at the bottom of the LCP.

	Key	Function
18	Hand On	Starts the frequency converter in hand-on mode. An external stop signal by control input or serial communication overrides the local hand on.
19	Off	Stops the motor but does not remove power to the frequency converter.
20	Auto On	Puts the system in remote operational mode. Responds to an external start command by control terminals or serial communication.
21	Reset	Resets the frequency converter manually after a fault has been cleared.

Table 5.12 Legend to *Illustration 5.8, Operation Keys and Reset*

NOTICE

To adjust the display contrast, press [Status] and the [▲]/[▼] keys.

5.3.6 Parameter Settings

Establishing the correct programming for applications often requires setting functions in several related parameters. Parameter details are provided in *chapter 10.2 Parameter Menu Structure*.

Programming data is stored internally in the frequency converter.

- For back-up, upload data into the LCP memory.
- To download data to another frequency converter, connect the LCP to that unit and download the stored settings.
- Restoring factory default settings does not change data stored in the LCP memory.

5.3.7 Changing Parameter Settings with GLCP

Access and change parameter settings from the *Quick Menu* or from the *Main Menu*. The *Quick Menu* only gives access to a limited number of parameters.

- Press [Quick Menu] or [Main Menu] on the LCP.
- Press [▲] [▼] to browse through the parameter groups, press [OK] to select a parameter group.
- Press [▲] [▼] to browse through the parameters, press [OK] to select a parameter.

- Press [▲] [▼] to change the value of a parameter setting.
- Press [◀] [▶] to shift digit when a decimal parameter is in the editing state.
- Press [OK] to accept the change.
- Press either [Back] twice to enter Status, or press [Main Menu] once to enter the Main Menu.

View changes

Quick Menu Q5 - Changes Made lists all parameters changed from default settings.

- The list only shows parameters, which have been changed in the current edit set-up.
- Parameters which have been reset to default values are not listed.
- The message *Empty* indicates that no parameters have been changed.

5.3.8 Uploading/Downloading Data to/from the GLCP

- Press [Off] to stop the motor before uploading or downloading data.
- Press [Main Menu] *parameter 0-50 LCP Copy* and press [OK].
- Select [1] *All to LCP* to upload data to the LCP or select [2] *All from LCP* to download data from the LCP.
- Press [OK]. A progress bar shows the uploading or downloading progress.
- Press [Hand On] or [Auto On] to return to normal operation.

5.3.9 Restoring Default Settings with LCP

NOTICE

Risk of losing programming, motor data, localization, and monitoring records by restoration of default settings. To provide a back-up, upload data to the LCP before initialization.

Restoring the default parameter settings is done by initialization of the frequency converter. Initialization is carried out through *parameter 14-22 Operation Mode* (recommended) or manually. Initialization does not reset the settings for *parameter 1-06 Clockwise Direction* and *parameter 0-03 Regional Settings*.

- Initialization using *parameter 14-22 Operation Mode* does not reset frequency converter settings, such as operating hours, serial communication

selections, fault log, alarm log, and other monitoring functions.

- Manual initialization erases all motor, programming, localization, and monitoring data and restores factory default settings.

Recommended initialization procedure, via parameter 14-22 Operation Mode

1. Select *parameter 14-22 Operation Mode* and press [OK].
2. Select *[2] Initialisation* and press [OK].
3. Remove power to the unit and wait until the display turns off.
4. Apply power to the unit.

Default parameter settings are restored during start-up. This may take slightly longer than normal.

5. *Alarm 80, Drive initialised to default value* is shown.
6. Press [Reset] to return to operation mode.

Manual initialization procedure

1. Remove power to the unit and wait until the display turns off.
2. Press and hold [Status], [Main Menu], and [OK] at the same time on the GLCP, or press [Menu] and [OK] at the same time on the NLCP while applying power to the unit (approximately 5 s or until a click is heard and the fan starts).

Factory default parameter settings are restored during start-up. This may take slightly longer than normal.

Manual initialization does not reset the following frequency converter information:

- *Parameter 15-00 Operating hours*
- *Parameter 15-03 Power Up's*
- *Parameter 15-04 Over Temp's*
- *Parameter 15-05 Over Volt's*

5.4 Basic Programming

5.4.1 Asynchronous Motor Set-up

Enter the following motor data in the listed order. Find the information on the motor nameplate.

1. *Parameter 1-20 Motor Power.*
2. *Parameter 1-22 Motor Voltage.*
3. *Parameter 1-23 Motor Frequency.*
4. *Parameter 1-24 Motor Current.*
5. *Parameter 1-25 Motor Nominal Speed.*

For optimum performance in VVC⁺ mode, extra motor data is required to set up the following parameters.

6. *Parameter 1-30 Stator Resistance (Rs).*
7. *Parameter 1-31 Rotor Resistance (Rr).*
8. *Parameter 1-33 Stator Leakage Reactance (Xl).*
9. *Parameter 1-35 Main Reactance (Xh).*

The data is found in the motor datasheet (this data is typically not available on the motor nameplate). Run a complete AMA using *parameter 1-29 Automatic Motor Adaption (AMA) [1] Enable Complete AMA* or enter the parameters manually.

Application-specific adjustment when running VVC⁺

VVC⁺ is the most robust control mode. In most situations, it provides optimum performance without further adjustments. Run a complete AMA for best performance.

5.4.2 PM Motor Set-up in VVC⁺

Initial programming steps

1. Set *parameter 1-10 Motor Construction* to the following options to activate PM motor operation:
 - 1a *[1] PM, non salient SPM*
 - 1b *[3] PM, salient IPM*
2. Select *[0] Open Loop* in *parameter 1-00 Configuration Mode*.

NOTICE

Encoder feedback is not supported for PM motors.

Programming motor data

After selecting 1 of the PM motor options in *parameter 1-10 Motor Construction*, the PM motor-related parameters in *parameter groups 1-2* Motor Data, 1-3* Adv. Motor Data, and 1-4* Adv. Motor Data II* are active. Find the information on the motor nameplate and in the motor datasheet.

Program the following parameters in the listed order:

1. *Parameter 1-24 Motor Current.*
2. *Parameter 1-26 Motor Cont. Rated Torque.*
3. *Parameter 1-25 Motor Nominal Speed.*
4. *Parameter 1-39 Motor Poles.*
5. *Parameter 1-30 Stator Resistance (Rs).*
Enter line-to-common stator winding resistance (Rs). If only line-line data is available, divide the line-line value by 2 to achieve the line-to-common (starpoint) value.
It is also possible to measure the value with an ohmmeter, which also takes the resistance of the cable into account. Divide the measured value by 2 and enter the result.
6. *Parameter 1-37 d-axis Inductance (Ld).*

Enter line-to-common direct axis inductance of the PM motor.

If only line-to-line data is available, divide the line-line value by 2 to achieve the line-common (starpoint) value.

It is also possible to measure the value with an inductance meter, which also takes the inductance of the cable into account. Divide the measured value by 2 and enter the result.

7. *Parameter 1-40 Back EMF at 1000 RPM.*

Enter line-to-line back EMF of the PM motor at 1000 RPM mechanical speed (RMS value). Back EMF is the voltage generated by a PM motor when no frequency converter is connected and the shaft is turned externally. Back EMF is normally specified for nominal motor speed or for 1000 RPM measured between 2 lines. If the value is not available for a motor speed of 1000 RPM, calculate the correct value as follows: For example, if back EMF at 1800 RPM is 320 V, the back EMF at 1000 RPM is:

$$\text{Back EMF} = (\text{Voltage} / \text{RPM}) \times 1000 = (320 / 1800) \times 1000 = 178.$$

Program this value for *parameter 1-40 Back EMF at 1000 RPM*.

Test motor operation

1. Start the motor at low speed (100–200 RPM). If the motor does not turn, check installation, general programming, and motor data.

Parking

This function is the recommended option for applications where the motor rotates at slow speed (for example windmilling in fan applications). *Parameter 2-06 Parking Current* and *parameter 2-07 Parking Time* are adjustable. Increase the factory setting of these parameters for applications with high inertia.

Start the motor at nominal speed. If the application does not run well, check the VVC⁺ PM settings. *Table 5.13* shows recommendations in different applications.

Application	Settings
Low inertia applications $I_{\text{Load}}/I_{\text{Motor}} < 5$	• Increase the value for <i>parameter 1-17 Voltage filter time const.</i> by factor 5–10. • Reduce the value for <i>parameter 1-14 Damping Gain</i>. • Reduce the value (<100%) for <i>parameter 1-66 Min. Current at Low Speed</i>.
Medium inertia applications $50 > I_{\text{Load}}/I_{\text{Motor}} > 5$	Keep calculated values.
High inertia applications $I_{\text{Load}}/I_{\text{Motor}} > 50$	Increase the values for <i>parameter 1-14 Damping Gain</i> , <i>parameter 1-15 Low Speed Filter Time Const.</i> , and <i>parameter 1-16 High Speed Filter Time Const.</i>
High load at low speed <30% (rated speed)	Increase the value for <i>parameter 1-17 Voltage filter time const.</i> Increase the value for <i>parameter 1-66 Min. Current at Low Speed</i> (>100% for longer time can overheat the motor).

Table 5.13 Recommendations in Different Applications

If the motor starts oscillating at a certain speed, increase *parameter 1-14 Damping Gain*. Increase the value in small steps.

Starting torque can be adjusted in *parameter 1-66 Min. Current at Low Speed*. 100% provides nominal torque as starting torque.

5.4.3 Automatic Motor Adaptation (AMA)

To optimize compatibility between the frequency converter and the motor in VVC⁺ mode, run AMA.

- The frequency converter builds a mathematical model of the motor for regulating output motor current, thus enhancing motor performance.
- Some motors may be unable to run the complete version of the test. In that case, select [2] *Enable reduced AMA* in *parameter 1-29 Automatic Motor Adaption (AMA)*.
- If warnings or alarms occur, see *chapter 8.4 List of Warnings and Alarms*.
- For best results, run this procedure on a cold motor.

To run AMA using the LCP

1. By default parameter setting, connect terminals 13 and 27 before running AMA.
2. Enter the *Main Menu*.
3. Go to *parameter group 1-** Load and Motor*.
4. Press [OK].
5. Set motor parameters using nameplate data for *parameter group 1-2* Motor Data*.
6. Set motor cable length in *parameter 1-42 Motor Cable Length*.
7. Go to *parameter 1-29 Automatic Motor Adaption (AMA)*.
8. Press [OK].
9. Select [1] *Enable complete AMA*.
10. Press [OK].
11. The test runs automatically and indicates when it is complete.

Depending on the power size, the AMA takes 3–10 minutes to complete.

NOTICE

The AMA function does not cause the motor to run and it does not harm the motor.

5.5 Checking Motor Rotation

Before running the frequency converter, check the motor rotation.

1. Press [Hand On].
2. Press [▲] for positive speed reference.
3. Check that the speed shown is positive.
4. Verify that the wiring between the frequency converter and the motor is correct.
5. Verify that the motor running direction matches the setting in *parameter 1-06 Clockwise Direction*.
 - 5a When *parameter 1-06 Clockwise Direction* is set to [0] *Normal* (default clockwise):
 - a. Verify that the motor turns clockwise.
 - b. Verify that the LCP direction arrow is clockwise.
 - 5b When *parameter 1-06 Clockwise Direction* is set to [1] *Inverse* (counterclockwise):

- a. Verify that the motor turns counterclockwise.
- b. Verify that the LCP direction arrow is counterclockwise.

5.6 Checking Encoder Rotation

Only check encoder rotation if encoder feedback is used.

1. Select [0] *Open Loop* in *parameter 1-00 Configuration Mode*.
2. Select [1] *24 V encoder* in *parameter 7-00 Speed PID Feedback Source*.
3. Press [Hand On].
4. Press [▲] for positive speed reference (*parameter 1-06 Clockwise Direction* at [0] *Normal*).
5. Check in *parameter 16-57 Feedback [RPM]* that the feedback is positive.

NOTICE**NEGATIVE FEEDBACK**

If the feedback is negative, the encoder connection is wrong. Use *parameter 5-71 Term 32/33 Encoder Direction* to inverse the direction, or reverse the encoder cables.

5.7 Local-control Test

1. Press [Hand On] to provide a local start command to the frequency converter.
2. Accelerate the frequency converter by pressing [▲] to full speed. Moving the cursor left of the decimal point provides quicker input changes.
3. Note any acceleration problems.
4. Press [Off]. Note any deceleration problems.

If acceleration or deceleration problems occur, see *chapter 8.5 Troubleshooting*. See *chapter 8.2 Warning and Alarm Types* for resetting the frequency converter after a trip.

5.8 System Start-up

The procedure in this section requires user-wiring and application programming to be completed. The following procedure is recommended after application set-up is completed.

1. Press [Auto On].
2. Apply an external run command.
3. Adjust the speed reference throughout the speed range.
4. Remove the external run command.

5. Check the sound and vibration levels of the motor to ensure that the system is working as intended.

If warnings or alarms occur, see *chapter 8.2 Warning and Alarm Types* for resetting the frequency converter after a trip.

5.9 STO Commissioning

Refer to *chapter 6 Safe Torque Off (STO)* for the correct installation and commissioning of STO.

6 Safe Torque Off (STO)

The Safe Torque Off (STO) function is a component in a safety control system. STO prevents the unit from generating the energy that is required to rotate the motor, thus ensuring safety in emergency situations.

The STO function is designed and approved suitable for the requirements of:

- IEC/EN 61508: 2010 SIL2
- IEC/EN 61800-5-2: 2007 SIL2
- IEC/EN 62061: 2012 SILCL of SIL2
- EN ISO 13849-1: 2008 Category 3 PL d

To achieve the required level of operational safety, select and apply the components in the safety control system appropriately. Before using STO, carry out a thorough risk analysis on the installation to determine whether the STO function and safety levels are appropriate and sufficient.

The STO function in the frequency converter is controlled via control terminals 37 and 38. When STO is activated, the power supply on the high side and low side of the IGBT gate driving circuits is cut off. *Illustration 6.1* shows the STO architecture. *Table 6.1* shows STO statuses based on whether terminals 37 and 38 are energized.

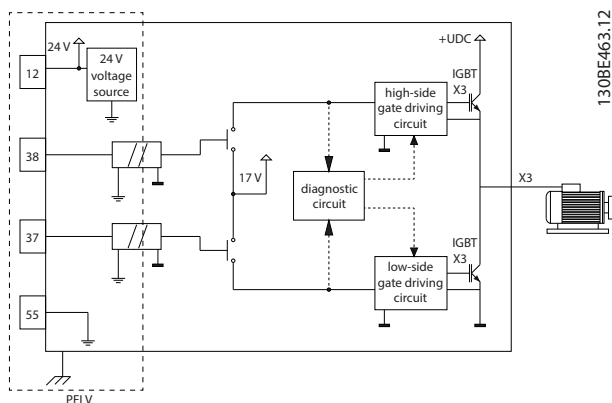


Illustration 6.1 STO Architecture

Terminal 37	Terminal 38	Torque	Warning or alarm
Energized ¹⁾	Energized	Yes ²⁾	No warnings or alarms.
De-energized ³⁾	De-energized	No	Warning/alarm 68: Safe Torque Off.
De-energized	Energized	No	Alarm 188: STO Function Fault.
Energized	De-energized	No	Alarm 188: STO Function Fault.

Table 6.1 STO Status

- 1) Voltage range is 24 V $\pm$ 5 V, with terminal 55 as the reference terminal.
- 2) Torque is present only when the frequency converter is operating.
- 3) Open circuit, or the voltage within the range of 0 V $\pm$ 1.5 V, with terminal 55 as the reference terminal.

Test pulse filtering

For safety devices that generate test pulses on the STO control lines: If the pulse signals stay at low level (≤ 1.8 V) for no longer than 5 ms, they are ignored, as shown in *Illustration 6.2*.

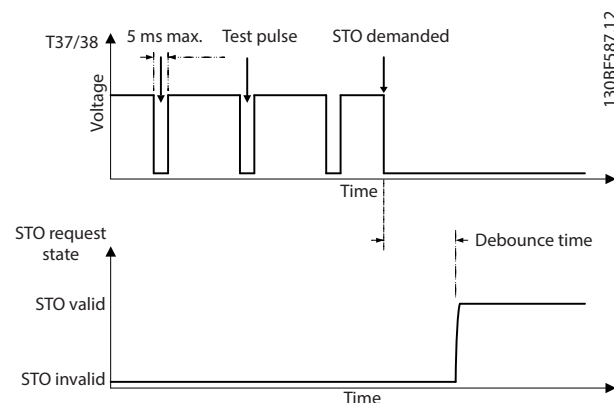


Illustration 6.2 Test Pulse Filtering

Asynchronous input tolerance

The input signals at the 2 terminals are not always synchronous. If the discrepancy between the 2 signals is longer than 12 ms, the STO fault alarm (alarm 188, STO Function Fault) occurs.

Valid signals

To activate STO, the 2 signals must both be at low level for at least 80 ms. To terminate STO, the 2 signals must both be at high level for at least 20 ms. Refer to *chapter 9.6 Control Input/Output and Control Data* for the voltage levels and input current of STO terminals.

6.1 Safety Precautions for STO

Qualified personnel

Only qualified personnel are allowed to install or operate this equipment.

Qualified personnel are defined as trained staff, who are authorized to install, commission, and maintain equipment, systems, and circuits in accordance with pertinent laws and regulations. Also, the personnel must be familiar with the instructions and safety measures described in this manual.

NOTICE

After installation of STO, perform a commissioning test as specified in *chapter 6.3.3 STO Commissioning Test*. A passed commissioning test is mandatory after first installation and after each change to the safety installation.

⚠ WARNING

RISK OF ELECTRICAL SHOCK

The STO function does NOT isolate mains voltage to the frequency converter or auxiliary circuits, and therefore does not provide electrical safety. Failure to isolate the mains voltage supply from the unit and wait the time specified could result in death or serious injury.

- Perform work on electrical parts of the frequency converter or the motor only after isolating the mains voltage supply and waiting the time specified in *chapter 2.3.1 Discharge Time*.

NOTICE

When designing the machine application, consider the timing and distance for a coast to stop (STO). For more information regarding stop categories, refer to EN 60204-1.

6.2 Safe Torque Off Installation

For motor connection, AC mains connection, and control wiring, follow the instructions for safe installation in *chapter 4 Electrical Installation*.

Enable the integrated STO as follows:

1. Remove the jumper between control terminals 12 (24 V), 37, and 38. Cutting or breaking the jumper is not sufficient to avoid short-circuiting. See the jumper in *Illustration 6.3*.

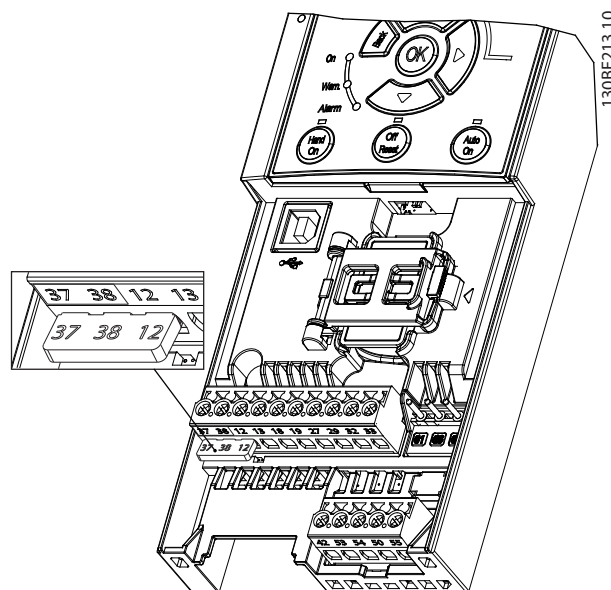
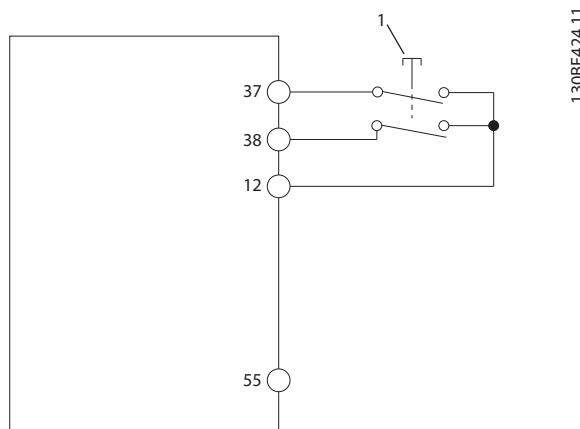


Illustration 6.3 Jumper between Terminal 12 (24 V), 37, and 38

2. Connect a dual-channel safety device (for example safety PLC, light curtain, safety relay, or emergency stop button) to terminals 37 and 38 to form a safety application. The device must comply with the required safety level based on the hazard assessment. *Illustration 6.4* shows the wiring schematic of STO applications where the frequency converter and the safety device are in the same cabinet. *Illustration 6.5* shows the wiring schematic of STO applications where external supply is used.

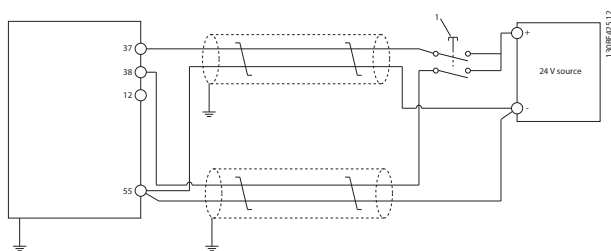
NOTICE

The STO signal must be PELV supplied.



1	Safety device
---	---------------

Illustration 6.4 STO Wiring in 1 Cabinet, the Frequency Converter Provides the Supply Voltage



1	Safety device
---	---------------

Illustration 6.5 STO Wiring, External Supply

3. Complete the wiring according to the instructions in *chapter 4 Electrical Installation*, and:
 - 3a Eliminate short circuit risks.
 - 3b Ensure that the STO cables are shielded if they are longer than 20 m (65.6 ft) or outside the cabinet.
 - 3c Connect the safety device directly to terminals 37 and 38.

6.3 STO Commissioning

6.3.1 Activation of Safe Torque Off

To activate the STO function, remove the voltage at terminals 37 and 38 of the frequency converter.

When STO is activated, the frequency converter issues *alarm 68, Safe Torque Off* or *warning 68, Safe Torque Off*, trips the unit, and coasts the motor to stop. Use the STO function to stop the frequency converter in emergency stop situations. In normal operating mode when STO is not required, use the standard stop function instead.

NOTICE

If STO is activated while the frequency converter issues *warning 8, DC undervoltage* or *alarm 8, DC undervoltage*, the frequency converter skips *alarm 68, Safe Torque Off*, but the STO operation is not affected.

6.3.2 Deactivation of Safe Torque Off

Follow the instructions in *Table 6.2* to deactivate the STO function and resume normal operation based on the restart mode of the STO function.

WARNING

RISK OF INJURY OR DEATH

Reapplying 24 V DC supply to either terminal 37 or 38 terminates the SIL2 STO state, potentially starting the motor. Unexpected motor start may cause personal injuries or death.

- Ensure that all safety measures are taken before reapplying 24 V DC supply to terminals 37 and 38.

Restart mode	Steps to deactivate STO and resume normal operation	Restart mode configuration
Manual restart	- Reapply 24 V DC supply to terminals 37 and 38. - Initiate a reset signal (via fieldbus, digital I/O, or [Reset]/[Off Reset] key on the LCP).	Default setting. <i>Parameter 5-19 Terminal 37/38 Safe Torque Off=[1] Safe Torque Off Alarm</i>
Automatic restart	Reapply 24 V DC supply to terminals 37 and 38.	<i>Parameter 5-19 Terminal 37/38 Safe Torque Off= [3] Safe Torque Off Warning.</i>

Table 6.2 STO Deactivation

6.3.3 STO Commissioning Test

After installation and before first operation, perform a commissioning test of the installation using STO. Perform the test again after each modification of the installation or application involving the STO.

NOTICE

A successful commissioning test of the STO function is required after the initial installation, and after each subsequent change to the installation.

To perform a commissioning test:

- Follow the instructions in *chapter 6.3.4 Test for STO Applications in Manual Restart Mode* if STO is set to manual restart mode.
- Follow the instructions in *chapter 6.3.5 Test for STO Applications in Automatic Restart Mode* if STO is set to automatic restart mode.

6.3.4 Test for STO Applications in Manual Restart Mode

For applications where *parameter 5-19 Terminal 37/38 Safe Torque Off* is set to the default value [1] *Safe Torque Off Alarm*, conduct the commissioning test as follows:

1. Set *parameter 5-40 Function Relay* to [190] *Safe Function active*.
2. Remove the 24 V DC voltage supply to terminals 37 and 38 using the safety device while the frequency converter drives the motor (that is, the mains supply is not interrupted).
3. Verify that:
 - 3a The motor coasts. It may take a long time for the motor to stop.
 - 3b If the LCP is mounted, *alarm 68, Safe Torque Off* shows on the LCP. If the LCP is not mounted, *alarm 68, Safe Torque Off* is logged in *parameter 15-30 Alarm Log: Error Code*.
4. Reapply 24 V DC to terminals 37 and 38.
5. Ensure that the motor remains in the coasted state, and the customer relay (if connected) remains activated.
6. Send reset signal (via fieldbus, digital I/O, or [Reset]/[Off Reset] key on the LCP).
7. Ensure that the motor becomes operational and runs within the original speed range.

The commissioning test is successfully completed when all the above-mentioned steps are passed.

6.3.5 Test for STO Applications in Automatic Restart Mode

For applications where *parameter 5-19 Terminal 37/38 Safe Torque Off* is set to [3] *Safe Torque Off Warning*, conduct the commissioning test as follows:

1. Remove the 24 V DC voltage supply to terminals 37 and 38 by the safety device while the frequency converter drives the motor (that is, the mains supply is not interrupted).
2. Verify that:
 - 2a The motor coasts. It may take a long time for the motor to stop.
 - 2b If the LCP is mounted *Warning 68, Safe Torque Off W68*, shows on the LCP. If the LCP is not mounted, *Warning 68, Safe Torque Off W68* is logged in bit 30 of *parameter 16-92 Warning Word*.
3. Reapply 24 V DC to terminals 37 and 38.

4. Ensure that the motor becomes operational and runs within the original speed range.

The commissioning test is successfully completed when all the above-mentioned steps are passed.

NOTICE

See the warning on the restart behavior in *chapter 6.1 Safety Precautions for STO*.

6.4 Maintenance and Service for STO

- The user is responsible for security measures.
- The frequency converter parameters can be protected with a password.

The functional test consists of 2 parts:

- Basic functional test.
- Diagnostic functional test.

When all the steps are completed successfully, the functional test is successful.

Basic functional test

If the STO function has not been used for 1 year, conduct a basic functional test to detect any failure or malfunction of STO.

1. Ensure that *parameter 5-19 Terminal 37/38 Safe Torque Off* is set to *[1] *Safe Torque Off Alarm*.
2. Remove the 24 V DC voltage supply for terminals 37 and 38.
3. Check if the LCP shows *alarm 68, Safe Torque Off*.
4. Verify that the frequency converter trips the unit.
5. Verify that the motor is coasting and stops completely.
6. Initiate a start signal (via fieldbus, digital I/O, or the LCP), and verify that the motor does not start.
7. Reconnect the 24 V DC voltage supply to terminals 37 and 38.
8. Verify that the motor is not started automatically and restarts only by giving a reset signal (via fieldbus, digital I/O, or [Reset]/[Off Reset] key on the LCP).

Diagnostic functional test

1. Verify that *warning 68, Safe Torque Off* and *alarm 68, Safe Torque Off* do not occur when 24 V supply is connected to terminals 37 and 38.
2. Remove the 24 V supply for terminal 37, and verify that the LCP shows *alarm 188, STO Function Fault* if the LCP is mounted. If the LCP is not mounted, verify that *alarm 188, STO Function Fault* is logged in *parameter 15-30 Alarm Log: Error Code*.
3. Reapply 24 V supply to terminal 37, and verify that resetting the alarm is successful.

4. Remove the 24 V supply for terminal 38 and verify that the LCP shows *alarm 188, STO Function Fault* if the LCP is mounted. If the LCP is not mounted, verify that *alarm 188, STO Function Fault* is logged in *parameter 15-30 Alarm Log: Error Code*.
5. Reapply 24 V supply to terminal 38 and verify that resetting the alarm is successful.

6.5 STO Technical Data

The Failure Modes, Effects, and Diagnostic Analysis (FMEDA) is performed based on the following assumptions:

- VLT® Midi Drive FC 280 takes 10% of the total failure budget for an SIL2 safety loop.
- Failure rates are based on the Siemens SN29500 database.
- Failure rates are constant; wear-out mechanisms are not included.
- For each channel, the safety-related components are considered to be of type A with a hardware fault tolerance of 0.
- The stress levels are average for an industrial environment and the working temperature of components is up to 85 °C (185 °F).
- A safe error (for example output in safe state) is repaired within 8 hours.
- No torque output is the safe state.

Safety standards	Safety of Machinery	ISO 13849-1, IEC 62061
	Functional Safety	IEC 61508
Safety function	Safe Torque Off	IEC 61800-5-2
Safety performance	ISO 13849-1	
	Category	Cat. 3
	Diagnostic coverage (DC)	60% (Low)
	Mean time to dangerous failure (MTTFd)	2400 years (High)
	Performance level	PL d
	IEC 61508/IEC 61800-5-2/IEC 62061	
	Safety Integrity Level	SIL2
	Probability of dangerous failure per hour (PFH) (high demand mode)	7.54E-9 (1/h)
	Probability of dangerous failure on demand (PFD _{avg} for PTI = 20 years) (low demand mode)	6.05E-4
	Safe failure fraction (SFF)	For dual-channel parts: >84%
		For single-channel parts: >99%
	Hardware fault tolerance (HFT)	For dual-channel parts: HFT = 1
		For single-channel parts: HFT = 0
	Proof test interval ²⁾	20 years
	Common cause failure (CCF)	$\beta = 5\%$; $\beta_D = 5\%$
	Diagnostic test interval (DTI)	160 ms
	Systematic capability	SC 2
Reaction time ¹⁾	Input to output response time	Enclosure sizes K1–K3: Maximum 50 ms Enclosure sizes K4 and K5: Maximum 30 ms

Table 6.3 Technical Data for STO

1) Reaction time is the amount of time from an input signal condition triggers the STO until the torque is off on the motor.

2) For proof test procedure, refer to chapter 6.4 Maintenance and Service for STO.

7 Application Examples

7.1 Introduction

The examples in this section are intended as a quick reference for common applications.

- Parameter settings are the regional default values unless otherwise indicated (selected in *parameter 0-03 Regional Settings*).
- Parameters associated with the terminals and their settings are shown next to the drawings.
- Required switch settings for analog terminals 53 or 54 are also shown.

NOTICE

When the STO feature is not used, a jumper wire is required between terminals 12, 37, and 38 for the frequency converter to operate with factory default programming values.

7.2 Application Examples

7.2.1 AMA

		Parameters	
FC		Function	Setting
+24 V	12	Parameter 1-29 Automatic Motor Adaptation (AMA)	[1] Enable complete AMA
+24 V	13		
D IN	18		
D IN	19		
D IN	27	Parameter 5-12 Terminal 27 Digital Input	*[2] Coast inverse
D IN	29		
D IN	32		
D IN	33		
		* = Default value	
		Notes/comments: Set parameter group 1-2* Motor Data according to motor specifications.	
		NOTICE If terminal 13 and 27 are not connected, set parameter 5-12 Terminal 27 Digital Input to [0] No operation.	
+10 V	50		
A IN	53		
A IN	54		
COM	55		
A OUT	42		

Table 7.1 AMA with T27 Connected

7.2.2 Speed

		Parameters	
FC		Function	Setting
+24 V	12	Parameter 6-10 Terminal 53 Low Voltage	0.07 V*
+24 V	13		
D IN	18		
D IN	19		
D IN	27	Parameter 6-11 Terminal 53 High Voltage	10 V*
D IN	29		
D IN	32		
D IN	33		
+10 V	50		
A IN	53	Parameter 6-14 Terminal 53 Low Ref./Feedb. Value	0
A IN	54	Parameter 6-15 Terminal 53 High Ref./Feedb. Value	50
COM	55	Parameter 6-19 Terminal 53 mode	[1] Voltage
A OUT	42		
		* = Default value	
		Notes/comments:	

Table 7.2 Analog Speed Reference (Voltage)

		Parameters	
FC		Function	Setting
+24 V	12	Parameter 6-22 Terminal 54 Low Current	4 mA*
+24 V	13		
D IN	18		
D IN	19		
D IN	27	Parameter 6-23 Terminal 54 High Current	20 mA*
D IN	29		
D IN	32		
D IN	33		
+10 V	50		
A IN	53	Parameter 6-24 Terminal 54 Low Ref./Feedb. Value	0
A IN	54	Parameter 6-25 Terminal 54 High Ref./Feedb. Value	50
COM	55	Parameter 6-29 Terminal 54 mode	[0] Current
A OUT	42		
		* = Default value	
		Notes/comments:	

Table 7.3 Analog Speed Reference (Current)

		Parameters		
FC		Function	Setting	
+24 V	12	130BE208.11 Parameter 6-10 Terminal 53 Low Voltage	0.07 V*	
+24 V	13			
D IN	18			
D IN	19			
D IN	27			
D IN	29			
D IN	32	Parameter 6-11 Terminal 53 High Voltage	10 V*	
D IN	33			
+10 V	50	Parameter 6-14 Terminal 53 Low Ref./Feedb. Value	0	
A IN	53			
A IN	54			
COM	55	Parameter 6-15 Terminal 53 High Ref./Feedb. Value	50	
A OUT	42			
		* = Default value		
		Notes/comments:		

Table 7.4 Speed Reference (Using a Manual Potentiometer)

		Parameters		
FC		Function	Setting	
+24 V	12	130BF100.10	Parameter 5-10 Terminal 18 Digital Input	
+24 V	13		*[8] Start	
D IN	18		Parameter 5-12 Terminal 27 Digital Input	
D IN	19			[19] Freeze Reference
D IN	27			
D IN	29		Parameter 5-13 Terminal 29 Digital Input	
D IN	32	[21] Speed Up		
D IN	33	Parameter 5-14 Terminal 32 Digital Input		
+10 V	50		[22] Speed Down	
A IN	53		* = Default value	
A IN	54	Notes/comments:		
COM	55			
A OUT	42			

Table 7.5 Speed Up/Speed Down

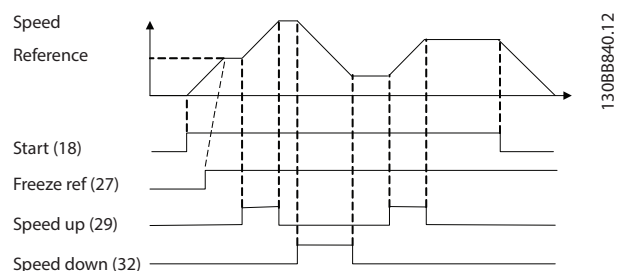


Illustration 7.1 Speed Up/Speed Down

7.2.3 Start/Stop

		Parameters	
FC		Function	Setting
+24 V	12	130BF098.10	Parameter 5-10 Terminal 18 Digital Input
+24 V	13		
D IN	18		
D IN	19		
D IN	27		
D IN	29		
D IN	32	Parameter 5-11 Terminal 19 Digital Input	*[10] Reversing
D IN	33		
D IN	33		
+10 V	50	Parameter 5-12 Terminal 27 Digital Input	[0] No operation
A IN	53		
A IN	54		
COM	55	Parameter 5-14 Terminal 32 Digital Input	[16] Preset ref bit 0
A OUT	42		
A OUT	42		
		Parameter 5-15 Terminal 33 Digital Input	[17] Preset ref bit 1
		Parameter 3-10 Preset Reference	
		* = Default value	
		Notes/comments:	

Table 7.6 Start/Stop with Reversing and 4 Preset Speeds

7.2.4 External Alarm Reset

Parameters	
Function	Setting
Parameter 5-11 Terminal 19 Digital Input	[1] Reset
* = Default value	
Notes/comments:	

Table 7.7 External Alarm Reset

7.2.5 Motor Thermistor

NOTICE

To meet PELV insulation requirements, use reinforced or double insulation on the thermistors.

Parameters	
Function	Setting
Parameter 1-90 Motor Thermal Protection	[2] Thermistor trip
Parameter 1-93 Thermistor Source	[1] Analog input 53
Parameter 6-19 Terminal 53 mode	[1] Voltage
* = Default value	
Notes/comments:	

If only a warning is needed, set parameter 1-90 Motor Thermal Protection to [1] Thermistor warning.

Table 7.8 Motor Thermistor

7.2.6 SLC

Parameters	
Function	Setting
Parameter 4-30 Motor Feedback Loss Function	[1] Warning
Parameter 4-31 Motor Feedback Speed Error	50
Parameter 4-32 Motor Feedback Loss Timeout	5 s
Parameter 7-00 Speed PID Feedback Source	[1] 24 V encoder
Parameter 5-70 Term 32/33 Pulses Per Revolution	1024*
Parameter 13-00 SL Controller Mode	[1] On
Parameter 13-01 Start Event	[19] Warning
Parameter 13-02 Stop Event	[44] Reset key
Parameter 13-10 Comparator Operand	[21] Warning no.
Parameter 13-11 Comparator Operator	*[1] ≈
Parameter 13-12 Comparator Value	61
Parameter 13-51 SL Controller Event	[22] Comparator 0
Parameter 13-52 SL Controller Action	[32] Set digital out A low
Parameter 5-40 Function Relay	[80] SL digital output A
* = Default value	
Notes/comments:	

If the limit in the feedback monitor is exceeded, warning 61, feedback monitor is issued. The SLC monitors warning 61, feedback monitor. If warning 61, feedback monitor becomes true, relay 1 is triggered. External equipment could indicate that service is required. If the feedback error goes below the limit again within 5 s, the frequency converter continues, and the warning disappears. Relay 1 persists until [Off/Reset] is pressed.

Table 7.9 Using SLC to Set a Relay

8 Maintenance, Diagnostics, and Troubleshooting

8.1 Maintenance and Service

Under normal operating conditions and load profiles, the frequency converter is maintenance-free throughout its designed lifetime. To prevent breakdown, danger, and damage, examine the frequency converter for terminal connections tightness, dust entry, and so on at regular intervals depending on the operating conditions. Replace worn or damaged parts with original spare parts or standard parts. For service and support, contact the local Danfoss supplier.

⚠ WARNING

UNINTENDED START

When the frequency converter is connected to AC mains, DC supply, or load sharing, the motor may start at any time. Unintended start during programming, service, or repair work can result in death, serious injury, or property damage. The motor can start with an external switch, a fieldbus command, an input reference signal from the LCP, via remote operation using MCT 10 Set-up Software, or after a cleared fault condition.

To prevent unintended motor start:

- Disconnect the frequency converter from the mains.
- Press [Off/Reset] on the LCP before programming parameters.
- Completely wire and assemble the frequency converter, motor, and any driven equipment before connecting the frequency converter to AC mains, DC supply, or load sharing.

8.2 Warning and Alarm Types

Warning/ alarm type	Description
Warning	A warning indicates an abnormal operating condition that leads to an alarm. A warning stops when the abnormal condition is removed.
Alarm	An alarm indicates a fault that requires immediate attention. The fault always triggers a trip or trip lock. Reset the drive after an alarm. Reset the drive in any of 4 ways: • Press [Reset]/[Off/Reset]. • Digital reset input command. • Serial communication reset input command. • Auto reset.

Trip

When tripping, the drive suspends operation to prevent damage to the drive and other equipment. When a trip occurs, the motor coasts to a stop. The drive logic continues to operate and monitor the drive status. After the fault condition is remedied, the drive is ready for a reset.

Trip lock

When trip locking, the drive suspends operation to prevent damage to the drive and other equipment. When a trip lock occurs, the motor coasts to a stop. The drive logic continues to operate and monitor the drive status. The drive starts a trip lock only when serious faults occur that can damage the drive or other equipment. After the faults are fixed, cycle the input power before resetting the drive.

8.3 Warning and Alarm Display

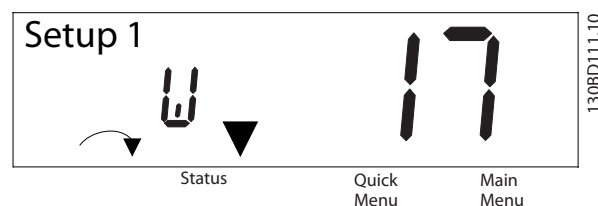


Illustration 8.1 Warning Display

An alarm or trip-lock alarm shows in the display along with the alarm number.

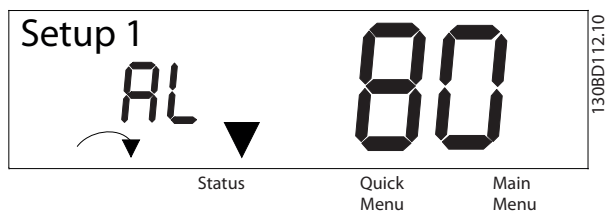


Illustration 8.2 Alarm/Trip Lock Alarm

In addition to the text and alarm code on the frequency converter display, there are 3 status indicator lights. The warning indicator light is yellow during a warning. The alarm indicator light is red and flashing during an alarm.

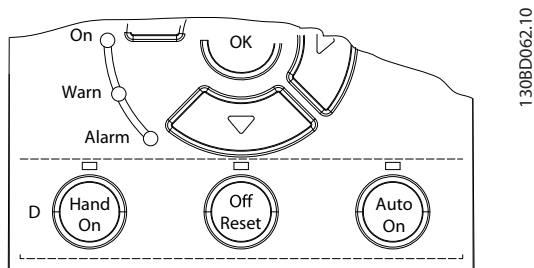


Illustration 8.3 Status Indicator Lights

8.4 List of Warnings and Alarms

8.4.1 Warning and Alarm Code List

An (X) marked in *Table 8.1* indicates that the warning or alarm has occurred.

No.	Description	Warning	Alarm	Trip lock	Cause
2	Live zero error	X	X	–	The signal on terminal 53 or 54 is less than 50% of the value set in <i>parameter 6-10 Terminal 53 Low Voltage</i> , <i>parameter 6-20 Terminal 54 Low Voltage</i> , and <i>parameter 6-22 Terminal 54 Low Current</i> .
3	No motor	X	–	–	No motor has been connected to the output of the frequency converter.
4	Mains phase loss ¹⁾	X	X	X	Missing phase on the supply side, or the voltage imbalance is too high. Check the supply voltage.
7	DC overvoltage ¹⁾	X	X	–	DC-link voltage exceeds limit.
8	DC undervoltage ¹⁾	X	X	–	DC-link voltage drops below the voltage warning low limit.
9	Inverter overloaded	X	X	–	More than 100% load for too long.
10	Motor ETR overtemperature	X	X	–	Motor is too hot due to more than 100% load for too long.
11	Motor thermistor overtemperature	X	X	–	Thermistor or thermistor connection is disconnected, or the motor is too hot.
12	Torque limit	X	X	–	Torque exceeds the value set in either <i>parameter 4-16 Torque Limit Motor Mode</i> or <i>parameter 4-17 Torque Limit Generator Mode</i> .
13	Overcurrent	X	X	X	Inverter peak current limit is exceeded. If this alarm occurs on power-up, check whether power cables are mistakenly connected to the motor terminals.
14	Ground fault	–	X	X	Discharge from output phases to ground.
16	Short circuit	–	X	X	Short circuit in motor or on motor terminals.
17	Control word timeout	X	X	–	No communication to frequency converter.
25	Brake resistor short-circuited	–	X	X	Brake resistor is short-circuited, thus the brake function is disconnected.
26	Brake overload	X	X	–	The power transmitted to the brake resistor over the last 120 s exceeds the limit. Possible corrections: Decrease brake energy via lower speed or longer ramp time.
27	Brake IGBT/brake chopper short-circuited	–	X	X	Brake transistor is short-circuited, thus the brake function is disconnected.
28	Brake check	–	X	–	Brake resistor is not connected/working.
30	U phase loss	–	X	X	Motor phase U is missing. Check the phase.
31	V phase loss	–	X	X	Motor phase V is missing. Check the phase.
32	W phase loss	–	X	X	Motor phase W is missing. Check the phase.
34	Fieldbus fault	X	X	–	PROFIBUS communication issues have occurred.
35	Option fault	–	X	–	Fieldbus detects internal faults.
36	Mains failure	X	X	–	This warning/alarm is only active if the supply voltage to the frequency converter is less than the value set in <i>parameter 14-11 Mains Fault Voltage Level</i> , and <i>parameter 14-10 Mains Failure</i> is NOT set to [0] No Function.
38	Internal fault	–	X	X	Contact the local Danfoss supplier.
40	Overload T27	X	–	–	Check the load connected to terminal 27 or remove short-circuit connection.
46	Gate drive voltage fault	–	X	X	–
47	24 V supply low	X	X	X	24 V DC may be overloaded.

No.	Description	Warning	Alarm	Trip lock	Cause
49	Speed limit	–	X	–	The motor speed is below the specified limit in <i>parameter 1-87 Trip Speed Low [Hz]</i> .
50	AMA calibration failed	–	X	–	A calibration error has occurred.
51	AMA check U_{nom} and I_{nom}	–	X	–	Wrong setting for motor voltage and/or motor current.
52	AMA low I_{nom}	–	X	–	Motor current is too low. Check the settings.
53	AMA big motor	–	X	–	The power size of the motor is too large for the AMA to operate.
54	AMA small motor	–	X	–	The power size of the motor is too small for the AMA to operate.
55	AMA parameter range	–	X	–	The parameter values of the motor are outside of the acceptable range. AMA does not run.
56	AMA interrupt	–	X	–	The AMA is interrupted.
57	AMA timeout	–	X	–	–
58	AMA internal	–	X	–	Contact Danfoss.
59	Current limit	X	X	–	Frequency converter overload.
60	External interlock	–	X	–	External interlock has been activated.
61	Encoder loss	X	X	–	–
63	Mechanical brake low	–	X	–	The actual motor current has not exceeded the release brake current within the start delay time window.
65	Control card temp	X	X	X	The cutout temperature of the control card has exceeded the upper limit.
67	Option change	–	X	–	A new option is detected or a mounted option is removed.
68	Safe Torque Off ²⁾	X	X	–	STO is activated. If STO is in manual restart mode (default), to resume normal operation, apply 24 V DC to terminals 37 and 38, and initiate a reset signal (via fieldbus, digital I/O, or [Reset]/[Off Reset] key). If STO is in automatic restart mode, applying 24 V DC to terminals 37 and 38 automatically resumes the frequency converter to normal operation.
69	Power card temp	X	X	X	The cutout temperature of the power card has exceeded the upper limit.
80	Drive initialized to default value	–	X	–	All parameter settings are initialized to default settings.
87	Auto DC braking	X	–	–	Occurs in IT mains when the frequency converter coasts, and the DC voltage is higher than 830 V for 400 V units and 425 V for 200 V units. The motor consumes energy on the DC link. This function can be enabled/disabled in <i>parameter 0-07 Auto DC Braking</i> .
88	Option detection	–	X	X	The option is removed successfully.
95	Broken belt	X	X	–	–
99	Locked rotor	–	X	–	Rotor is blocked.
120	Position control fault	–	X	–	–
126	Motor rotating	–	X	–	PM motor is rotating when AMA is performed.
127	Back EMF too high	X	–	–	The back EMF of PM motor is too high before starting.
188	STO internal fault ²⁾	–	X	–	24 V DC supply is connected to only 1 of the 2 STO terminals (37 and 38), or a failure in STO channels is detected. Ensure that both terminals are powered by a 24 V DC supply, and that the discrepancy between the signals at the 2 terminals is less than 12 ms. If the fault still occurs, contact the local Danfoss supplier.
nw run	Not while running	–	–	–	Parameters can only be changed when the motor is stopped.

No.	Description	Warning	Alarm	Trip lock	Cause
Err.	A wrong password was entered	–	–	–	Occurs when using a wrong password for changing a password-protected parameter.

Table 8.1 Warnings and Alarms Code List

1) Mains distortions may cause these faults. Installing a Danfoss line filter may rectify this problem.

2) This alarm cannot be reset via parameter 14-20 Reset Mode automatically.

For diagnosis, read out the alarm words, warning words, and extended status words.

Bit	Hex	Dec	Alarm word (parameter 1 6-90 Alarm Word)	Alarm word 2 (parameter 16-91 Alarm Word 2)	Alarm word 3 (parameter 1 6-97 Alarm Word 3)	Warning word (parameter 16- 92 Warning Word)	Warning word 2 (parameter 16 -93 Warning Word 2)	Extended status word (parameter 16- 94 Ext. Status Word)	Extended status word 2 (parameter 16-95 Ext . Status Word 2)
0	000000 01	1	Brake check	Reserved	STO function fault	Reserved	Reserved	Ramping	Off
1	000000 02	2	Pwr. card temp	Gate drive voltage fault	MM alarm	Pwr. card temp	Reserved	AMA tuning	Hand/Auto
2	000000 04	4	Earth fault	Reserved	Reserved	Reserved	Reserved	Start CW/CCW	Profibus OFF1 active
3	000000 08	8	Ctrl. card temp	Reserved	Reserved	Ctrl. card temp	Reserved	Slowdown	Profibus OFF2 active
4	000000 10	16	Ctrl. word TO	Reserved	Reserved	Ctrl. word TO	Reserved	Catchup	Profibus OFF3 active
5	000000 20	32	Overcurrent	Reserved	Reserved	Overcurrent	Reserved	Feedback high	Reserved
6	000000 40	64	Torque limit	Reserved	Reserved	Torque limit	Reserved	Feedback low	Reserved
7	000000 80	128	Motor Th. over	Reserved	Reserved	Motor Th. over	Reserved	Output current high	Control ready
8	000001 00	256	Motor ETR over	Broken belt	Reserved	Motor ETR over	Broken belt	Output current low	Frequency converter ready
9	000002 00	512	Inverter overld.	Reserved	Reserved	Inverter overld.	Reserved	Output freq. high	Quick stop
10	000004 00	1024	DC undervolt.	Start failed	Reserved	DC undervolt.	Reserved	Output freq. low	DC brake
11	000008 00	2048	DC overvolt.	Speed limit	Reserved	DC overvolt.	Reserved	Brake check OK	Stop
12	000010 00	4096	Short circuit	External interlock	Reserved	Reserved	Reserved	Braking max	Reserved
13	000020 00	8192	Reserved	Reserved	Reserved	Reserved	Reserved	Braking	Freeze output request
14	000040 00	16384	Mains ph. loss	Reserved	Reserved	Mains ph. loss	Reserved	Reserved	Freeze output
15	000080 00	32768	AMA not OK	Reserved	Reserved	No motor	Auto DC braking	OVC active	Jog request
16	000100 00	65536	Live zero error	Reserved	Reserved	Live zero error	Reserved	AC brake	Jog
17	000200 00	131072	Internal fault	Reserved	Reserved	Reserved	Reserved	Reserved	Start request

Bit	Hex	Dec	Alarm word (parameter 1 6-90 Alarm Word)	Alarm word 2 (parameter 16-91 Alarm Word 2)	Alarm word 3 (parameter 1 6-97 Alarm Word 3)	Warning word (parameter 16- 92 Warning Word)	Warning word 2 (parameter 16 -93 Warning Word 2)	Extended status word (parameter 16- 94 Ext. Status Word)	Extended status word 2 (parameter 16-95 Ext . Status Word 2)
18	000400 00	262144	Brake overload	Reserved	Reserved	Brake resistor power limit	Reserved	Reserved	Start
19	000800 00	524288	U phase loss	Reserved	Reserved	Reserved	Reserved	Reference high	Reserved
20	001000 00	1048576	V phase loss	Option detection	Reserved	Reserved	Overload T27	Reference low	Start delay
21	002000 00	2097152	W phase loss	Option fault	Reserved	Reserved	Reserved	Reserved	Sleep
22	004000 00	4194304	Fieldbus fault	Locked rotor	Reserved	Fieldbus fault	Memory module	Reserved	Sleep boost
23	008000 00	8388608	24 V supply low	Position ctrl. fault	Reserved	24 V supply low	Reserved	Reserved	Running
24	010000 00	16777216	Mains failure	Reserved	Reserved	Mains failure	Reserved	Reserved	Bypass
25	020000 00	33554432	Reserved	Current limit	Reserved	Current limit	Reserved	Reserved	Reserved
26	040000 00	67108864	Brake resistor	Reserved	Reserved	Reserved	Reserved	Reserved	External interlock
27	080000 00	13421772 8	Brake IGBT	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved
28	100000 00	26843545 6	Option change	Reserved	Reserved	Encoder loss	Reserved	Reserved	FlyStart active
29	200000 00	53687091 2	Frequency converter initialized	Encoder loss	Reserved	Reserved	Back EMF too high	Reserved	Heat sink clean warning
30	400000 00	10737418 24	Safe Torque Off	Reserved	Reserved	Safe Torque Off	Reserved	Reserved	Reserved
31	800000 00	21474836 48	Mech. brake low	Reserved	Reserved	Reserved	Reserved	Database busy	Reserved

Table 8.2 Description of Alarm Word, Warning Word, and Extended Status Word

8.5 Troubleshooting

Symptom	Possible cause	Test	Solution
Motor not running	LCP stop	Check if [Off] has been pressed.	Press [Auto On] or [Hand On] (depending on operating mode) to run the motor.
	Missing start signal (standby)	Check <i>parameter 5-10 Terminal 18 Digital Input</i> of correct setting for terminal 18 (use default setting).	Apply a valid start signal to start the motor.
	Motor coast signal active (coasting)	Check <i>parameter 5-12 Terminal 27 Digital Input</i> for correct setting of terminal 27 (use default setting).	Apply 24 V on terminal 27 or program this terminal to [0] No operation.
	Wrong reference signal source	Check the following: - The reference signal is local, remote, or bus reference? - Preset reference is active? - Terminal connection is correct? - The scaling of terminals is correct? - The reference signal is available?	Program correct settings. Set preset reference active in <i>parameter group 3-1* References</i> . Check for correct wiring. Check scaling of terminals. Check reference signal.
Motor is running in the wrong direction	Motor rotation limit	Check that <i>parameter 4-10 Motor Speed Direction</i> is programmed correctly.	Program correct settings.
	Active reversing signal	Check if a reversing command is programmed for the terminal in <i>parameter group 5-1* Digital inputs</i> .	Deactivate reversing signal.
	Wrong motor phase connection	Change <i>parameter 1-06 Clockwise Direction</i> .	
Motor is not reaching maximum speed	Frequency limits are set incorrectly	Check output limits in <i>parameter 4-14 Motor Speed High Limit [Hz]</i> and <i>parameter 4-19 Max Output Frequency</i> .	Program correct limits.
	Reference input signal not scaled correctly	Check reference input signal scaling in <i>parameter group 6-** Analog I/O mode</i> and <i>parameter group 3-1* References</i> .	Program correct settings.
Motor speed is unstable	Possible incorrect parameter settings	Check the settings of all motor parameters, including all motor compensation settings. For closed-loop operation, check PID settings.	Check settings in <i>parameter group 6-** Analog I/O mode</i> .
Motor runs roughly	Possible overmagnetization	Check for incorrect motor settings in all motor parameters.	Check motor settings in <i>parameter groups 1-2* Motor data, 1-3* Adv motor data, and 1-5* Load indep. setting</i> .
Motor does not brake	Possible incorrect settings in the brake parameters. Possible too short ramp-down times.	Check brake parameters. Check ramp time settings.	Check <i>parameter groups 2-0* DC brake and 3-0* Reference limits</i> .

Symptom	Possible cause	Test	Solution
Open power fuses or circuit breaker trip	Phase-to-phase short	Motor or panel has a short phase-to-phase. Check motor and panel phase for shorts.	Eliminate any shorts detected.
	Motor overload	Motor is overloaded for the application.	Perform the start-up test and verify that motor current is within specifications. If motor current exceeds the nameplate full load current, the motor may run only with reduced load. Review the specifications for the application.
	Loose connections	Perform pre-start-up check for loose connections.	Tighten loose connections.
Mains current imbalance greater than 3%	Problem with mains power (see <i>alarm 4, Mains phase loss</i> description)	Rotate input power leads into the frequency converter 1 position: A to B, B to C, C to A.	If the imbalanced leg follows the wire, it is a power problem. Check mains supply.
	Problem with the frequency converter unit	Rotate input power leads into the frequency converter 1 position: A to B, B to C, C to A.	If the imbalanced leg stays on same input terminal, it is a problem with the unit. Contact the supplier.
Motor current imbalance greater than 3%	Problem with motor or motor wiring	Rotate output motor leads 1 position: U to V, V to W, W to U.	If the imbalanced leg follows the wire, the problem is in the motor or motor wiring. Check motor and motor wiring.
	Problem with the frequency converter unit	Rotate output motor leads 1 position: U to V, V to W, W to U.	If the imbalanced leg stays on same output terminal, it is a problem with the unit. Contact the supplier.
Acoustic noise or vibration (for example a fan blade is making noise or vibrations at certain frequencies)	Resonances, for example, in the motor/fan system	Bypass critical frequencies by using parameters in <i>parameter group 4-6* Speed Bypass</i> .	Check if noise and/or vibration have been reduced to an acceptable limit.
		Turn off overmodulation in <i>parameter 14-03 Overmodulation</i> .	
		Increase resonance damping in <i>parameter 1-64 Resonance Dampening</i> .	

Table 8.3 Troubleshooting

9 Specifications

9.1 Electrical Data

Frequency converter typical shaft output [kW (hp)]	PK37 0.37 (0.5)	PK55 0.55 (0.75)	PK75 0.75 (1.0)	P1K1 1.1 (1.5)	P1K5 1.5 (2.0)	P2K2 2.2 (3.0)	P3K0 3.0 (4.0)
Enclosure protection rating IP20 (IP21/Type 1 as option)	K1	K1	K1	K1	K1	K1	K2
Output current							
Shaft output [kW]	0.37	0.55	0.75	1.1	1.5	2.2	3
Continuous (3x380–440 V) [A]	1.2	1.7	2.2	3	3.7	5.3	7.2
Continuous (3x441–480 V) [A]	1.1	1.6	2.1	2.8	3.4	4.8	6.3
Intermittent (60 s overload) [A]	1.9	2.7	3.5	4.8	5.9	8.5	11.5
Continuous kVA (400 V AC) [kVA]	0.9	1.2	1.5	2.1	2.6	3.7	5.0
Continuous kVA (480 V AC) [kVA]	0.9	1.3	1.7	2.5	2.8	4.0	5.2
Maximum input current							
Continuous (3x380–440 V) [A]	1.2	1.6	2.1	2.6	3.5	4.7	6.3
Continuous (3x441–480 V) [A]	1.0	1.2	1.8	2.0	2.9	3.9	4.3
Intermittent (60 s overload) [A]	1.9	2.6	3.4	4.2	5.6	7.5	10.1
More specifications							
Maximum cable cross-section (mains, motor, brake, and load sharing) [mm ² (AWG)]	4 (12)						
Estimated power loss at rated maximum load [W] ¹⁾	20.9	25.2	30	40	52.9	74	94.8
Weight, enclosure protection rating IP20 [kg (lb)]	2.3 (5.1)	2.3 (5.1)	2.3 (5.1)	2.3 (5.1)	2.3 (5.1)	2.5 (5.5)	3.6 (7.9)
Weight, enclosure protection rating IP21 [kg (lb)]	4.0 (8.8)	4.0 (8.8)	4.0 (8.8)	4.0 (8.8)	4.0 (8.8)	4.0 (8.8)	5.5 (12.1)
Efficiency [%] ²⁾	96.0	96.6	96.8	97.2	97.0	97.5	98.0

Table 9.1 Mains Supply 3x380–480 V AC

Specifications

VLT® Midi Drive FC 280

Frequency converter typical shaft output [kW (hp)]	P4K0 4 (5.5)	P5K5 5.5 (7.5)	P7K5 7.5 (10)	P11K 11 (15)	P15K 15 (20)	P18K 18.5 (25)	P22K 22 (30)
Enclosure protection rating IP20 (IP21/Type 1 as option)	K2	K2	K3	K4	K4	K5	K5
Output current							
Shaft output	4	5.5	7.5	11	15	18.5	22
Continuous (3x380–440 V) [A]	9	12	15.5	23	31	37	42.5
Continuous (3x441–480 V) [A]	8.2	11	14	21	27	34	40
Intermittent (60 s overload) [A]	14.4	19.2	24.8	34.5	46.5	55.5	63.8
Continuous kVA (400 V AC) [kVA]	6.2	8.3	10.7	15.9	21.5	25.6	29.5
Continuous kVA (480 V AC) [kVA]	6.8	9.1	11.6	17.5	22.4	28.3	33.3
Maximum input current							
Continuous (3x380–440 V) [A]	8.3	11.2	15.1	22.1	29.9	35.2	41.5
Continuous (3x441–480 V) [A]	6.8	9.4	12.6	18.4	24.7	29.3	34.6
Intermittent (60 s overload) [A]	13.3	17.9	24.2	33.2	44.9	52.8	62.3
More specifications							
Maximum cable cross-section (mains, motor, brake, and load sharing) [mm ² (AWG)]	4 (12)			16 (6)			
Estimated power loss at rated maximum load [W] ¹⁾	115.5	157.5	192.8	289.5	393.4	402.8	467.5
Weight enclosure protection rating IP20 [kg (lb)]	3.6 (7.9)	3.6 (7.9)	4.1 (9.0)	9.4 (20.7)	9.5 (20.9)	12.3 (27.1)	12.5 (27.6)
Weight enclosure protection rating IP21 [kg (lb)]	5.5 (12.1)	5.5 (12.1)	6.5 (14.3)	10.5 (23.1)	10.5 (23.1)	14.0 (30.9)	14.0 (30.9)
Efficiency [%] ²⁾	98.0	97.8	97.7	98.0	98.1	98.0	98.0

Table 9.2 Mains Supply 3x380–480 V AC

Frequency converter typical shaft output [kW (hp)]	PK37 0.37 (0.5)	PK55 0.55 (0.75)	PK75 0.75 (1.0)	P1K1 1.1 (1.5)	P1K5 1.5 (2.0)	P2K2 2.2 (3.0)	P3K7 3.7 (5.0)
Enclosure protection rating IP20 (IP21/Type 1 as option)	K1	K1	K1	K1	K1	K2	K3
Output current							
Continuous (3x200–240 V) [A]	2.2	3.2	4.2	6	6.8	9.6	15.2
Intermittent (60 s overload) [A]	3.5	5.1	6.7	9.6	10.9	15.4	24.3
Continuous kVA (230 V AC) [kVA]	0.9	1.3	1.7	2.4	2.7	3.8	6.1
Maximum input current							
Continuous (3x200–240 V) [A]	1.8	2.7	3.4	4.7	6.3	8.8	14.3
Intermittent (60 s overload) [A]	2.9	4.3	5.4	7.5	10.1	14.1	22.9
More specifications							
Maximum cable cross-section (mains, motor, brake, and load sharing) [mm ² (AWG)]	4 (12)						
Estimated power loss at rated maximum load [W] ¹⁾	29.4	38.5	51.1	60.7	76.1	96.1	147.5
Weight enclosure protection rating IP20 [kg (lb)]	2.3 (5.1)	2.3 (5.1)	2.3 (5.1)	2.3 (5.1)	2.3 (5.1)	2.5 (5.5)	3.6 (7.9)
Weight enclosure protection rating IP21 [kg (lb)]	4.0 (8.8)	4.0 (8.8)	4.0 (8.8)	4.0 (8.8)	4.0 (8.8)	5.5 (12.1)	6.5 (14.3)
Efficiency [%] ²⁾	96.4	96.6	96.3	96.6	96.5	96.7	96.7

Table 9.3 Mains Supply 3x200–240 V AC

Frequency converter typical shaft output [kW (hp)]	PK37 0.37 (0.5)	PK55 0.55 (0.75)	PK75 0.75 (1.0)	P1K1 1.1 (1.5)	P1K5 1.5 (2.0)	P2K2 2.2 (3.0)
Enclosure protection rating IP20 (IP21/Type 1 as option)	K1	K1	K1	K1	K1	K2
Output current						
Continuous (3x200–240 V) [A]	2.2	3.2	4.2	6	6.8	9.6
Intermittent (60 s overload) [A]	3.5	5.1	6.7	9.6	10.9	15.4
Continuous kVA (230 V AC) [kVA]	0.9	1.3	1.7	2.4	2.7	3.8
Maximum input current						
Continuous (1x200–240 V) [A]	2.9	4.4	5.5	7.7	10.4	14.4
Intermittent (60 s overload) [A]	4.6	7.0	8.8	12.3	16.6	23.0
More specifications						
Maximum cable cross-section (mains and motor) [mm ² (AWG)]	4 (12)					
Estimated power loss at rated maximum load [W] ¹⁾	37.7	46.2	56.2	76.8	97.5	121.6
Weight enclosure protection rating IP20 [kg (lb)]	2.3 (5.1)	2.3 (5.1)	2.3 (5.1)	2.3 (5.1)	2.3 (5.1)	2.5 (5.5)
Weight enclosure protection rating IP21 [kg (lb)]	4.0 (8.8)	4.0 (8.8)	4.0 (8.8)	4.0 (8.8)	4.0 (8.8)	5.5 (12.1)
Efficiency [%] ²⁾	94.4	95.1	95.1	95.3	95.0	95.4

Table 9.4 Mains Supply 1x200–240 V AC

1) The typical power loss is at nominal load conditions and expected to be within $\pm 15\%$ (tolerance relates to variety in voltage and cable conditions).

Values are based on a typical motor efficiency (IE2/IE3 border line). Motors with lower efficiency add to the power loss in the frequency converter, and motors with high efficiency reduce power loss.

Applies to dimensioning of frequency converter cooling. If the switching frequency is higher than the default setting, the power losses sometimes rise. LCP and typical control card power consumptions are included. Further options and customer load sometimes add up to 30 W to the losses (though typically only 4 W extra for a fully loaded control card or fieldbus).

For power loss data according to EN 50598-2, refer to www.danfoss.com/vltenergyefficiency.

2) Measured using 50 m (164 ft) shielded motor cables at rated load and rated frequency. For energy efficiency class, see chapter 9.4 Ambient Conditions. For part load losses, see www.danfoss.com/vltenergyefficiency.

9.2 Mains Supply

Mains supply (L1/N, L2/L, L3)

Supply terminals	(L1/N, L2/L, L3)
Supply voltage	380–480 V: -15% (-25%) ¹⁾ to +10%
Supply voltage	200–240 V: -15% (-25%) ¹⁾ to +10%

1) The frequency converter can run at -25% input voltage with reduced performance. The maximum output power of the frequency converter is 75% if input voltage is -25%, and 85% if input voltage is -15%.

Full torque cannot be expected at mains voltage lower than 10% below the lowest rated supply voltage of the frequency converter.

Supply frequency	50/60 Hz $\pm 5\%$
Maximum imbalance temporary between mains phases	3.0% of rated supply voltage
True power factor (λ)	≥ 0.9 nominal at rated load
Displacement power factor ($\cos \phi$)	Near unity (> 0.98)
Switching on input supply (L1/N, L2/L, L3) (power-ups) ≤ 7.5 kW (10 hp)	Maximum 2 times/minute
Switching on input supply (L1/N, L2/L, L3) (power-ups) 11–22 kW (15–30 hp)	Maximum 1 time/minute

9.3 Motor Output and Motor Data

Motor output (U, V, W)

Output voltage	0–100% of supply voltage
Output frequency	0–500 Hz
Output frequency in VVC ⁺ mode	0–200 Hz
Switching on output	Unlimited
Ramp time	0.01–3600 s

Torque characteristics

Starting torque (constant torque)	Maximum 160% for 60 s ¹⁾
Overload torque (constant torque)	Maximum 160% for 60 s ¹⁾
Starting current	Maximum 200% for 1 s
Torque rise time in VVC ⁺ mode (independent of f_{sw})	Maximum 50 ms

1) Percentage relates to the nominal torque. It is 150% for 11–22 kW (15–30 hp) frequency converters.

9.4 Ambient Conditions

Ambient conditions

Enclosure protection rating, frequency converter	IP20 (IP21/Type 1 as option)
Enclosure protection rating, conversion kit	IP21/Type 1
Vibration test, all enclosure sizes	1.14 g
Relative humidity	5–95% (IEC 721-3-3; Class 3K3 (non-condensing) during operation)
Ambient temperature (at DPWM switching mode)	
- with derating	Maximum 55 °C (131 °F) ¹⁾²⁾³⁾
- at full constant output current	Maximum 45 °C (113 °F) ⁴⁾
Minimum ambient temperature during full-scale operation	0 °C (32 °F)
Minimum ambient temperature at reduced performance	-10 °C (14 °F)
Temperature during storage/transport	-25 to +65/70 °C (-13 to +149/158 °F)
Maximum altitude above sea level without derating	1000 m (3280 ft)
Maximum altitude above sea level with derating	3000 m (9243 ft)
EMC standards, emission	EN 61800-3, EN 61000-3-2, EN 61000-3-3, EN 61000-3-11, EN 61000-3-12, EN 61000-6-3/4, EN 55011, IEC 61800-3
EMC standards, immunity	EN 61800-3, EN 61000-6-1/2, EN 61000-4-2, EN 61000-4-3
Energy efficiency class ⁵⁾	EN 61000-4-4, EN 61000-4-5, EN 61000-4-6, EN 61326-3-1
	IE2

1) Refer to Special Conditions in the design guide for:

- Derating for high ambient temperature.
- Derating for high altitude.

2) To prevent control card overtemperature on PROFIBUS, PROFINET, EtherNet/IP, and POWERLINK variants of VLT® Midi Drive FC 280, avoid full digital/analog I/O load at ambient temperature higher than 45 °C (113 °F).

3) Ambient temperature for K152 with derating is maximum 50 °C (122 °F).

4) Ambient temperature for K152 at full constant output current is maximum 40 °C (104 °F).

5) Determined according to EN 50598-2 at:

- Rated load.
- 90% rated frequency.
- Switching frequency factory setting.
- Switching pattern factory setting.
- Open type: Surrounding air temperature 45 °C (113 °F).
- Type 1 (NEMA kit): Ambient temperature 45 °C (113 °F).

9.5 Cable Specifications

Cable lengths and cross-sections¹⁾

Maximum motor cable length, shielded	50 m (164 ft)
Maximum motor cable length, unshielded	75 m (246 ft)
Maximum cross-section of control terminals, flexible/rigid wire	2.5 mm ² /14 AWG
Minimum cross-section of control terminals	0.55 mm ² /30 AWG
Maximum STO input cable length, unshielded	20 m (66 ft)

1) For power cables cross-sections, see Table 9.1, Table 9.2, Table 9.3 and Table 9.4.

When complying with EN 55011 1A and EN 55011 1B the motor cable must in certain instances be reduced. See chapter 2.6.2

EMC Emission in the VLT® Midi Drive FC 280 Design Guide for more details.

9.6 Control Input/Output and Control Data

Digital inputs

Terminal number	18, 19, 27 ¹⁾ , 29, 32, 33
Logic	PNP or NPN
Voltage level	0–24 V DC
Voltage level, logic 0 PNP	<5 V DC
Voltage level, logic 1 PNP	>10 V DC
Voltage level, logic 0 NPN	>19 V DC
Voltage level, logic 1 NPN	<14 V DC
Maximum voltage on input	28 V DC
Pulse frequency range	4–32 kHz
(Duty cycle) minimum pulse width	4.5 ms
Input resistance, R _i	Approximately 4 kΩ

1) Terminal 27 can also be programmed as output.

STO inputs¹⁾

Terminal number	37, 38
Voltage level	0–30 V DC
Voltage level, low	<1.8 V DC
Voltage level, high	>20 V DC
Maximum voltage on input	30 V DC
Minimum input current (each pin)	6 mA

1) Refer to chapter 6 Safe Torque Off (STO) for more details about STO inputs.

Analog inputs

Number of analog inputs	2
Terminal number	53 ¹⁾ , 54
Modes	Voltage or current
Mode select	Software
Voltage level	0–10 V
Input resistance, R _i	Approximately 10 kΩ
Maximum voltage	-15 V to +20 V
Current level	0/4 to 20 mA (scaleable)
Input resistance, R _i	Approximately 200 Ω
Maximum current	30 mA
Resolution for analog inputs	11 bit
Accuracy of analog inputs	Maximum error 0.5% of full scale
Bandwidth	100 Hz

The analog inputs are galvanically isolated from the supply voltage (PELV) and other high-voltage terminals.

1) Terminal 53 supports only voltage mode and can also be used as digital input.

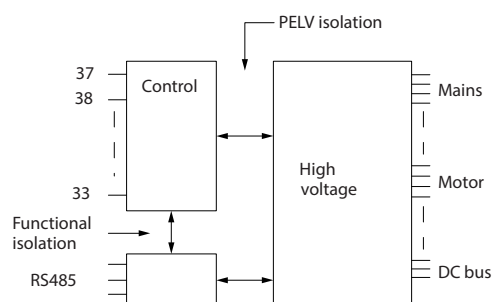


Illustration 9.1 Galvanic Isolation

NOTICE

HIGH ALTITUDE

For installation at altitudes above 2000 m (6562 ft), contact Danfoss hotline regarding PELV.

Pulse inputs

Programmable pulse inputs	2
Terminal number pulse	29, 33
Maximum frequency at terminal 29, 33	32 kHz (push-pull driven)
Maximum frequency at terminal 29, 33	5 kHz (open collector)
Minimum frequency at terminal 29, 33	4 Hz
Voltage level	See the section on digital input
Maximum voltage on input	28 V DC
Input resistance, R_i	Approximately 4 k Ω
Pulse input accuracy	Maximum error: 0.1% of full scale

Digital outputs

Programmable digital/pulse outputs	1
Terminal number	27 ¹⁾
Voltage level at digital/frequency output	0–24 V
Maximum output current (sink or source)	40 mA
Maximum load at frequency output	1 k Ω
Maximum capacitive load at frequency output	10 nF
Minimum output frequency at frequency output	4 Hz
Maximum output frequency at frequency output	32 kHz
Accuracy of frequency output	Maximum error: 0.1% of full scale
Resolution of frequency output	10 bit

1) Terminal 27 can also be programmed as input.

The digital output is galvanically isolated from the supply voltage (PELV) and other high-voltage terminals.

Analog outputs

Number of programmable analog outputs	1
Terminal number	42
Current range at analog output	0/4–20 mA
Maximum resistor load to common at analog output	500 Ω
Accuracy on analog output	Maximum error: 0.8% of full scale
Resolution on analog output	10 bit

The analog output is galvanically isolated from the supply voltage (PELV) and other high-voltage terminals.

Control card, 24 V DC output

Terminal number	12, 13
Maximum load	100 mA

The 24 V DC supply is galvanically isolated from the supply voltage (PELV). However, the supply has the same potential as the analog and digital inputs and outputs.

Control card, +10 V DC output

Terminal number	50
Output voltage	10.5 V $\pm$ 0.5 V
Maximum load	15 mA

The 10 V DC supply is galvanically isolated from the supply voltage (PELV) and other high-voltage terminals.

Control card, RS485 serial communication

Terminal number	68 (PTX+, RX+), 69 (N,TX-, RX-)
Terminal number 61	Common for terminals 68 and 69

The RS485 serial communication circuit is galvanically isolated from the supply voltage (PELV).

Control card, USB serial communication

USB standard	1.1 (full speed)
USB plug	USB type B plug

Connection to PC is carried out via a standard host/device USB cable.

The USB connection is galvanically isolated from the supply voltage (PELV) and other high-voltage terminals.

The USB ground connection is not galvanically isolated from protective earth. Use only an isolated laptop as PC connection to the USB connector on the frequency converter.

Relay outputs

Programmable relay outputs	1
Relay 01	01–03 (NC), 01–02 (NO)
Maximum terminal load (AC-1) ¹⁾ on 01–02 (NO) (resistive load)	250 V AC, 3 A
Maximum terminal load (AC-15) ¹⁾ on 01–02 (NO) (inductive load @ cos ϕ 0.4)	250 V AC, 0.2 A
Maximum terminal load (DC-1) ¹⁾ on 01–02 (NO) (resistive load)	30 V DC, 2 A
Maximum terminal load (DC-13) ¹⁾ on 01–02 (NO) (inductive load)	24 V DC, 0.1 A
Maximum terminal load (AC-1) ¹⁾ on 01–03 (NC) (resistive load)	250 V AC, 3 A
Maximum terminal load (AC-15) ¹⁾ on 01–03 (NC) (inductive load @ cos ϕ 0.4)	250 V AC, 0.2 A
Maximum terminal load (DC-1) ¹⁾ on 01–03 (NC) (resistive load)	30 V DC, 2 A
Minimum terminal load on 01–03 (NC), 01–02 (NO)	24 V DC 10 mA, 24 V AC 20 mA

1) IEC 60947 parts 4 and 5

The relay contacts are galvanically isolated from the rest of the circuit by reinforced isolation.

Control card performance

Scan interval	1 ms
---------------	------

Control characteristics

Resolution of output frequency at 0–500 Hz	$\pm$ 0.003 Hz
System response time (terminals 18, 19, 27, 29, 32, and 33)	$\leq$ 2 ms
Speed control range (open loop)	1:100 of synchronous speed
Speed accuracy (open loop)	$\pm$ 0.5% of nominal speed
Speed accuracy (closed loop)	$\pm$ 0.1% of nominal speed

All control characteristics are based on a 4-pole asynchronous motor.

9.7 Connection Tightening Torques

Make sure to use the right torques when tightening all electrical connections. Too low or too high torque sometimes causes electrical connection problems. To ensure that correct torques are applied, use a torque wrench. Recommended slot screwdriver type is SZS 0.6x3.5 mm.

Enclosure type	Power [kW (hp)]	Torque [Nm (in-lb)]						
		Mains	Motor	DC connection	Brake	Ground	Control	Relay
K1	0.37–2.2 (0.5–3.0)	0.8 (7.1)	0.8 (7.1)	0.8 (7.1)	0.8 (7.1)	1.6 (14.2)	0.4 (3.5)	0.5 (4.4)
K2	3.0–5.5 (4.0–7.5)	0.8 (7.1)	0.8 (7.1)	0.8 (7.1)	0.8 (7.1)	1.6 (14.2)	0.4 (3.5)	0.5 (4.4)
K3	7.5 (10)	0.8 (7.1)	0.8 (7.1)	0.8 (7.1)	0.8 (7.1)	1.6 (14.2)	0.4 (3.5)	0.5 (4.4)
K4	11–15 (15–20)	1.2 (10.6)	1.2 (10.6)	1.2 (10.6)	1.2 (10.6)	1.6 (14.2)	0.4 (3.5)	0.5 (4.4)
K5	18.5–22 (25–30)	1.2 (10.6)	1.2 (10.6)	1.2 (10.6)	1.2 (10.6)	1.6 (14.2)	0.4 (3.5)	0.5 (4.4)

Table 9.5 Tightening Torques

9.8 Fuses and Circuit Breakers

Use fuses and/or circuit breakers on the supply side to protect service personnel and equipment from injuries and damage if there is component breakdown inside the frequency converter (first fault).

Branch circuit protection

Protect all branch circuits in an installation (including switch gear and machines) against short circuit and overcurrent according to national/international regulations.

NOTICE

Integral solid-state short-circuit protection does not provide branch circuit protection. Provide branch circuit protection in accordance with the national and local rules and regulations.

Table 9.6 lists the recommended fuses and circuit breakers that have been tested.

CAUTION

PERSONAL INJURY AND EQUIPMENT DAMAGE RISK

Malfunction or failing to follow the recommendations may result in personal risk and damage to the frequency converter and other equipment.

- Select fuses according to recommendations. Possible damage can be limited to be inside the frequency converter.

NOTICE

EQUIPMENT DAMAGE

Using fuses and/or circuit breakers is mandatory to ensure compliance with IEC 60364 for CE. Failure to follow the protection recommendations can result in damage to the frequency converter.

Danfoss recommends using the fuses and circuit breakers in Table 9.6 and Table 9.7 to ensure compliance with UL 508C or IEC 61800-5-1. For non-UL applications, design circuit breakers for protection in a circuit capable of delivering a maximum of 50000 A_{rms} (symmetrical), 240 V/400 V maximum. The frequency converter short-circuit current rating (SCCR) is suitable for use on a circuit capable of delivering not more than 100000 A_{rms}, 240 V/480 V maximum when protected by Class T fuses.

Enclosure size		Power [kW (hp)]	Non-UL fuse	Non-UL circuit breaker (Eaton)
3-phase 380–480 V	K1	0.37 (0.5)	gG-10	PKZM0-16
		0.55–0.75 (0.75–1.0)		
		1.1–1.5 (1.5–2.0)	gG-20	
		2.2 (3.0)		
	K2	3.0–5.5 (4.0–7.5)	gG-25	PKZM0-20
	K3	7.5 (10)		PKZM0-25
	K4	11–15 (15–20)	gG-50	–
	K5	18.5–22 (25–30)	gG-80	–
3-phase 200–240 V	K1	0.37 (0.5)	gG-10	PKZM0-16
		0.55 (0.75)	gG-20	
		0.75 (1.0)		
		1.1 (1.5)		
		1.5 (2.0)		
	K2	2.2 (3.0)	gG-25	PKZM0-20
	K3	3.7 (5.0)		PKZM0-25
Single-phase 200–240 V	K1	0.37 (0.5)	gG-10	PKZM0-16
		0.55 (0.75)	gG-20	
		0.75 (1.0)		
		1.1 (1.5)		
		1.5 (2.0)		
	K2	2.2 (3.0)	gG-25	PKZM0-20

Table 9.6 Non-UL Fuse and Circuit Breaker

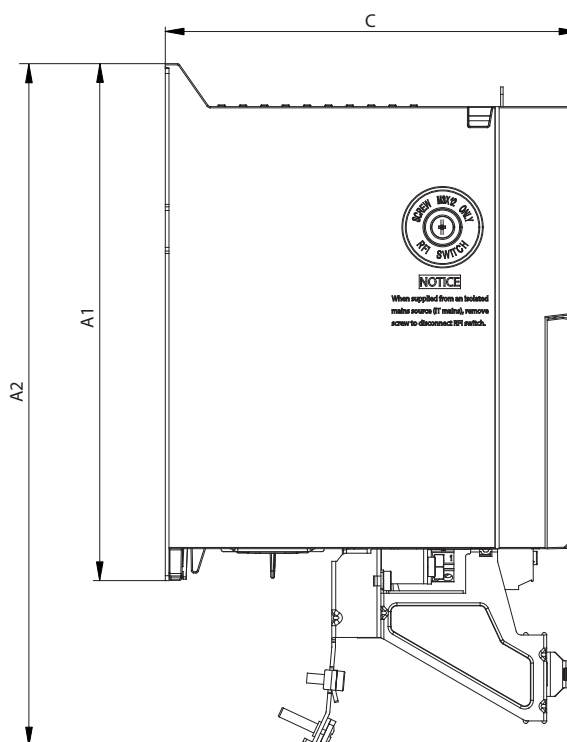
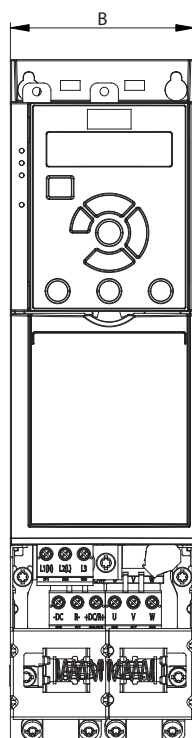
Enclosure size		Power [kW (hp)]	Bussmann E4273						Littelfuse E81895	MERSEN E163267/ E2137	MERSEN E163267/ E2138
			Class RK1	Class J	Class T	Class CC	Class CC	Class CC			
3-phase 380–480 V	K1	0.37–0.75 (0.5–1.0)	KTS-R-6	JKS-6	JJS-6	FNQ-R-6	KTK-R-6	LP-CC-6	KLSR-6	ATM-R6	A6K-6R
		1.1–1.5 (1.5–2.0)	KTS-R-10	JKS-10	JJS-10	FNQ-R-10	KTK-R-10	LP-CC-10	KLSR-10	ATM-R10	A6K-10R
		2.2 (3.0)	KTS-R-15	JKS-15	JJS-15	FNQ-R-15	KTK-R-15	LP-CC-15	KLSR-15	ATM-R15	A6K-15R
	K2–K3	3.0–7.5 (4.0–10)	KTS-R-25	JKS-25	JJS-25	FNQ-R-25	KTK-R-25	LP-CC-25	KLSR-25	ATM-R25	A6K-25R
	K4	11–15 (15–20)	KTS-R-50	JKS-50	JJS-50	–	–	–	KLSR-50	–	A6K-50R
	K5	18.5–22 (25–30)	–	JKS-80	JJS-80	–	–	–	–	–	–
3-phase 200–240 V	K1	0.37 (0.5)	KTN-R-6	JKS-6	JJN-6	FNQ-R-6	KTK-R-6	LP-CC-6	KLNR-6	ATM-R6	A2K-6R
		0.55 (0.75)	KTN-R-10	JKS-10	JJN-10	FNQ-R-10	KTK-R-10	LP-CC-10	KLNR-10	ATM-R10	A2K-10R
		0.75 (1.0)	KTN-R-15	JKS-15	JJN-15	FNQ-R-15	KTK-R-15	LP-CC-15	KLNR-15	ATM-R15	A2K-15R
		1.1–1.5 (1.5–2.0)	KTN-R-20	JKS-20	JJN-20	FNQ-R-20	KTK-R-20	LP-CC-20	KLNR-20	ATM-R20	A2K-20R
	K2–K3	2.2–3.7 (3.0–5.0)	KTN-R-25	JKS-25	JJN-25	–	–	–	KLNR-25	ATM-R25	A2K-25R
Single-phase 200–240 V	K1	0.37 (0.5)	KTN-R-6	JKS-6	JJN-6	FNQ-R-6	KTK-R-6	LP-CC-6	KLNR-6	ATM-R6	A2K-6R
		0.55 (0.75)	KTN-R-10	JKS-10	JJN-10	FNQ-R-10	KTK-R-10	LP-CC-10	KLNR-10	ATM-R10	A2K-10R
		0.75 (1.0)	KTN-R-15	JKS-15	JJN-15	FNQ-R-15	KTK-R-15	LP-CC-15	KLNR-15	ATM-R15	A2K-15R
		1.1–1.5 (1.5–2.0)	KTN-R-20	JKS-20	JJN-20	FNQ-R-20	KTK-R-20	LP-CC-20	KLNR-20	ATM-R20	A2K-20R
	K2	2.2 (3.0)	KTN-R-25	JKS-25	JJN-25	–	–	–	KLNR-25	ATM-R25	A2K-25R

Table 9.7 UL fuse

9.9 Enclosure Sizes, Power Ratings, and Dimensions

	Enclosure size	K1						K2			K3		K4		K5	
Power size [kW (hp)]	Single-phase 200–240 V	0.37 (0.5)	0.55 (0.75)	0.75 (1.0)	1.1 (1.5)	1.5 (2.0)		2.2 (3.0)			–		–		–	
	3-phase 200–240 V	0.37 (0.5)	0.55 (0.75)	0.75 (1.0)	1.1 (1.5)	1.5 (2.0)		2.2 (3.0)			3.7 (5.0)		–		–	
	3-phase 380–480 V	0.37 (0.5)	0.55 (0.75)	0.75 (1.0)	1.1 (1.5)	1.5 (2.0)	2.2 (3.0)	3 (4.0)	4 (5.5)	5.5 (7.5)	7.5 (10)		11 (15)	15 (20)	18.5 (25)	22 (30)
Dimensions [mm (in)]	FC 280 IP20															
	Height A1	210 (8.3)						272.5 (10.7)			272.5 (10.7)		317.5 (12.5)		410 (16.1)	
	Height A2	278 (10.9)						340 (13.4)			341.5 (13.4)		379.5 (14.9)		474 (18.7)	
	Width B	75 (3.0)						90 (3.5)			115 (4.5)		133 (5.2)		150 (5.9)	
	Depth C	168 (6.6)						168 (6.6)			168 (6.6)		245 (9.6)		245 (9.6)	
	FC 280 with IP21/UL/Type 1 kit															
	Height A	338.5 (13.3)						395 (15.6)			395 (15.6)		425 (16.7)		520 (20.5)	
	Width B	100 (3.9)						115 (4.5)			130 (5.1)		153 (6.0)		170 (6.7)	
	Depth C	183 (7.2)						183 (7.2)			183 (7.2)		260 (10.2)		260 (10.2)	
	FC 280 with bottom cable entry cover (w/o top cover)															
	Height A	294 (11.6)						356 (14)			357 (14.1)		391 (15.4)		486 (19.1)	
	Width B	75 (3.0)						90 (3.5)			115 (4.5)		133 (5.2)		150 (5.9)	
	Depth C	168 (6.6)						168 (6.6)			168 (6.6)		245 (9.6)		245 (9.6)	
Weight [kg (lb)]	IP20	2.5 (5.5)						3.6 (7.9)			4.6 (10.1)		8.2 (18.1)		11.5 (25.4)	
	IP21	4.0 (8.8)						5.5 (12.1)			6.5 (14.3)		10.5 (23.1)		14.0 (30.9)	
Mounting holes [mm (in)]	a	198 (7.8)						260 (10.2)			260 (10.2)		297.5 (11.7)		390 (15.4)	
	b	60 (2.4)						70 (2.8)			90 (3.5)		105 (4.1)		120 (4.7)	
	c	5 (0.2)						6.4 (0.25)			6.5 (0.26)		8 (0.32)		7.8 (0.31)	
	d	9 (0.35)						11 (0.43)			11 (0.43)		12.4 (0.49)		12.6 (0.5)	
	e	4.5 (0.18)						5.5 (0.22)			5.5 (0.22)		6.8 (0.27)		7 (0.28)	
	f	7.3 (0.29)						8.1 (0.32)			9.2 (0.36)		11 (0.43)		11.2 (0.44)	

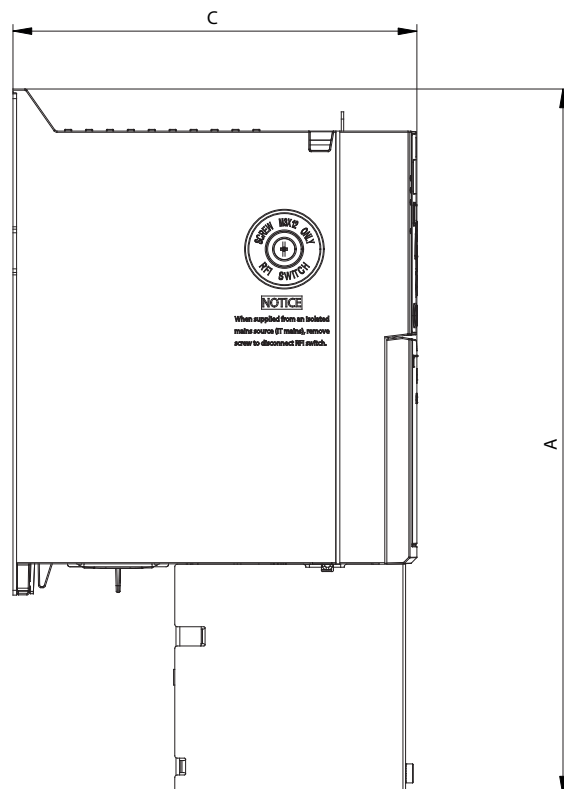
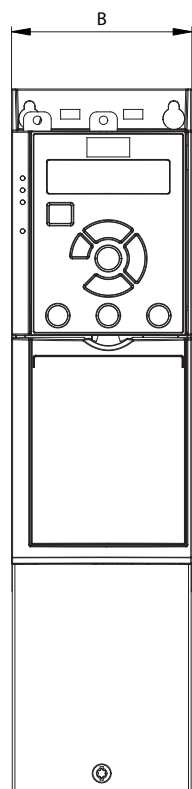
Table 9.8 Enclosure Sizes, Power Ratings, and Dimensions



130BE84.11

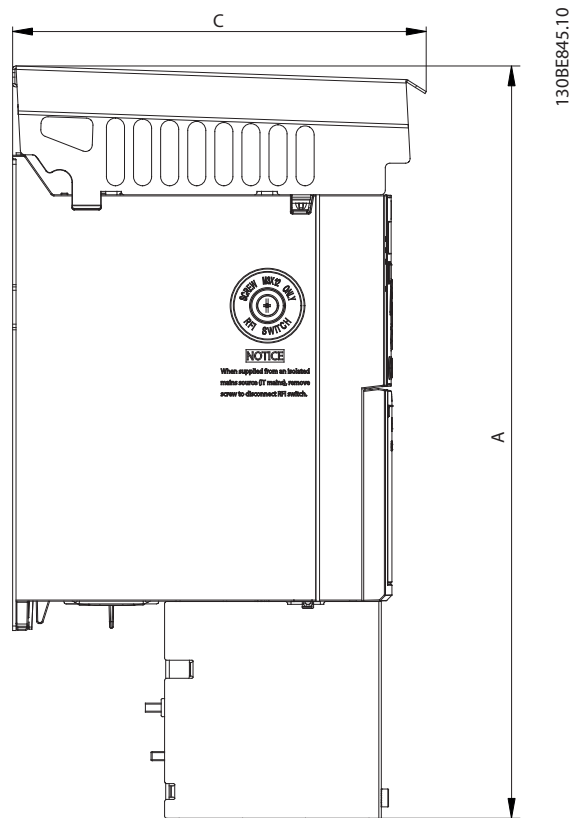
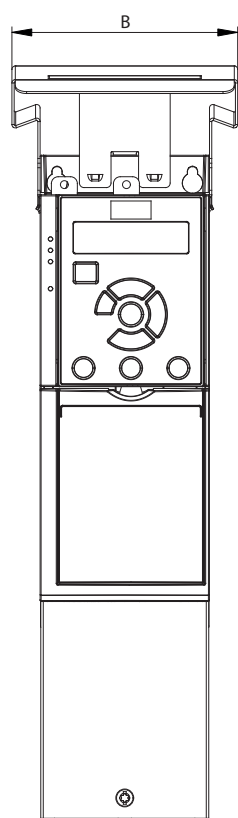
9

Illustration 9.2 Standard with Decoupling Plate



130BE846.10

Illustration 9.3 Standard with Bottom Cable Entry Cover (w/o Top Cover)



9

Illustration 9.4 Standard with IP21/UL/Type 1 kit

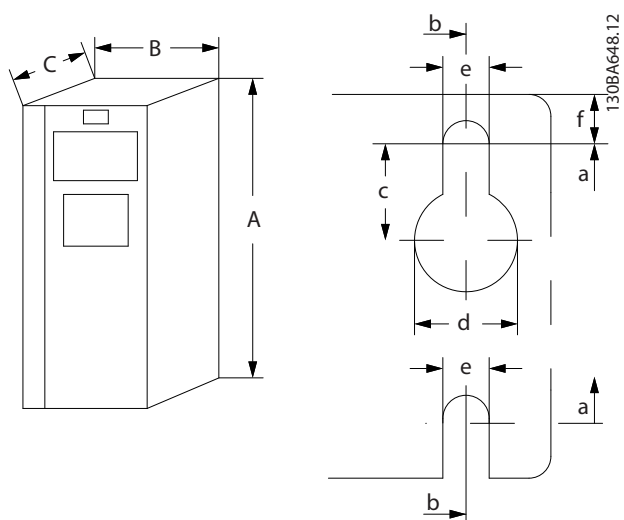


Illustration 9.5 Top and Bottom Mounting Holes

10 Appendix

10.1 Symbols, Abbreviations, and Conventions

°C	Degrees celsius
°F	Degrees fahrenheit
AC	Alternating current
AEO	Automatic energy optimization
AWG	American wire gauge
AMA	Automatic motor adaptation
DC	Direct current
EMC	Electromagnetic compatibility
ETR	Electronic thermal relay
$f_{M,N}$	Nominal motor frequency
FC	Frequency converter
I_{INV}	Rated inverter output current
I_{LIM}	Current limit
$I_{M,N}$	Nominal motor current
$I_{VLT,MAX}$	Maximum output current
$I_{VLT,N}$	Rated output current supplied by the frequency converter
IP	Ingress protection
LCP	Local control panel
MCT	Motion control tool
n_s	Synchronous motor speed
$P_{M,N}$	Nominal motor power
PELV	Protective extra low voltage
PCB	Printed circuit board
PM Motor	Permanent magnet motor
PWM	Pulse width modulation
RPM	Revolutions per minute
STO	Safe Torque Off
T_{LIM}	Torque limit
$U_{M,N}$	Nominal motor voltage

Table 10.1 Symbols and Abbreviations

Conventions

- For illustrations, all dimensions are in [mm (in)].
- An asterisk (*) indicates the default setting of a parameter.
- Numbered lists indicate procedures.
- Bullet lists indicate other information.
- Italicized text indicates:
 - Cross-reference.
 - Link.
 - Parameter name.

10.2 Parameter Menu Structure

10

1-2*	Motor Data	1-45	q-axis Inductance Sat. (LqSat) 0 - 65535 mH *Size related	1-8*	Stop Adjustments	1-80	Function at Stop	2-12	0 - 6200 Ohm *Size related Brake Power Limit (kW) 0.001 - 2000 kW *Size related	[80]	kW
[2]	Motor Power	1-46	Position Detection Gain	[0]	Coast	[1]	DC hold / Motor Preheat	2-14	Brake voltage reduce	[121]	GPM
[3]	0.12 kW - 0.16 hp	1-48	20 - 200 % *100 %	[1]	Pre-magnetizing	[3]	Min Speed for Function at Stop [Hz]	2-16	0 - 500 V *0 V	[122]	gal/s
[4]	0.18 kW - 0.25 hp	1-49	Current at Min Inductance for d-axis	1-82	0 - 20 Hz *0 Hz	[1]	Precise Stop Function	2-17	AC Brake, Max current	[123]	gal/h
[5]	0.25 kW - 0.33 hp	1-50	20 - 200 % *100 %	[0]	Precise ramp stop	[2]	Counter stop with reset	[10]	Over-voltage Control	[124]	CFM
[6]	0.37 kW - 0.5 hp	1-51	Current at Min Inductance for q-axis	[2]	Counter stop without reset	[3]	Speed compensated stop	[11]	Disabled	[125]	ft ³ /min
[7]	0.55 kW - 0.75 hp	1-52	Min Speed Normal Magnetising [Hz]	[3]	Speed compensated counter stop with reset	[4]	Speed compensated counter stop with reset	[12]	Enabled (not at stop)	[126]	ft ³ /h
[8]	0.75 kW - 1 hp	1-53	0.1 - 10.0 Hz *1 Hz	[4]	Speed compensated counter stop with reset	[5]	Speed compensated counter stop without reset	[13]	Enabled	[127]	lb/s
[9]	1.1 kW - 1.5 hp	1-54	U/f Characteristic - U	[5]	Speed compensated counter stop without reset	[6]	Precise Stop Counter Value	[14]	Over-voltage Gain	[128]	lb/min
[10]	1.5 kW - 2 hp	1-55	0 - 1000 V *Size related	[6]	Speed compensated counter stop without reset	[7]	Precise Stop Speed Compensation	[15]	0 - 200 % *100 %	[129]	lb/h
[11]	2.2 kW - 3 hp	1-56	U/f Characteristic - F	[7]	Speed compensated counter stop without reset	[8]	0 - 500.0 Hz *Size related	[16]	Mechanical Brake	[130]	ft/min
[12]	3 kW - 4 hp	1-57	0 - 300 % *100 %	[8]	Speed compensated counter stop without reset	[9]	0 - 99999999 *100000	[17]	Release Brake Current	[131]	ft
[13]	3.7 kW - 5 hp	1-58	High Speed Load Compensation	[9]	Speed compensated counter stop without reset	[10]	Delay	[18]	0 - 100 A *0 A	[132]	lb ft
[14]	4 kW - 5.4 hp	1-59	0 - 300 % *100 %	[10]	Speed compensated counter stop without reset	[11]	0 - 100 ms *10 ms	[19]	Activate Brake Speed [Hz]	[133]	°F
[15]	5.5 kW - 7.5 hp	1-60	Slip Compensation	[11]	Speed compensated counter stop without reset	[12]	AC Brake Gain	[20]	0 - 400 Hz *0 Hz	[134]	psi
[16]	7.5 kW - 10 hp	1-61	-400 - 400.0 % *Size related	[12]	Speed compensated counter stop without reset	[13]	1.0 - 2.0 *1.4	[21]	0 - 5 s *0 s	[135]	lb/in2
[17]	11 kW - 15 hp	1-62	Slip Compensation Time Constant	[13]	Speed compensated counter stop without reset	[14]	Motor Temperature	[22]	Adv. Mech Brake	[136]	in WG
[18]	15 kW - 20 hp	1-63	0.05 - 5 s *0.1 s	[14]	Speed compensated counter stop without reset	[15]	0 - 100 ms *10 ms	[23]	Mech. Brake w/ dir. Change	[137]	ft WG
[19]	18.5 kW - 25 hp	1-64	Resonance Dampening	[15]	Speed compensated counter stop without reset	[16]	AC Brake Gain	[24]	OFF	[138]	HP
[20]	22 kW - 30 hp	1-65	0 - 500 % *100 %	[16]	Speed compensated counter stop without reset	[17]	0 - 100 ms *10 ms	[25]	ON	[139]	Minimum Reference
[21]	30 kW - 40 hp	1-66	Resonance Dampening Time Constant	[17]	Speed compensated counter stop without reset	[18]	0 - 100 ms *10 ms	[26]	ON with start delay	[140]	-4999.0 - 4999 ReferenceFeedbackUnit
1-22	Motor Voltage	1-67	0.001 - 0.05 s *0.005 s	[18]	Speed compensated counter stop without reset	[19]	0 - 100 ms *10 ms	[27]	Reference / Ramps	[141]	*0 ReferenceFeedbackUnit
1-23	Motor Frequency	1-68	Min. Current at Low Speed	[19]	Speed compensated counter stop without reset	[20]	0 - 100 ms *10 ms	[28]	Reference Limits	[142]	Maximum Reference
1-24	Motor Current	1-69	0 - 120 % *50 %	[20]	Speed compensated counter stop without reset	[21]	0 - 100 ms *10 ms	[29]	*Size related	[143]	-4999.0 - 4999 ReferenceFeedbackUnit
1-25	0.01 - 1000.0 A *Size related	1-70	Start Mode	[21]	Speed compensated counter stop without reset	[22]	0 - 100 ms *10 ms	[30]	Reference Function	[144]	*Size related
1-26	Motor Nominal Speed	1-71	Rotor Detection	[22]	Speed compensated counter stop without reset	[23]	0 - 100 ms *10 ms	[31]	Sum	[145]	Sum
1-27	50 - 60000 RPM *Size related	1-72	Parking	[23]	Speed compensated counter stop without reset	[24]	0 - 100 ms *10 ms	[32]	External/Preset	[146]	3-1*
1-28	Motor Cont. Rated Torque	1-73	Start Delay	[24]	Speed compensated counter stop without reset	[25]	0 - 100 ms *10 ms	[33]	Preset Reference	[147]	3-10
1-29	0.1 - 10000.0 Nm *Size related	1-74	0 - 10 s *0 s	[25]	Speed compensated counter stop without reset	[26]	0 - 100 ms *10 ms	[34]	-100 - 100 % *0 %	[148]	3-11
1-30	Automatic Motor Adaption (AMA)	1-75	0 - 10 s *0 s	[26]	Speed compensated counter stop without reset	[27]	0 - 100 ms *10 ms	[35]	Jog Speed [Hz]	[149]	3-12
[0]	Off	1-76	Start Function	[27]	Speed compensated counter stop without reset	[28]	0 - 100 ms *10 ms	[36]	0 - 500.0 Hz *5 Hz	[150]	3-13
1-31	Enable Complete AMA	1-77	DC Hold/delay time	[28]	Speed compensated counter stop without reset	[29]	0 - 100 ms *10 ms	[37]	Catch up/slow Down Value	[151]	3-14
1-32	Enable Reduced AMA	1-78	DC-Brake/delay time	[29]	Speed compensated counter stop without reset	[30]	0 - 100 ms *10 ms	[38]	Preset Relative Reference	[152]	3-15
1-33	0.0 - 9999.000 Ohm *Size related	1-79	Coast/delay time	[30]	Speed compensated counter stop without reset	[31]	0 - 100 ms *10 ms	[39]	Reference 1 Source	[153]	[0]
1-34	Stator Leakage Reactance (X1)	1-80	Start speed cw	[31]	Speed compensated counter stop without reset	[32]	0 - 100 ms *10 ms	[40]	No function	[154]	[1]
1-35	Main Reactance (Xh)	1-81	Horizontal operation	[32]	Speed compensated counter stop without reset	[33]	0 - 100 ms *10 ms	[41]	Analog Input 53	[155]	[2]
1-36	0.0 - 9999.000 Ohm *Size related	1-82	VVC+ clockwise	[33]	Speed compensated counter stop without reset	[34]	0 - 100 ms *10 ms	[42]	Analog Input 54	[156]	[7]
1-37	d-axis Inductance (Ld)	1-83	Flying Start	[34]	Speed compensated counter stop without reset	[35]	0 - 100 ms *10 ms	[43]	Frequency Input 29	[157]	[8]
1-38	0 - 65535 mH *Size related	1-84	Disabled	[35]	Speed compensated counter stop without reset	[36]	0 - 100 ms *10 ms	[44]	Frequency Input 33	[158]	[11]
1-39	q-axis Inductance (Lq)	1-85	Enabled	[36]	Speed compensated counter stop without reset	[37]	0 - 100 ms *10 ms	[45]	Local bus reference	[159]	[20]
1-40	Motor Poles	1-86	Enabled Always	[37]	Speed compensated counter stop without reset	[38]	0 - 100 ms *10 ms	[46]	Digital potmeter	[160]	[32]
1-41	2 - 100 *Size related	1-87	Enabled Ref. Dir.	[38]	Speed compensated counter stop without reset	[39]	0 - 100 ms *10 ms	[47]	Bus PC	[161]	3-16
1-42	Back EMF at 1000 RPM	1-88	Enab. Always Ref. Dir.	[39]	Speed compensated counter stop without reset	[40]	0 - 100 ms *10 ms	[48]	Reference 2 Source	[162]	3-17
1-43	1 - 9000 V *Size related	1-89	Start Speed [Hz]	[40]	Speed compensated counter stop without reset	[41]	0 - 100 ms *10 ms	[49]	Same choices with 3-15	[163]	3-18
1-44	Motor Cable Length	1-90	0 - 5000 Hz *Size related	[41]	Speed compensated counter stop without reset	[42]	0 - 100 ms *10 ms	[50]	Reference 3 Source	[164]	*[0]
1-45	0 - 100 m *50 m	1-91	Start Current	[42]	Speed compensated counter stop without reset	[43]	0 - 100 ms *10 ms	[51]	Same choices with 3-15	[165]	[1]
1-46	Motor Cable Length Feet	1-92	Compressor Start Max Speed [Hz]	[43]	Speed compensated counter stop without reset	[44]	0 - 100 ms *10 ms	[52]	Relative Scaling Reference	[166]	[2]
1-47	0 - 328 ft *164 ft	1-93	Compressor Start Max Time to Trip	[44]	Speed compensated counter stop without reset	[45]	0 - 100 ms *10 ms	[53]	No function	[167]	[1]
1-48	d-axis Inductance Sat. (LdSat)	1-94	Compressor Start Max Time to Trip	[45]	Speed compensated counter stop without reset	[46]	0 - 100 ms *10 ms	[54]	Analog Input 53	[168]	[2]
1-49	0 - 65535 mH *Size related	1-95	0 - 10 s *5 s	[46]	Speed compensated counter stop without reset	[47]	0 - 100 ms *10 ms	[55]	Analog Input 54	[169]	[7]
1-50	0 - 65535 mH *Size related	1-96	0 - 10 s *5 s	[47]	Speed compensated counter stop without reset	[48]	0 - 100 ms *10 ms	[56]	Frequency Input 29	[170]	[8]

5-4* Relays

[5]	Running	[169]	Drive in auto mode	[150]	Go To Home	[6]	Running / no warning
[6]	Running / no warning	[170]	Homing Completed	[151]	Home Ref. Switch	[7]	Run in range/no warn
[7]	Run in range/no warn	[171]	Target Position Reached	[155]	HW Limit Positive Inv	[8]	Run on ref/no warn
[8]	Run on ref/no warn	[172]	Position Control Fault	[156]	HW Limit Negative Inv	[9]	Alarm
[9]	Alarm	[173]	Position Mech Brake	[157]	Pos. Quick Stop Inv	[10]	Alarm or warning
[10]	Alarm or warning	[190]	STO function active	[160]	Go To Target Pos.	[11]	At torque limit
[11]	At torque limit	[193]	Sleep Mode	[162]	Pos. Idx Bit0	[12]	Out of current range
[12]	Out of current range	[194]	Broken Belt Function	[163]	Pos. Idx Bit1	[13]	Below current, low
[13]	Below current, low	[239]	STO function fault	[164]	Pos. Idx Bit2	[14]	Above current, high
[14]	Above current, high	5-41	On Delay Relay	[171]	Limit switch cw inverse	[15]	Out of frequency range
[15]	Out of frequency range	5-42	Off Delay Relay	[172]	Limit switch ccw inverse	[16]	Below frequency, low
[16]	Below frequency, low	5-42	Off Delay, Relay	6-19	Terminal 53 mode	[17]	Above frequency, high
[17]	Above frequency, high	5-5*	Pulse Input	*[11]	Voltage mode	[18]	Out of feedb. range
[18]	Out of feedb. range	5-50	Term. 29 Low Frequency	[6]	Digital input	[19]	Below feedback, low
[19]	Below feedback, low	5-51	Term. 29 High Frequency	6-2*	Analog Input 54	[20]	Above feedback, high
[20]	Above feedback, low	5-51	Term. 29 High Frequency	6-20	Terminal 54 Low Voltage	[21]	Thermal warning
[21]	Thermal warning	5-52	1 - 32000 Hz *32000 Hz	6-21	Terminal 54 High Voltage	[22]	Ready, no thermal warning
[22]	Ready, no thermal warning	5-52	Term. 29 Low Ref/Feedb. Value	6-22	Terminal 54 Low Current	[23]	Remote,ready,no TW
[23]	Remote,ready,no TW	5-53	Term. 29 High Ref/Feedb. Value	6-23	Terminal 54 High Current	[24]	Ready, no over-/ under voltage
[24]	Ready, no over-/ under voltage	5-55	Term. 33 Low Frequency	6-24	Terminal 54 Low Ref/Feedb. Value	[25]	Reverse
[25]	Reverse	5-56	Term. 33 High Frequency	6-25	Terminal 54 High Ref/Feedb. Value	[26]	Bus OK
[26]	Torque limit & stop	5-57	Term. 33 Low Ref/Feedb. Value	6-26	Terminal 54 Filter Time Constant	[27]	Torque limit & stop
[27]	Torque limit & stop	5-58	Term. 33 High Ref/Feedb. Value	6-29	Terminal 54 mode	[28]	Brake, no brake warning
[28]	Brake, no brake warning	5-6*	Pulse Output	[10]	Current mode	[29]	Brake ready, no fault
[29]	Brake ready, no fault	5-60	Terminal 27 Pulse Output Variable	*[11]	Voltage mode	[30]	Brake fault (IGBT)
[30]	Brake fault (IGBT)	*[0]	No operation	6-9*	Analog/Digital Output 42	[31]	Relay 123
[31]	Relay 123	[45]	Bus ctrl.	6-90	Terminal 42 Mode	[32]	Mech brake ctrl
[32]	Mech brake ctrl	[48]	Bus ctrl., timeout: On	*[0]	0-20 mA	[36]	Control word bit 11
[33]	Control word bit 11	[100]	Output frequency	[1]	4-20 mA	[37]	Control word bit 12
[34]	Control word bit 12	[101]	Reference	[2]	Digital Output	[40]	Out of ref range
[35]	Out of ref range	[102]	Process Feedback	6-91	Terminal 42 Analog Output	[41]	Below reference, low
[36]	Below reference, low	[103]	Motor Current	*[0]	No operation	[42]	Above ref, high
[37]	Above ref, high	[104]	Torque rel to limit	[1]	Terminal 42 Analog Output	[45]	Bus ctrl.
[38]	Bus ctrl.	[105]	Torque relate to rated	6-92	Terminal 42 Analog Output	[46]	Bus control, timeout: On
[39]	Bus control, timeout: On	[106]	Power	*[0]	0-20 mA	[47]	Bus control, timeout: Off
[40]	Bus control, timeout: Off	[107]	Speed	[2]	Digital Output	[56]	Heat sink cleaning warning, high
[41]	Heat sink cleaning warning, high	[109]	Max Out Freq	6-93	Terminal 42 Analog Output	[60]	Comparator 0
[42]	Above ref, high	[113]	PID Clamped Output	*[0]	No operation	[61]	Comparator 1
[43]	Bus ctrl.	5-62	Pulse Output Max Freq 27	[100]	Output frequency	[62]	Comparator 2
[44]	Bus control, timeout: On	5-7*	24V Encoder Input	[101]	Reference	[63]	Comparator 3
[45]	Bus control, timeout: Off	5-70	Term 32/33 Pulses Per Revolution	[102]	Process Feedback	[64]	Comparator 4
[46]	Heat sink cleaning warning, high	5-71	Term 32/33 Encoder Direction	[103]	Motor Current	[65]	Comparator 5
[47]	Heat sink cleaning warning, high	*[0]	Clockwise	[104]	Torque rel to limit	[70]	Logic rule 0
[48]	Comparator 0	[1]	Counter clockwise	[105]	Torque relate to rated	[71]	Logic rule 1
[49]	Comparator 1	[55]	Bus Controlled	[106]	Power	[72]	Logic rule 2
[50]	Comparator 2	5-90	Digital & Relay Bus Control	[107]	Speed	[73]	Logic rule 3
[51]	Comparator 3	5-93	Pulse Out 27 Bus Control	[111]	Speed Feedback	[74]	Logic rule 4
[52]	Comparator 4	0 - 100 % *0 %	0 - 100 % *0 %	[113]	PID Clamped Output	[75]	Logic rule 5
[53]	Comparator 5	5-94	Pulse Out 27 Timeout Preset	[139]	Bus Control	[80]	SL digital output A
[54]	Logic rule 0			[143]	Ext. CL 1	[81]	SL digital output B
[55]	Logic rule 1			[254]	DC Link Voltage	[82]	SL digital output C
[56]	Logic rule 2			6-92	Terminal 42 Digital Output	[83]	SL digital output D
[57]	Logic rule 3			*[0]	No operation	[160]	No alarm
[58]	Logic rule 4			[1]	Control Ready	[161]	Running reverse
[59]	Logic rule 5			[2]	Drive ready	[165]	Local ref active
[60]	SL digital output A			[3]	Drive rdy/rem ctrl	[166]	Remote ref active
[61]	SL digital output B			[4]	Stand-by / no warning	[167]	Start command activ
[62]	SL digital output C			[5]	Running	[168]	Drive in hand mode
[63]	SL digital output D					[169]	Drive in auto mode

[170]	Homing Completed	[0]	Off	7-6*	Feedback Conversion	[72]	Logic Rule 2	[16]	FC Port REF
[171]	Target Position Reached	*[1]	On	7-60	Feedback 1 Conversion	[73]	Logic Rule 3	8-43	PCD Read Configuration
[172]	Position Control Fault	7-32	Process PID Start Speed	*[0]	Linear	[74]	Logic Rule 4	[0]	None
[173]	Position Mech Brake	7-33	0 - 6000 RPM *0 RPM	[1]	Square root	[75]	Logic Rule 5	[1]	[1500] Operation Hours
[193]	Sleep Mode	7-33	Process PID Proportional Gain	7-62	Feedback 2 Conversion	[80]	SL digital out A	[2]	[1501] Running Hours
[194]	Broken Belt Function	7-34	0 - 10 *0.01	*[0]	Linear	[81]	SL digital out B	[3]	[1502] kWh Counter
[198]	Drive Bypass	7-34	Process PID Integral Time	[1]	Square root	[82]	SL digital out C	[4]	[1600] Control Word
6-93	Terminal 42 Output Min Scale	7-35	0.10 - 9999 s *9999 s	8-2*	Comm. and Options	[83]	SL digital out D	[5]	[1601] Reference [Unit]
6-94	Terminal 42 Output Max Scale	7-35	Process PID Differentiation Time	8-0*	General Settings	[93]	Configurable Control Word CTW	[6]	[1602] Reference %
6-96	Terminal 42 Output Bus Control	7-36	Process PID Diff. Gain Limit	8-01	Control Site	[93]	Alarm68 or Alarm188	[7]	[1603] Status Word
	0 - 200 % *0	7-36	1 - 50 *5	*[0]	Digital and ctrl word	[10]	None	[8]	[1605] Main Actual Value [%]
	0 - 200 % *100	7-38	Process PID Feed Forward Factor	[1]	Digital only	*[1]	Profile default	[9]	[1609] Custom Readout
	0 - 16384 *0	7-39	On Reference Bandwidth	[2]	Control word only	[2]	CTW Valid, active low	[10]	[1610] Power [kW]
	0 - 200 % *0	7-40	Process PID Feed Fwd Reset	8-02	Control Source	[4]	PID error inverse	[11]	[1611] Power [hp]
	0 - 200 % *5	7-41	Process PID Output Neg. Clamp	[0]	None	[5]	PID reset l part	[12]	[1612] Motor Voltage
	0 - 200 % *100	7-42	Process PID Output Pos. Clamp	[1]	FC Port	[6]	PID enable	[13]	[1613] Frequency
	0 - 200 % *50	7-43	Process PID Gain Scale at Min. Ref.	[2]	FC USB	8-19	Product Code	[14]	[1614] Motor Current
	0 - 200 % *100	7-44	Process PID Gain Scale at Max. Ref.	[3]	Option A	8-3*	0 - 2147483647 *Size related	[15]	[1615] Frequency [%]
	0 - 200 % *50	7-45	Process PID Feed Fwd Resource	8-03	Control Timeout Time	8-30	Protocol	[16]	[1616] Torque [Nm]
	0 - 200 % *100	7-46	Process PID Feed Fwd Normal/ Inv.	8-30	Control Timeout Function	*[0]	FC	[17]	[1618] Motor Thermal
	0 - 200 % *50	7-47	Process PID Feed Fwd Inverse	[1]	Off	[2]	Modbus RTU Address	[18]	[1630] DC Link Voltage
	0 - 200 % *100	7-48	Process PID Feed Fwd Inverse	[2]	Freeze output	8-31	0.0 - 247 *1	[19]	[1634] Inverter Thermal
	0 - 200 % *50	7-49	Process PID Feed Fwd Inverse	[3]	Jogging	8-32	Baud Rate	[20]	[1638] SL Controller State
	0 - 200 % *100	7-50	Process PID Feed Fwd Inverse	[4]	Max. speed	[32]	2400 Baud	[21]	[1650] External Reference
	0 - 200 % *50	7-51	Process PID Feed Fwd Inverse	[5]	Stop and trip	[1]	4800 Baud	[22]	[1652] Feedback [Unit]
	0 - 200 % *100	7-52	Process PID Feed Fwd Inverse	[6]	Diagnosis Trigger	[1]	8000 Baud	[23]	[1660] Digital Input 18,19,27,33
	0 - 200 % *50	7-53	Process PID Feed Fwd Inverse	[7]	Disable	[3]	19200 Baud	[24]	[1661] Terminal 53 Switch Setting
	0 - 200 % *100	7-54	Process PID Feed Fwd Inverse	[8]	Trigger on alarms	[4]	38400 Baud	[25]	[1662] Analog input 53
	0 - 200 % *50	7-55	Process PID Feed Fwd Inverse	[9]	Trigger alarm/warn.	[5]	57600 Baud	[26]	[1663] Terminal 54 Switch Setting
	0 - 200 % *100	7-56	Process PID Feed Fwd Inverse	[10]	Control Word Profile	[6]	76800 Baud	[27]	[1664] Analog input 54
	0 - 200 % *50	7-57	Process PID Feed Fwd Inverse	[11]	FC profile	[7]	115200 Baud	[28]	[1665] Analog output 42 [mA]
	0 - 200 % *100	7-58	Process PID Feed Fwd Inverse	[12]	PROFIdrive profile	8-33	Parity / Stop Bits	[29]	[1671] Relay output
	0 - 200 % *50	7-59	Process PID Feed Fwd Inverse	[13]	ODVA	[31]	Even Parity, 1 Stop Bit	[30]	[1672] Counter A
	0 - 200 % *100	7-60	Process PID Feed Fwd Inverse	[14]	CANopen DSP 402	[0]	Odd Parity, 1 Stop Bit	[32]	[1673] Counter B
	0 - 200 % *50	7-61	Process PID Feed Fwd Inverse	[15]	Configurable Status Word STW	[1]	No Parity, 1 Stop Bit	[33]	[1690] Alarm Word
	0 - 200 % *100	7-62	Process PID Feed Fwd Inverse	[16]	Profile Default	[2]	No Parity, 2 Stop Bits	[34]	[1692] Warning Word
	0 - 200 % *50	7-63	Process PID Feed Fwd Inverse	[17]	Alarm 68 Only	[3]	Minimum Response Delay	[35]	[1694] Ext. Status Word
	0 - 200 % *100	7-64	Process PID Feed Fwd Inverse	[18]	Trip excl Alarm 68	8-35	0.0010 - 0.5 s *0.01 s	8-5*	Digital/Bus
	0 - 200 % *50	7-65	Process PID Feed Fwd Inverse	[19]	T18 DI status	8-36	Maximum Response Delay	8-50	Coasting Select
	0 - 200 % *100	7-66	Process PID Feed Fwd Inverse	[20]	T19 DI status	[0]	0.1 - 10.0 s *Size related	[1]	Digital input
	0 - 200 % *50	7-67	Process PID Feed Fwd Inverse	[21]	T27 DI status	8-4*	FC MC protocol set	[2]	Bus
	0 - 200 % *100	7-68	Process PID Feed Fwd Inverse	[22]	T32 DI status	8-42	PCD Write Configuration	[3]	Logic AND
	0 - 200 % *50	7-69	Process PID Feed Fwd Inverse	[23]	T33 DI status	[0]	None	[2]	Logic OR
	0 - 200 % *100	7-70	Process PID Feed Fwd Inverse	[24]	Thermal warning	[1]	[302] Minimum Reference	8-51	Quick Stop Select
	0 - 200 % *50	7-71	Process PID Feed Fwd Inverse	[25]	Brake fault (IGBT)	[2]	[303] Maximum Reference	[0]	Digital input
	0 - 200 % *100	7-72	Process PID Feed Fwd Inverse	[26]	Out of ref range	[3]	[341] Ramp 1 Ramp up time	[1]	Bus
	0 - 200 % *50	7-73	Process PID Feed Fwd Inverse	[27]	Comparator 0	[4]	[342] Ramp 1 Ramp down time	[2]	Logic AND
	0 - 200 % *100	7-74	Process PID Feed Fwd Inverse	[28]	Comparator 1	[5]	[351] Ramp 2 Ramp up time	*[3]	Logic OR
	0 - 200 % *50	7-75	Process PID Feed Fwd Inverse	[29]	Comparator 2	[6]	[352] Ramp 2 Ramp down time	8-52	DC Brake Select
	0 - 200 % *100	7-76	Process PID Feed Fwd Inverse	[30]	Comparator 3	[7]	[380] Jog Ramp Time	[0]	Digital input
	0 - 200 % *50	7-77	Process PID Feed Fwd Inverse	[31]	Comparator 4	[8]	[381] Quick Stop Time	[1]	Bus
	0 - 200 % *100	7-78	Process PID Feed Fwd Inverse	[32]	Comparator 5	[9]	[412] Motor Speed Low Limit [Hz]	[2]	Logic AND
	0 - 200 % *50	7-79	Process PID Feed Fwd Inverse	[33]	Logic Rule 0	[10]	[414] Motor Speed High Limit [Hz]	*[3]	Logic OR
	0 - 200 % *100	7-80	Process PID Feed Fwd Inverse	[34]	Logic Rule 1	[11]	[590] Digital & Relay Bus Control	8-53	Start Select
	0 - 200 % *50	7-81	Process PID Feed Fwd Inverse	[35]	Logic Rule 2	[12]	[676] Terminal45 Output Bus Control	[0]	Digital input
	0 - 200 % *100	7-82	Process PID Feed Fwd Inverse	[36]	Logic Rule 3	[13]	[696] Terminal 42 Output Bus Control	[1]	Bus
	0 - 200 % *50	7-83	Process PID Feed Fwd Inverse	[37]	Logic Rule 4	[14]	FC Port CTW	[2]	Logic AND
	0 - 200 % *100	7-84	Process PID Feed Fwd Inverse	[38]	Logic Rule 5	[15]		*[3]	Logic OR

8-54	Reversing Select	[341]	Ramp 1 Ramp Up Time	[1639]	Control Card Temp.	[0]	Disabled	0 - 9999 *0
[0]	Digital input	[342]	Ramp 1 Ramp Down Time	[1650]	External Reference	*[1]	Enabled	9-84 Defined Parameters (5)
[1]	Bus	[351]	Ramp 2 Ramp Up Time	[1652]	Feedback[Unit]	9-28	Process Control	0 - 9999 *0
[2]	Logic AND	[352]	Ramp 2 Ramp Down Time	[1653]	Digi Pot Reference	[0]	Disable	9-85 Defined Parameters (6)
*[3]	Logic OR	[380]	Jog Ramp Time	[1657]	Feedback [RPM]	*[1]	Enable cyclic master	0 - 9999 *0
8-55	Set-up Select	[381]	Quick Stop Ramp Time	[1660]	Digital Input	9-44	Fault Message Counter	Changed Parameters (1)
[0]	Digital input	[412]	Motor Speed Low Limit [Hz]	[1661]	Terminal 53 Setting	0 - 65535 *0	Fault Code	0 - 9999 *0
[1]	Bus	[414]	Motor Speed High Limit [Hz]	[1662]	Analog input 53	9-45	Fault Code	0 - 9999 *0
[2]	Logic AND	[416]	Torque Limit Motor Mode	[1663]	Terminal 54 Setting	0 - 0 *0	Fault Number	0 - 9999 *0
*[3]	Logic OR	[417]	Torque Limit Generator Mode	[1664]	Analog output 54	9-47	Fault Number	0 - 9999 *0
8-56	Preset Reference Select	[553]	Term. 29 High Ref./Feedb. Value	[1665]	Analog output 42 [mA]	0 - 0 *0	Fault Situation Counter	0 - 9999 *0
[0]	Digital input	[558]	Term. 33 High Ref./Feedb. Value	[1666]	Digital Output	9-52	Fault Situation Counter	0 - 9999 *0
[1]	Bus	[590]	Digital & Relay Bus Control	[1667]	Pulse input 29 [Hz]	0 - 1000 *0	Profibus Warning Word	0 - 9999 *0
[2]	Logic AND	[593]	Terminal 53 High Ref./Feedb. Value	[1668]	Pulse input 33 [Hz]	0 - 65535 *0	Actual Baud Rate	0 - 9999 *0
*[3]	Logic OR	[615]	Terminal 54 High Ref./Feedb. Value	[1669]	Pulse output 27 [Hz]	9-53	Actual Baud Rate	0 - 9999 *0
8-57	Profidrive OFF2 Select	[625]	Terminal 42 Output Bus Control	[1671]	Relay output	9-63	Actual Baud Rate	0 - 9999 *0
[0]	Digital input	[696]	PCD Feed Forward	[1672]	Counter A	[0]	9,6 kbit/s	0 - 65535 *0
[1]	Bus	[748]	Bus Jog 1 Speed	[1673]	Counter B	[1]	19,2 kbit/s	10-00
[2]	Logic AND	[890]	Bus Jog 2 Speed	[1674]	Prec. Stop Counter	[2]	93,75 kbit/s	10-01
*[3]	Logic OR	[891]	Fieldbus CTW 1	[1684]	Comm. Option STW	[3]	187,5 kbit/s	10-01
8-58	Profidrive OFF3 Select	[1680]	Fieldbus CTW 1	[1685]	FC Port CTW 1	[4]	500 kbit/s	[16]
[0]	Digital input	[1682]	Fieldbus REF 1	[1690]	Alarm Word	[6]	1500 kbit/s	[17]
[1]	Bus	[3401]	PCD 1 Write For Application	[1691]	Alarm Word 2	[7]	3000 kbit/s	[18]
[2]	Logic AND	[3402]	PCD 2 Write For Application	[1692]	Warning Word	[8]	6000 kbit/s	*[20]
[3]	Logic OR	[3403]	PCD 3 Write For Application	[1693]	Warning Word 2	[9]	12000 kbit/s	[21]
8-79	Protocol SW Version	[3404]	PCD 4 Write For Application	[1694]	Ext. Status Word	[10]	31,25 kbit/s	[22]
8-79	Protocol Firmware version	[3405]	PCD 5 Write For Application	[1695]	Ext. Status Word 2	[11]	45,45 kbit/s	[23]
8-8*	FC Port Diagnostics	[3406]	PCD 6 Write For Application	[1697]	Alarm Word 3	*[25]	No baudrate found	[24]
8-80	Bus Message Count	[3407]	PCD 7 Write For Application	[3421]	PCD 1 Read For Application	9-64	Device Identification	10-02
8-81	Bus Error Count	[3408]	PCD 8 Write For Application	[3422]	PCD 2 Read For Application	9-65	Profile Number	1 - 127 *127
8-82	Slave Messages Rcvd	[3409]	PCD 9 Write For Application	[3423]	PCD 3 Read For Application	0 - 0 *0	Readout Transmit Error Counter	0 - 255 *0
8-83	Slave Error Count	[3410]	PCD 10 Write For Application	[3424]	PCD 4 Read For Application	9-67	Control Word 1	0 - 255 *0
8-84	Slave Messages Sent	9-16	PCD Read Configuration	[3425]	PCD 5 Read For Application	9-68	Status Word 1	0 - 65535 *0
8-85	Slave Timeout Errors	[0]	None	[3426]	PCD 6 Read For Application	0 - 65535 *0	Edit Set-up	10-31
8-88	Reset FC port Diagnostics	[1500]	Operating hours	[3427]	PCD 7 Read For Application	9-70	Set-up 1	Store all setups
*[0]	Do not reset	[1501]	Running hours	[3428]	PCD 8 Read For Application	[1]	Set-up 2	Store edit setup
[1]	Reset counter	[1502]	kWh Counter	[3429]	PCD 9 Read For Application	[2]	Set-up 3	Store Always
8-9*	Bus Feedback	[1600]	Control Word	[3430]	PCD 10 Read For Application	[3]	Set-up 4	Off
8-90	Bus Jog 1 Speed	[1601]	Reference [Unit]	[3450]	Actual Position	*[9]	Active Set-up	On
8-91	Bus Jog 2 Speed	[1602]	Reference [%]	[3456]	Track Error	9-71	Profibus Save Data Values	12-00
9-00	Setpoint	[1603]	Status Word	9-18	Node Address	9-71	Profibus Save Data Values	12-00
9-07	Actual Value	[1605]	Main Actual Value [%]	9-19	Drive Unit System Number	[0]	Off	IP Address Assignment
9-15	PCD Write Configuration	[1609]	Custom Readout	9-22	Telegram Selection	9-72	Store all setups	[0]
[0]	None	[1610]	Power [kW]	[1]	Standard telegram 1	*[100]	ProfibusDriveReset	[1]
[302]	Minimum Reference	[1611]	Power [hp]	[101]	None	[0]	No action	[1]
[303]	Maximum Reference	[1612]	Motor Voltage	[102]	PPO 1	[1]	Power-on reset	[2]
[312]	Catch up/slow Down Value	[1613]	Frequency	[103]	PPO 2	[2]	Power-on reset prep	*[10]
		[1614]	Motor current	[104]	PPO 3	[3]	Comm option reset	[20]
		[1615]	Frequency [%]	[105]	PPO 4	9-75	DO Identification	12-01
		[1616]	Torque [Nm]	[106]	PPO 5	0 - 65535 *0	IP Address	0 - 4294967295 *0
		[1617]	Speed [RPM]	[107]	PPO 6	0 - 9999 *0	Subnet Mask	0 - 4294967295 *0
		[1618]	Motor Thermal	[108]	PPO 7	0 - 9999 *0	Default Gateway	0 - 4294967295 *0
		[1620]	Motor Angle	[200]	Custom telegram 1	9-81	Defined Parameters (2)	0 - 4294967295 *0
		[1622]	Torque [%]	9-23	Parameters for Signals	9-82	Defined Parameters (3)	DHCP Server
		[1630]	DC Link Voltage	9-27	Parameter Edit	9-83	Defined Parameters (4)	0 - 2147483647 *0
		[1633]	Brake Energy /2 min					Lease Expires
		[1634]	Heatsink Temp.					
		[1635]	Inverter Thermal					
		[1638]	SL Controller State					

0 - 4294967295 *0	[3401] PCD 1 Write For Application	[1691] Alarm Word 2	0 - 2147483647 *0	[2]	Running
12-06 Name Servers	[3402] PCD 2 Write For Application	[1692] Warning Word	12-69 Ethernet PowerLink Status	[3]	In range
0 - 4294967295 *0	[3403] PCD 3 Write For Application	[1693] Warning Word 2	0 - 4294967295 *0	[4]	On reference
12-07 Domain Name	[3404] PCD 4 Write For Application	[1694] Ext. Status Word	12-8* Other Ethernet Services	[7]	Out of current range
1 - 48 *0	[3405] PCD 5 Write For Application	[1695] Ext. Status Word 2	12-80 FTP Server	[8]	Below l low
12-08 Host Name	[3406] PCD 6 Write For Application	[1697] Alarm Word 3	*[0] Disabled	[9]	Above l high
1 - 48 *0	[3407] PCD 7 Write For Application	[3421] PCD 1 Read For Application	[1] Enabled	[16]	Thermal warning
12-09 Physical Address	[3408] PCD 8 Write For Application	[3422] PCD 2 Read For Application	12-81 HTTP Server	[17]	Mains out of range
12-1* Ethernet Link Parameters	[3409] PCD 9 Write For Application	[3423] PCD 3 Read For Application	*[0] Disabled	[18]	Reversing
12-10 Link Status	[3410] PCD 10 Write For Application	[3424] PCD 4 Read For Application	[1] Enabled	[19]	Warning
*[0] No Link	12-22 Process Data Config Read	[3425] PCD 5 Read For Application	12-82 SMTP Service	[20]	Alarm (trip)
[1] Link	[0] None	[3426] PCD 6 Read For Application	*[0] Disabled	[21]	Alarm (trip lock)
12-11 Link Duration	[1500] Operating hours	[3427] PCD 7 Read For Application	[1] Enabled	[22]	Comparator 0
0 - 0 *Size related	[1501] Running Hours	[3428] PCD 8 Read For Application	12-83 SNMP Agent	[23]	Comparator 1
12-12 Auto Negotiation	[1502] kWh Counter	[3429] PCD 9 Read For Application	[0] Disabled	[24]	Comparator 2
[0] Off	[1600] Control Word	[3430] PCD 10 Read For Application	*[1] Enabled	[25]	Comparator 3
*[1] On	[1601] Reference [Unit]	[3450] Actual Position	12-84 Address Conflict Detection	[26]	Logic rule 0
12-13 Link Speed	[1602] Reference [%]	[3456] Track Error	[0] Disabled	[27]	Logic rule 1
*[0] None	[1603] Status Word	12-23 Process Data Config Write Size	*[1] Enabled	[28]	Logic rule 2
[1] 10 Mbps	[1605] Main Actual Value [%]	8 - 32 *16	12-89 Transparent Socket Channel Port	[29]	Logic rule 3
[2] 100 Mbps	[1609] Custom Readout	12-24 Process Data Config Read Size	0 - 65535 *4000	[33]	Digital input DI18
12-14 Link Duplex	[1610] Power [kW]	8 - 32 *16	12-9* Advanced Ethernet Services	[34]	Digital input DI19
[0] Half Duplex	[1611] Power [hp]	12-28 Store Data Values	12-90 Cable Diagnostic	[35]	Digital input DI27
*[1] Full Duplex	[1612] Motor Voltage	[0] Off	*[0] Disabled	[36]	Digital input DI29
12-18 Supervisor MAC	[1613] Frequency	[2] Store all setups	[1] Enabled	[39]	Start command
0 - 2147483647 *0	[1614] Motor current	12-29 Store Always	12-91 Auto Cross Over	[40]	Drive stopped
12-19 Supervisor IP Addr.	[1615] Frequency [%]	*[0] Off	[0] Disabled	[42]	Auto Reset Trip
0 - 2147483647 *0	[1616] Torque [Nm]	[1] On	*[1] Enabled	[50]	Comparator 4
12-2* Process Data	[1617] Speed [RPM]	12-3* EtherNet/IP	12-92 IGMP Snooping	[51]	Comparator 5
12-20 Control Instance	[1618] Motor Thermal	12-30 Warning Parameter	[0] Disabled	[60]	Logic rule 4
0 - 255 *Size related	[1620] Motor Angle	0 - 2147483647 *0	*[1] Enabled	[61]	Logic rule 5
12-21 Process Data Config Write	[1622] Torque [%]	12-31 Net Reference	12-93 Cable Error Length	[83]	Broken Belt
[0] None	[1630] DC Link Voltage	*[0] Off	0 - 65535 *0	13-02	Stop Event
[302] Minimum Reference	[1633] Brake Energy /2 min	[1] On	12-94 Broadcast Storm Protection	[0] False	
[303] Maximum Reference	[1634] Heatsink Temp.	12-32 Net Control	-1 - 20 % *1 %	[1] True	
[312] Catch up/slow Down Value	[1635] Inverter Thermal	*[0] Off	12-95 Inactivity timeout	[2]	Running
[341] Ramp 1 Ramp Up Time	[1638] SL Controller State	[1] On	0 - 3600 *120	[3]	In range
[342] Ramp 1 Ramp Down Time	[1639] Control Card Temp.	12-33 CIP Revision	12-96 Port Config	[4]	On reference
[351] Ramp 2 Ramp Up Time	[1650] External Reference	0 - 65535 *Size related	[0] Normal	[7]	Out of current range
[352] Ramp 2 Ramp Down Time	[1652] Feedback[Unit]	0 - 65535 *Size related	[1] Mirror Port 1 to 2	[8]	Below l low
[380] Jog Ramp Time	[1653] Digi Pot Reference	12-35 EDS Parameter	[2] Mirror Port 2 to 1	[9]	Above l high
[381] Quick Stop Ramp Time	[1657] Feedback [RPM]	0 - 0 *0	[10] Port 1 disabled	[16]	Thermal warning
[412] Motor Speed Low Limit [Hz]	[1660] Digital Input	12-37 COS Inhibit Timer	[11] Port 2 disabled	[17]	Mains out of range
[414] Motor Speed High Limit [Hz]	[1661] Terminal 53 Setting	0 - 65535 *0	[254] Mirror Int. Port to 1	[18]	Reversing
[416] Torque Limit Motor Mode	[1662] Analog input 53	12-38 COS Filter	[255] Mirror Int. Port to 2	[19]	Warning
[417] Torque Limit Generator Mode	[1663] Terminal 54 Setting	0 - 65535 *0	12-97 QoS Priority	[20]	Alarm (trip)
[553] Term. 29 High Ref/Feedb. Value	[1664] Analog input 54	12-6* Ethernet PowerLink	0 - 63 *Size related	[21]	Alarm (trip lock)
[558] Term. 33 High Ref/Feedb. Value	[1665] Analog output 42 [mA]	12-60 Node ID	12-98 Interface Counters	[22]	Comparator 0
[590] Digital & Relay Bus Control	[1666] Digital Output	1 - 239 *1	0 - 4294967295 *4000	[23]	Comparator 1
[593] Pulse Out 27 Bus Control	[1667] Pulse input 29 [Hz]	12-62 SDO Timeout	0 - 4294967295 *0	[24]	Comparator 2
[615] Terminal 53 High Ref/Feedb. Value	[1669] Pulse output 27 [Hz]	0 - 2000000000 ms *30000 ms	13-* Smart Logic	[25]	Comparator 3
[625] Terminal 54 High Ref/Feedb. Value	[1671] Relay output	12-63 Basic Ethernet Timeout	13-0* SLC Settings	[26]	Logic rule 0
[696] Terminal 42 Output Bus Control	[1672] Counter A	0 - 2000000.000 ms *5000.000 ms	13-00 SL Controller Mode	[27]	Logic rule 1
[748] PCD Feed Forward	[1673] Counter B	12-66 Threshold	*[0] Off	[29]	Logic rule 3
[890] Bus Jog 1 Speed	[1674] Prec. Stop Counter	0 - 2000000000 *15	[1] On	[30]	SL Time-out 0
[891] Bus Jog 2 Speed	[1684] Comm. Option STW	12-67 Threshold Counters	[0] Off	[31]	SL Time-out 1
[1680] Fieldbus CTW 1	[1685] FC Port CTW 1	0 - 4294967295 *0	[1] On	[32]	SL Time-out 2
[1682] Fieldbus REF 1	[1690] Alarm Word	12-68 Cumulative Counters	[0] False	[33]	Digital input DI18
			[1] True		

[34]	Digital input DI19	[21]	Alarm (trip lock)	[20]	Alarm (trip)	[34]	Set digital out C low	[2]	Automatic reset x 2
[35]	Digital input DI27	[22]	Comparator 0	[21]	Alarm (trip lock)	[35]	Set digital out D low	[3]	Automatic reset x 3
[36]	Digital input DI29	[23]	Comparator 1	[22]	Comparator 0	[38]	Set digital out A high	[4]	Automatic reset x 4
[39]	Start command	[24]	Comparator 2	[23]	Comparator 1	[39]	Set digital out B high	[5]	Automatic reset x 5
[40]	Drive stopped	[25]	Comparator 3	[24]	Comparator 2	[40]	Set digital out C high	[6]	Automatic reset x 6
[42]	Auto Reset Trip	[26]	Logic rule 0	[25]	Comparator 3	[41]	Set digital out D high	[7]	Automatic reset x 7
[50]	Comparator 4	[27]	Logic rule 1	[26]	Logic rule 0	[60]	Reset Counter A	[8]	Automatic reset x 8
[51]	Comparator 5	[28]	Logic rule 2	[27]	Logic rule 1	[61]	Reset Counter B	[9]	Automatic reset x 9
[60]	Logic rule 4	[29]	Logic rule 3	[28]	Logic rule 2	[70]	Start Timer 3	[10]	Automatic reset x 10
[61]	Logic rule 5	[30]	SL Time-out 0	[29]	Logic rule 3	[71]	Start Timer 4	[11]	Automatic reset x 15
[70]	SL Time-out 3	[31]	SL Time-out 1	[30]	SL Time-out 0	[72]	Start Timer 5	[12]	Automatic reset x 20
[71]	SL Time-out 4	[32]	SL Time-out 2	[31]	SL Time-out 1	[73]	Start Timer 6	[13]	Infinite auto reset
[72]	SL Time-out 5	[33]	Digital input DI18	[32]	SL Time-out 2	[74]	Start Timer 7	[14]	Reset at power-up
[73]	SL Time-out 6	[34]	Digital input DI19	[33]	Digital input DI18				Automatic Restart Time
[74]	SL Time-out 7	[35]	Digital input DI27	[34]	Digital input DI19				0 - 600 s *10 s
[83]	Broken Belt	[36]	Digital input DI29	[35]	Digital input DI27				Operation Mode
[13-41]	Logic Rule Operator 1	[39]	Start command	[36]	Digital input DI29				Normal operation
[13-41]	Logic Rule Operator 1	[40]	Drive stopped	[39]	Start command				Initialisation
[13-41]	Logic Rule Operator 1	[42]	Auto Reset Trip	[40]	Drive stopped				Trip Delay at Current Limit
[13-41]	Logic Rule Operator 1	[50]	Comparator 4	[42]	Auto Reset Trip				0 - 60 s *60 s
[13-41]	Logic Rule Operator 1	[51]	Comparator 5	[50]	Comparator 4				Trip Delay at Torque Limit
[13-41]	Logic Rule Operator 1	[60]	Logic rule 4	[51]	Comparator 5				0 - 60 s *60 s
[13-41]	Logic Rule Operator 1	[61]	Logic rule 5	[60]	Logic rule 4				Action At Inverter Fault
[13-41]	Logic Rule Operator 1	[70]	SL Time-out 3	[61]	Logic rule 5				Trip
[13-41]	Logic Rule Operator 1	[71]	SL Time-out 4	[70]	SL Time-out 3				Warning
[13-41]	Logic Rule Operator 1	[72]	SL Time-out 5	[71]	SL Time-out 4				Production Settings
[13-41]	Logic Rule Operator 1	[73]	SL Time-out 6	[72]	SL Time-out 5				No action
[13-41]	Logic Rule Operator 1	[74]	SL Time-out 7	[73]	SL Time-out 6				Service reset
[13-41]	Logic Rule Operator 1	[83]	Broken Belt	[74]	SL Time-out 7				Software Reset
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[83]	Broken Belt				Service Code
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				0 - 0xFFFFFFF *0
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				Current Limit Ctrl.
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				Current Lim Ctrl, Proportional Gain
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				0 - 500 % *100 %
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				Current Lim Ctrl, Integration Time
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				0.002 - 2 s *0.020 s
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				Current Lim Ctrl, Filter Time
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				1 - 100 ms *5 ms
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				Energy Optimising
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				40 - 90 % *66 %
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				40 - 75 % *66 %
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				40 - 75 % *66 %
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				d-axis current optimization for IPM
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				0 - 200 % *100 %
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				Environment
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				DC-Link Voltage Compensation
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				Off
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				On
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				Fan Control
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				Constant-on mode
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				Constant-off mode
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				On-when-Inverter-is-on-else-off Mode
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				Variable-speed mode
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				Output Filter
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				No Filter
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				Sine-Wave Filter
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				Auto Derate
[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1	[13-41]	Logic Rule Operator 1				Function at Inverter Overload

* [0]	15-4* Drive Identification	15-40 FC Type	0 - 0 %	16-05 Main Actual Value [%]	0 - 65535 °C	16-61 Terminal 53 Setting	18-92 Process PID Clamped Output
		15-41 Power Section	0 - 0 °C	16-09 Custom Readout	-200 - 200 °C %	[6] Digital input	-200 - 200 °C %
		15-42 Voltage	0 - 20 °C	16-09 Custom ReadoutUnit °C	0 - 9999 CustomReadoutUnit °C	16-62 Analog input 53	18-93 Process PID Gain Scaled Output
		15-43 Software Version	0 - 0 °C	16-11 Motor Status	0 - 9999 CustomReadoutUnit °C	16-63 Terminal 54 Setting	-200 - 200 °C %
* [0]	15-44 Ordered TypeCode	15-44 Ordered TypeCode	0 - 0 °C	16-10 Power [kW]	0 - 1000 kW °C kW	[0] Current mode	21-1** Ext. Closed Loop
		15-45 Actual TypeCode String	0 - 41 °C	16-11 Power [hp]	0 - 1000 hp °C hp	[1] Voltage mode	
		15-46 Drive Ordering No	0 - 40 °C	16-12 Motor Voltage	0 - 1000 V °C V	[1] Disabled	
		15-47 LCP Id No	0 - 0 °C	16-13 Frequency	0 - 65535 V °C V	[1] Enabled Ext CL1 PID	
* [0]	15-48 LCP Id No	15-48 LCP Id No	0 - 0 °C	16-14 Motor current	0 - 65535 Hz °C Hz	21-0* Ext. CL Autotuning	21-0* Ext. CL Autotuning
		15-49 SW ID Control Card	0 - 0 °C	16-15 Frequency [%]	0 - 65535 A °C A	21-09 Extended PID Enable	
		15-50 SW ID Power Card	0 - 0 °C	16-16 Torque [Nm]	0 - 65535 % °C %	[0] Disabled	
		15-51 Drive Serial Number	0 - 0 °C	16-17 Speed [RPM]	-30000 - 30000 RPM °C RPM	[1] Enabled Ext CL1 Ref/Fb.	
* [0]	15-52 OEM Information	15-52 OEM Information	0 - 0 °C	16-18 Motor Thermal	0 - 100 °C %	21-11 Ext. 1 Minimum Reference	21-11 Ext. 1 Minimum Reference
		15-53 Power Card Serial Number	0 - 0 °C	16-20 Motor Angle	0 - 65535 °C	Ext. 1 Reference Source	
		15-57 File Version	0 - 255 °C	16-22 Torque [%]	-200 - 200 °C %	Ext. 1 Maximum Reference	
		15-59 Filename	0 - 16 °C	16-3* Drive Status	0 - 65535 V °C V	*100 ExtPID1Unit	
* [0]	15-6* Option Ident	15-60 Option Mounted	0 - 30 °C related	16-33 Brake Energy /2 min	0 - 10000 kW °C kW	Ext. 1 Setpoint	21-15 Ext. 1 Setpoint
		15-61 Option SW Version	0 - 20 °C related	16-34 Heatsink Temp.	-128 - 127 °C °C	Ext. 1 Reference [Unit]	
		15-70 Option in Slot A	0 - 30 °C	16-35 Inverter Thermal	0 - 255 °C °C	Ext. 1 Feedback [Unit]	
		15-71 Slot A Option SW Version	0 - 20 °C	16-36 Inv. Nom. Current	0 - 65535 A °C A	Ext. 1 Output [%]	
* [0]	15-9* Parameter Info	15-92 Defined Parameters	0 - 2000 °C	16-37 Inv. Max. Current	0 - 65535 A °C A	Ext. 1 PID	21-2* Ext. CL 1 PID
		15-97 Application Type	0 - 0xFFFFFFF °C	16-38 SL Controller State	0 - 20 °C	Ext. 1 Normal/Inverse Control	
		15-98 Drive Identification	0 - 56 °C	16-39 Control Card Temp.	0 - 65535 °C °C	[1] Inverse	
		15-99 Parameter Metadata	0 - 9999 °C	16-5* Ref. & Feeds.	0 - 65535 °C °C	Ext. 1 Proportional Gain	
* [0]	16-0* General Status	16-00 Control Word	0 - 65535 °C	16-50 External Reference	-200 - 200 °C %	Ext. 1 Integral Time	21-22 Ext. 1 Integral Time
		16-01 Reference [Unit]	-4999 - 4999 ReferenceFeedbackUnit °C	16-52 Feedback[Unit]	-4999 - 4999 ProcessCtrlUnit °C	0.01 - 10000 s *10000 s	
		16-02 ReferenceFeedbackUnit	0 - 255 °C	16-53 Digi Pot Reference	-200 - 200 °C	Ext. 1 Differentiation Time	
		16-03 Status Word	-32767 - 32767 °C	16-57 Feedback [RPM]	0 - 30000 - 30000 RPM °C RPM	0 - 10 s °C s	
* [0]	16-3* Alarm Log	16-30 Alarm Log: Error Code	0 - 255 °C	16-60 Digital input	0 - 4095 °C	Ext. 1 Dif. Gain Limit	22-4* Sleep Mode
		16-31 InternalFaultReason	-32767 - 32767 °C	16-6* Inputs & Outputs	0 - 4095 °C	Ext. 1 Gain Limit	
		16-32 Status Word	-32767 - 32767 °C	16-60 Digital input	0 - 4095 °C	1 - 50 °C	
		16-33 Status Word	-32767 - 32767 °C	16-60 Digital input	0 - 4095 °C	1 - 50 °C	

0 - 600 s *10 s	33-02	Home Ramp Time	34-29	PCD 9 Read For Application	[4]	Pos. SW Limit
22-41 Minimum Sleep Time		1 - 1000 ms *10 ms		0 - 65535 *	[5]	Neg. SW Limit
22-43 Wake-Up Speed [Hz]	33-03	Homing Velocity	34-30	PCD 10 Read For Application	[7]	Brake Wear Limit
0 - 600 s *10 s		-1500 - 1500 RPM *100 RPM		0 - 65535 *	[8]	Quick Stop
22-44 Wake-Up Ref/FB Diff	33-04	Homing Behaviour	34-5*	Process Data	[9]	PID Error Too Big
0 - 4000 *10		Reverse no index	34-50	Actual Position	[12]	Rev. Operation
22-45 Setpoint Boost	[1]	[3]		-1073741824 - 1073741824 *	[13]	Fwd. Operation
0 - 100 % *10 %		Forward no index	34-56	Track Error	[20]	Can not find home position
22-46 Maximum Boost Time	33-4*	Limit Handling		-2147483647 - 2147483647 *	37-19	Pos. New Index
-100 - 100 % *0 %		Negative Software Limit			0 - 255 *	
22-47 Sleep Speed [Hz]	33-41	-1073741824 - 1073741824 *-500000	37-2**	Application Settings		
0 - 600 s *60 s		Positive Software Limit	37-0*	Application Mode		
22-48 Sleep Delay Time	33-42	-1073741824 - 1073741824 *500000	37-00	Application Mode		
0 - 4000 *0		Negative Software Limit Active	[0]	Drive mode		
22-49 Wake-Up Delay Time	[0]	Inactive	37-1*	Position Control		
0 - 3600 s *0 s	[1]	Active				
22-50 Broken Belt Detection	33-44	Positive Software Limit Active	37-01	Pos. Feedback Source		
0 - 3600 s *0 s		Inactive	[0]	24V Encoder		
22-60 Broken Belt Function	[0]	Active	37-02	Pos. Target		
[0]		Target Position Window		-1073741824 - 1073741824 *		
[1] Warning	33-47	1 - 10000 *512	37-03	Pos. Type		
[2] Trip			[0]	Absolute		
22-61 Broken Belt Torque	34-0*	PCD Write Par.	[1]	Relative		
5 - 100 % *10 %	34-01	PCD 1 Write For Application	37-04	Pos. Velocity		
22-62 Broken Belt Delay		0 - 65535 *		1 - 30000 RPM *100 RPM		
0 - 600 s *10 s	34-02	PCD 2 Write For Application	37-05	Pos. Ramp Up Time		
30-2** Special Features		0 - 65535 *		50 - 100000 ms *5000 ms		
30-2* Adv. Start Adjust	34-03	PCD 3 Write For Application	37-06	Pos. Ramp Down Time		
30-20 High Starting Torque Time [s]		0 - 65535 *		50 - 100000 ms *5000 ms		
0 - 60 s *Size related	34-04	PCD 4 Write For Application	37-07	Pos. Auto Brake Ctrl		
30-21 High Starting Torque Current [%]		0 - 65535 *	[0]	Disable		
0 - 2000 % *Size related	34-05	PCD 5 Write For Application	[1]	Enable		
30-22 Locked Rotor Protection		0 - 65535 *	37-08	Pos. Hold Delay		
[0]	34-06	PCD 6 Write For Application		0 - 10000 ms *0 ms		
[1] On		0 - 65535 *	37-09	Pos. Coast Delay		
30-23 Locked Rotor Detection Time [s]	34-07	PCD 7 Write For Application		0 - 1000 ms *200 ms		
0.05 - 1 s *0.10 s		0 - 65535 *	37-10	Pos. Brake Delay		
32-2** Motion Control Basic Settings	34-08	PCD 8 Write For Application		0 - 1000 ms *200 ms		
32-1* User Unit		0 - 65535 *	37-11	Pos. Brake Wear Limit		
32-11 User Unit Denominator	34-09	PCD 9 Write For Application		0 - 1073741824 *		
1 - 65535 *		0 - 65535 *	37-12	Pos. PID Anti Windup		
32-12 User Unit Numerator	34-10	PCD 10 Write For Application	[0]	Disable		
1 - 65535 *		0 - 65535 *	[1]	Enable		
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32-67 Max. Tolerated Position Error		PCD 1 Read For Application		1 - 10000 *1000		
1 - 2147483648 *2000000	34-21	0 - 65535 *	37-14	Pos. Ctrl. Source		
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1 - 30000 RPM *1500 RPM		0 - 65535 *	37-15	Pos. Direction Block		
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50 - 3600000 ms *1000 ms		0 - 65535 *	[1]	Block Reverse		
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[2] Forced automated homing		0 - 65535 *	[0]	No Fault		
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