

IMPULSE•VG+

Series 3

Flux Vector Crane Controls

Instruction Manual



MAGNETEK
MATERIAL HANDLING

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Part Number: 140-10257-R5
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***DANGER, WARNING, CAUTION, and NOTE* Statements**

DANGER, WARNING, CAUTION, and Note statements are used throughout this manual to emphasize important and critical information. You must read these statements to help ensure safety and to prevent product damage. The statements are defined below.



DANGER

DANGER indicates an imminently hazardous situation which, if not avoided, will result in death or serious injury. This signal word is to be limited to the most extreme situations.



WARNING

WARNING indicates a potentially hazardous situation which, if not avoided, could result in death or serious injury.



CAUTION

CAUTION indicates a potentially hazardous situation which, if not avoided, could result in minor or moderate injury. It may also be used to alert against unsafe practices.

NOTE: A *NOTE* statement is used to notify installation, operation, programming, or maintenance information that is important, but not hazard-related.

Disclaimer of Warranty

Magnetek, hereafter referred to as Company, assumes no responsibility for improper programming of a drive by untrained personnel. A drive should only be programmed by a trained technician who has read and understand the contents of this manual. Improper programming of a drive can lead to unexpected, undesirable, or unsafe operation or performance of the drive. This may result in damage to equipment or personal injury. Company shall not be liable for economic loss, property damage, or other consequential damages or physical injury sustained by the purchaser or by any third party as a result of such programming. Company neither assumes nor authorizes any other person to assume for Company any other liability in connection with the sale or use of this product.



WARNING

Improper programming of a drive can lead to unexpected, undesirable, or unsafe operation or performance of the drive.

Contents:

| | |
|------------------------------|--------|
| Disclaimer of Warranty | ii-iii |
|------------------------------|--------|

Chapter1: Introduction

| | |
|------------------------------|-----|
| Introduction | 1-5 |
| General Specifications | 1-6 |

Chapter 2: Installation

| | |
|----------------------------|-----|
| Long Time Storage | 2-5 |
| Installing the Drive | 2-7 |

Chapter 3:Wiring

| | |
|---|------|
| Wiring Practices | 3-3 |
| Standard Connection Diagram | 3-5 |
| Typical Circuit Protection Specifications and Wire Size | 3-6 |
| Wiring the Encoder Circuit | 3-15 |

Chapter 4: Getting Started

| | |
|------------------------|------|
| Overview | 4-3 |
| Using the Keypad | 4-4 |
| Auto-Tuning | 4-14 |

Chapter 5 : Programming Advanced Features

| | |
|------------------------------|------|
| Application | 5-3 |
| Reference Limits | 5-5 |
| Special Functions | 5-16 |
| Slack Cable Detection | 5-41 |
| Motor Parameters | 5-56 |
| Option Card Parameters | 5-61 |
| Terminal Parameters | 5-68 |

| | |
|-----------------------------|------|
| Protection Parameters | 5-85 |
| Operator Parameters | 5-95 |

Chapter 6: Troubleshooting

| | |
|---|------|
| Troubleshooting the Drive..... | 6-3 |
| Troubleshooting Encoder Related Faults..... | 6-12 |
| Fault Display and Corrective Actions at Auto-tuning | 6-17 |
| Power Section Check | 6-18 |

Appendix A: Parameter Listing

| | |
|--------------------------|-----|
| Parameter Listings | A-3 |
|--------------------------|-----|

chapter 1

Introduction

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WARNING

Do not touch any circuitry components while the main AC power is on. In addition, you must wait until the red “CHARGE” LED is out before performing any service on that unit. (As you look at the face of the circuitry, the “CHARGE” LED is located in the lower right corner of the board.) It may take as long as 10 minutes for the charge on the main DC bus capacitors to drop to a safe level.

Do not check signals during operation.

Do not connect the main output terminals (U/T1, V/T2, W/T3) to the incoming, three-phase AC source.

Before executing Auto-Tuning, ensure that the motor is disconnected from the drive train and the electric brake is released. If the electric brake cannot be released, you must ensure that the brake is disengaged for the entire tuning process.

Read and understand this manual before installing, operating, or servicing this Drive. All warnings, cautions, and instructions must be followed. All activity must be performed by qualified personnel. The Drive must be installed according to this manual and local codes.

Do not connect or disconnect wiring while the power is on. Do not remove covers or touch circuit boards while the power is on. Do not remove or insert the digital operator while power is on.

Before servicing, disconnect all power to the equipment. The internal capacitor remains charged even after the power supply is turned off. The charge indicator LED will extinguish when the DC bus voltage is below 50VDC. To prevent electric shock, wait at least five minutes after all indicators are OFF and measure DC bus voltage to confirm safe level.

Do not perform a withstand voltage test on any part of the unit. This equipment uses sensitive devices and may be damaged by high voltage.

The Drive is suitable for circuits capable of delivering not more than 100,000 RMS symmetrical Amperes, 240VAC maximum (200V Class) and 480VAC maximum (400V Class). Install adequate branch circuit short circuit protection per applicable codes. Failure to do so may result in equipment damage and/or personal injury.

Do not connect unapproved LC or RC interference suppression filters, capacitors, or overvoltage protection devices to the output of the Drive. These devices may generate peak currents that exceed Drive specifications.

The instructions in the next three chapters apply to most IMPULSE•VG+ Series 3 crane, hoist, and monorail applications. However, you need to carefully evaluate your specific situation and ensure that you follow NEC codes and your local wiring practices.

These chapters tell you how to install IMPULSE•VG+ Series 3 and, to some extent, the components that it interconnects. It explains how to: assess the drive's environment, mount the drive, and wire the drive circuits. It is important to develop a "plan of attack" for both the mounting and wiring since each task has an effect on the other one. To assist you, "IMPULSE•VG+ Series 3 Wiring Practices" is included.

NOTE: If your IMPULSE•VG+ Series 3 is part of an Magnetek pre-engineered motor control panel, disregard this chapter and turn to Chapter 4.

Introduction

Assessing the System Requirements

It is important to know how you're going to use the drive before you start installation and wiring. You will need to know your requirements for the following components:

- Speed control method(s)
- Braking method(s)
- Power source voltage, number of phases, and kVA rating
- Power source location
- Wire size
- Grounding location and method

Assessing the Drive Environment

When you choose a location for IMPULSE•VG+ Series 3, perform the following steps:

1. Ensure that a 220 or 230VAC (-15% to +10%) three-phase power source is available for a 230VAC-rated drive, and that a 380, 400, 415, 440, or 460VAC (-15% to +10%) three-phase power source is available for a 460VAC-rated drive.
2. Ensure the encoder is supplied with +12VDC.
3. If the amperage requirement is greater than 200 mA, provide an auxiliary power supply to the encoder.
4. Ensure that the drive-to-motor wiring distance is less than 150 ft. unless appropriate reactors, filters, and/or inverter duty motor is used.
5. If required, install reactors.

When connecting a drive (230/460VAC, Model 2085-FVG+/4045-FVG+ and smaller) to a large-capacity power supply transformer (500kVA or greater or more than 10 times the inverter kVA rating), or when switching a phase-advancing capacitor, excessive peak current can flow through the input power supply circuit. To prevent damage to the rectifier section in such cases, install a DC reactor between drive Terminals 1 and 2, or an AC reactor on the input side. Installing reactors also improves the power factor on the power supply side.

6. Ensure that the encoder wiring is less than 300 feet, unless fiber optic cables are used.
7. Ensure that the encoder wiring is isolated from the power wiring.
8. Ensure that the encoder wiring shield is grounded only at drive end.
9. Ensure that the drive circuit wiring is protected or isolated from:
 - Ambient temperatures outside the range of +14°F to +140°F (-10°C to +60°C) (2 kHz carrier frequency).
 - Rain or moisture
 - Corrosive gases or liquids
 - Direct sunlight
 - Severe mechanical vibration
10. Ensure that the drive is housed in an appropriate NEMA-rated enclosure.
11. For severe-duty applications (for example—long lifts) or with 75-HP-or-greater motors, ensure that the drive control system is adequately cooled, even though the ambient temperature limit is not exceeded. For more information, contact Magnetek.

IMPULSE•VG+ Series 3 General Specifications

230V Class

| Specification | Specification Values and Information for Each 230V-Class Model | | | | | | | | | | | | |
|-------------------|--|------|------|------|------|------|------|------|------|------|------|------|------|
| | 2007 | 2009 | 2015 | 2023 | 2031 | 2045 | 2058 | 2071 | 2085 | 2145 | 2215 | 2283 | 2346 |
| Rated current (A) | 7 | 9.6 | 15 | 23 | 31 | 45 | 58 | 71 | 85 | 145 | 215 | 283 | 346 |
| Capacity (kVA) | 2.7 | 3.7 | 5.7 | 8.8 | 12 | 17 | 22 | 27 | 32 | 55 | 82 | 110 | 130 |

460V Class

| Specification | Specification Values and Information for Each 460V-Class Model | | | | | | | | | | | | | | | | | | | | |
|-------------------|--|------|------|------|------|------|------|------|------|------|------|------|------|------|------|------|------|------|------|------|------|
| | 4002 | 4003 | 4005 | 4008 | 4012 | 4017 | 4024 | 4031 | 4039 | 4045 | 4060 | 4075 | 4091 | 4112 | 4150 | 4180 | 4260 | 4304 | 4370 | 4477 | 4590 |
| Rated current (A) | 2.1 | 3.7 | 5.3 | 8.7 | 12.5 | 17 | 24 | 31 | 39 | 45 | 60 | 75 | 91 | 112 | 150 | 180 | 260 | 304 | 370 | 477 | 590 |
| Capacity (kVA) | 1.6 | 2.8 | 4.0 | 6.6 | 9.5 | 13 | 18 | 24 | 30 | 34 | 46 | 57 | 69 | 85 | 110 | 140 | 200 | 230 | 280 | 390 | 510 |

230V and 460V Classes

| Specification | Specification Value and Information for All Models |
|---------------------------------------|---|
| Certification | UL, CUL |
| Crane Duty Classification | Rated for CMAA Crane Duty Class A - F only (or equivalent) |
| Rated input power supply volts & freq | 3-phase 200/208/220/230VAC or 380/400/415/440/460/480VAC |
| Allowable input voltage fluctuation | +10% or -15% of nominal |
| Allowable input frequency fluctuation | ±5% of nominal |
| Control method | Fully digital, flux vector control; sine-wave, pulse-width-modulated |
| Maximum output voltage (VAC) | Max output voltage 3-phase, 200/208/220/230VAC; 380/400/415/440/460/480VAC (proportional to input voltage). |
| Rated frequency (Hz) | Up to twice motor nameplate RPM (Ultra-Lift) 150 Hz standard (400 Hz, consult factory) |
| Output speed control range | 1000:1 |
| Output frequency accuracy | .01%—with digital reference command .1%—with analog reference command; 10 bits/10V |
| Frequency reference resolution | Digital: .01 Hz; analog: .03 Hz (at 60 Hz) |
| Output frequency resolution | .01 Hz |
| Overload capacity | 150% of rated load for 1 min |
| Remote frequency reference sources | 0–10VDC (20kΩ); 4–20mA (250Ω); ±10VDC serial (RS-485) |
| Accel/decel times | 0.1 to 6000.0 sec—4 sets; 8 parameters are independently adjustable |
| Braking torque | 150% or more with dynamic braking |
| Motor overload protection | UL recognized electronic thermal overload relay; field-programmable |
| Overcurrent protection level (OC1) | 200% of rated current |
| Circuit protection | Ground fault and blown-fuse protection |
| Overvoltage protection level | 410/820VDC |
| Undervoltage protection level | 190/380VDC |

| Specification | Specification Value and Information for All Models |
|-------------------------------|---|
| Heatsink overtemperature | Thermostat trips at 105°C |
| Torque limit selection | Separate functions for FORWARD, REVERSE, REGEN.; all selectable from 0–300% |
| Stall prevention | Separate functions for accel, decel, at-speed, and constant horsepower region |
| Other protection features | Speed deviation, overspeed, mechanical brake failure, lost output phase, failed-oscillator, PG-disconnect, mechanical overload, roll-back detection, and internal braking transistor failure. |
| DC bus voltage indication | Charge LED is on until DC bus voltage drops below 50VDC |
| Location | Indoors; requires protection from moisture, corrosive gases, and liquids |
| Ambient operating temperature | 14° to 140°F (-10° to 60°C)* 14° to 149°F (-10° to 65°C)** |
| Storage temperature | -4° to 158°F (-20° to 70°C) |
| Humidity | 95% relative; noncondensing |
| Vibration | 1 G less than 20 Hz; 0.2 G for 20–50 Hz |
| Elevation | 3300 Ft. (1000M) or less |

* 2kHz carrier frequency
** Maximum rated temperature of 65°C at the drive chassis with factory approved air handling system

AC Reactor Specifications

Reactors, both as input (line) and output (load) devices, protect adjustable frequency drives, motors, and other load devices against excessive voltage and current.

The following guidelines may help determine input and output reactor requirements:

- The following table is only a guideline. The motor FLA should not exceed the reactor FLA.
- Install an input reactor if the power source is greater than 500kVA.
- Install an output reactor if the distance between the drive and the motor exceeds 150 feet.
- Install an output reactor if a device, such as a power limit switch, is used to disconnect the motor from the drive.
- Install one output reactor per drive for a multiple-drive arrangement requiring reactor protection.
- For a multiple drive arrangement, an input reactor for each drive is recommended for optimal protection. However, if the drives are within two drive sizes of each other, a single input reactor can be used. The reactor must be rated at amperage equal to or greater than the sum of the amperage for all the drives.

230V Class

| Model Number | 230V Part Number | Maximum Amps of Reactor |
|---------------------|-------------------------|--------------------------------|
| 2007-FVG+S3 | REA230-2 | 8 |
| 2009-FVG+S3 | REA230-3 | 12 |
| 2015-FVG+S3 | REA230-5 | 18 |
| 2023-FVG+S3 | REA230-7.5 | 25 |
| 2031-FVG-S3 | REA230-10 | 35 |
| 2045-FVG+S3 | REA230-15 | 45 |
| 2058-FVG+S3 | REA230-20 | 55 |
| 2071-FVG+S3 | REA230-25 | 80 |
| 2085-FVG+S3 | REA230-30 | 80 |
| 2145-FVG+S3 | REA230-50 | 130 |

| Model Number | 230V Part Number | Maximum Amps of Reactor |
|---------------------|-------------------------|--------------------------------|
| 2215-FVG+S3 | REA230-75 | 200 |
| 2283-FVG+S3 | REA230-100 | 250 |
| 2346-FVG+S3 | REA230-125 | 320 |

460V Class

| Model Number | 460 V Part Number | Maximum Amps of Reactor |
|---------------------|--------------------------|--------------------------------|
| 4002-FVG+S3 | REA460-1 | 2 |
| 4003-FVG+S3 | REA460-2 | 4 |
| 4005-FVG+S3 | REA460-5 | 8 |
| 4008-FVG+S3 | REA460-5 | 8 |
| 4012-FVG+S3 | REA460-7.5 | 12 |
| 4017-FVG+S3 | REA460-10 | 18 |
| 4024-FVG+S3 | REA460-15 | 25 |
| 4031-FVG+S3 | REA460-20 | 35 |
| 4039-FVG+S3 | REA460-25 | 35 |
| 4045-FVG+S3 | REA460-30 | 45 |
| 4060-FVG+S3 | REA460-40 | 55 |
| 4075-FVG+S3 | REA460-50 | 80 |
| 4091-FVG+S3 | REA460-60 | 80 |
| 4112-FVG+S3 | REA460-75 | 100 |
| 4150-FVG+S3 | REA460-100 | 130 |
| 4180-FVG+S3 | REA460-150 | 200 |
| 4260-FVG+S3 | REA460-200 | 250 |
| 4304-FVG+S3 | REA460-250 | 320 |
| 4370-FVG+S3 | REA460-300 | 400 |
| 4477-FVG+S3 | REA460-400 | 500 |
| 4590-FVG+S3 | REA460-500 | 600 |

Interface Specifications

IMPULSE•VG+ Series 3 is designed to interface with 120VAC user input and output devices through the GIF7 interface board. This eliminates the need for an additional interface relay or isolation circuitry.

The GIF7 has eight optically isolated input terminals which can be used to connect with the user input device. Terminals S1 and S2 are always used for the directional run commands (Forward and Reverse, Up and Down). The rest of six terminals are multi-function terminals, and are used for speed control and other characteristics. With multi-function terminals you can assign various functions and performance characteristics without having to rewire the drive.

A maximum of 3 inputs shall be capable of continuously remaining in the on state, as is the case with normally closed fail-safe limit switches and overload type devices. It is recommended wherever possible that these inputs be spaced out in such a way that two or more N.C. inputs are not right next to each other. For four position geared limit switches, a G5IN4 option card is recommended.

G5IN4 card has four additional input terminals, which can have a total of 14 sets of input selections. The individual terminals can be enabled/disabled within a set. For program information refer to Chapter 5, Programming Advanced Features.

The drive has four 250VAC, 1.0 Amp relays for output devices. It includes three programmable multi-function output terminals.

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chapter 2

Installation

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WARNING

- When preparing to mount the IMPULSE•VG+ Series 3 drive, lift it by its base. Never lift it by the front cover.
- Mount the drive on nonflammable material.
- The IMPULSE•VG+ Series 3 drive generates heat. For the most effective cooling possible, mount it vertically. For more details, refer to the “IMPULSE•VG+ Series 3 Dimensions/Heat Loss—Open Chassis” in this chapter.
- When mounting units in an enclosure, install a fan or other cooling device to keep the enclosure temperature below 140°F (60°C)*.

Failure to observe these Warnings may result in equipment damage.

This chapter explains the following:

1. Choosing a location
2. IMPULSE•VG+ Series 3 components and external devices
3. Drive environment
4. Drive installation

In addition, this section will cover information on the components that interconnect with IMPULSE•VG+ Series 3.

Choosing a Location

Be sure that the drive is mounted in a location protected against the following conditions:

- Extreme cold and heat. Use only within the ambient temperature range:
+14° to 140°F (-10 to 60°C)*
- Direct sunlight (not for use outdoors)
- Rain, moisture
- High humidity
- Oil sprays, splashes
- Salt spray
- Dust or metallic particles in the air
- Corrosive gases (e.g. sulfurized gas or liquids)
- Radioactive substances
- Combustibles (e.g. thinner, solvents, etc.)
- Physical shock, vibration
- Magnetic noise (e.g. welding machines, power devices, etc.)

* 2 kHz carrier frequency

IMPULSE•VG+ Series 3 System Components And External Devices

Standard IMPULSE•VG+ Series 3 Drive Components

- PG-T2 Encoder Card

Optional Drive Components

- G5IN4 Control Input Card
- DO-08 Control Output Board
- DO-02 Control Output Relay Board
- AI-14B Analog Input Card

As-Required Drive Components

- AC reactor—line or load
- DC bus reactor
- External dynamic braking resistor(s)
- External dynamic braking unit

Required External Devices

- Motor
- User input device (pendant, joystick, PC, PLC, radio, or infrared control)
- External circuit protection devices (fuses or circuit breakers) (See “Suggested Circuit Protection Specifications and Wire Size” in Chapter 3.)
- R-C surge suppressors on contactor coils

Long Time Storage

Powering up the drives every six months is quite beneficial. Over longer periods of time without power, the drives' electrolytic DC bus capacitors require reformation, especially if stored in an area of high temperatures. Capacitor reforming is required if drives are stored without power for more than 2 to 3 years. This process can be avoided by powering up the drive bi-annually for 30 to 60 minutes.

NOTE: Bus cap reforming alone may not restore full drive functionality after 2 to 3 years of storage without power.

Inverter drives contain large bus capacitors that have the potential to be reformed. However, printed circuit boards also contain electrolytic capacitors that may not function after several years without power. Magnetek recommends replacing the PCBs should the drive's functionality not be restored after bus cap reforming.

Capacitor Storage and their Reforming Process

The electrical characteristics of aluminum electrolytic capacitors are dependent on temperature; the higher the ambient temperature, the faster the deterioration of the electrical characteristics (i.e., leakage current increase, capacitance drop, etc.). If an aluminum electrolytic capacitor is exposed to high temperatures such as direct sunlight, heating elements, etc., the life of the capacitor may be adversely affected. When capacitors are stored under humid conditions for long periods of time, the humidity will cause the lead wires and terminals to oxidize, which impairs their solderability. Therefore, aluminum electrolytic capacitors should be stored at room temperature, in a dry location and out of direct sunlight.

In the event that a capacitor has been stored in a high ambient environment for more than 2 or 3 years, a voltage treatment reformation process to electrolytic capacitors may have to be performed. When stored above room temperatures for long periods of time, the anode foil may react with the electrolyte, increasing the leakage current. After storage, the application of even normal voltages to these capacitors may result in higher than normal leakage currents. In most cases the leakage current levels will decrease in a short period of time as the normal chemical reaction within the capacitor occurs. However, in extreme cases, the amount of gas generated may cause the safety vent to open.

Capacitors, when used in inverter drives that are stored for long periods of time, should be subjected to a voltage treatment/reforming process as noted below, which will reform the dielectric and return the leakage current to the initial level.

Inverter Bus Capacitor Reforming Procedure:

1. Remove the fuse from the 8PCB tap change card for this procedure (models 4150-FVG+S3 to 4590-FVG+S3 only).
2. Connect the inverter inputs L1, L2, and L3 to a variac.
3. Make sure the variac voltage setting is turned down so that when input power is applied to the variac, the output of the variac will be at or near 0 volts.
4. Apply power to the variac, listening for abnormal sounds and watching for abnormal visual indications in the drive. If the variac has an output current indication, make sure the current is very near zero with zero or a steady output voltage applied.
5. Slowly turn the variac up, increasing the variac's output voltage to nominal rated input voltage over a time period of 2 to 3 minutes. In other words, ramp the voltage up at a rate of approximately 75 to 100 volts/minute for 230VAC units and 150 to 200 volts/minute for 460VAC units.

6. Let the output voltage remain at rated voltage for 30 to 60 minutes while keeping close watch for abnormal signs within the inverter. While increasing the variac's output voltage, the current will momentarily increase as current is necessary to charge the capacitors.
7. Once 30 to 60 minutes elapse, remove power and package the drive for shipment.

If any abnormal indications occur during this process, it is recommended that the process be repeated. Otherwise, this completes the capacitor reforming procedure.

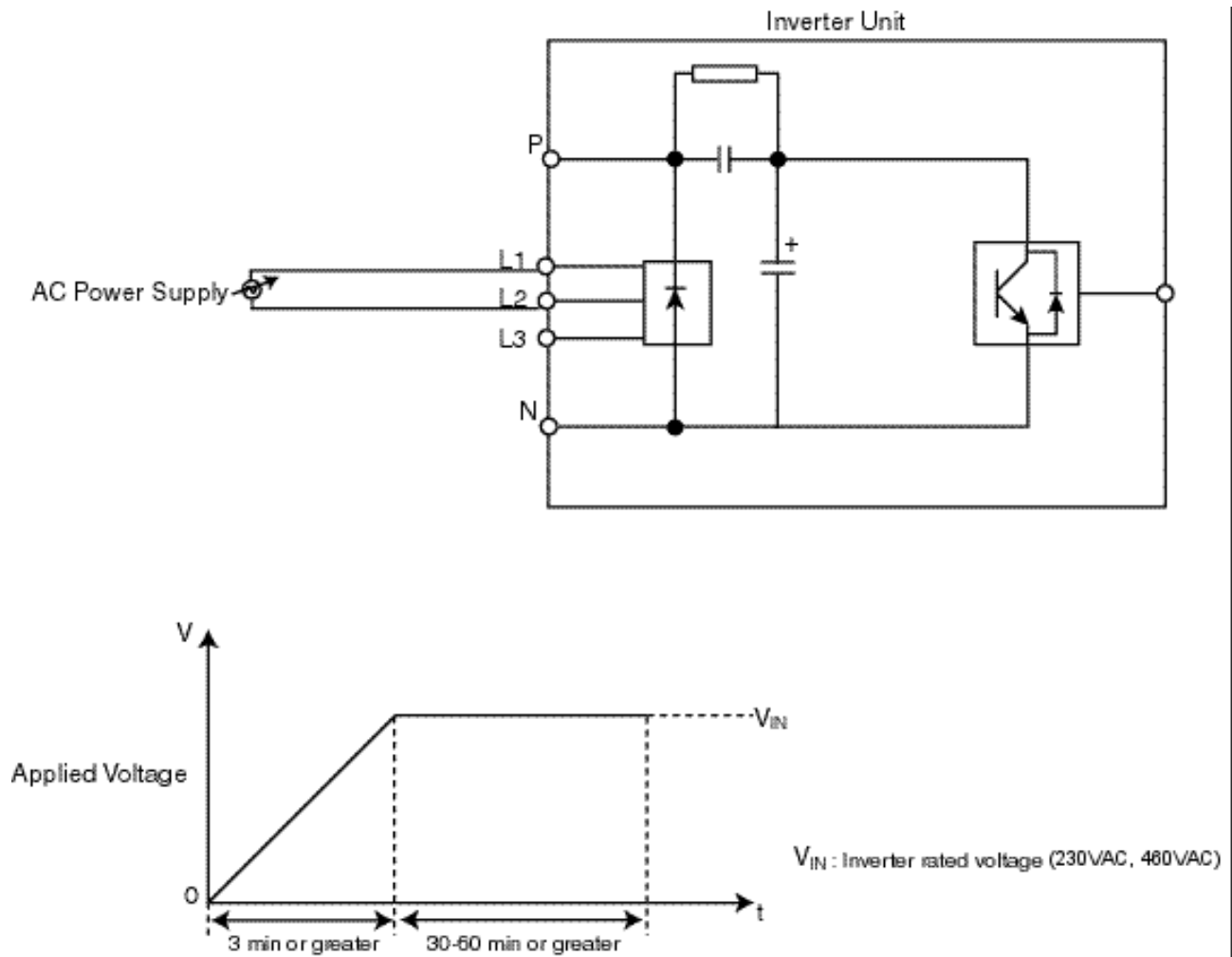


Figure 2-1: Long Time Storage

Installing the Drive

To install IMPULSE•VG+ Series 3:

1. Ensure the drive will be used in a proper environment. Refer to page 1-5.
2. Review “IMPULSE•VG+ Series 3 Terminal Diagram”.
3. Determine the sizes and connection locations for the drive components and external devices that need to be wired. Locate the ground.
4. Determine the position of the subpanel.
5. Ensure that the drive is positioned vertically so that the heat can dissipate properly.
6. Ensure that the air can flow freely around the heat sink as shown below in Figure 2-2.

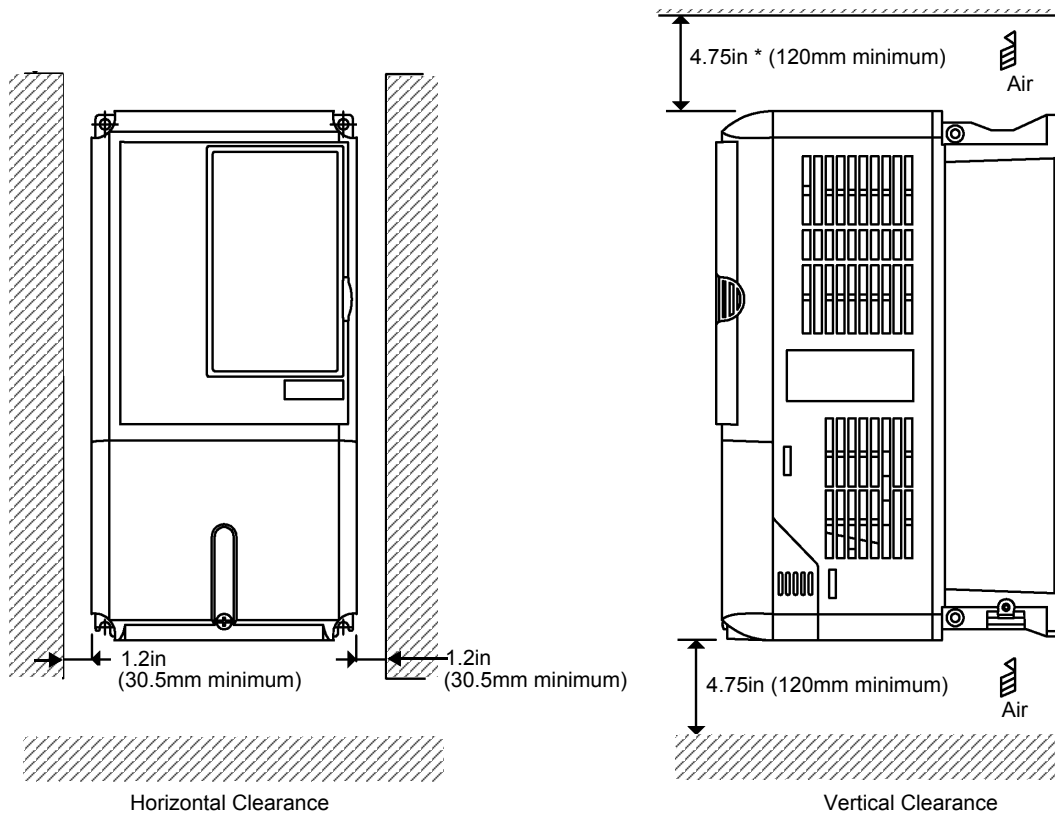


Figure 2-2

NOTE:

- The recommended clearances at the top, bottom, and both sides of the inverter are the same for both open chassis and NEMA 1 enclosures.
- Allowable intake air temperature: 14° to 140°F (-10° to +60°C) (2 kHz carrier frequency)
- If necessary, a heater or air conditioner must be used to maintain the temperature range listed above.
- For drive model 4590-FVG+S3, the top clearance is 11.8 inches.

7. Lay out the wire runs. Size the wire according to NEC Table 610-14(a). At a minimum, use #16 AWG for control wiring and #12 AWG for power wiring. When performing this step:
 - Ensure that the drive control circuit and power circuit wires are perpendicular to each other at any point they cross.
 - Keep power and control festoon wiring in separate cables.
 - Separate control drive circuit and power circuit wiring on the terminal block strip.
8. Obtain the appropriate hardware for mounting.
9. Mount the subpanel or surface to which you are mounting the drive. (Contact Magnetek if you need advice on mounting, especially for larger drives.)
10. Fasten the drive and components to the subpanel.
11. Remove the terminal cover.
12. Follow the wiring practices outlined in Chapter 3.

IMPULSE•VG+ Series 3 Dimensions/Heat Loss—Open Chassis

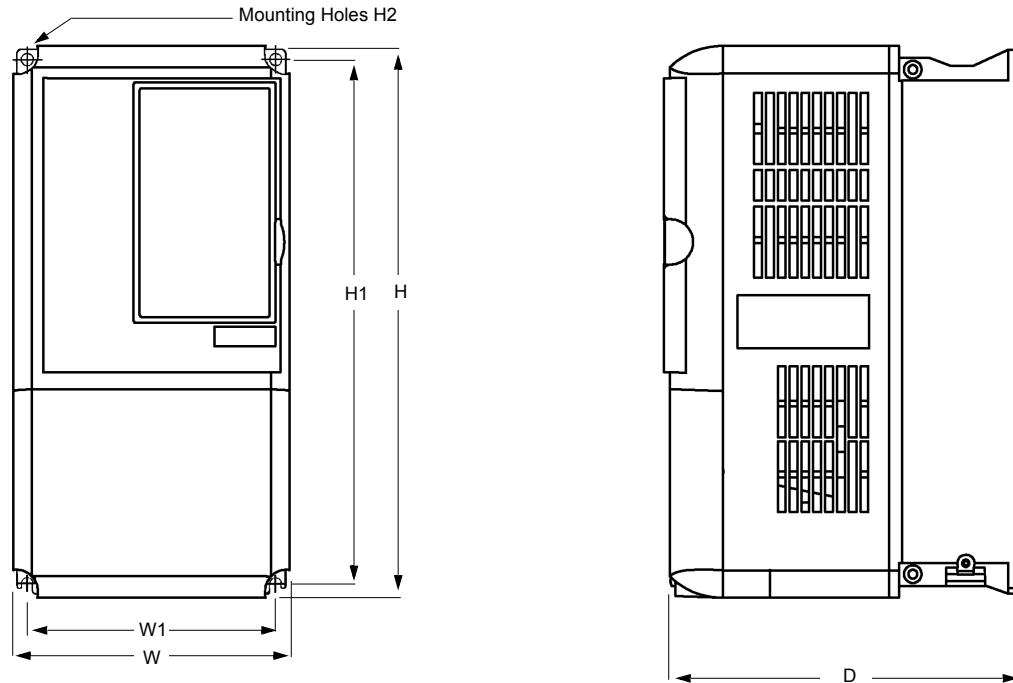


Figure 2-3: Open Chassis

NOTE: Some models are shipped with metal enclosures that can be removed and discarded.

230V Class

| Model | Overall Dimensions in inches and (mm) | | | Mounting Dimensions in inches and (mm) | | | Wt Lbs | Heat Loss (W) |
|-------------|--|----------------|----------------|---|----------------|----------------|--------|------------------|
| | W | H | D | W1 | H1 | H2 | | Total |
| 2007-FVG+S3 | 5.51 (140) | 11.02 (280) | 6.30 (160) | 4.95 (126) | 10.47 (266) | 0.28 (7) | 6.6 | 98 |
| 2009-FVG+S3 | 5.51 (140) | 11.02 (280) | 6.30 (160) | 4.95 (126) | 10.47 (266) | 0.28 (7) | 6.6 | 127 |
| 2015-FVG+S3 | 5.51 (140) | 11.02 (280) | 7.09 (180) | 4.95 (126) | 10.47 (266) | 0.28 (7) | 8.8 | 134 |
| 2023-FVG+S3 | 5.51 (140) | 11.02 (280) | 7.09 (180) | 4.95 (126) | 10.47 (266) | 0.28 (7) | 8.8 | 184 |
| 2031-FVG+S3 | 7.87 (200) | 11.81 (300) | 7.87 (200) | 7.32 (186) | 11.22 (285) | 0.28 (7) | 13.2 | 332 |
| 2045-FVG+S3 | 7.87 (200) | 12.20 (310) | 7.87 (200) | 7.32 (186) | 11.22 (285) | 0.28 (7) | 15.4 | 525 |
| 2058-FVG+S3 | 9.45 (240) | 13.78 (350) | 8.27 (210) | 8.50 (216) | 13.19 (335) | 0.30 (7.62) | 24.2 | 598 |
| 2071-FVG+S3 | 9.45 (240) | 14.96 (380) | 8.27 (210) | 8.50 (216) | 13.19 (335) | 0.30 (7.62) | 24.2 | 680 |
| 2085-FVG+S3 | 10.0 (254) | 21.06 (535) | 10.24 (260) | 7.68 (195) | 15.16 (385) | 0.30 (7.62) | 53 | 835 |
| 2145-FVG+S3 | 14.76 (375) | 23.62 (600) | 11.81 (300) | 9.84 (250) | 22.64 (575) | 0.49 (12.5) | 125 | 1431 |
| 2215-FVG+S3 | 17.72 (450) | 28.54 (725) | 13.78 (350) | 12.80 (325) | 27.56 (700) | 0.49 (12.5) | 189 | 2207 |

| Model | Overall Dimensions in inches and (mm) | | | Mounting Dimensions in inches and (mm) | | | Wt Lbs | Heat Loss (W) |
|-------------|--|----------------|----------------|---|----------------|----------------|--------|------------------|
| | W | H | D | W1 | H1 | H2 | | Total |
| 2283-FVG+S3 | 17.72 (450) | 28.54 (725) | 13.78 (350) | 12.80 (325) | 27.56 (700) | 0.49 (12.5) | 191 | 2800 |
| 2346-FVG+S3 | 19.69 (500) | 33.46 (850) | 14.17 (360) | 14.57 (370) | 32.28 (820) | 0.59 (15) | 238 | 3158 |

460V Class

| Model | Overall Dimensions in inches and (mm) | | | Mounting Dimensions in inches and (mm) | | | Wt Lbs | Heat Loss (W) |
|-------------|--|-----------------|----------------|---|-----------------|----------------|--------|------------------|
| | W | H | D | W1 | H1 | H2 | | Total |
| 4002-FVG+S3 | 5.51 (140) | 11.02 (280) | 6.30 (160) | 4.95 (126) | 10.47 (266) | 0.28 (7) | 6.6 | 58 |
| 4003-FVG+S3 | 5.51 (140) | 11.02 (280) | 6.30 (160) | 4.95 (126) | 10.47 (266) | 0.28 (7) | 6.6 | 84 |
| 4005-FVG+S3 | 5.51 (140) | 11.02 (280) | 7.09 (180) | 4.95 (126) | 10.47 (266) | 0.28 (7) | 8.8 | 115 |
| 4008-FVG+S3 | 5.51 (140) | 11.02 (280) | 7.09 (180) | 4.95 (126) | 10.47 (266) | 0.28 (7) | 8.8 | 148 |
| 4012-FVG+S3 | 5.51 (140) | 11.02 (280) | 7.09 (180) | 4.95 (126) | 10.47 (266) | 0.28 (7) | 8.8 | 208 |
| 4017-FVG+S3 | 7.87 (200) | 11.81 (300) | 7.87 (200) | 7.32 (186) | 11.22 (285) | .28 (7) | 13.2 | 307 |
| 4024-FVG+S3 | 7.87 (200) | 11.81 (300) | 7.87 (200) | 7.32 (186) | 11.22 (285) | .28 (7) | 13.2 | 390 |
| 4031-FVG+S3 | 9.45 (240) | 13.78 (350) | 8.27 (210) | 8.5 (215) | 13.19 (335) | 0.30 (7.5) | 22 | 465 |
| 4039-FVG+S3 | 9.45 (240) | 13.78 (350) | 8.27 (210) | 8.5 (215) | 13.19 (335) | 0.30 (7.5) | 22 | 590 |
| 4045-FVG+S3 | 10.98 (275) | 17.72 (450) | 10.24 (260) | 8.66 (220) | 17.13 (435) | 0.30 (7.5) | 53 | 653 |
| 4060-FVG+S3 | 10.98 (275) | 17.72 (450) | 10.24 (260) | 8.66 (220) | 17.13 (435) | 0.30 (7.5) | 53 | 988 |
| 4075-FVG+S3 | 12.80 (325) | 21.65 (550) | 11.22 (285) | 10.24 (260) | 21.06 (535) | 0.30 (7.5) | 88 | 1133 |
| 4091-FVG+S3 | 12.80 (325) | 21.65 (550) | 11.22 (285) | 10.24 (260) | 21.06 (535) | 0.30 (7.5) | 88 | 1287 |
| 4112-FVG+S3 | 12.80 (325) | 21.65 (550) | 11.22 (285) | 10.24 (260) | 21.06 (535) | 0.30 (7.5) | 88 | 1682 |
| 4150-FVG+S3 | 17.72 (450) | 28.54 (725) | 13.78 (350) | 12.80 (325) | 27.56 (700) | 0.49 (12.5) | 194 | 1847 |
| 4180-FVG+S3 | 17.72 (450) | 28.54 (725) | 13.78 (350) | 12.80 (325) | 27.56 (700) | 0.49 (12.5) | 196 | 2287 |
| 4260-FVG+S3 | 19.69 (500) | 33.46 (850) | 14.17 (360) | 14.57 (370) | 32.28 (820) | 0.59 (15) | 265 | 3393 |
| 4304-FVG+S3 | 22.64 (575) | 36.06 (916) | 14.88 (373) | 17.52 (445) | 33.66 (855) | 0.59 (15) | 352 | 3935 |
| 4370-FVG+S3 | 27.95 (710) | 51.38 (1305) | 16.26 (413) | 10.63 (270) | 50.00 (1270) | 0.79 (20) | 572 | 3964 |
| 4477-FVG+S3 | 27.95 (710) | 51.38 (1305) | 16.26 (413) | 10.63 (270) | 50.00 (1270) | 0.79 (20) | 616 | 5509 |
| 4590-FVG+S3 | 36.06 (916) | 58.07 (1475) | 16.26 (413) | 14.37 (365) | 56.70 (1440) | 0.79 (20) | 891 | 8320 |

chapter 3

Wiring

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IMPULSE•VG+ Series 3 Wiring Practices



WARNING

Before you wire the drive, review the following practices to help ensure that your system is wired properly.

- Connect the incoming three-phase AC source to terminals R/L1, S/L2, T/L3.
- Connect the Motor leads to terminals U/T1, V/T2, W/T3.
- Ensure that the drive-to-motor wiring distance is less than 150 ft unless appropriate reactors, filters, and/or inverter duty motor is used.
- If a device that can interrupt power is installed between the drive and the motor, install a reactor on the output side of the drive.
- On external user input devices, use hard contact inputs rather than solid-state inputs.
- If the power source is 500 kVA or greater, or more than 10 times the inverter kVA rating, ensure that there is at least 3 percent impedance between the power source and the drive input. To accomplish this, you can install a DC reactor between inverter terminals 1 and 2, or use an AC line reactor on the input of the drive. If you don't provide enough impedance, excessive peak currents could damage the input power supply circuit.
- If the user input device is a PLC TRIAC output, use a 5K Ω , 5W resistor between the signal and L2 (X2).
- Comply with "Suggested Circuit Protection Specifications" on page 3-6.
- Use time delay fuses, which are sized at 150% of drive's continuous-rated current, for drive input protection.
- Use appropriate R-C or MOV type surge absorbers across the coil of all contactors and relays in the system. Failure to do so could result in noise-related, nuisance fault incidents.
- Use external dynamic braking resistors for all applications.
- Do not ground the drive with any large-current machines.
- Before you use any welding or high-current machines near the crane, disconnect all line and ground wiring.
- Do not use output contactors between the drive and the motor.
- Do not let the wiring leads come in contact with the drive enclosure.
- Do not connect power factor correction capacitors to the drive input or output.
- Hard-wire the drive and motor (e.g., festoon cable). Do not use sliding collector bars.
- If you have a user input device or interface board that is remote, use shielded cable between the drive input terminals and the interface output terminals or user input device(s).
- Before turning on the drive, check the output circuit (T1, T2 and T3) for possible short circuits and ground faults.
- Increase the wire size by one gauge for every 250 feet (76.2 meters) between the drive and motor; suggested for center driven cranes, trolleys, and bridges. (Voltage drop is significant at low frequencies.)

- When using more than one transformer for the drive's power, properly phase each transformer.
- To reverse the direction of rotation, program B3-04 = 1 (exchange phases), or interchange any two motor leads (changing R/L1, S/L2 or T/L3 will not affect the shaft rotation direction) as well as encoder phasing (F5-01 = 0/1 or swapping A and \bar{A} wires).
- Use shielded cable for all low-level DC speed reference signals (0 to 10VDC, 4 to 20 mA). Ground the shield only at the drive side.
- Please observe National Electrical Code (NEC) guidelines when wiring electrical devices.

NOTE: Failure to observe these warnings may result in equipment damage.

IMPULSE•VG+ Series 3 Typical Connection Diagram

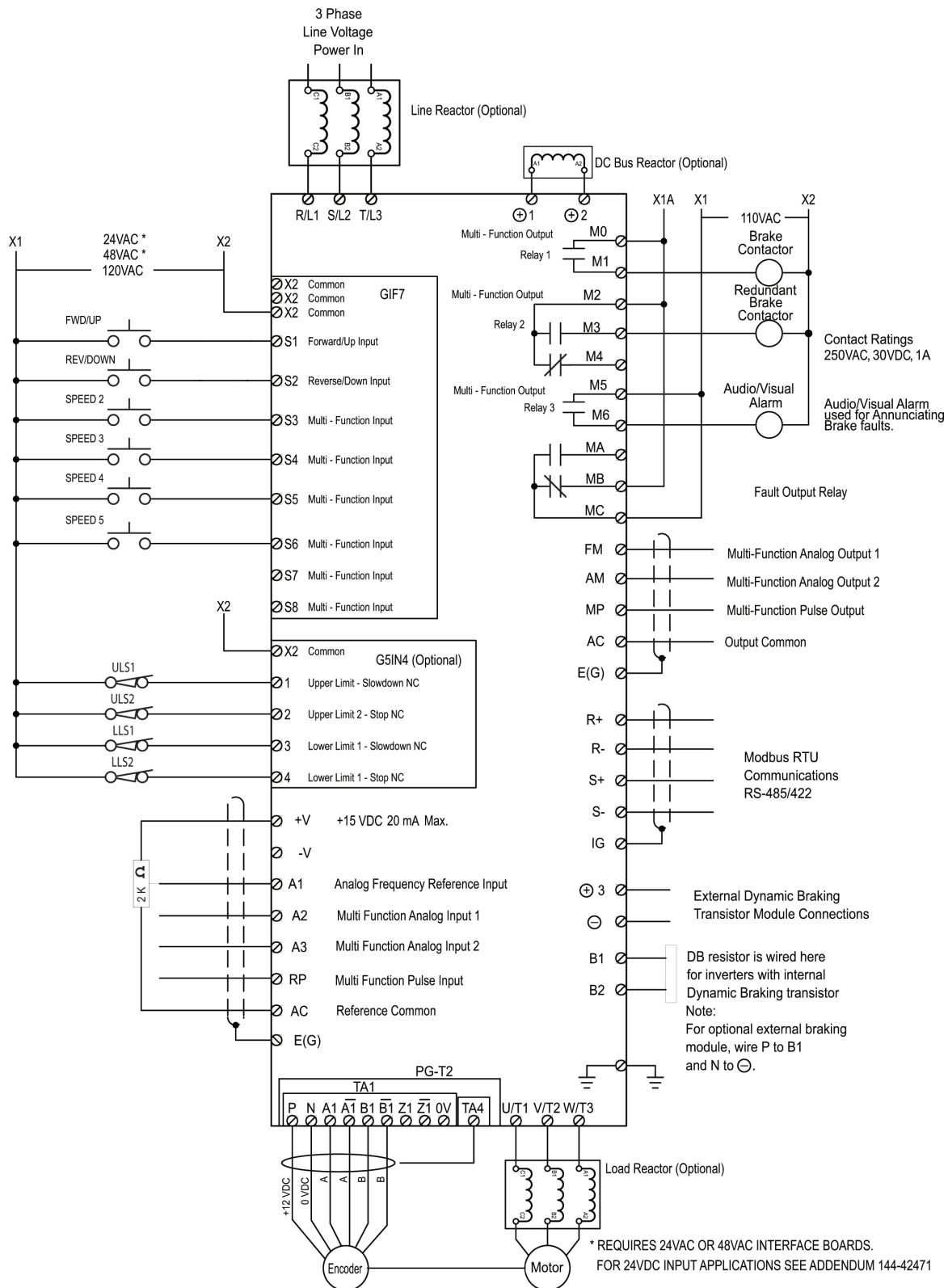


Figure 3-1: IMPULSE•VG+ Series 3 Terminal Diagram

Suggested Circuit Protection Specifications and Wire Size

In order to comply with most safety standards, some circuit protective devices should be used between the incoming three-phase power supply and the IMPULSE•VG+ Series 3. These devices can be thermal, magnetic, or molded-case breakers (MCCB); or “slow-blow” type fuses such as “CCMR” or “J.”



CAUTION:

The following guidelines are only suggested values. Always conform to local electrical codes and wiring practices.

| Model # | Continuous HD Input Amps | Time Delay Input Fuse (A) | Time Delay Input Fuse Class | Inverse Time Molded/Case Circuit Breaker ³ | Recommended Gauge ^{1, 4} | | |
|-------------------|--------------------------------|---------------------------------|-----------------------------------|---|-----------------------------------|-------------------|-------------------------------|
| | | | | | Power Circuit Wiring | Control Wiring | Ground Copper ² |
| 230V Class | | | | | | | |
| 2007-FVG+-S3 | 8.4 | 12 | CC | 15 | 12 | 16/14 | 12 |
| 2009-FVG+-S3 | 11.5 | 15 | CC | 20 | 12 | 16/14 | 12 |
| 2015-FVG+-S3 | 18 | 25 | CC | 30 | 12 | 16/14 | 10 |
| 2023 -FVG+S3 | 24 | 30 | J | 45 | 12 | 16/14 | 10 |
| 2031-FVG+S3 | 37 | 45 | J | 60 | 8 | 16/14 | 10 |
| 2045-FVG+S3 | 52 | 60 | J | 70 | 6 | 16/14 | 10 |
| 2058-FVG+S3 | 68 | 80 | J | 110 | 4 | 16/14 | 8 |
| 2071-FVG+S3 | 84 | 100 | J | 125 | 2 | 16/14 | 8 |
| 2085-FVG+S3 | 94 | 125 | J | 150 | 2 | 16/14 | 6 |
| 2145-FVG+S3 | 160 | 200 | J | 250 | 2/0 | 16/14 | 6 |
| 2215-FVG+S3 | 237 | 300 | J | 350 | 250 2-2/0 | 16/14 | 4 |
| 2283-FVG+S3 | 317 | 400 | J | 450 | 350 2-3/0 | 16/14 | 2 |
| 2346-FVG+S3 | 381 | 500 | J | 600 | 400 2-250 | 16/14 | 2 |
| 460V Class | | | | | | | |
| 4002-FVG+S3 | 2.5 | 3.5 | CC | 15 | 12 | 16/14 | 12 |
| 4003-FVG+S3 | 4.4 | 6 | CC | 15 | 12 | 16/14 | 12 |
| 4005-FVG+S3 | 6.4 | 9 | CC | 15 | 12 | 16/14 | 12 |
| 4008-FVG+S3 | 10.4 | 15 | CC | 20 | 12 | 16/14 | 12 |
| 4012-FVG+S3 | 15 | 20 | CC | 25 | 12 | 16/14 | 12 |
| 4017-FVG+S3 | 20 | 25 | J | 35 | 12 | 16/14 | 10 |
| 4024-FVG+S3 | 29 | 35 | J | 45 | 10 | 16/14 | 10 |
| 4031-FVG+S3 | 37 | 45 | J | 60 | 8 | 16/14 | 10 |

1) NFPA 70 National Electric Code 2008. 430.122(a) and Table 610-14(a) 40°C, 60-minute, copper 50°C ambient

2) NFPA 70 National Electric Code 2008. Table 250.122.

3) NFPA 70 National Electric Code 2008. Table 430.52.

4) NFPA 40 National Electric Code 2008. Table 315(b)(2)(a).

Recommended Gauge^{1, 4}

| Model # | Continuous HD Input Amps | Time Delay Input Fuse (A) | Time Delay Input Fuse Class | Inverse Time Molded/Case Circuit Breaker³ | Power Circuit Wiring | Control Wiring | Ground Copper² |
|----------------|---|--|--|---|-----------------------------|---------------------------|--------------------------------------|
| 4039-FVG+S3 | 47 | 50 | J | 70 | 6 | 16/14 | 10 |
| 4045-FVG+S3 | 50 | 60 | J | 80 | 6 | 16/14 | 10 |
| 4060-FVG+S3 | 66 | 80 | J | 100 | 4 | 16/14 | 8 |
| 4075-FVG+S3 | 83 | 100 | J | 125 | 2 | 16/14 | 8 |
| 4091-FVG+S3 | 100 | 125 | J | 175 | 1 | 16/14 | 6 |
| 4112-FVG+S3 | 120 | 150 | J | 225 | 1/0 | 16/14 | 6 |
| 4150-FVG+S3 | 198 | 200 | J | 300 | 3/0 | 16/14 | 6 |
| 4180-FVG+S3 | 2383 | 250 | J | 350 | 250 2-2/0 | 16/14 | 4 |
| 4260-FVG+S3 | 286 | 350 | J | 500 | 350 2-3/0 | 16/14 | 2 |
| 4304-FVG+S3 | 334 | 400 | J | 600 | 350 2-4/0 | 16/14 | 2 |
| 4370-FVG+S3 | 407 | 500 | J | 700 | 500 2-250 | 16/14 | 2 |
| 4477-FVG+S3 | 457 | 700 | J | 900 | 500 2-300 4-3/0 | 16/14 | 1/0 |
| 4590-FVG+S3 | 649 | 800 | J | 1000 | 4-250 | 16/14 | 1/0 |

1) NFPA 70 National Electric Code 2008. 430.122(a) and Table 610-14(a) 40°C, 60-minute, copper 50°C ambient

2) NFPA 70 National Electric Code 2008. Table 250.122.

3) NFPA 70 National Electric Code 2008. Table 430.52.

4) NFPA 40 National Electric Code 2008. Table 315(b)(2)(a).

Power Circuit Wiring Procedures

To wire the power circuit for IMPULSE•VG+ Series 3:

1. Run the three-phase power supply wires through an appropriate enclosure hole.
2. Referring to “Suggested Circuit Protection Specifications—IMPULSE•VG+ Series 3” and the following two tables, connect the three-phase power supply wires to a circuit protection system.
3. Connect the three-phase power supply wires from the circuit protection Terminals L1, L2 and L3.
4. From Terminals T1, T2 and T3, connect the power output wires to the motor. If a load reactor is used, connect these output wires to the reactor input instead; then connect the reactor output to the motor.

NOTE: If a device that can interrupt power is installed between the drive and the motor, install a reactor on the output side of the drive.

5. For Models 4150-FVG+S3 and greater, ensure the jumper plug is inserted in the printed-circuit board (8PCB), which is underneath the control board, as follows:

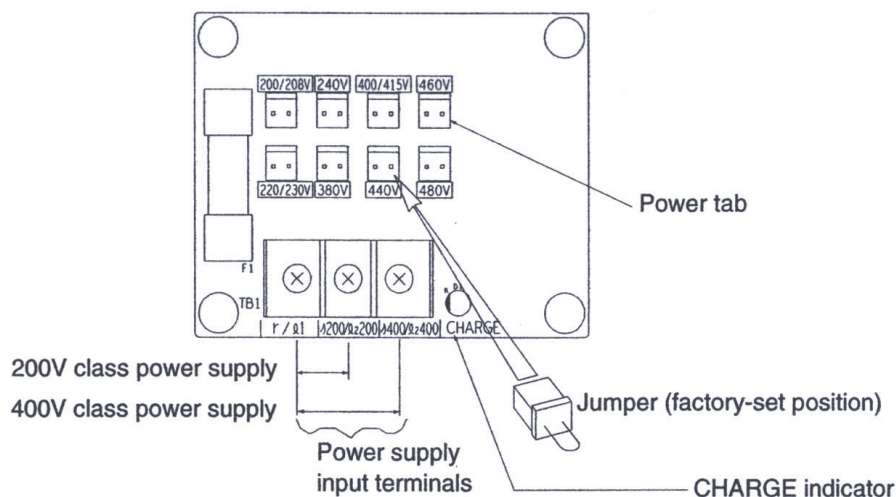




Figure 3-2: Models 4150-FVG+S3 to 4590-FVG+S3

230 V Class Terminal Functions

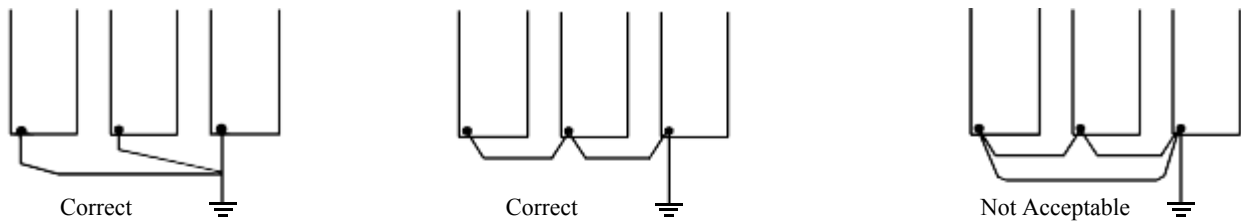
| | <i>Model</i> | 2007-FVG+ to 2071-FVG+ | 2085-FVG+ | 2145-FVG+ | 2180-FVG+ to 2346-FVG+ |
|---|--|--|---|--------------------------|------------------------|
| | <i>Rated Current</i> | 7 to 71 Amps | 85 Amps | 145 Amps | 180 to 346 Amps |
| T e r m i n a l | R/L1 | Main circuit input power supply | | | |
| | S/L2 | | | | |
| | T/L3 | | | | |
| | U/T1 | Inverter output | | | |
| | V/T2 | | | | |
| | W/T3 | | | | |
| | B1 | Braking resistor | n/a | | |
| | B2 | | | | |
| | ⊖ | DC reactor (⊕1-⊕2) DC Power supply (⊕1-⊖) | DC power supply (⊕1-⊖) Braking unit (⊕3-⊖) ⊕2 terminal not provided | | |
| | ⊕1 | | | | |
| | ⊕2 | | | | |
| | ⊕3 | | | | |
| | r (l 1) | n/a | | Cooling fan power supply | |
| | s (l 2) | | | | |
|  | Ground terminal (Ground resistance: 100 Ω or less) | | | | |

460 V Class Terminal Functions

| | <i>Model</i> | 4002-FVG+ to 4039-FVG+ | 4045-FVG+ to 4112-FVG+ | 4150-FVG+ to 4304-FVG+ | 4477-FVG+ to 4590-FVG+ |
|---|---|--|---|------------------------|--|
| | <i>Rated Current</i> | 2.1 to 39 Amps | 45 to 112 Amps | 150 to 304 Amps | 477 to 590 Amps |
| T e r m i n a l | R/L1 | Main circuit input power supply | | | |
| | S/L2 | | | | |
| | T/L3 | | | | |
| | U/T1 | Inverter output | | | |
| | V/T2 | | | | |
| | W/T3 | | | | |
| | B1 | Braking resistor | n/a | | |
| | B2 | | | | |
| | ⊖ | DC reactor (⊕1-⊕2) DC power supply (⊕1-⊖) | DC power supply (⊕1-⊖) Braking unit (⊕3-⊖) | | |
| | ⊕1 | | | | |
| | ⊕2 | | | | |
| | ⊕3 | | | | |
| | s (l 1) | n/a | | n/a | n/a |
| | r (l 2) | | | n/a | Cooling fan power supply (Control power supply) r-s200: 200 to 230VAC input r-s400: 380 to 460VAC input |
| s200 | | | | | |
| s400 | | | | | |
|  | Ground terminal (Ground resistance: 10 Ω or less) | | | | |

Grounding

6. Connect terminal G to the common panel ground. Use ground wiring as specified in “Suggested Circuit Protection and Wire Size” on page 3-6, and keep the length as short as possible.
 - Ground Resistance: 230V class; 100Ω or less, 460V or greater class; 10Ω or less.
 - Never run the IMPULSE•VG+ Series 3 drive ground wires in common with welding machines, or other high-current electrical equipment.
 - When more than one drive is used for the same system, ground each directly or daisy-chain to the ground pole. Do not loop the ground wires.



Grounding of three IMPULSE VG+ Series 3 Drives



Grounding of IMPULSE VG+ Series 3 Drive and Vector Control Motor

Figure 3-3: Grounding

Control Circuit Terminals - Continued

Control Circuit board GIF7

DIP Switch S1 and Jumper CN15

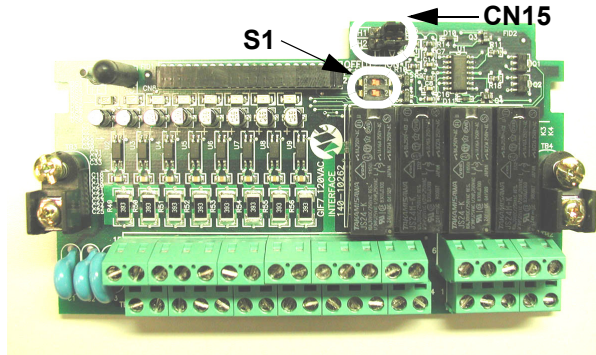


Figure 3-4: DIP Switch S1 and Jumper CN15 Location

Table 1: Terminal and Wire Specifications

| Terminal Symbol | Terminal Screw | Clamping Torque Lb-in (N-m) | Wire Range AWG (mm ²) |
|-----------------|----------------|--------------------------------|---|
| J1 | M3 | 4.2 to 5.3 (0.5 to 0.6) | 26 to 16 (Stranded: 0.14 to 1.5) (Solid: 0.14 to 1.5) |

Dip Switch S1

DIP Switch S1 is described in this section. The functions of DIP switch S1 are shown in the table below.

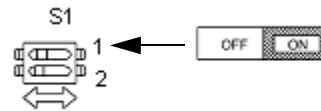
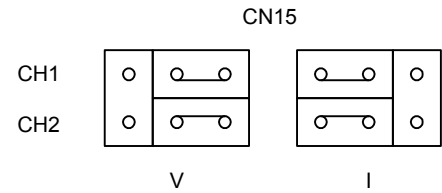


Figure 3-5: DIP Switch S1 Function

| DIP Switch S1 | | |
|---------------|--|---|
| Name | Function | Setting |
| S1-1 | RS-485 and RS-422 terminating resistance | OFF: No terminating resistance (default) ON: Terminating resistance of 110 Ohm |
| S1-2 | Input method for analog input A2 | OFF: 0 to 10VDC or -10 to 10VDC (internal resistance: 20kΩ) (default) ON: 4-20mA (internal resistance: 250 Ohm) |

Jumper CN15

Jumper CN15 is described in this section. The jumper position of CH1 and CH2 determines the signal level of the multi-function analog output FM and AM, respectively. The functions and positions of CN15 are shown in the table below.



| Jumper CN15 | | |
|-------------|------------------------------|---|
| Name | Multi-function Analog Output | Output Range |
| CH1 | FM | V: 0 to 10VDC or -10 to +10VDC (default) I: 4 to 20mA |
| CH2 | AM | V: 0 to 10VDC or -10 to +10VDC (default) I: 4 to 20mA |

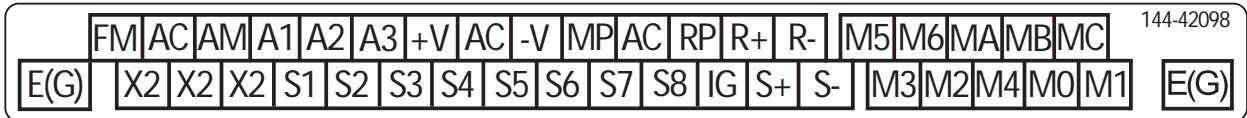
Control Circuit Terminals

The table below outlines the functions of the control circuit terminals.

| Classification | Terminal | Signal Function | Description | | Signal Level |
|-----------------------|----------|--|--|---|---|
| Sequence Input Signal | S1 | Forward run/stop | Forward run when closed, stop when open | | 120VAC ± 10% |
| | S2 | Reverse run/stop | Reverse run when closed, stop when open | | |
| | S3 | Speed 2* | Multi-function contact inputs (H1-01 to H1-06) *Programmable input | | |
| | S4 | Speed 3* | | | |
| | S5 | Speed 4* | | | |
| | S6 | Speed 5* | | | |
| | S7 | External Fault* | | | |
| | S8 | M-Speed Gain 1* | | | |
| | SN | Control Input Common | | | |
| Analog Input Signal | +V | +15VDC Power supply output | For analog command +15VDC power supply | | +15VDC (Allowable current 20 mA max.) |
| | -V | -15VDC Power supply output | For analog command -15VDC power supply | | -15VDC (Allowable current 20 mA max.) |
| | A1 | Master frequency reference | -10 to +10VDC/-100% to 100% 0 to +10VDC/0 to 100% | | -10 to +10VDC (20k Ohm), 0 to +10VDC/(20k Ohm) |
| | A2 | Multi-function analog reference | 4 to 20 mA/0 to 100% -10 to +10VDC/-100% to 100% 0 to 10 VDC/0 to 100% | Multi-function analog reference (H3-09) | 4 to 20mA (250 Ohm) -10 to +10VDC (20k Ohm), 0 to +10VDC/(20k Ohm) |
| | A3 | Multi-function analog input | -10 to +10VDC/-100% to +100% 0 to +10 VDC/0 to 100% | Auxiliary analog input (H3-05) | -10 to +10VDC (20k Ohm), 0 to +10VDC/(20k Ohm) |
| | AC | Common terminal for control circuit | 0V | | — |
| | E(G) | Connection to shield sheath of signal lead | — | | — |
| Relay Output Signal | M0 | Brake output | Multi-function output (H2-01 to H2-03) | | Dry contact Contact capacity: 250VAC, 1A or less 30VDC, 1A or less |
| | M1 | N.O. Contact | | | |
| | M2 | N.O./N.C. Contact | | | |
| | M3 | | | | |
| | M4 | | | | |
| | M5 | | | | |
| | M6 | Fault annunciate | | | |
| | MA | Fault contact output (NO/NC contact) | Terminals MA & MC N/O; closed at major faults Terminals MB & MC N/C open at major fault | | |
| | MB | | | | |
| MC | | | | | |

| Classification | Terminal | Signal Function | Description | | Signal Level |
|----------------------|---------------|--------------------------------|--|--|--|
| Analog Output Signal | FM | Multi-Function Analog Output 1 | 0 to ± 10 VDC | Multi-function analog monitor (H4-01 to H4-03) | 0 to ± 10 VDC Max. $\pm 5\%$ 2mA or less |
| | AC | Common | | | |
| | AM | Multi-Function Analog Output 2 | 0 to ± 10 VDC | Multi-function analog monitor 2 (H4-04 to H4-06) | 0 to ± 10 VDC Max. $\pm 5\%$ 2mA or less |
| Pulse I/O Signal | RP | Pulse Input | Pulse input frequency reference | Function set by H6-01 | 0 to 32kHz (3k Ω) $\pm 5\%$ High level voltages 3.5 to 13.2 Low level voltages 0.0 to 0.8 Duty Cycle (on/off) 30% to 70% |
| | MP | Pulse Monitor | Pulse output frequency | Function set by H6-06 | 0 to 32kHz $\pm 5\%$ output (load: 1.5k Ω) |
| RS-485/422 | R+ | Modbus communication input | For 2-wire RS-485, jumper R+ and S+ and jumper R- and S- | | Differential input, PHC isolation |
| | R- | | | | |
| | S+ | Modbus communication output | | | Differential output, PHC isolation |
| | S- | | | | |
| IG | Signal Common | | | | |

Control Circuit Terminal Diagram



Wiring the Encoder Circuit

A shaft-mounted encoder is required to provide speed and shaft position feedback to IMPULSE•VG+ Series 3. Without an encoder, a flux vector control cannot operate properly.

Before you wire the encoder circuit, refer to the specification tables in this section and to “Wiring Specifications.”

Encoder Circuit Wiring Procedures

Encoder Specifications

| | |
|------------------------|--|
| Power supply | +12VDC; if current demand is greater than 200 mA, an auxiliary power supply must be provided |
| Output Type | Quadrature (A and B channels; Z is not necessary) |
| Type of output circuit | High-speed, differential line driver. |
| Resolution | 1024 PPR |
| Mounting method | Encoder must be direct-coupled to motor shaft, using a zero-backlash-type coupling. |

To wire the encoder circuit for IMPULSE•VG+ Series 3 (assuming the cover and keypad are detached):

1. Direct-couple the encoder to the motor shaft, using a zero-backlash-type coupling.
NOTE: Do not connect the encoder to the motor with roller chain or gear drive. If unable to direct-couple the encoder, use a timing belt to drive the encoder. (Contact Magnetek for encoder kits.) Also, do not connect the encoder to the low-speed shaft of a speed reducer.
2. Connect the encoder to the PG-T2 Encoder Interface Card. Refer to Figure 3-9: “PG-T2 Encoder Card Wiring” on page 3-15.
NOTE: Use twisted-pair, shielded cable W100Ω impedance (Magnetek R-20/6, R-22/6, Belden 9730, or Brand Rex T-11651). Use 08/6 encoder wire on runs less than 100 feet. Strip the encoder wires .25 in. (5.5 mm). Keep the wiring length less than 300 feet. (For cable lengths greater than 300 feet, contact Magnetek for information on available fiber optic cable systems.)
3. Ground the shielded cable to Terminal TA4 of the PG-T2 Encoder Interface Card. (Ground only one end of the shielded cable.)
NOTE: For LakeShore encoders, the shield connection is not considered “Ground.” The shield should be grounded at TA4 and connected to the shield at the encoder.
4. Whenever possible, the encoder cable should be wired in a continuous run between the motor and drive. If it cannot be a direct run, the splice should be in its own junction box and isolated from the power wires.

Encoder Wiring Diagrams and Information

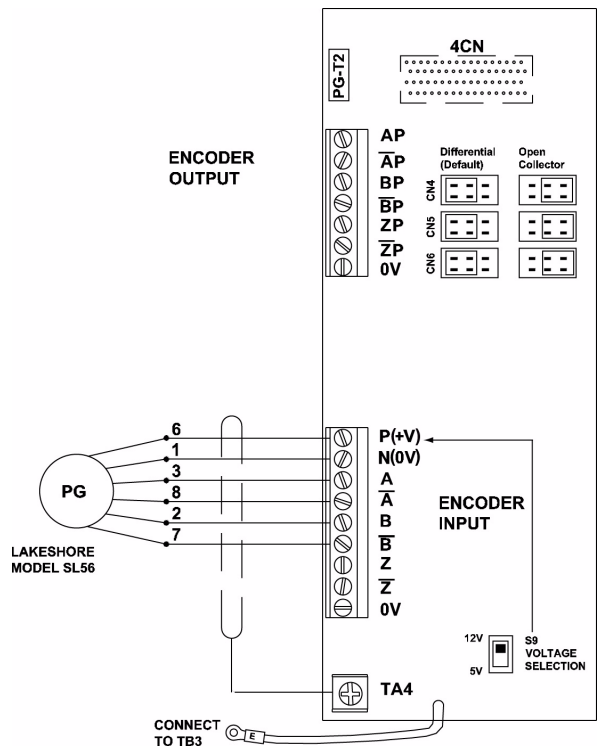
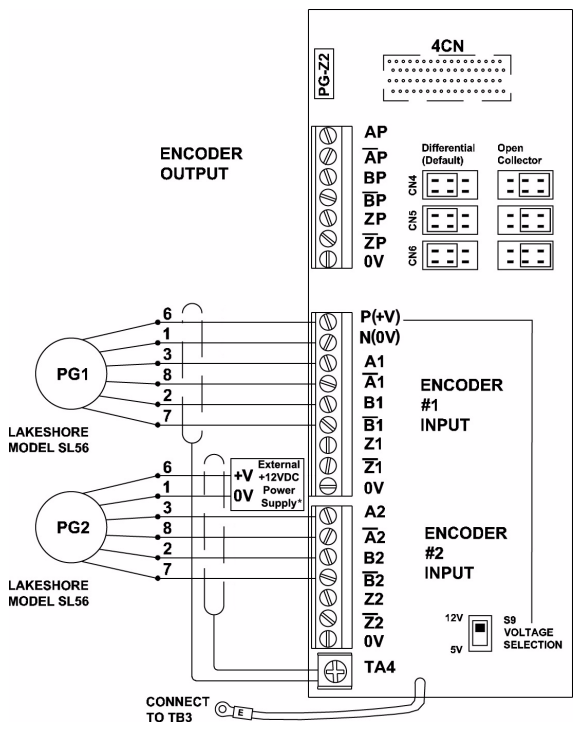


Figure 3-6: PG-T2 Encoder Card Wiring



*Separate Power Supply
Required for Encoder 2 Power

Figure 3-7: PG-Z2 Encoder Card Wiring

Encoder Wiring (Lakeshore Model: SL56 and SL85; Avtron Models: M56 and M85)

| Encoder Signal | Wire Color | PG-T2 Terminal |
|-----------------------|-------------------|-----------------------|
| +5 to 15VDC | Red | 8 |
| OV | Black | 9 |
| A+ | Blue | 10 |
| A- | Gray | 11 |
| B+ | Green | 12 |
| B- | Yellow | 13 |
| Shield | N/A | FG |

PG-T2 Encoder Interface Card Specifications

| | |
|---|--|
| Power supply to encoder: | Dual; +5VDC or +12VDC; 20 mA maximum |
| Encoder input signal: | RS-422-level, line-driver-type |
| Pulse monitor output signal (repeater): | RS-422-level, line-driver-type or open collector |
| Pulse phases accepted: | Phases A and B (both + and -) |
| Maximum input frequency: | 30 kHz |

PG-Z2 Encoder Interface Card Terminal Functions

| Terminal Block | Function |
|-----------------------|---------------------------|
| 1 | A+ pulse output |
| 2 | A- pulse output |
| 3 | B+ pulse output |
| 4 | B- pulse output |
| 5 | Z+ pulse output |
| 6 | Z- pulse output |
| 7 | OV (signal common) |
| 8 | +12VDC power supply |
| 9 | Power supply common |
| 10 | A+ pulse input, Channel 1 |
| 11 | A- pulse input, Channel 1 |
| 12 | B+ pulse input, Channel 1 |
| 13 | B- pulse input, Channel 1 |
| 14 | Z+ pulse input, Channel 1 |
| 15 | Z- pulse input, Channel 1 |
| 16 | Signal common |
| 17 | A+ pulse input, Channel 2 |
| 18 | A- pulse input, Channel 2 |
| 19 | B+ pulse input, Channel 2 |
| 20 | B- pulse input, Channel 2 |
| 21 | Z+ pulse input, Channel 2 |
| 22 | Z- pulse input, Channel 2 |
| 23 | Signal common |
| FG | Shield terminal |

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chapter **4**

Getting Started

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Overview

With its easy-to-use keypad and X-Press Programming, IMPULSE•VG+ Series 3 makes it easy to get up and running right away. In addition to explaining the keypad and X-Press Programming, this chapter explains how to view the scroll settings, get into the programming mode, and program speeds.

Checks Before Powering

After mounting and interconnections are completed, verify:

- Correct connections.
- Correct input power supply. (No voltage drop or imbalance, source kVA \leq 500, unless a line reactor is used.)



WARNING

DO not power 230V-rated drives with 460V power.

- No short circuit conditions.
- No loose screw terminals. (Check especially for loose wire clippings.)
- Proper load conditions.

Precautions

- Only start the motor if motor shaft rotation is stopped.
- Even with small loading, never use a motor whose nameplate amperage exceeds the inverter rated current.



DANGER

Extreme caution should be used if braking method is set for Decelerate to stop. If deceleration time is too long, equipment could run into end stop device, causing damage to equipment or injury to personnel.

Using the Keypad

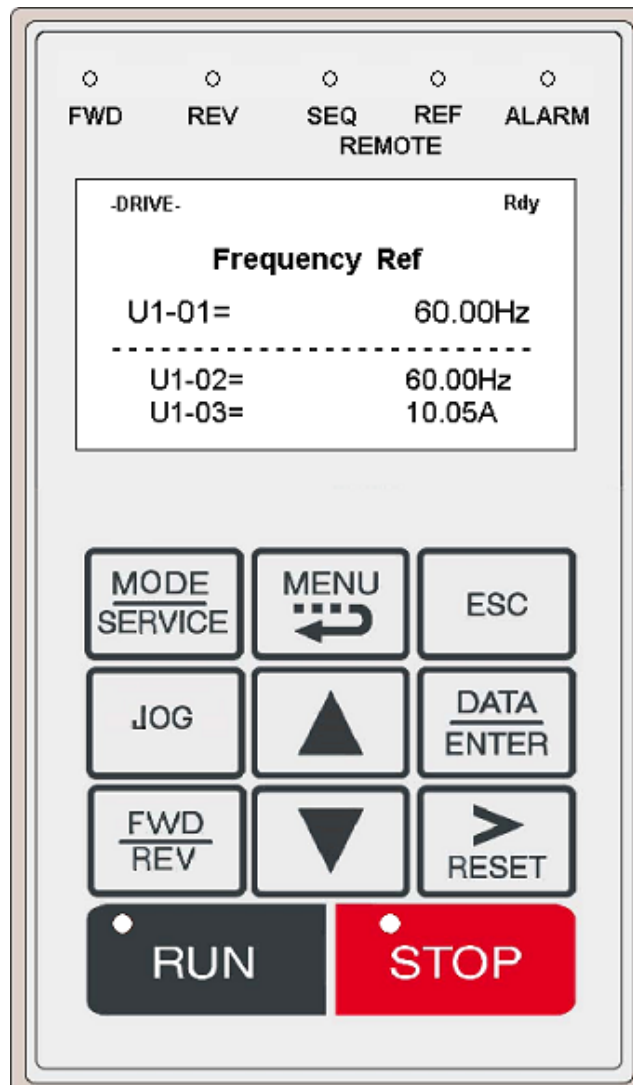
With five 16-character lines available, the keypad display makes it possible to view fault codes and change parameter settings. Parameter settings, with their parameter codes, are displayed in most cases. In addition, the parameter description is included on the top line of the display. The keypad enables you to:

- Program the various drive parameters.
- Monitor the functions of the drive.
- Read alpha-numeric fault-diagnostic indications.
- Operate the drive using the keypad (local operation).



WARNING

Because of the additional potential hazards that are introduced when any drive is operated locally, we advise you to avoid operating it this way. If you do operate the drive locally, be aware that the crane or hoist will move when you press the RUN button. If you have questions, contact Magnetek.



Keypad LED and Button Functions

Some of the keypad buttons, whose functions are described below, are dual-purpose. The dual-purpose keys have one function when used in a view-only mode, and another function when used in a programming mode.



This LED lights when a fault has occurred, flashes when an alarm has occurred.



This LED lights when the FORWARD command is given.



This LED lights when the REVERSE command is given.



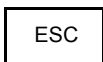
- The SEQ LED lights when selecting the RUN command from the control circuit terminals or communication option card.
- The REF LED lights when the **Speed Reference** is input through control circuit terminals or communication option card.



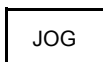
- Pressing this key toggles between the mode display and the phone number for Magnetek Service Department.
- Also toggles between REMOTE and LOCAL (operate from keypad) operation when O2-01 is set to 1.
- Pressing the key 3 times resets the maintenance timer, U1-52.



Displays the four key pad functions; operation, programming, modified constants and auto tuning.



Backs up to the previous display (before the DATA/ENTER key is depressed).



Jog run is enabled when local operation is selected.



Selects the next parameter group, parameter or parameter setting. It also increases the blinking digit of a parameter setting.



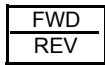
Selects the previous parameter group, parameter or parameter setting. It also decreases the blinking digit of a parameter setting.



Selects the digit—from left to right—to be changed (indicated by blinking). It also resets the operation at faults.



Selects mode or parameter. Displays each parameter's set value. By pressing this key again, the set value is entered.



Selects forward or reverse run when LOCAL operation is selected.



- Pressing this key initiates run command when LOCAL operation is selected.
- The red LED lights steadily during run.



- Pressing this key initiates Base Block stop command.
- The red LED lights steadily when drive is at stop; blinks when Run command is active but output frequency reference is zero, off when drive output is controlling motor speed.

Parameters

There are hundreds of parameters that determine how the drive functions. These parameters are programmed into the drive's software as measurable values or options - both of which will be referred to in this manual as *settings*. While some of these parameters are associated with one setting, others are tied to a number of possible settings.

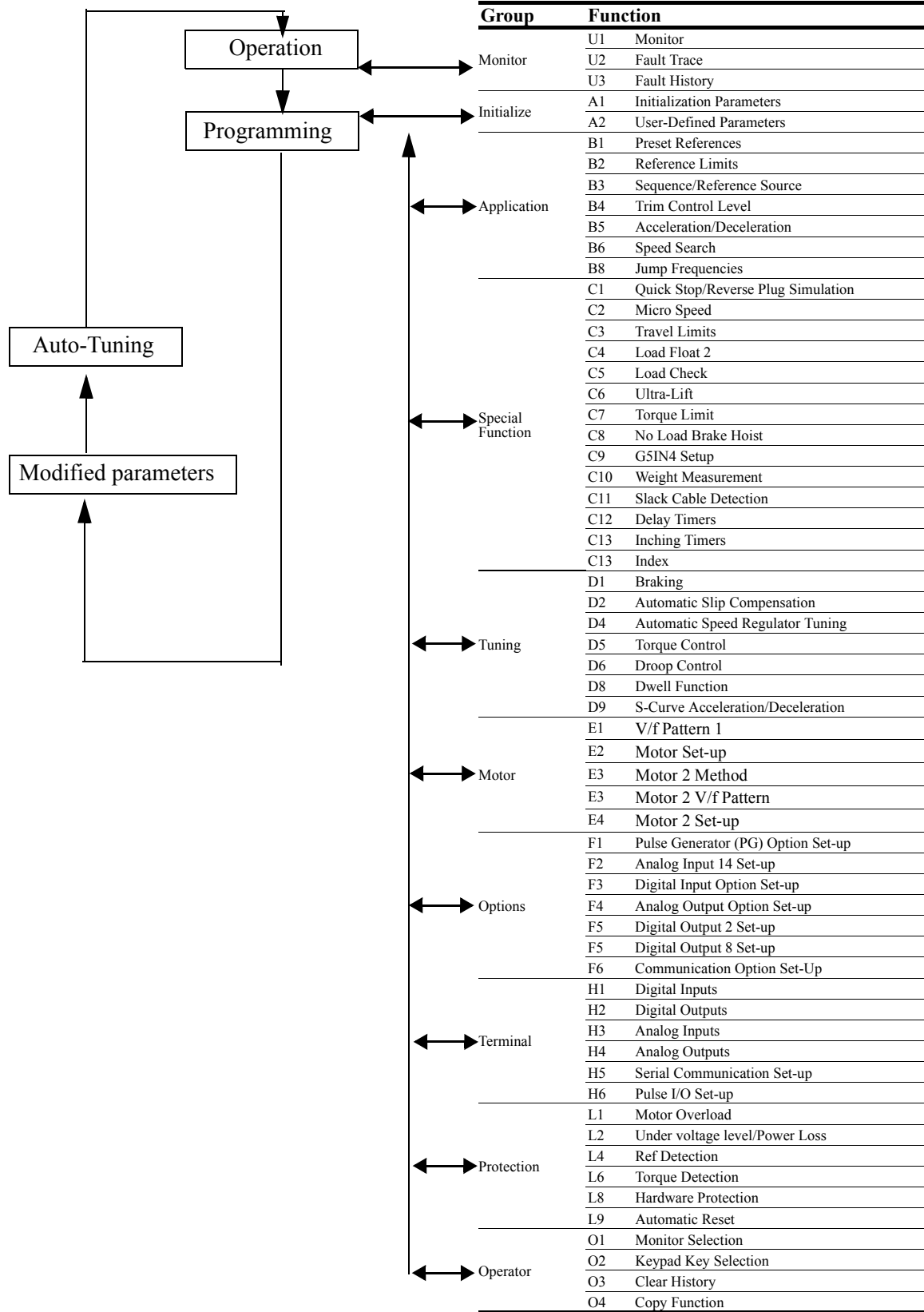
NOTE: The terms "constant" and "parameter" have the same meaning.

Before shipping the drive, Magnetek programmed initial settings in the drive's software so that most, if not all, of the crane system requirements are supported. However, if it is necessary to change the initial settings, Magnetek recommends that only qualified crane system technicians program the drive. This can be accomplished by using the **Password** and **Access Level** features. For more information on these security features, see Initializaton Set-Up on page 4-9.

The drive can be programmed to allow personnel with limited crane system knowledge to program only certain parameters, called **User Parameters**. To select these parameters, see "User Parameters (A2-01 through 32)" on page 4-13.

Two other features to be aware of are **Initialize Parameters** (A1-05) and **User Defaults** (O2-03). Both of these features are related and revert back to previously saved parameter settings. This is especially helpful when a number of programming changes were made, but the previous settings may still be needed. To program these features, see "Initialize Parameters (A1-05)" and "User Defaults (O2-03)".

IMPULSE•VG+ Series 3 Structure of Parameters



Parameter Modes

All parameters are organized under four modes:

Operation Mode

Drive operation is enabled. Drive status LED is lit.

Programming Mode

Parameter access levels, control method, motion, speed control mode, and passwords are selected.

Parameters are set/read. Items to be set/read vary depending on the access level setting.

Auto-Tuning Mode

Motor parameters are automatically set by entering tuning data (motor nameplate values).

Modified Constants Mode

Only parameters that have been changed from the factory settings are set/read.

Initialization Set-up

Language Selection (A1-00)

This allows for the language selection for the digital operator display, as follows:

| Setting | Description |
|---------|-------------|
| 0 | English |
| 1 | French |
| 2 | Spanish |

Parameter Access Level (A1-01)

This parameter allows the “masking” of parameters according to user level. See the following table:

| Setting | Description |
|---------|--|
| 0 | Operation Only |
| 1 | User Program - Accesses parameters selected by OEM (A2-01 to A2-32). |
| 2 | Advanced Level - For advanced programming in special applications. |

Refer to the parameter code table in Chapter 5 for available parameters at each level.

Control Method Selection (A1-02)

Select the control method best suited for your application.

| Setting | Description |
|---------|-------------|
| 3 | Flux Vector |

NOTE: An auto-tune must be performed for all flux vector applications. Refer to the Auto-Tuning section on page 4-14.

Select Motion (A1-03)

Set this parameter to match the motion of application. See tables 4.1 and 4.2 (X-Press Programming) for details.

| Setting | Description |
|---------|--|
| 0 | Traverse - Decelerate to stop upon removal of RUN command. |
| 2 | No-Load Brake Hoist |

Speed Reference (A1-04)

This parameter will automatically define the input terminals for the selections listed below. See tables 4.1 and 4.2 (X-Press Programming) for details.

| Setting | Description |
|---------|---|
| 0 | 2-SPD Multi-step — Defines Terminal 3 = 2nd speed. |
| 1 | 3-SPD multi-step — Defines Terminals 3 and 4 as speeds 2 and 3 respectively. |
| 2 | 5-SPD Multi-step — Defines Terminals 3-6 as speeds 2-5. |
| 3 | 2-Step infinitely variable — Terminals 1 and 2 = b1-01 (Reference 1) and speed hold. Terminal 3 = Accelerate. |
| 4 | 3-Step infinitely variable — Terminals 1 and 2 = b1-01 (Reference 1). Terminal 3 = Speed Hold. Terminal 4 = Accelerate. |
| 5 | Uni-polar analog — Terminals 1 and 2 = A directional input. Terminal A1 = 0-10V. Terminal A2 = 4-20mA. |
| 6 | Bi-polar analog — Terminal A1 = Run Command. Terminal A1 = direction and frequency -10 to +10VDC. |
| 7 | Defines Terminals 3-8 as not used. Use this setting if using the G5IN4 option card for inputting speed references. |
| 8 | Serial option card. Sets terminals to “not used.” |

Parameters Changed by X-Press Programming

Table 4-1: Traverse (A1-03= 0)

| A1-04 | Description | B1-01 | B1-02 | B1-03 | B1-04 | B1-05 | B1-06 | B1-07 | B1-08 | B1-09 | B1-10 | B1-11 | B1-12 | B1-13 | B1-14 | B1-15 | B1-16 | B1-17 | B1-18 | B2-01 | B2-03 | B3-03 | B5-01 | B5-02 |
|-------|----------------------------|---------|---------|---------|---------|---------|---------|---------|---------|---------|----------|----------|----------|----------|----------|----------|----------|---------|--------------|------------------|------------------|-----------------|--------------|--------------|
| | | Speed 1 | Speed 2 | Speed 3 | Speed 4 | Speed 5 | Speed 6 | Speed 7 | Speed 8 | Speed 9 | Speed 10 | Speed 11 | Speed 12 | Speed 13 | Speed 14 | Speed 15 | Speed 16 | Jog Ref | Ref Priority | Ref. Upper Limit | Ref. Lower Limit | Stopping Method | Accel Time 1 | Decel Time 1 |
| 0 | 2-Speed Multi-Step | 20.00 | 60.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 6.00 | 0 | 100.0 | 2.0 | 0 | 10.0 | 10.0 |
| 1 | 3-Speed Multi-Step | 15.00 | 30.00 | 60.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 6.00 | 0 | 100.0 | 2.0 | 0 | 10.0 | 10.0 |
| 2 | 5-Speed Multi-Step | 6.00 | 15.00 | 30.00 | 45.00 | 60.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 6.00 | 0 | 100.0 | 2.0 | 0 | 10.0 | 10.0 |
| 3 | 2-Step Infinitely Variable | 6.00 | 0.00 | 0.00 | 0.00 | 60.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 6.00 | 0 | 100.0 | 2.0 | 0 | 10.0 | 10.0 |
| 4 | 3-Step Infinitely Variable | 6.00 | 0.00 | 0.00 | 0.00 | 60.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 6.00 | 0 | 100.0 | 2.0 | 0 | 10.0 | 10.0 |
| 5 | Uni-Polar Analog | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 6.00 | 1 | 100.0 | 2.0 | 0 | 10.0 | 10.0 |
| 6 | Bi-Polar Analog | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 6.00 | 1 | 100.0 | 2.0 | 0 | 10.0 | 10.0 |
| 7 | G5IN4 Opt. Card | 15.00 | 30.00 | 60.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 6.00 | 0 | 100.0 | 2.0 | 0 | 10.0 | 10.0 |
| 8 | Serial Opt. Card | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 6.00 | 1 | 100.0 | 2.0 | 0 | 10.0 | 10.0 |

| A1-04 | Description | C1-01 | C3-07 | C8-10 | D9-01 | D9-02 | D9-03 | E1-03 | H1-01 | H1-02 | H1-03 | H1-04 | H1-05 | H1-06 | H2-01 | H2-02 | H2-03 | H3-01 | H3-05 |
|-------|----------------------------|----------------|------------------|-----------------|------------------------|----------------------|------------------------|---------------|--------------------|--------------------|--------------------|--------------------|--------------------|--------------------|-------------------------|-------------------------|-------------------------|--------------------|--------------------|
| | | Quick Stop 0/1 | Action @ LL2/UL2 | Load Float Time | S-Curve Accel at Start | S-Curve Accel at End | S-Curve Decel at Start | V/F Selection | Terminal S3 Select | Terminal S4 Select | Terminal S5 Select | Terminal S6 Select | Terminal S7 Select | Terminal S8 Select | Terminal M1 / M2 Select | Terminal M3 / M4 Select | Terminal M5 / M6 Select | Terminal A1 Signal | Terminal A3 Select |
| 0 | 2-Speed Multi-Step | 0 | 2 | 0 | 1.50 | 1.50 | 1.50 | 01 | 00 | 0F | 0F | 0F | 0F | 0F | 00 | 0F | 0F | 0 | 1F |
| 1 | 3-Speed Multi-Step | 0 | 2 | 0 | 1.50 | 1.50 | 1.50 | 01 | 00 | 01 | 0F | 0F | 0F | 0F | 00 | 0F | 0F | 0 | 1F |
| 2 | 5-Speed Multi-Step | 0 | 2 | 0 | 1.50 | 1.50 | 1.50 | 01 | 00 | 01 | 02 | 03 | 0F | 0F | 00 | 0F | 0F | 0 | 1F |
| 3 | 2-Step Infinitely Variable | 0 | 2 | 0 | 1.50 | 1.50 | 1.50 | 01 | 05 | 0F | 0F | 0F | 0F | 0F | 00 | 0F | 0F | 0 | 1F |
| 4 | 3-Step Infinitely Variable | 0 | 2 | 0 | 1.50 | 1.50 | 1.50 | 01 | 04 | 05 | 0F | 0F | 0F | 0F | 00 | 0F | 0F | 0 | 1F |
| 5 | Uni-Polar Analog | 0 | 2 | 0 | 1.50 | 1.50 | 1.50 | 01 | 0F | 0F | 0F | 0F | 0F | 0F | 00 | 0F | 0F | 0 | 1F |
| 6 | Bi-Polar Analog | 0 | 2 | 0 | 1.50 | 1.50 | 1.50 | 01 | 0F | 0F | 0F | 0F | 0F | 0F | 00 | 0F | 0F | 1 | 1F |
| 7 | G5IN4 Opt. Card | 0 | 2 | 0 | 1.50 | 1.50 | 1.50 | 01 | 0F | 0F | 0F | 0F | 0F | 0F | 00 | 0F | 0F | 0 | 1F |
| 8 | Serial Opt. Card | 0 | 2 | 0 | 1.50 | 1.50 | 1.50 | 01 | 0F | 0F | 0F | 0F | 0F | 0F | 00 | 0F | 0F | 0 | 1F |

Parameters Changed by X-Press Programming

Table 4-2: No Load Brake Hoist (A1-03 = 2)

| A1-04 | Description | B1-01 | B1-02 | B1-03 | B1-04 | B1-05 | B1-06 | B1-07 | B1-08 | B1-09 | B1-10 | B1-11 | B1-12 | B1-13 | B1-14 | B1-15 | B1-16 | B1-17 | B1-18 | B2-01 | B2-03 | B3-03 | B5-01 | B5-02 |
|-------|----------------------------|---------|---------|---------|---------|---------|---------|---------|---------|---------|----------|----------|----------|----------|----------|----------|----------|---------|--------------|------------------|------------------|-----------------|--------------|--------------|
| | | Speed 1 | Speed 2 | Speed 3 | Speed 4 | Speed 5 | Speed 6 | Speed 7 | Speed 8 | Speed 9 | Speed 10 | Speed 11 | Speed 12 | Speed 13 | Speed 14 | Speed 15 | Speed 16 | Jog Ref | Ref Priority | Ref. Upper Limit | Ref. Lower Limit | Stopping Method | Accel Time 1 | Decel Time 1 |
| 0 | 2-Speed Multi-Step | 20.00 | 60.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 6.00 | 0 | 100.0 | 0.0 | 6 | 5.0 | 3.0 |
| 1 | 3-Speed Multi-Step | 15.00 | 30.00 | 60.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 6.00 | 0 | 100.0 | 0.0 | 6 | 5.0 | 3.0 |
| 2 | 5-Speed Multi-Step | 6.00 | 15.00 | 30.00 | 45.00 | 60.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 6.00 | 0 | 100.0 | 0.0 | 6 | 5.0 | 3.0 |
| 3 | 2-Step Infinitely Variable | 6.00 | 0.00 | 0.00 | 0.00 | 60.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 6.00 | 0 | 100.0 | 0.0 | 6 | 5.0 | 3.0 |
| 4 | 3-Step Infinitely Variable | 6.00 | 0.00 | 0.00 | 0.00 | 60.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 6.00 | 0 | 100.0 | 0.0 | 6 | 5.0 | 3.0 |
| 5 | Uni-Polar Analog | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 6.00 | 1 | 100.0 | 0.0 | 6 | 5.0 | 3.0 |
| 6 | Bi-Polar Analog | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 6.00 | 1 | 100.0 | 0.0 | 6 | 5.0 | 3.0 |
| 7 | G5IN4 Opt. Card | 15.00 | 30.00 | 60.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 6.00 | 0 | 100.0 | 0.0 | 6 | 5.0 | 3.0 |
| 8 | Serial Opt. Card | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 6.00 | 1 | 100.0 | 0.0 | 6 | 5.0 | 3.0 |

| A1-04 | Description | C1-01 | C3-07 | C8-10 | D9-01 | D9-02 | D9-03 | E1-03 | H1-01 | H1-02 | H1-03 | H1-04 | H1-05 | H1-06 | H2-01 | H2-02 | H2-03 | H3-01 | H3-05 |
|-------|----------------------------|----------------|------------------|-----------------|------------------------|----------------------|------------------------|---------------|--------------------|--------------------|--------------------|--------------------|--------------------|--------------------|-------------------------|-------------------------|-------------------------|--------------------|--------------------|
| | | Quick Stop 0/1 | Action @ LL2/UL2 | Load Float Time | S-Curve Accel at Start | S-Curve Accel at End | S-Curve Decel at Start | V/F Selection | Terminal S3 Select | Terminal S4 Select | Terminal S5 Select | Terminal S6 Select | Terminal S7 Select | Terminal S8 Select | Terminal M1 / M2 Select | Terminal M3 / M4 Select | Terminal M5 / M6 Select | Terminal A1 Signal | Terminal A3 Select |
| 0 | 2-Speed Multi-Step | 1 | 2 | 10 | 0.50 | 0.50 | 0.50 | 0F | 00 | 0F | 0F | 0F | 0F | 0F | 00 | 00 | 78 | 0 | 1F |
| 1 | 3-Speed Multi-Step | 1 | 2 | 10 | 0.50 | 0.50 | 0.50 | 0F | 00 | 01 | 0F | 0F | 0F | 0F | 00 | 00 | 78 | 0 | 1F |
| 2 | 5-Speed Multi-Step | 1 | 2 | 10 | 0.50 | 0.50 | 0.50 | 0F | 00 | 01 | 02 | 03 | 0F | 0F | 00 | 00 | 78 | 0 | 1F |
| 3 | 2-Step Infinitely Variable | 1 | 2 | 10 | 0.50 | 0.50 | 0.50 | 0F | 05 | 0F | 0F | 0F | 0F | 0F | 00 | 00 | 78 | 0 | 1F |
| 4 | 3-Step Infinitely Variable | 1 | 2 | 10 | 0.50 | 0.50 | 0.50 | 0F | 04 | 05 | 0F | 0F | 0F | 0F | 00 | 00 | 78 | 0 | 1F |
| 5 | Uni-Polar Analog | 1 | 2 | 10 | 0.50 | 0.50 | 0.50 | 0F | 0F | 0F | 0F | 0F | 0F | 0F | 00 | 00 | 78 | 0 | 1F |
| 6 | Bi-Polar Analog | 1 | 2 | 10 | 0.50 | 0.50 | 0.50 | 0F | 0F | 0F | 0F | 0F | 0F | 0F | 00 | 00 | 78 | 1 | 1F |
| 7 | G5IN4 Opt. Card | 1 | 2 | 10 | 0.50 | 0.50 | 0.50 | 0F | 0F | 0F | 0F | 0F | 0F | 0F | 00 | 00 | 78 | 0 | 1F |
| 8 | Serial Opt. Card | 1 | 2 | 10 | 0.50 | 0.50 | 0.50 | 0F | 0F | 0F | 0F | 0F | 0F | 0F | 00 | 00 | 78 | 0 | 1F |

Initial Parameters (A1-05)

Use this parameter to reset the inverter to its factory default settings.

| Setting | Description |
|---------|--|
| 0 | No Initialization (factory default) |
| 1110 | User Initialization - resets the inverter to user-specified initial values. To set user-specified initial values, make all required changes to parameter settings, and then set 02-03 to "1". The inverter will memorize all current settings as the user-specified initial values. Up to 50 changed parameters can be stored. |

Password Entry (A1-06)

This parameter enables the user to set a password that inhibits the programming of the parameters *A1-01* to *A1-03*. This function is useful when used in conjunction with the access level parameter *A1-01*. To set the password, press the MENU and RESET buttons at the same time and the display will change from *A1-06* to *A1-07*. Program in a password number, and then if *A1-06* is not the same as *A1-07* parameter *A1-01* to *A1-03* cannot be changed. When *A1-06* is the same as *A1-07*, then *A1-01* to *A1-03* can be changed.

User Parameters (A2-01 through 32)

The user can select up to 32 parameters for quick-access programming. By setting the user access level (*A1-01*) to "User Program," only the parameters selected in function A2 can be accessed by the user. To assign a parameter as a user parameter, go to the A2 level in the initialize menu. Once the A2 parameters are set and *A1-01* is programmed to "User Program," only the parameters visible in the program menu will be assigned to an A2 parameter.

Auto-Tuning



CAUTION

The brake output is not energized during Auto-Tune. The brake must be manually released and set when Auto-Tuning is complete.

The IMPULSE•VG+ Series 3 can adapt to nearly all motors manufactured worldwide with its automatic tuning function. The inverter asks the user for minimal motor information, and then guides the user through a quick simple tuning process. Ideally, perform a standard Auto-Tune with the motor uncoupled from the load. When the motor cannot be disconnected from the load, perform a static or non-rotating Auto-Tune.

NOTE: Contact Magnetek's service department if an auto-tune can not be performed.

| Parameter Code | Display | Description | Default Setting |
|----------------|------------------|--|-----------------|
| T1-00 | Select Motor | Selects between motor 1 or 2 (Available only when H1-XX=41) | 1 |
| T1-01 | Tuning Mode Sel | Selects Tuning Method <i>0 Standard Tuning (preferred method - motor will rotate)</i> <i>1 Tune - no rotate (first operation should be no load)</i> <i>2 Term Resistance (used to obtain motor lead resistance)</i> | 0 |
| T1-02 | Rated Horsepower | Sets the motor size in HP (note: $KW = HP \times .746$) | kVA dependent |
| T1-03 | Rated Voltage | Sets motor rated voltage in VAC | kVA dependent |
| T1-04 | Rated Current | Sets motor rated current in Amps | kVA dependent |
| T1-05 | Rated Frequency | Sets motor rated frequency in Hertz | 60.0 Hz |
| T1-06 | Number of Poles | Sets the number of motor poles | 4 |
| T1-07 | Rated Speed | Sets motor rated speed in RPM | 1750 RPM |
| T1-08 | PG Pulses/Rev | Sets encoder PPR | 1024 PPR |

After scrolling through the tuning parameters using the Up Arrow key, depress the RUN key to begin auto-tuning. During tuning, “Tuning Proceeding” flashes on the digital operator display. When complete, “Tune Successful”, is displayed. Depress the Menu key to exit auto-tuning mode. Please refer to the “Fault Display and Corrective Actions at Auto-Tuning” section if “Tune Successful” is not displayed.

NOTE: If the STOP key is depressed during tuning, auto-tuning is interrupted and the motor coasts to a stop. The data changed during tuning returns to its original values.

chapter **5**

**Programming Advanced
Features**

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Application

- B1 Preset References
- B2 Reference Limits
- B3 Sequence/Reference Source
- B4 Trim Control Level
- B5 Acceleration/Deceleration
- B6 Phase Loss Detection
- B8 Jump Frequencies

Preset Reference

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|---|---|------------------|---------------|--------------|
| B1-01* | Reference 1 | Sets the frequency of Minimum Speed/Speed 1. | 0.00–150.00 Hz** | 15.00 | Adv |
| B1-02* | Reference 2 | Sets the Speed 2 frequency. | 0.00–150.00 Hz | 30.00 | Adv |
| B1-03* | Reference 3 | Sets the Speed 3 frequency. | 0.00–150.00 Hz | 60.00 | Adv |
| B1-04* | Reference 4 | Sets the Speed 4 frequency. | 0.00–150.00 Hz | 0.00 | Adv |
| B1-05* | Reference 5 | Sets the Speed 5 frequency. | 0.00–150.00 Hz | 0.00 | Adv |
| B1-06* | Reference 6 | Sets the Speed 6 frequency. | 0.00–150.00 Hz | 0.00 | Adv |
| B1-07* | Reference 7 | Sets the Speed 7 frequency. | 0.00–150.00 Hz | 0.00 | Adv |
| B1-08* | Reference 8 | Sets the Speed 8 frequency. | 0.00–150.00 Hz | 0.00 | Adv |
| B1-09* | Reference 9 | Sets the Speed 9 frequency. | 0.00–150.00 Hz | 0.00 | Adv |
| B1-10* | Reference 10 | Sets the Speed 10 frequency. | 0.00–150.00 Hz | 0.00 | Adv |
| B1-11* | Reference 11 | Sets the Speed 11 frequency. | 0.00–150.00 Hz | 0.00 | Adv |
| B1-12* | Reference 12 | Sets the Speed 12 frequency. | 0.00–150.00 Hz | 0.00 | Adv |
| B1-13* | Reference 13 | Sets the Speed 13 frequency. | 0.00–150.00 Hz | 0.00 | Adv |
| B1-14* | Reference 14 | Sets the Speed 14 frequency. | 0.00–150.00 Hz | 0.00 | Adv |
| B1-15* | Reference 14 | Sets the Speed 15 frequency. | 0.00–150.00 Hz | 0.00 | Adv |
| B1-16* | Reference 16 | Sets the Speed 16 frequency. | 0.00–150.00 Hz | 0.00 | Adv |
| B1-17* | Jog Reference | Jog Control and Inching Control frequency reference. | 0.00–150.00 Hz | 6.00 | Adv |
| B1-18* | Ref Priority 0 Digital Ref Only 1 Analog Ref Only 2 Higher Ref Sel | Determines whether the digital or analog frequency reference is used. NOTE: When using Higher Reference Select, 2-Step Infinitely Variable should NOT be used for a Speed Reference setting in parameter A1-04. The two functions are not intended to work in conjunction. | 0–2 | 0 | Adv |

* Initial value is determined by X-Press Programming (Table 4.1-4.2).

**Maximum frequency above 150 Hz is available, consult Magnetek.

Table 5-1: Multi-Step Speed Processing by Multi-Function Input (B1-01 ~ B1-16)

| Speed Reference | Forward/Reverse Terminal 1 or 2 | Multi-Step Speed 2 H1-01 ~ 06 = 0 | Multi-Step Speed 3 H1-01 ~ 06 = 1 | Multi-Step Speed 4 H1-01 ~ 06 = 2 | Multi-Step Speed 5 H1-01 ~ 06 = 3 | Fwd/Rev Jog-Fwd/Rev Inch H1-01 ~ 06 = 15, 16, 17, 18 |
|-----------------------|---------------------------------|--------------------------------------|--------------------------------------|--------------------------------------|--------------------------------------|---|
| STOP | Off | – | – | – | – | Off |
| B1-01 Speed Ref 1 | On | Off | Off | Off | Off | Off |
| B1-02 Speed Ref 2 | On | On | Off | Off | Off | Off |
| B1-03 Speed Ref 3 | On | On | On | Off | Off | Off |
| B1-04 Speed Ref 4 | On | On | On | On | Off | Off |
| B1-05 Speed Ref 5 | On | On | On | On | On | Off |
| B1-06 Speed Ref 6 | On | Off | On | Off | Off | Off |
| B1-07 Speed Ref 7 | On | Off | On | On | Off | Off |
| B1-08 Speed Ref 8 | On | Off | Off | On | Off | Off |
| B1-09 Speed Ref 9 | On | Off | On | On | On | Off |
| B1-10 Speed Ref 10 | On | Off | Off | On | On | Off |
| B1-11 Speed Ref 11 | On | Off | Off | Off | On | Off |
| B1-12 Speed Ref 12 | On | On | Off | Off | On | Off |
| B1-13 Speed Ref 13 | On | On | On | Off | On | Off |
| B1-14 Speed Ref 14 | On | Off | On | Off | On | Off |
| B1-15 Speed Ref 15 | On | On | Off | On | Off | Off |
| B1-16 Speed Ref 16 | On | On | Off | On | On | Off |

Reference Limits

These parameters limit the frequency range as a percentage of maximum output frequency (E1-04). However, if the lower limit is below the DC Inj Start Freq (D1-01), then operation will continue according to B3-05.

An alternate upper limit frequency can be used during operation when a Multi-Function Input (MFI) is set to 59 (Alt F-Ref UpLimit) and the MFI is on.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|-------------------|---|----------|---------------|--------------|
| B2-01 | Ref Upper Limit | Sets as a percentage of the maximum output frequency (E1-04), which determines the maximum frequency at which the drive is able to run. | 0.0–110% | 100.0 | Adv |
| B2-02 | Ref Lower Limit | Sets as a percentage of the maximum output frequency (E1-04), which determines the minimum master frequency reference only. | 0.0–110% | 0.0 | Adv |
| B2-03 | Ref 1 Lower limit | Sets as a percentage of the maximum output frequency (E1-04), which determines the minimum frequency at which the drive is able to run. | 0.0–110% | 0.0* | Adv |
| B2-04 | Alt Upper Limit | Alternate of B2-01 set by MFI=59. | 0-110% | 100.0 | Adv |

*Initial value set by X-Press programming.

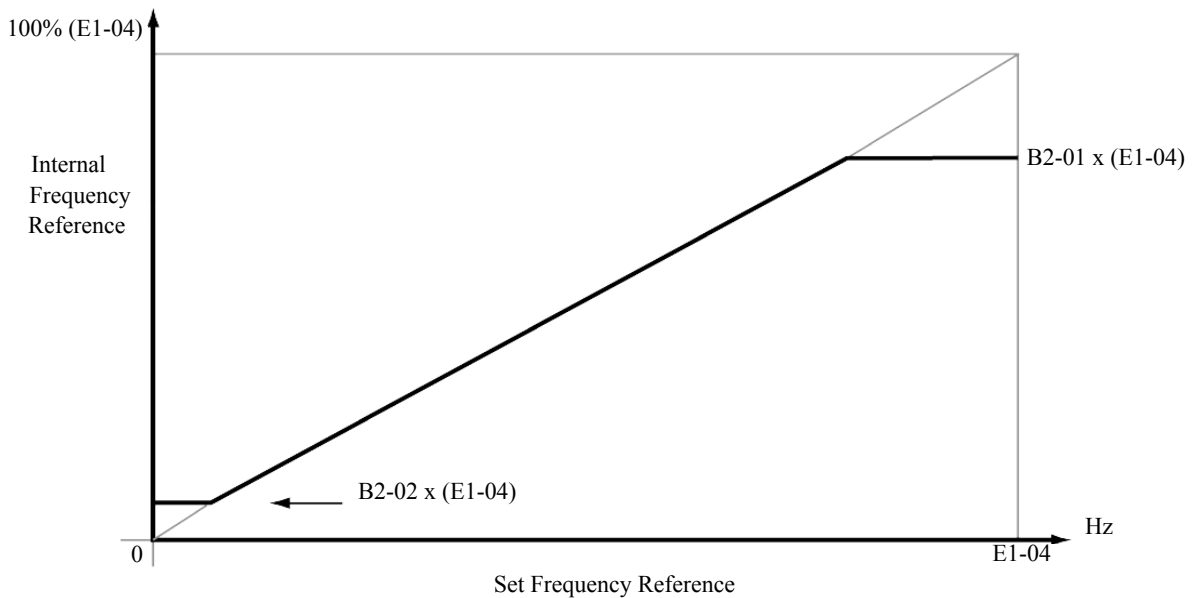


Figure 5-1: Setting Frequency Upper and Lower Limits

Sequence/Reference Source

B3-01 and B3-02 determine the source from where the frequency reference and RUN command are generated.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|-----------------------|---------------------------|---|-------|---------------|--------------|
| B3-01 | Reference Source | Source from where the frequency reference is generated. | 0-4 | 1 | Adv |
| | 0 Operator | Digital operator (Keypad). | | | |
| | 1 Terminals | Control circuit terminal | | | |
| | 2 Communication | Serial communication (Port 6CN). | | | |
| | 3 Option PCB | Optional card (Port 2CN). | | | |
| 4 Pulse Input (H6-01) | Pulse input. | | | | |
| B3-02 | Run Source | Source from where the RUN command is generated. | 0-3 | 1 | Adv |
| | 0 Operator | Digital operator (Keypad). | | | |
| | 1 Terminals | Control circuit terminal. | | | |
| | 2 Communication | Serial communication (Port 6CN). | | | |
| 3 Option PCB | Optional card (Port 2CN). | | | | |

Stop Method

B3-03 selects the stopping method suitable for the particular application.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|---|-------------------------|------------|---------------|--------------|
| B3-03 | Stop Method | Determines stop method. | 0, 1, 4, 6 | 6* | Adv |
| | 0 <i>Decel to Stop (A1-03=0)</i> | (Fig 5-2) | | | |
| | 1 <i>Coast to Stop (A1-03=1)</i> | (Fig 5-3) | | | |
| | 4 <i>Decel with timer (Traverse mode only)</i> | (Fig 5-4) | | | |
| | 6 <i>No Load Brake (A1-03=2) (See No-Load Brake Start/Stop)</i> | | | | |

* Initial value is determined by X-Press Programming (Table 4.1-4.2)

Decel to Stop (B3-03=0)

Upon removal of the FWD or REV run command, the motor decelerates at a rate determined by the time set in deceleration time 1 (B5-02) and DC injection braking is applied after the DC injection start frequency D1-01 has been reached. If the deceleration time is set too short or the load inertia is large, an overvoltage fault (OV) may occur during deceleration. In this case, increase the deceleration time or install an optional braking transistor and/or braking resistor.

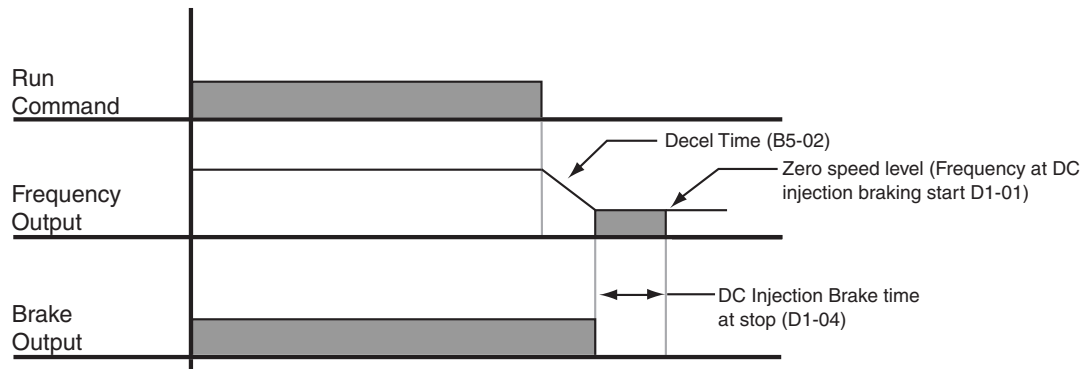


Figure 5-2: Decel to Stop

Coast to Stop (B3-03=1)

Upon removal of the FWD or REV run command, the motor starts to coast and the electric brake sets.

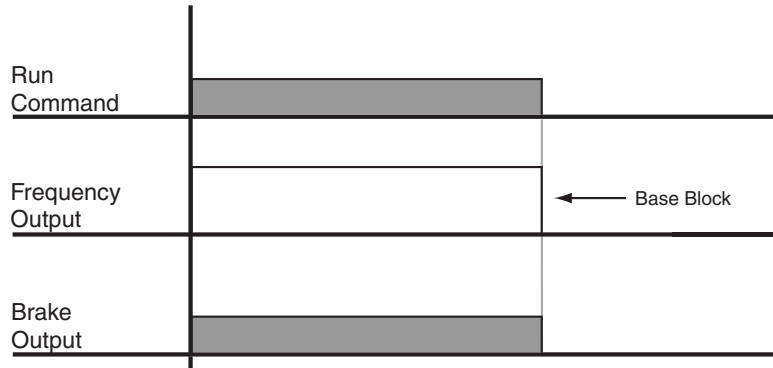


Figure 5-3: Coast to Stop

Decel w/Timer (B3-03=4)

(This option is only available in traverse motion). Upon run command removal, the motor decelerates to stop. The brake delays for a time interval (C12-02) before it is set. This option reduces brake wear for applications that involve frequent stopping and starting.

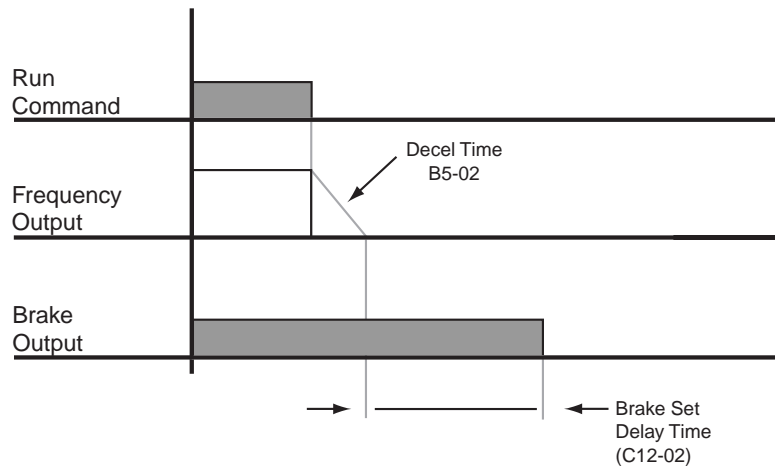


Figure 5-4: Decel w/Timer

Motor Rotation Change

This parameter allows you to change the motor direction without changing the motor leads.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|--|-------------------------|-------|---------------|--------------|
| B3-04 | Reverse Oper 0 Normal Rotation 1 Exchange Phases | Reverse motor direction | 0-1 | 0 | Adv |

Zero-Speed Operation

This parameter sets the speed reference level at which Zero Speed mode operation will activate, in accordance with the selection programmed B3-05 (see the figures below).

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|---|--|-------|---------------|--------------|
| B3-05 | Zero-Speed Oper <i>0 RUN at Freq Ref</i> <i>1 Stop</i> <i>2 RUN at Min. Freq (E1-09)</i> <i>3 RUN at Zero RPM</i> | Operation Selection at Zero Speed. Operate according to the Frequency Reference Coast when the Frequency Reference is below E1-09 Output the Frequency set in E1-09 | 0-3 | 0 | Adv. |

Input Scan Time

B3-06 selects the microprocessor scan time for reading sequence input data from the control circuit terminals. Set B3-06 to “0” when a quicker response is needed from the control circuit terminal.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|--|--------------------------------|-------|---------------|--------------|
| B3-06 | Cntl Input Scans <i>0 2ms–2 scans</i> <i>1 5ms–2 scans</i> | Selects the terminal scan time | 0-1 | 1 | Adv |

LOC/REM Run Select

If the run reference/speed reference is switched between serial mode and drive terminal mode, B3-07 determines action after the switch.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|---|---|-------|---------------|--------------|
| B3-07 | LOC/REM Run Sel <i>0 Cycle Extrn Run</i> <i>1 Accep Extrn Run</i> | Determines action after switching Run/Speed reference source. If the run command is present at the time when the Run/Speed reference source is switched, it requires the run command to be removed and then reapply the run command from the new source to resume the normal operation. If the run command is present at the time when the Run/Speed reference source is switched, it does not require the run command from the new source to be removed. The normal operation will continue. | 0-1 | 0 | Adv |
| B3-08 | Run Command at Program <i>0 Disabled</i> <i>1 Enabled (B3-02=0 is Disabled)</i> | | 0-1 | 0 | Adv |
| B3-10 | Allow Run at Power UP <i>0 Disabled</i> <i>1 Enabled</i> | | 0-1 | 0 | Adv |
| B4-01 | MOP Ref Memory <i>0 Disabled</i> <i>1 Enabled</i> | Motor operated Pot frequency reference. Enabled when mult. function input = 38, 3D, or 3E. Will memorize previous held frequency after a re-start or power is cycled. | 0-1 | 0 | Adv |

Trim Control Level

The trim control level is valid when the trim control increase command (setting: 45) or trim control decrease command (setting: 46) is set for a multi-function input (H1-01 to H1-06).

If the trim control increase command is ON when a frequency reference is input on the analog input, the trim control level will be added to the analog frequency reference and then that sum will be output as the output frequency. If the trim control decrease command is ON, the frequency reference will be decreased by the trim control level.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|-----------------------|------------------|-------------------------------|--------------|----------------------|---------------------|
| B4-02 | Trim Control LVL | Sets Trim Control speed level | 0–100% | 10 | Adv |

Set the trim control level as a percentage of the maximum output frequency.

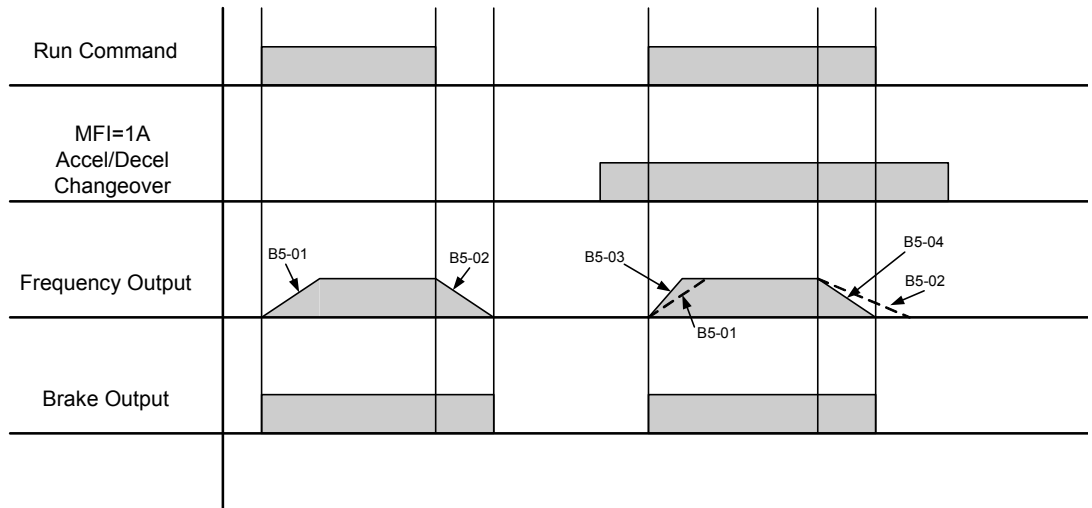
If the frequency reference minus the trim control level is less than zero, the output frequency will be zero.

Acceleration/Deceleration

Acceleration time sets the time necessary for the output frequency to accelerate from 0 Hz to maximum output frequency (E1-04). Deceleration time sets the time necessary for the output frequency to decelerate from the maximum output frequency (E1-04) to 0 Hz.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|--------------|--|----------------|---------------|--------------|
| B5-01* | Accel Time 1 | Sets acceleration time. | 0.0–25.5 sec | 5.0 | Adv |
| B5-02* | Decel Time 1 | Sets deceleration time. | 0.0–25.5 sec | 3.0 | Adv |
| B5-03 | Accel Time 2 | Sets alternate accel. time. Enabled by multifunction input=1A. | 0.0–6000.0 sec | 2.0 | Adv |
| B5-04 | Decel Time 2 | Sets alternate decel. time. Enabled by multi-function input=1A. | 0.0–6000.0 sec | 2.0 | Adv |

* Initial value is determined by X-Press Programming (Table 4.1 to 4.12).



NOTE: Assume the constant B3-03 is set to "0" (Decel to Stop).

Figure 5-5: Normal Accel/Decel Time and Multiple Accel/Decel Changeover

Accel/Decel Time Switching Frequency

Accel/Decel times can be changed automatically without using multi-function inputs. When multi-function contact inputs are set for Accel/Decel selection, this command has priority over automatic change of Accel/Decel.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|---|--|--------------|---------------|--------------|
| B5-05 | Accel Time N Chg | Sets acceleration time at Speed Switch frequency. | 0.0–25.5 sec | 2.0 | Adv |
| B5-06 | Dec Time N Chg | Sets deceleration time at Speed Switch frequency. | 0.0–25.5 sec | 2.0 | Adv |
| B5-08 | Fast Stop Time | Sets deceleration time for complete stop at external fault. See External Response Selection page 5-89. | 0.0–25.5 sec | 0.5 | Adv |
| B5-09 | Acc/Dec Units <i>0 0.01sec for 0.00–2.55 sec</i> <i>1 0.1sec for 0.0–25.5</i> | Determines acceleration and deceleration time interval and range. <i>Note: Setting will not change if any acc/dec time is > 255 sec.</i> | 0-1 | 1 | Adv |
| B5-10 | Acc/Dec SW Freq | Determines acceleration/deceleration switching level | 0.0–150.0Hz | 120.0 | Adv |
| B5-11 | SW Freq Compare <i>0 lower SW Freq</i> <i>1 upper SW Freq</i> | Determines when Acceleration Time and Deceleration Time at Speed Switch Hz is enabled; 0: B5-05/06 is enabled, N-out≤B5-10 1: B5-05/06 is enabled, N-out≥B5-10 | 0-1 | 1 | Adv |
| B5-12 | Accel Time 3 | Acceleration time when H1-01 to H1-06 = 1B | 0.0-6000.0 | 3.0 | Adv |
| B5-13 | Decel Time 3 | Deceleration time when H1-01 to H1-06 = 1B | 0.0-6000.0 | 3.0 | Adv |
| B5-14 | Accel Time 4 | Acceleration time when H1-01 to H1-06 = 1C | 0.0-6000.0 | 3.0 | Adv |
| B5-15 | Decel Time 4 | Deceleration time when H1-01 to H1-06 = 1C | 0.0-6000.0 | 3.0 | Adv |

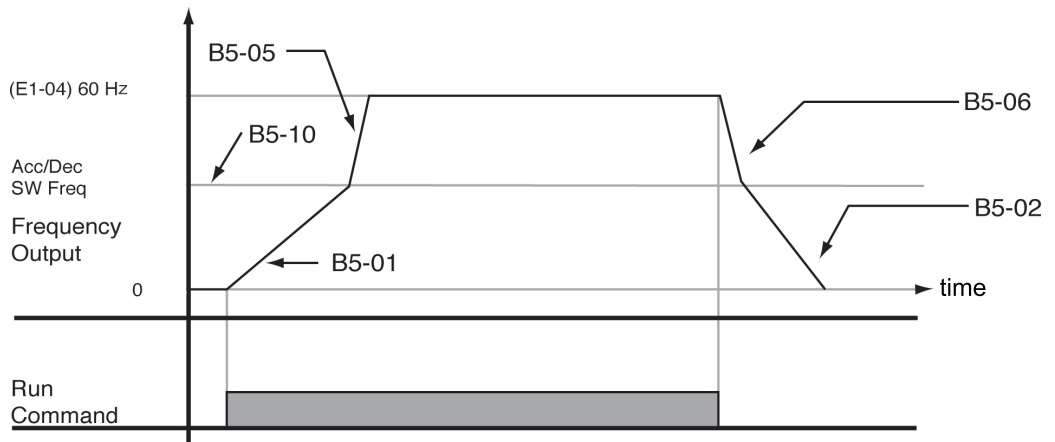


Figure 5-6: When B5-11=1 (Upper Switch Frequency)

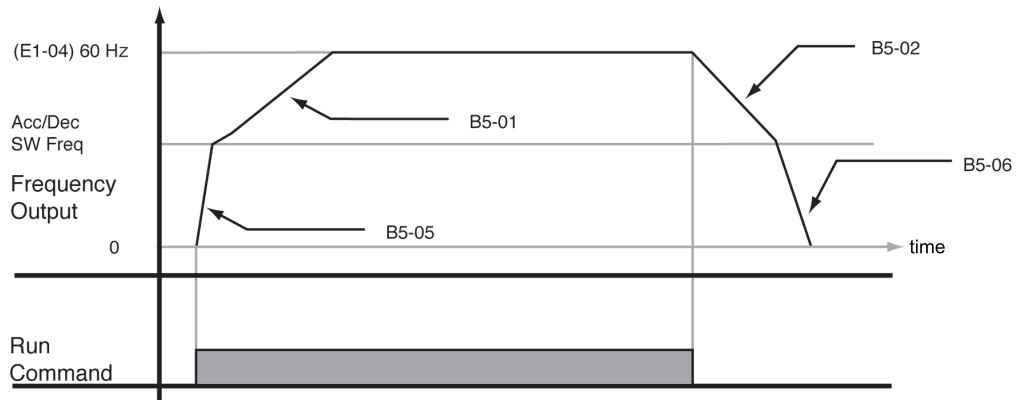


Figure 5-7: B5-11=0 (Lower Switch Frequency)

Speed Search

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|--------------|---------------------------------------|--------------|---------------|--------------|
| B6-05 | Search Delay | Delay timer for speed search at start | 0.0-20.0 sec | 0.2 | Adv |

Jump Frequencies

This function allows the “jumping” of critical frequencies so that the motor can operate without resonant vibrations caused by some machine systems. This function is also used for deadband control. Setting the value to 0.0 Hz disables this function.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|----------------|-------------------------------------|--------------|---------------|--------------|
| B8-01 | Jump Freq 1 | First of three jump frequencies. | 0.0–150.0 Hz | 0.0 | Adv |
| B8-02 | Jump Freq 2 | Second of three jump frequencies. | 0.0–150.0 Hz | 0.0 | Adv |
| B8-03 | Jump Freq 3 | Third of three jump frequencies. | 0.0–150.0 Hz | 0.0 | Adv |
| B8-04 | Jump Bandwidth | Jump frequency reference bandwidth. | 0.0–20.0 Hz | 1.0 | Adv |

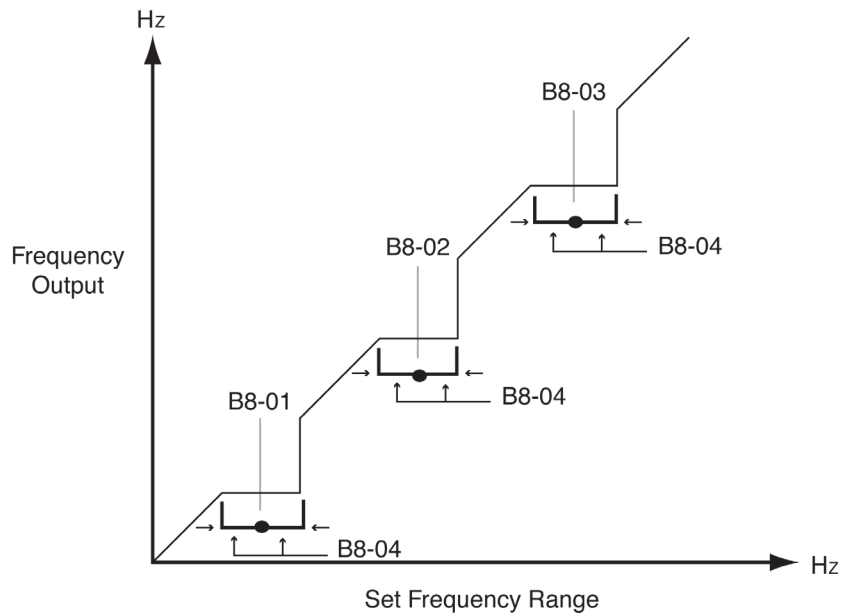


Figure 5-8: Jump Frequencies

Special Functions

- C1 Quick Stop/Reverse Plug Simulation
- C2 Micro-Positioning Control Multiplier
- C3 End of Travel Limit
- C4 Load Float
- C5 Load Check
- C6 Ultra-Lift
- C7 Torque Limit
- C8 No Load Brake
- C9 G5IN4 Setup
- C10 Weight Measurement
- C11 Slack Cable Detection
- C12 Delay Timers
- C13 Inching/Indexing Control

| Special Function | Motion (A1-03) | |
|--|--------------------|-------------------------|
| | Traverse (A1-03=0) | No-Load Brake (A1-03=2) |
| C1: Quick Stop/Reverse Plug Simulation | Yes | Yes |
| C2: Micro Positioning | Yes | Yes |
| C3: End of Travel Limits | Yes | Yes |
| C4: Load Float | Yes | Yes |
| C5: Load Check | No | Yes |
| C6: Ultra Lift | No | Yes |
| C7: Torque Limit | Yes | Yes |
| C8: No-Load Brake Hoist | No | Yes |
| C9: G5IN4 Setup | Yes | Yes |
| C10: Weight Measurement | No | Yes |
| C11: Slack Cable Detection | No | Yes |
| C12: Delay Timers | Yes | No |
| C13: Inching Control | Yes | Yes |
| C13: Index Control | Yes | Yes |

Quick Stop™/Reverse Plug Simulation™

The **Quick Stop Function** provides an automatic Alternate Deceleration at Stop Command.

NOTE: The Quick Stop Deceleration time differs from the normal deceleration time and is applied only when the RUN command is removed.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|---|---|--------------|---------------|--------------|
| C1-01* | Quick Stop 0/1 0 Disabled 1 Enabled | Determines whether Quick Stop is enabled | 0-1 | 1 | Adv |
| C1-02 | Quick Stop Time | Deceleration time during Quick Stop function. | 0.0–25.5 sec | 1.0 | Adv |

* Initial value is determined by X-Press Programming (Table 4.1 to 4.2).

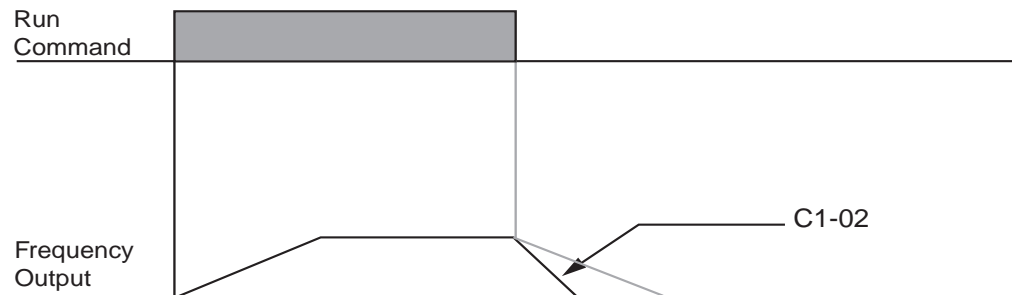


Figure 5-9: Quick Stop

The **Reverse Plug Simulation** provides an automatic alternate deceleration time/acceleration time at a change direction command. The deceleration time and the acceleration time are set independently of the normal acceleration and deceleration times.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|------------------|--|--------------|---------------|--------------|
| C1-03 | Reverse Plug 0/1 | Determines whether Reverse Plug Simulation is enabled. | 0-1 | 0 | Adv |
| | 0 Disabled | | | | |
| | 1 Enabled | | | | |
| C1-04 | Rev-Plg Dec Time | Deceleration time during Reverse Plug Simulation. | 0.0–25.5 sec | 2.0 | Adv |
| C1-05 | Rev-Plg Acc Time | Acceleration time during Reverse Plug Simulation | 0.0–25.5 sec | 2.0 | Adv |

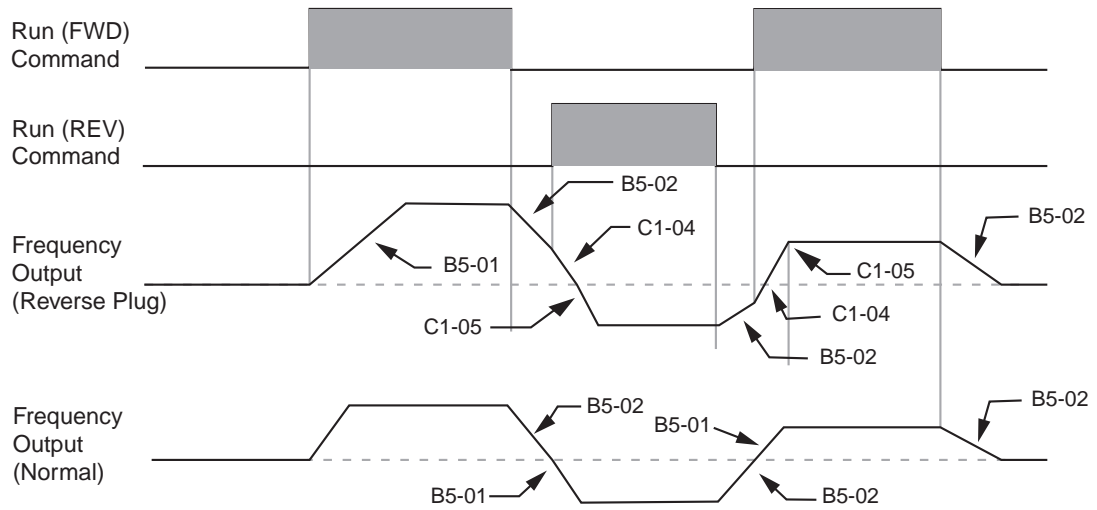


Figure 5-10: Reverse Plug Simulation

Micro-Positioning Control™

Micro-Positioning Control function can provide a reduced speed range operation for precise positioning. Enabled by a Multi-Function Input, it multiplies the normal speed reference by the Micro-Speed Gain. Two Micro-Speed Gains are available: Gain 1 (C2-01) and Gain 2 (C2-02). They can be adjusted and enabled independently.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|-----------------|---|-----------|---------------|--------------|
| C2-01 | MicroSpd Gain 1 | The multiplier of the Analog or Digital Speed Reference to achieve slow-speed operation. Multi function Input = E | 0.00–2.55 | 1.00 | Adv |
| C2-02 | MicroSpd Gain 2 | An alternate multiplier of the Analog or Digital Speed Reference to achieve slow-speed operation. Multi function Input = 10 | 0.00–2.55 | 1.00 | Adv |

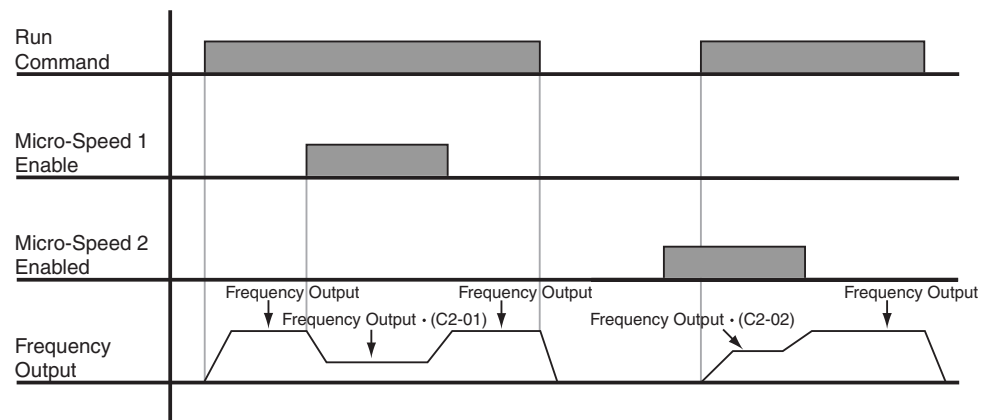


Figure 5-11: Micro-Positioning Control

NOTE: If both Micro-Speed 1 and Micro-Speed 2 are enabled, Micro-Speed 1 always takes higher priority over Micro-Speed 2.

Travel Limits

This function can automatically slow and stop a crane or hoist when it reaches the end of travel limits. Two types of limit inputs (slowdown and stop) are available in both travel directions. Inputs can be programmed through either the GIF7 or the G5IN4 card.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|---|--|--------------|---------------|--------------|
| C3-01 | Up Limit 1 Speed | Speed at Upper Limit input. | 0–400 Hz | 6.00 | Adv |
| C3-02 | UL 1 Decel Time | Decel time to Upper Limit Speed. | 0.0–25.5 sec | 1.0 | Adv |
| C3-03 | UL 2 Stop Time | Decel time to STOP when Upper Limit is Input. | 0.0–25.5 sec | 1.0 | Adv |
| C3-04 | Low Limit 1 Speed | Speed at Lower Limit input. | 0–400 Hz | 6.00 | Adv |
| C3-05 | LL 1 Decel Time | Decel time to Lower Limit Speed | 0.0–25.5 sec | 1.0 | Adv |
| C3-06 | LL 2 Stop Time | Decel time to STOP when Lower Limit is input. | 0.0–25.5 sec | 1.0 | Adv |
| C3-07* | Lmt Stop Method | Determine the stop method at Upper Limit 2 and Lower Limit 2 Input. | 0-2 | 2* | Adv |
| | 0 Decel to Stop | | | | |
| | 1 Coast to Stop | | | | |
| | 2 Use B3-03 Method | | | | |
| C3-08 | UL3 Stop Method | Weight Limit Stop Method and action when Multi Function Input = 12 or 62 | 0-5 | 4 | Adv |
| | 0 Decel/Alarm (no further raise allowed) | | | | |
| | 1 Coast/Alarm (no further raise allowed) | | | | |
| | 2 Use B3-03 /Alarm (no further raise allowed) | | | | |
| | 3 Decel/Fault | | | | |
| | 4 Coast/Fault | | | | |
| | 5 Use B3-03/Fault | | | | |
| | Note: For setting 0, 2, 3, 5, deceleration is by B5-08. | | | | |
| C3-09 | Phantom Stop Method | Stopping Method when Multi Function Input = 5F and 63 | 0-2 | 1 | Adv |
| | 0 Decel to Stop | | | | |
| | 1 Coast to Stop | | | | |
| | 2 Use B3-03 Method | | | | |
| C3-10 | Load Share Lim | Load Share enable/disable | 0-1 | 0 | Adv |
| C3-11 | Klixon Action | | 0-1 | 0 | Adv |
| | 0 Use B3-03 method | | | | |
| | 1 Allow Lower only | | | | |

* Initial value is determined by X-Press Programming

Electronic Programmable Limit Switches

Using a stored height measurement (U1-50, U1-51), it is possible to program UL1, UL2, LL1, and LL2 functions without the use of rotary limit switches. When C3-12 or C3-13 or C3-14 or C3-15 has a value other than 0, the Electronic Limit Switch function will be enabled, and it will use the logic in the table below. Height Measurement must be correctly set up before using EPLS.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|-----------------|----------|-------------|---------------|--------------|
| C3-12 | UL2 Revolutions | | 0-65535 Rev | 0 | Adv |
| C3-13 | UL1 Revolutions | | 0-65535 Rev | 0 | Adv |
| C3-14 | LL1 Revolutions | | 0-65535 Rev | 0 | Adv |
| C3-15 | LL2 Revolutions | | 0-65535 Rev | 0 | Adv |

OPE26: Limit Sw/C8-24 — (C8-24 = 0 or 1) AND (C3-13 or C3-15 not equal to 0): Can't use UL2 or LL2 to home Height Measurement when using Height Measurement for limit switch operations. UL1 and LL1 can be used.

F5-0x, H2-0x =

- 2BH - Upper Limit 1 - Output ON when keypad displays UL1
- 2CH - Upper Limit 2 - Output ON when keypad displays UL2
- 2DH - Lower Limit 1 - Output ON when keypad displays LL1
- 2EH - Lower Limit 2 - Output ON when keypad displays LL2

NOTE: MFDO 2BH - 2EH work with MFDI 6H - BH or EPLS.

Example: Limit Switch Revolution Settings (C8-21 = 250 Rev)

| C8-24 Home Option | C8-25 Home = 0% or 100% | C3-12 UL2 | C3-13 UL1 | C3-14 LL1 | C3-15 LL2 | Remark |
|-------------------|-------------------------|----------------------------|----------------------------|----------------------------|----------------------------|--------|
| 2 | 0 | 20 Rev (U1-51 ≤ C3-12) | 55 Rev (U1-51 ≤ C3-13) | 220 Rev (U1-51 ≤ C3-14) | 240 Rev (U1-51 ≤ C3-15) | |
| | 1 | 240 Rev (U1-51 ≥ C3-12) | 220 Rev (U1-51 ≥ C3-13) | 55 Rev (U1-51 ≥ C3-14) | 20 Rev (U1-51 ≥ C3-15) | |
| 3 | 0 | 20 Rev (U1-51 ≤ C3-12) | 20 Rev (U1-51 ≤ C3-12) | 20 Rev (U1-51 ≤ C3-12) | 20 Rev (U1-51 ≤ C3-12) | |
| | 1 | 20 Rev (U1-51 ≤ C3-12) | 20 Rev (U1-51 ≤ C3-12) | 20 Rev (U1-51 ≤ C3-12) | 20 Rev (U1-51 ≤ C3-12) | |

** Please consult the factory for additional information on Height Measurement and Electronic Programmable Limit Switches*

Lower Limit 2/Upper Limit 2 Bypass MFDI 73H

C9-0x, H1-0x = 73H “LL2/UL2 Bypass”: bypasses LL2 and UL2. When input is ON, the following are bypassed:

- MFDI 7H (Upper Limit 2 N.O.)
- MFDI BH (Upper Limit N.C.)
- MFDI 9H (Lower Limit 2 N.O.)
- MFDI DH (Lower Limit 2 N.C.)
- UL2 detected by Electronic Limit Switch (C3-12)
- LL2 detected by Electronic Limit Switch (C3-15)

The intent of this “bypass” MFDI is two-fold. It allows for the following without the use of jumpers or re-programming of the drive parameters:

1. Ease of testing of the Weighted Upper Limit Switch (UL3) (or possibly re-homing Height Measurement function)
2. To allow changing of the wire ropes (spooling all the rope off of the hoist drum)

NOTE: The momentary key-switch to operate this function should only be accessible to maintenance personnel, not the crane operator. A functional description and usage procedure should be included in an administrative control program to avoid confusion and potentially have the End of Travel Limit switches left in a bypassed state during normal operation of the crane.

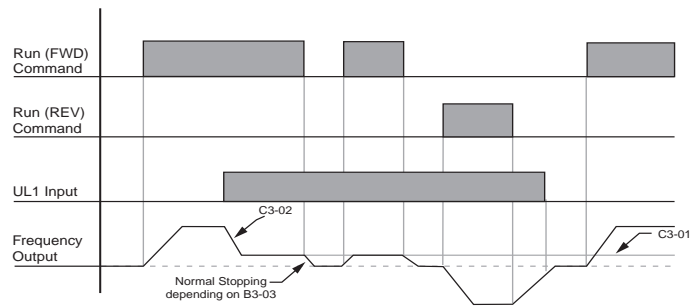


Figure 5-12: Upper Limit (UL1)

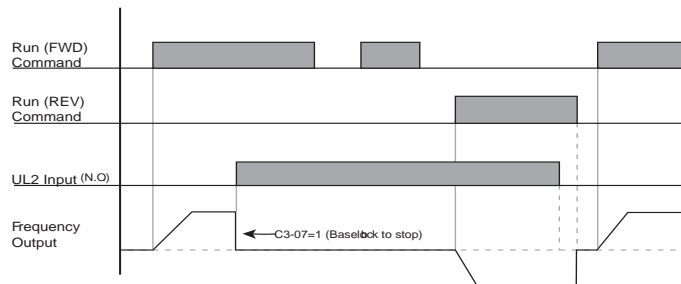


Figure 5-13: Upper Limit 2 (UL2)

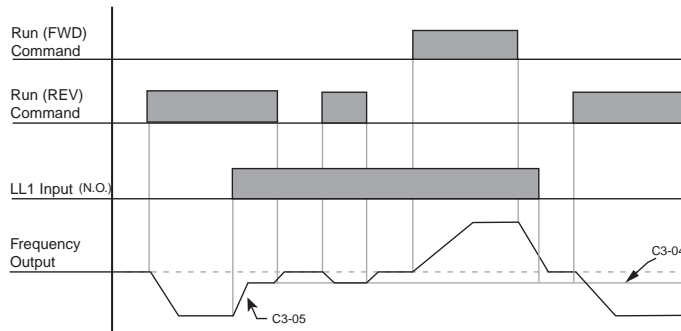


Figure 5-14: Lower Limit 1 (LL1)

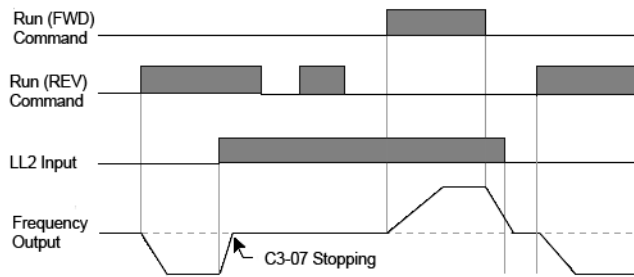


Figure 5-15: Lower Limit 2 (LL2)

Load Sharing/Torque Following—2 or more mechanically coupled motors

The VG+ Series 3 Software allows one or more Impulse VG+ Series 3 driven motors to be connected in a Master/Slave fashion such that slave inverter will follow the torque reference of the master inverter. It can be configured in two ways, either as a dedicated Slave or as a Master/Slave that can be switched on or off by multi-function input. When it is in Load Share Mode (Slave), it is essentially nothing more than a torque helper to the master motor. The Master Inverter outputs the commanded amount of torque from a ± 10 VDC analog signal into the Slave inverter, which correlates directly to the direction and quantity of torque the slave inverter should apply to its own motor. This can be particularly useful when two or more motors are driving a common load (i.e. single drum, gear box, etc.) and it is important that they share the load. This will allow one inverter/motor to handle the speed reference and speed regulation while the others simply “help” the master. This overcomes inherent problems with having more than one inverter/motor trying to regulate speed on a common load. The Load Sharing function can be used when the master is configured for Hoist or Traverse motions (i.e. for a hoist motion, two or more motors coupled to a single gearbox.) For a traverse motion, a circular crane, multiple motors driving a single end truck, cable reel, etc. **Note:** The master drive can be of an Impulse VG+ Series 1, 2 or 3 generation.

When using Multi-function input H1-0x = “66”—Load Share 0/1 (Torque Following mode), setting C3-10 = **Enabled** will allow the inverter to accept the Limit Switch inputs where H1-0x = 6 ~ D. When C3-10 = **Disabled** (Factory Default), the Slave inverter will ignore any change in state of the Limit switch inputs. The setting of this parameter is only in effect when the Multi-function input H1-0x = “66” Load Share 0/1 is **ON**. It is important to understand that when in a Load Sharing mode, the Slave inverter is only supplying torque to “help” the Master inverter. The master inverter generally handles the logic of limit switches or other special functions. If this is not the case, each inverter may try to move or decelerate at a different speed placing extra strain on the drive train and potentially resulting in a speed deviation fault.

Notes:

1. The Limit Switch stopping method is not selectable in Load Sharing mode. If a Stop Limit is input, the output is turned off and the brake output will set immediately.
2. Weight Limit Input (12, 62) — Upper Limit 3 is always active regardless of the setting of parameter C3-10.

Minimum Programming Requirement for “Load Sharing” Operation

1. The **Master** and **Slave** drives must be programmed for the Flux Vector control method, A1-02 = 3.
2. The **Slave** drive requires a Multi-function Digital Input programmed for 66 — ‘Load Share 0/1’
3. The **Slave** drive requires a ± 10 VDC Multi-function Analog Input programmed for 13 — ‘Torque Reference’.
4. The output gain should be = 50%.
5. The **Master** drive requires a Multi-function Digital Output programmed for 2A — ‘During Run 1’.
6. The **Master** drive requires a ± 10 VDC Multi-function Analog Output programmed for 9 — ‘Torque Reference’.
7. The input gain should be = 200%.
8. The digital operator must not be in LOCAL mode.

Load Float Time 2

When Load Float (C8-10) is enabled, it maintains the motor shaft at a stationary position. Load Float Time 2 is enabled by a MFI (Multi-Function Input) that is programmed as the digital input data 35 (H1-01~06=35). If load float is being used, this time (C4-01) will be added to the standard load float time (C8-10).

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|-------------------|--|-----------|---------------|--------------|
| C4-01 | Load Float Time 2 | Maximum duration of Load Float action at multi-function input. Data = 35 | 0–255 sec | 10 | Adv |
| C4-02 | Load Float Gain | Load Float Gain. | 0–100 | * | Adv |
| C4-03 | Load Float Count | Load Float completion width. Enables Multi Function output = 25 | 0–16383 | 10 | Adv |

* 10/20 depending on drive size

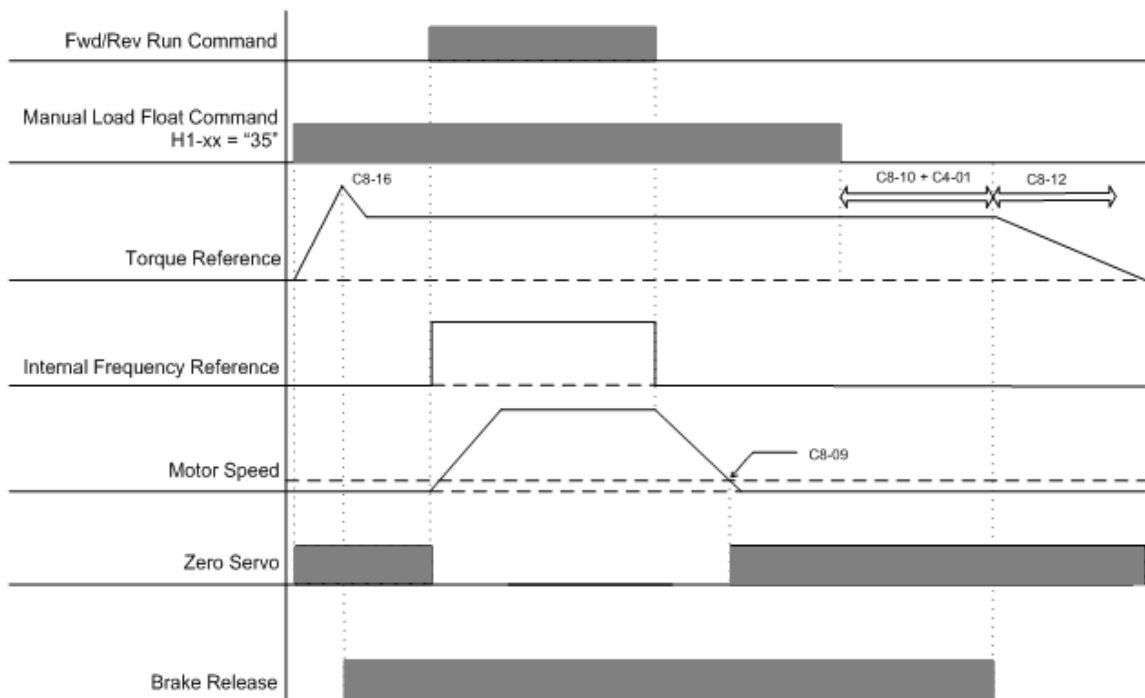


Figure 5-16: Load Float Time 2

Load Check™

Load Check function is a load-limiting feature that ensures the programmed load limit of the hoist is not exceeded. It prevents the lifting (and potential loss) of a load that is overweight. When IMPULSE•VG+ Series 3 detects an overload condition, it prevents any further rising. However, the load can be lowered at the speed that is specified by constant C5-14 (Load Check Fault speeds).

NOTE: Precautions should be taken when using load check where two or more hoists are used to lift a single load.

Example: Use a normally closed relay from the load check output to break the raise (FWD Run) command to the other hoist(s). This will insure that all hoists stop lifting if one hoist is being overloaded. Ensure that C5-02 = 3 to prevent uneven lowering or design lowering logic accordingly.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|---|---|---------------|---------------|--------------|
| C5-01 | Load Check 0/1 0 Disabled 1 Enabled | Determines whether Load Check is enabled. | 0-1 | 0 | Adv |
| C5-02 | LC Alarm Action 0 Alarm Only 1 Decel to Stop 2 Coast to Stop 3 Fault Stop 4 Use B3-03 Method (allows Lower only) | Action at Load Check alarm or fault. L.C. blinking, can continue raising Allows lower only Allows lower only Fault contacts change state - requires reset | 0-4 | 4 | Adv |
| C5-03 | Min Torque Ref | Minimum current/torque reference during acceleration that triggers Load Check. | 0–100% | 60 | Adv |
| C5-04 | Look Speed 1 | First Load Check frequency reference. | 0–150 Hz | 6 | Adv |
| C5-05 | I/T Ref for LS 1 | Torque Reference at Look Speed 1 | 1-300% | 160 | Adv |
| C5-07 | Look Speed 2 | Second Load Check frequency reference. | 0–150 Hz | 20 | Adv |
| C5-08 | I/T Ref for LS 2 | Torque Reference at Look Speed 2 | 1-300% | 160 | Adv |
| C5-09 | Look Speed 3 | Third Load Check frequency reference. | 0–150 Hz | 40 | Adv |
| C5-10 | I/T Ref for LS 3 | Torque Reference at Look Speed 3 | 1-300% | 160 | Adv |
| C5-11 | I/T Ref for > LS 3 | Load Check Current when Output Frequency > Look Speed 3. | 1-300% | 160 | Adv |
| C5-12 | LC Holding Time | Time for holding Output Frequency to stabilize Output Current. | 0.00–2.55 sec | 1.00 | Adv |
| C5-13 | LC Testing Time | Time (after the LC Setting Time) for comparing Output Current with Reference Current | 0.00–2.55 sec | 0.25 | Adv |
| C5-14 | LC Fault Speed | Maximum lowering speed after Load Check fault | 0–30 Hz | 6.0 | Adv |

Ultra-Lift™

Ultra-Lift provides additional productivity by allowing a crane or hoist to quickly move into position. The feature enables the motor to over speed when the load is less than 100 percent of the rated capacity. Ultra-Lift determines the torque required for the load, calculates the maximum safe speed, and automatically accelerates to this speed. However, the maximum speed cannot exceed the lesser value of the Ultra-Lift Maximum Output Frequency-RAISE (C6-02), Ultra-Lift Maximum Output Frequency-LOWER (C6-03), and Maximum Frequency (E1-04).

NOTE: Note: Ultra-Lift is disabled when in traverse applications. Maximum Frequency (E1-04) must be \geq C6-02 and C6-03.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|--|--|--------------|---------------|--------------|
| C6-01 | Ultra Lift 0/1 0 Disabled 1 Enabled Automatic 2 Enabled by MFI = 13 | Determines whether Ultra Lift is enabled. | 0-2 | 0 | Adv |
| C6-02 | Ultra Lift ForSpd | Maximum Output Frequency during Ultra Lift—FORWARD. | 0–150 Hz | 60 | Adv |
| C6-03 | Ultra Lift RevSpd | Maximum Output Frequency during Ultra Lift—REVERSE. | 0–150 Hz | 60 | Adv |
| C6-04 | UL Fwd torque | Maximum output torque below which Ultra Lift—FORWARD is enabled. | 0–100% | 50 | Adv |
| C6-05 | UL Rev Torque | Maximum output torque below which Ultra Lift REVERSE is enabled. | 0–100% | 30 | Adv |
| C6-06 | UL Enabling Spd | Threshold frequency at which Ultra Lift is enabled. | 0–150 Hz | 59.0 | Adv |
| C6-07 | UL Delay Time | Delay time at enabling speed prior to torque-compare function. | 0.0–25.5 sec | 2.0 | Adv |
| C6-08 | SFS Acc Gain | Speed feedback acceleration multiplier. | 0.1–9.9 | 1.0 | Adv |
| C6-09 | Normal OS Level | Overspeed level when not in Ultra Lift mode | 40-150 Hz | 60 | Adv |

Enable Ultra-Lift Function:

2, 3, 5-Speed Multi-Step (A1-04=0, 1, or 2):

1. Set C6-01=1 or 2 to enable the **Ultra-Lift Function**, 1= Enable Automatic, 2= Enable by Multi-Function Input (MFI).
2. Set C6-02 and C6-03 to determine **Ultra-Lift** maximum FWD/REV output frequency.
3. Set C6-04 and C6-05 to determine **Ultra-Lift** maximum enable output current.
4. Set the **Ultra-Lift Enabling Speed (C6-06)** one or two hertz below the maximum normal running speed reference.

For example: If the maximum normal running speed is at 60 Hz, set C6-06 to 59 Hz or 58 Hz as the **Ultra-Lift Enabling Speed**.

5. Ensure that the **Maximum Frequency (E1-04)** is increased from 60 Hz.

2, 3 Step Infinitely Variable (A1-04=3 or 4)

1. If the system is using **2-Step** or **3-Step Infinitely Variable** as the **Speed Control Method**, the following formula is used to adjust the constant **B2-01 (Reference Upper Limit)**.

$$B2-01=60 \text{ Hz} \times 100 / E1-04$$

Uni-Polar/Bi-Polar Analog (A1-04=5 or 6)

1. If the system is using **Bi-Polar Analog** or **Uni-Polar Analog** as the **Speed Control Method**, the following formula is used to adjust the constant **H3-02 (Gain Multiplier for Terminal A1 analog input signal)**, **H3-10 (Gain Multiplier for Terminal A2 analog input signal)**.

$$H3-02=60 \text{ Hz} \times 100 / E1-04 \text{ or } H3-10=60 \text{ Hz} \times 100/E1-04$$



WARNING

Motors and drive machinery must be capable of operating above motor base speed. Consult the motor/gearbox/hoist manufacturer before enabling Ultra Lift function. Failure to observe this warning may result in damage to equipment and possible injury or death to personnel.

Torque Limit

IMPULSE•VG+ Series 3 dynamically controls the torque output of the motor at all times. The Torque Limit Function limits the amount of motor torque on all four quadrants of vector control operation:

- *Forward Motoring*
- *Reverse Motoring*
- *Forward Regenerating*
- *Reverse Regenerating*

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|--------------------|---|---------|---------------|--------------|
| C7-01 | Torq Limit Fwd | FORWARD torque limit | 0–300% | 150 | Adv |
| C7-02 | Torq Limit Rev | REVERSE torque limit | 0–300% | 150 | Adv |
| C7-03 | Torq Lmt Fwd Rgn | Regenerative torque limit at FORWARD | 0–300% | 180 | Adv |
| C7-04 | Torq Limit Rev Rgn | Regenerative torque limit at REVERSE | 0–300% | 180 | Adv |
| C7-05 | Torq Limit Gain | Used when H1-01~H1-06 = 14 and MFI is on | 0–2.55 | 1.25 | Adv |
| C7-08 | Trav Trq Limiter | Disables regen torque when motor frequency is within C7-09 of frequency reference. 0: Disabled 1: Enabled | 0–1 | 0 | Adv |
| C7-09 | Limiter Freq | Windows size around frequency reference where regen torque is disabled | 0.50–10 | 2.0 | Adv |

Trav Trq Limiter

This function is used in multi-drive, closed-loop traverse applications to reduce drive fighting due to speed discrepancies between the two sides of a bridge. This resolves the situation where one side of a bridge will be at full forward torque, while the other side is a full regen torque. When moving below the Limiter Freq (C7-09) this feature is disabled and the drive behaves as normal. When accelerating past the Limiter Freq, the ASR I time is reduced to zero to limit torque imbalance. Once the motor has accelerated to within the Limiter Freq (i.e. 60 Hz - C7-09) the regen torque limit also goes to zero. The drive will remain in this state until the speed reference is changed. When the speed reference is raised or lowered, regen torque is re-enabled to accel or decel the bridge as required.

Note that a heavy swinging load may pull the bridge faster than the PG Overspeed level. It is therefore highly suggested that a PG Overspeed Sel (F1-03) be set to Alarm Only.

No-Load Brake Start/Stop

The No-Load Brake Hoist mode provides a special start/stop sequence designed specifically for No-Load Brake Hoists. This mode is enabled automatically when the Motion is set to NLB Hoist (A1-03=2). This will also automatically set the Stopping Method to No-Load Brake (B3-03 = 6).

The NLB Sequence is comprised of a series of Timers and Counters that monitor certain feedback devices. The sequence is divided into two parts, NLB Start and NLB Stop.

The NLB Start Sequence begins by building up torque in the motor to a predefined level within the C8-01 (Torque Compensation Time) timer. This level is determined by several factors which are defined below. During the C8-01 time, the drive is monitoring current to motor. The internal current feedback equation must be satisfied within the time set in C8-02 (IFB OK Time). If it is not, a BE2 (No-Current) alarm will be displayed on the keypad and the drive will stop outputting voltage to the motor. The brake will remain closed.

Factor 1: On the first run command after power up, or after any major fault which causes the NLB Stop sequence to be skipped, the NLB Start sequence by default looks at the value programmed in C8-16, the Initial Brake Release torque.

Factor 2: Once the system has completed a successful NLB Start and NLB Stop, a new value is used. This value is one that has been memorized and stored into memory during the NLB Stop Sequence. It is equivalent to the amount of torque required for the motor to hold the load that is on the hook in Load Float with the brake released. Some benefits of memorized Load Float torque for the next brake release are:

- *Faster response to run commands when drive is in Base Block Status.*
- *Upon brake release, shaft rotation begins in the direction of the run command.*

If the memorized value is less than the programmed value in C8-03 (Minimum Brake Release torque), then C8-03 is used as the next brake release value. If the feature must be disabled, C8-03 will override C8-16 if it is a greater value than C8-16.

Once the brake has been commanded to release, the output remains in Load Float for the amount of time programmed into C8-04. During C8-04, the drive waits for the brake to completely open and watches encoder feedback. If the amount of feedback is less than the setting in C8-05 (Roll Back Count), then the drive proceeds to the BE3 check. If it is not, a BE1 alarm is displayed on the keypad and the sequence stops. For the BE3 check, if the brake opened mechanically, then the encoder feedback must be greater than or equal to the value programmed in C8-07 (BE3 Detect Count) within the time set in C8-06 (BE3/Alternate Torque Time). If it is not, then BE3 is displayed. By the time the drive has completed the BE3 check, there should be a significant amount of motor shaft movement and the NLB start sequence is complete.


The NLB Stop Sequence begins when the run command has been removed and the output frequency has decelerated to zero. Once at zero speed, the motor maintains a Load Float position for the duration of C8-10 (Load Float Time). During the Load Float time, run commands in either direction are accepted and will begin accelerating immediately in the commanded direction, thereby skipping the NLB Start Sequence entirely. The Load Float Timer is reset after each new run command. Once the Load Float Timer expires, the brake output command is removed (thereby closing the brake) and Load Float is maintained for the time set in C8-11 (Brake Delay Time) to allow the brake to fully close. Once the Brake Delay Time has expired, the BE6 check is executed. The BE6 check monitors encoder feedback and compares it to C8-13 (BE6 Max count). The encoder feedback must not exceed the number of counts in C8-13 within the C8-12 (BE6 Detect Timer) time. If it does (meaning the load slipped through the brake), a BE6 alarm is displayed on the keypad and the drive will reset its Load Float position and maintain its new position. Run commands will still be accepted with the exception of a reduced speed in the up direction set by C8-17 (BE6 Up speed) and the NLB stop sequence will begin again once the run command had been removed.

NOTE: All brake faults are annunciated by both the keypad, and via a programmed digital output. Since the keypad is not visible by the operator, an external warning device must be used to ensure proper safety of personnel and equipment. Annunciating a brake fault can be accomplished by using one, or both, of the following methods: 1) An indicator or strobe light

that is continuously “ON”, indicating proper operation. If the light should turn “OFF”, this indicates that the light bulb has either burned out, or there is a drive or brake problem. Either scenario requires immediate corrective action. 2) The use of an indicating light wired to relay output terminals MC-MB, an N/C contact, or an audible warning device that will sound during a brake fault condition. A 120 VAC audible warning device can be wired directly to terminals MC-MA, provided that its ratings do not exceed the 1 Amp, 120 VAC, Inductive.

If a brake fault is annunciated during a “Start” sequence, it is recommended that the crane be moved to a safe location with the load on the hook. The hoist should only be operated if absolutely necessary. In this type of alarm sequence, either the brake is seized or the drive cannot develop enough torque in the motor in the time allotted. To troubleshoot the hoist it will be necessary to monitor the keypad on the drive and operate the hoist at the same time. Two people are recommended for this procedure. With one person operating the hoist and the other person monitoring the keypad, run the hoist. The keypad should display one of the following alarms: BE1, BE2, BE3, or BE4. For corrective action, refer to “Troubleshooting the Drive” in Chapter 6 of this manual.

If a brake fault is annunciated after the hoist has come to a complete stop, and Load Float (C8-10) has timed out, it would indicate that the drive has checked the brake and determined that the brake has insufficient torque available to hold the load. **DO NOT TURN OFF POWER.** This condition indicates that the brake has failed and the drive / motor combination is suspending the load. If, during this condition, the hoist is operated in the “Raise” direction, it will only be allowed to run at a speed equal to or less than the “BE6 Up Speed” setting in parameter C8-17 (C8-17 is 6 Hz by default.) This is an additional indication that the brake has failed open, or the load is slipping through the brake. It is recommended that the crane be moved to a safe location and the load lowered to the ground. Corrective action should be taken to repair the brake. The keypad will be displaying one of two alarms during this condition: BE5 or BE6. Refer to “Troubleshooting the Drive” in Chapter 6 of this manual.



WARNING

DO NOT turn off power to the drive during a BE6 alarm. This may result in loss of control of the load if the brake has failed in the open position or is unable to hold the load.

To enable BE6 detection, C8-12 must be greater than 0.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|------------------|--|---------------|---------------|--------------|
| C8-01 | Torque Comp Time | Time for torque to build to 300% at start. | 0.00–2.55 sec | *1.0/1.5 | Adv |
| C8-02 | IFB OK Timer | Sets the amount of time to look for the current feedback to be OK before posting a BE2 alarm. Setting this parameter to 0 (Zero) will disable torque proving at start & eliminate BE2 detection (Not recommended). | 0.00–2.55 sec | *1.0/1.5 | Adv |
| C8-03 | Min Brk Rel Torq | Minimum brake release torque. | 0–300% | 10 | Adv |

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|-------------------|---|----------------|---------------|--------------|
| C8-04 | Roll Back Timer | Sets the amount of time for the brake to release and for brake feedback to be received into the Brake Answer Back Multi-Function input at start before posting BE4 alarm. It is also the time period during which the amount of roll back is checked. | 0.00–2.55 sec | 0.30 | Adv |
| C8-05 | Roll Back Count | Detection counts for excessive roll back. | 0–16536 pulses | 800 | Adv |
| C8-06 | BE3/Alt Torq Tim | Time period during which C8-07 is measured. Also see C8-08. | 0.00–2.55 sec | 0.30 | Adv |
| C8-07 | BE3 Detect Count | Detection count for Encoder/ Seized-Brake Alarm (BE3). It is the minimum encoder pulse count, during the time period of C8-06, below which the BE3 alarm is triggered. | 0–16536 pulses | 10 | Adv |
| C8-08 | Alt Rev Torq Lim | For a LOWER command in the NLB Hoist Motion Mode only—Torque limit for time of C8-06 to prevent driving through a brake that has failed closed with a load on the hook. | 0–100% | 25 | Adv |
| C8-09 | Zero Speed Level | Determines speed feedback at which Load Float activates. | 0–10 Hz | 1 | Adv |
| C8-10 | Load Float Time | After stop command time period during which the load is held at the zero-position and the electric brake is not set. | 0-255 sec | 10 | Adv |
| C8-11 | Brake Set Delay | Sets the amount of time for the brake to set and for brake feedback to be removed from the Brake Answer Back Multi-Function input at stop before posting a BE5 Alarm. | 0.0–25.5 sec | 0.7 | Adv |
| C8-12 | BE6 Detect Timer | Time period during which the electric brake is set and tested for sustaining the load. NOTE: To disable BE6 detection, set C8-12 to 0.0. | 0.0–25.5 sec | 5.0 | Adv |
| C8-13 | BE6 Max Count | Total pulse counts must be less than C8-13, during C8-12, otherwise BE6 alarm. | 0–16536 pulses | 250 | Adv |
| C8-14 | Brake Hold Speed | Sets the output frequency in the forward direction during IFB OK time. This is used to remove backlash between the motor and the brake. <i>Note: to disable this feature, set C8-14 to 0.0</i> | 0.0–25.5% | 0.0 | Adv |
| C8-15 | Load Float Ext. T | Load Float extension time enabled by MFI=5D. | 0–255 sec | 10 | Adv |
| C8-16 | Init Brk Rel Trq | Brake release torque at power up and after UL2, LL2, EF faults or MFI's which cause the output to base block. | 0-300% | 100 | Adv |
| C8-17 | BE6 Up Speed | Maximum up speed after BE6 is detected. | 0.00–150.00 Hz | 6.00 | Adv |
| C8-19 | Brake Test Torq | Motor will push against brake in FWD direction at C8-20 speed when input by MFI=61 | 0-300% | 125 | Adv |

*Depends on drive size

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|-----------------------|--|--|--------------|----------------------|---------------------|
| C8-20 | Brake Test Speed | Speed to push against brake while testing | 0-10 Hz | 6 | Adv |
| C8-21 | Height Measure | Number of motor revolutions from UL2 to lowest hook position | 0-65535 | 10000 | Adv |
| C8-24 | Hook Height Home <i>0 Home = UL2 (Home by Upper Limit MFDI = 07H or 0BH)</i> <i>1 Home = LL2 (Home by Lower Limit MFDI = 09H or 0DH)</i> <i>2 Home = Hook Height Home (Home by Top MFDI = 67H)</i> <i>4 Home = UL3 (Home by Upper Limit MFDI = 62H or 12H)</i> | | 0-4 | 0 | Adv |
| C8-25 | Hook Height Out <i>0 At Home = 0V - U1-50 = 0%, MFAO = 0V</i> <i>1 At Home = 10V - U1-50 = 100%, MFAO = 10V</i> | | 0-1 | 0 | |
| C8-26 | Load Float Fault Revolutions | Adjust this setting for Load Float Fault | 1-99 revs | 4 | Adv |

Optional Digital Input Set-up (G5IN4 Digital Multi-Function Inputs)

| Parameter | | | | | Access |
|-----------|--|--|--|---------------|--------|
| Code | Display | Function | Range | Initial Value | Level |
| C9-01 | Digital In Setup 0 Disabled 1 G5IN4/C9-02 2 G5IN4/C9-03 - 06 3 DI-08/C9-03 - 10 DI-08 8 CH Individual 4 DI-16/C9-03 - 12 DI-16 Terminals 10 CH Individual 5 Serial/C9-03 - 12 10 CH Individual | There are several Digital Input Option (DIO) cards that may be used depending on how much I/O is required for the application. The G5IN4 provides 4 additional 120VAC inputs, the DI-08 provides 8 additional 24VDC inputs, and the DH-16H2 provides 10 additional 24VDC inputs. | 0 - 5 | 0 | Adv |
| C9-02 | G5IN4 Setup | Determines the four settings for G5IN4 Digital Multi-Function Inputs. | 0000–FFFF | 0 | Adv |
| C9-03 | DIO Terminal 1 | Multi-Function Digital Input (MFDI) by G5IN4/DI-08/DI-16 Options. (Hidden and Disabled when using [C9-01 < 2]) | 0–FF | 0F | Adv |
| C9-04 | DIO Terminal 2 | | 0–FF | 0F | Adv |
| C9-05 | DIO Terminal 3 | | 0–FF | 0F | Adv |
| C9-06 | DIO Terminal 4 | | 0–FF | 0F | Adv |
| C9-07 | DIO Terminal 5 | | Same as H1-0x selection except: 04H, 05H, 15H - 19H, 1FH, 20 - 2FH, 31H, 34H, 35H, 38H, 47H, 51H, 52H, and 58H are not programmable to these terminals. | 0–FF | 0F |
| C9-08 | DIO Terminal 6 | MFDI by G5IN4/DI-08/DI-16 Options. (Hidden and Disabled when using [C9-01 < 3]) | 0–FF | 0F | Adv |

The optional G5IN4 board accepts four additional multi-function inputs. The G5IN4 board has four terminals, each of which can be programmed to one of the fourteen sets of inputs. Each input in the set can be enabled or disabled.

1. Set C9-01 to 1.
2. Determine the parameter C9-02 setting by specifying the first digit (from left) and the fourth digit (from left) using tables 5-3 and 5-4. The second and third digit should always be "0".
3. Set parameter C9-02.

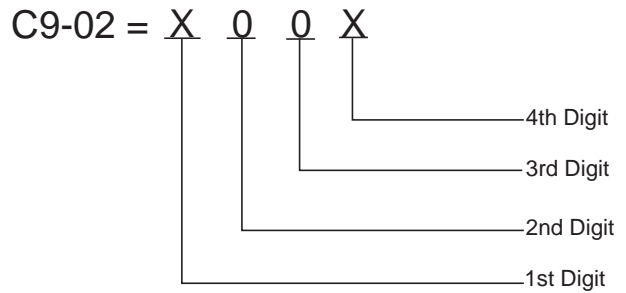


Table 5-2:

1 = 120V is present on terminal

0 = No voltage is present on terminal

| MONITOR | TERMINAL | | | |
|---------|----------|---|---|---|
| | U1-25 | 1 | 2 | 3 |
| 1 | 1 | 0 | 0 | 0 |
| 2 | 0 | 1 | 0 | 0 |
| 3 | 1 | 1 | 0 | 0 |
| 4 | 0 | 0 | 1 | 0 |
| 5 | 1 | 0 | 1 | 0 |
| 6 | 0 | 1 | 1 | 0 |
| 7 | 1 | 1 | 1 | 0 |
| 8 | 0 | 0 | 0 | 1 |
| 9 | 1 | 0 | 0 | 1 |
| A | 0 | 1 | 0 | 1 |
| B | 1 | 1 | 0 | 1 |
| C | 0 | 0 | 1 | 1 |
| D | 1 | 0 | 1 | 1 |
| E | 0 | 1 | 1 | 1 |
| F | 1 | 1 | 1 | 1 |

Table 5-3: G5IN4 Digital Multi-Function Input Sets (0 through F)

| First Digit (From Left) You Enter | Multi-Function Input Assigned to Each Terminal | | | |
|-----------------------------------|--|--|--|--|
| | Terminal 1 | Terminal 2 | Terminal 3 | Terminal 4 |
| 0 | <i>No function</i> | <i>No function</i> | <i>No function</i> | <i>No function</i> |
| 1 | <i>Upper Limit–SLOW DOWN; Normally Closed</i> | <i>Upper Limit–STOP; Normally Closed</i> | <i>Lower Limit–SLOW DOWN; Normally Closed</i> | <i>Lower Limit–STOP; Normally Closed</i> |
| 2 | <i>Upper Limit–SLOW DOWN; Normally Open</i> | <i>Upper Limit–STOP; Normally Open</i> | <i>Lower Limit–SLOW DOWN; Normally Open</i> | <i>Lower Limit–STOP; Normally Open</i> |
| 3* | <i>Multi-Step Speed 2</i> | <i>Multi-Step Speed 3</i> | <i>Multi-Step Speed 4</i> | <i>Multi-Step Speed 5</i> |
| 4* | <i>Hold function (2nd step of Three-Step Infinitely Variable).</i> | <i>Acceleration function (2nd step of Two-Step Infinitely Variable or 3rd step of Three-Step Infinitely Variable).</i> | <i>Micro-Positioning Control Multiplier 1</i> | <i>Upper Limit–STOP; Normally Closed</i> |
| 5 | <i>Upper Limit–STOP; Normally Closed</i> | <i>Upper Limit–SLOW DOWN; Normally Closed</i> | <i>Lower Limit–STOP; Normally Closed</i> | <i>Lower Limit–SLOW DOWN; Normally Closed</i> |
| 6 | <i>Upper Limit–STOP; Normally Open</i> | <i>Upper Limit–SLOW DOWN; Normally Open</i> | <i>Lower Limit–STOP; Normally Open</i> | <i>Lower Limit–SLOW DOWN; Normally Open</i> |
| 7* | <i>Multi-Step Speed 5</i> | <i>Multi-Step Speed 4</i> | <i>Multi-Step Speed 3</i> | <i>Multi-Step Speed 2</i> |
| 8* | <i>Upper Limit–STOP; Normally Closed</i> | <i>Micro-Positioning Control Multiplier 1</i> | <i>Acceleration function (2nd step or Two-Step Infinitely Variable or 3rd step of Three-Step Infinitely Variable).</i> | <i>Hold function (2nd step of Three-Step Infinitely Variable).</i> |
| 9 | <i>Upper Limit–STOP; Normally Closed</i> | <i>Lower Limit–STOP; Normally Closed</i> | <i>Micro-Positioning Control Multiplier 1</i> | <i>External base block N/O</i> |
| A | <i>Upper Limit–STOP; Normally Closed</i> | <i>Lower Limit–STOP; Normally Closed</i> | <i>Micro-Positioning Control Multiplier 1</i> | <i>Weight Measurement Control</i> |
| B | <i>Ultra-Lift Enable</i> | <i>Brake answerback</i> | <i>Micro-Positioning Control Multiplier 1</i> | <i>Micro-Positioning Control Multiplier 2</i> |
| C | <i>External Base Block N/O</i> | <i>Phantom Fault N/O</i> | <i>Klixon N/O</i> | <i>BE6 Up Speed Limit</i> |
| D | <i>External Base Block N/O</i> | <i>Brake Answerback</i> | <i>Micro-Positioning Control Multiplier 1</i> | <i>Micro-Positioning Control Multiplier 2</i> |
| E | <i>Alternate Upper Limit Frequency Reference</i> | <i>Option/Inverter Run and Speed Reference Changeover</i> | <i>Micro-Positioning Control Multiplier 1</i> | <i>Brake Answerback</i> |
| F | <i>External Base Block N/C</i> | <i>Phantom Fault N/C</i> | <i>Klixon N/C</i> | <i>BE6 Up Speed Limit</i> |

* If using the G5IN4 to input speed references, A1-04 should be set for Data 7 (G5IN4 Opt Card). This will help to avoid an OPE03 fault caused by having more than one terminal programmed with the same data.

Table 5-4:Enabling/Disabling Decision Table for C9-02

| Input for Terminal 1 | Input for Terminal 2 | Input for Terminal 3 | Input for Terminal 4 | Fourth Digit (From Left) You Enter |
|-----------------------------|-----------------------------|-----------------------------|-----------------------------|---|
| <i>E</i> | D | D | D | 1 |
| D | <i>E</i> | D | D | 2 |
| <i>E</i> | <i>E</i> | D | D | 3 |
| D | D | <i>E</i> | D | 4 |
| <i>E</i> | D | <i>E</i> | D | 5 |
| D | <i>E</i> | <i>E</i> | D | 6 |
| <i>E</i> | <i>E</i> | <i>E</i> | D | 7 |
| D | D | D | <i>E</i> | 8 |
| <i>E</i> | D | D | <i>E</i> | 9 |
| D | <i>E</i> | D | <i>E</i> | A |
| <i>E</i> | <i>E</i> | D | <i>E</i> | B |
| D | D | <i>E</i> | <i>E</i> | C |
| <i>E</i> | D | <i>E</i> | <i>E</i> | D |
| D | <i>E</i> | <i>E</i> | <i>E</i> | E |
| <i>E</i> | <i>E</i> | <i>E</i> | <i>E</i> | F |

Key Enable = *E*
 Disable = D

Weight Measurement

The IMPULSE•VG+ Series 3 includes a Weight Calculation function that can be used in hoisting applications. The weight measurement calculation is based on motor torque at a constant speed. The drive must pause the acceleration, wait for the torque to stabilize and then perform the weight calculation based on the system tare values. The function takes a reading one time per lift (Raise Run command) when C10-01 = 1 or 3 (Automatic) or it can be configured to take a reading at any speed with a Multi-function input when C10-01 = 2 or 3 (Manual). The calculated weight can be displayed on the keypad of the hoist drive or by an external display device connected to an analog output of the hoist drive.

NOTE: Weight Calculations will be more consistent when a weight measurement is calculated at the same speed every time. Example: C10-01 = 1, weight measurement is always calculated at C5-04 speed. It is important to note that after the load has been rigged, it should be suspended and the brakes should be set on the hoist. When the next raise command is given, the hoist is now ready to calculate the load weight. The function only works in the Raising motion (Fwd Run). If extreme accuracy is required, a load cell should be used. The Weight Measurement function of the hoist drive should be within 5% or better accuracy of the rated capacity.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|--|---|-------------|---------------|--------------|
| C10-01 | Load Weight 0/1 0 Disabled 1 Enabled at C5-04 (Automatic for the duration of C5-12 + C5-13) 2 Enabled at MFI=5C 3 Both Auto & MFI=5C 4 Analog Input (Load Cell) MFAI=16 | Determines whether Load Weight is enabled. | 0~4 | 0 | Adv |
| C10-02 | Torque Pri Delay | Torque Output Calculation primary delay time. | 0–1000 msec | 200 | Adv |
| C10-03 | LW Display Hold 0 Hold Display 1 Hold Disp 3 sec | Until next run command is on | 0, 1 | 0 | Adv |
| C10-04* ** | LW Conversion | Multiplier of torque output calculation for display. Data is n0000, so multiplier is 10000; “n” is decimal point. | 00000–39999 | 0 | Adv |
| C10-05 | Full Load Torque | Percentage of Torque Output that is defined as Full-Load Torque Output. | 0.0–200.0% | 100.0 | Adv |
| C10-06 | No Load Torque | Percentage of Torque Output that is defined as No-Load Torque Output. | 0.0–200.0% | 20.0 | Adv |
| C10-07** | Unit Displayed 0 Tons 1 Pounds 2 Kilograms 3 Metric Tons 4 Percent Load | Determines “weight” measurement units in which the parameter settings will be expressed. The unit abbreviations appear on line 2 of the display | 0~4 | 0 | Adv |
| C10-08 | Weight Limit Output | Turn on Level for MFO=33 Weight Measurement enabled by Multi-Function Input = 5C. | 0.0-200.0% | 125% | Adv |

*For an example, please refer to Table 5.14 on page 5-97.

** Used for keypad display; consult factory for assistance.

System Care and Calibration

1. Attach all of the under hook attachments that are required during **normal** lifting (Chains, Slings, spreader beam, etc.). Remove the load from the bottom block. If there is a spreader beam or other lifting device that is **constantly** attached to the bottom block, it may be left in place. If the lifting device changes, it should be removed for this procedure and the known weight of the lifting device used for each lift should be manually subtracted from weight that is calculated by the hoist drive.
2. Run the **Unloaded** hoist in the raise direction at the speed that the weight will be calculated at. For example: If C10-01 = 1, then the hoist will automatically pause at the speed programmed in parameter C5-04 (6 Hz is the factory setting) while calculating the weight on the hook. This is the speed the hoist should be run at. An easy method would be to set the first speed point equal to C5-04 or, if using an analog speed reference, then program B2-02 (minimum speed) so that it is equal to C5-04.
3. Record the torque reading being displayed by the monitor parameter U1-09 (Torque Reference). Repeat this step several times and record the average “No Load Torque” in parameter C10-06 (No Load Torque).
4. Attach all of the under hook attachments that are required during **normal** lifting (Chains, Slings, spreader beam, etc.). Rig the **FULL** load that the hoist and weight measurement system will be expected to calculate. If the rigging used for the full load is different than that used in steps 2 and 3, it will need to be added to the known weight being lifted to obtain an accurate total weight at a later time.
5. Run the **Loaded** hoist in the raise direction at the speed that the weight will be calculated at. See Step 2 for an example.
6. Record the torque reading being displayed by the monitor parameter U1-09 (Torque Reference). Repeat this step several times and record the average “Full Load Torque” in parameter C10-05 (Full Load Torque).
7. The monitor parameter U1-29 should now be displaying a value when lifting a full load. This value is a raw number that could later be converted into a meaningful weight to be displayed on the keypad. For this procedure, it is not imperative that the number is converted to tons or pounds. Most importantly, it should read a value of zero or very close to zero when lifting no load and should be relatively consistent when lifting the same weight repeatedly.

Setting up an External Display Device

NOTE: This procedure assumes that the System Tare and Calibration procedure has been completed. The setup of parameter C10-03 and C10-07 should be returned to the factory default settings for this procedure or may be skipped entirely if the displayed weight does not need to be read on the keypad of the hoist drive. C10-03 and C10-07 = 0. The external display device should be configured to accept a 0 - 10VDC input where 0 V = no load and 10V - Full load or 125% load. (This may be site specific.)

1. Program the desired analog output terminal (FM or AM) for 'Load Weight'
Example: H4-01 = 29 (Terminal FM) or H4-04 = 29 (Terminal AM).
2. Remove the load from the bottom block. If there is a spreader beam or other lifting device that is constantly attached to the bottom block, it may be left in place. If the lifting device changes, it should be removed for this procedure and the weight of the lifting device used for each lift should be manually subtracted from weight that is calculated by the drive.
3. Lift **no-load** and monitor the 'Weight Measurement' on U1-29 on the keypad. The keypad digital display should read 0; however, if it does not, lower C10-06 until the keypad digital display reads zero. Re-test as necessary to get as close to 0 as possible.
4. After lifting **no-load** again, read the weight displayed on the display device. If the displayed weight is greater than 0, begin to add a **negative bias** to terminal FM by adjusting H4-03 down from 0.00. It will be in -xx.x format. To switch from a positive bias to a negative bias, move the cursor to the far left digit and press the up arrow key, which will display the - sign. As the **negative bias** is increased, the weight displayed on the digital display device will decrease. Continue to add **negative bias** until the weight displayed on the digital display device reads as close to 0 as possible without going negative.
5. Pick up a known load of approximately 50% or greater and read the weight displayed on the display device. If the indicated weight does not match the actual weight, adjust H4-02 or H4-05 (Terminal FM or AM Gain) to obtain the required reading. H4-02 and H4-05 are gain multiplier parameters for the respective analog output and will raise or lower the 0-10V dc signal to the display device.
6. Re-test with no load. If the weight displayed on the display device does not equal zero, re-adjust the negative bias at H4-03.
7. This procedure may be repeated as many times as necessary until the correct combination of gain and bias is found to make the system within tolerance at the high and low end of maximum capacity of the hoist.

Slack Cable Detection

IMPULSE•VG+ Series 3 offers Slack Cable Detection in the hoist application. The Slack Cable condition is detected when the torque output is drastically reduced and has dipped below a set-point (C11-03) level. When Slack Cable condition occurs, the output action is defined by the C11-02 which has 6 selections.

The Slack Cable Detection is not executed, unless both of the following conditions are true:

- *The output frequency is between C11-04 and C11-06.*
- *The Slack Cable Detection delay time is between C11-05 and C11-07.*

Setup Procedure:

- *To set the Slack Cable Detection torque level (C11-03), by lowering the hoist without load at a constant speed that the hoist would normally run during the operation. Monitor and record the torque reference (U1-09). Repeat the above operation several times to ensure an accurate reading.*
- *Then Set C11-03 = [(U1-09)-2].*
- *Enable Slack Cable Detection by setting the C11-01 to 1.*
- *Select output action when Slack Cable is detected by defining C11-02.*

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|-------------------|--|-------|---------------|--------------|
| C11-01 | Slack Cable 0/1 | (For Hoist Application) Determines whether Slack Cable Detection is enabled. | 0~1 | 0 | Adv |
| | 0 Disabled | | | | |
| | 1 Enabled | | | | |
| C11-02 | Action at SLC | Multi-function output that occurs at Slack Cable Detection. For all Selections, RAISE command is permitted (MFO=28). | 0~5 | 2 | Adv |
| | 0 No Action | Alarm Only | | | |
| | 1 No Act/C3-04 | Next LOWER command is at Lower Limit 1 speed (C3-04). | | | |
| | 2 Decel/C3-04 | Decelerate to Lower Limit 1 Speed C3-04. Continued LOWER commands allowed, but at C3-04. | | | |
| | 3 Decel/No Opr | Decelerate to Lower Limit 1 Speed C3-04. Continued LOWER commands are <i>not</i> allowed. | | | |
| | 4 Dec Stop/C3-04 | Decel (by C3-05) to Lower Limit 1 Speed C3-04. Continued LOWER commands allowed, but at C3-04. | | | |
| | 5 Dec Stop/No Opr | Decel (by C3-06) to stop. Continued LOWER commands are <i>not</i> allowed. | | | |

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|-----------------------|------------------|---|---------------|----------------------|---------------------|
| C11-03 | SLC Detect Torq | Percentage of Output Torque below which the enabled Slack Cable Detection is activated—as long as the Frequency output is between C11-04 and C11-06, and the delay time is between C11-05 and C11-07. | 0–100% | 30 | Adv |
| C11-04 | SLC Detect Spd 1 | The Frequency Output that is required for the enabled Slack Cable Detection to be activated. It corresponds to Slack Cable Detection Delay Time 1 (C11-05). | 0–150Hz | 2 | Adv |
| C11-05 | SLC Delay Time 1 | The delay time before the enabled Slack Cable Detection can be activated. It corresponds to Slack Cable Detection Speed 1. Prevents false outputs. | 0.00–2.55sec. | 0.50 | Adv |
| C11-06 | SLC Detect Spd 2 | The Frequency Output below which the enabled Slack Cable Detection can be activated. It corresponds to Slack Cable Detection Delay Time 2 (C11-07). | 0–150Hz | 60 | Adv |
| C11-07 | SLC Delay Time 2 | The delay time before the enabled Slack Cable Detection can be activated. It corresponds to Slack Cable Detection Speed 2. Prevents false outputs. | 0.00–2.55sec. | 0.10 | Adv |

Snap Shaft Detection/Drive Train Discontinuity Detection

This feature is designed to detect a broken or loose coupling by looking for a speed deviation between rotating shafts on a drive train. Ideally, mount one encoder on the motor, which drives the gearbox and one encoder on the last rotating part of the motion, usually near the drum if used for a hoist motion. It is recommended that a second brake be mounted near the second encoder. The encoders are wired into the optional PG-Z2 dual channel encoder input card, with channel 1 being the high speed shaft input and channel 2 being the low speed shaft input. The drive will use channel 1 as the flux vector feedback. The software monitors and compares the speed of both encoders. A gear ratio is entered into parameters C11-12 and C11-13. In an example, if the gearbox ratio is 46.34 : 1, then you would program C11-12 to 4634 and C11-13 to 100. If the difference in speed is greater than the value in C11-10 for a period longer than the setting of C11-11, a “Snap Shaft” is displayed on the keypad display and the programmed action in C11-09 is executed.

Set Up

Parameter U1-30 should be monitored during operation to obtain the exact speed difference in Hz between the two shafts. The low speed shaft speed is normalized internally by multiplying the speed of the gear ratio. The value of C11-12 should be adjusted at start up such that U1-30 approaches 0.0.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|---|--|-----------|---------------|--------------|
| C11-08 | Snap Shaft 0/1 0 <i>Disabled</i> 1 <i>Enabled</i> | Determines whether snap shaft detection is enabled. | 0-1 | 0 | Adv |
| C11-09 | Action at Snap 0 <i>Brake/fault out</i> 1 <i>Alarm Only</i> | Action taken at detection. A setting of 0 will set the brake and display a fault. With a setting of 1, the drive will continue to run. | 0-1 | 0 | Adv |
| C11-10 | SS Delta speed | Difference in speeds of the two shafts normalized by the gear ratio. | 0-150 Hz | 1.0 Hz | Adv |
| C11-11 | SS Delay Time | Gear backlash time in milliseconds | 0-2000 ms | 250 ms | Adv |
| C11-12 | SS Gear Ratio Num | Gear ratio numerator | 1-10000 | 10000 | Adv |
| C11-13 | SS Gear Ratio Den | Gear ratio denominator | 1-10000 | 10000 | Adv |

Delay Timers

This function is used in trolley or bridge applications. It can reduce the mechanical brake wear when the operator tries to position a load. This function is available only in traverse mode and the constant B3-03 must be set to 4 (Ramp With Timer).

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|-----------------|--|---------------|---------------|--------------|
| C12-01 | Brake Jog Delay | Brake set delay time at Jog Control input. | 0.0–100.0 sec | 0.0 sec | Adv |
| C12-02 | Brake Run Delay | Brake set delay time at RUN input. | 0.0–100.0 sec | 0.0 sec | Adv |

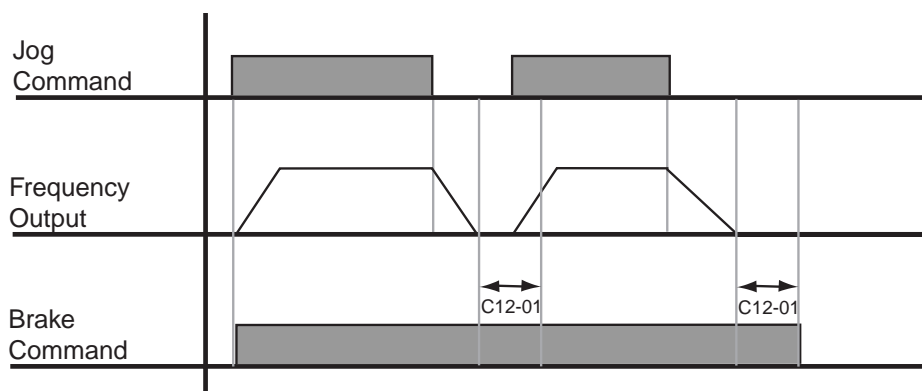


Figure 5-17: Brake Delay Timers

NOTE: The Jog control input is a multi-function input. It is enabled by programming data 15 or 16 in H1-01~06.

Timer Function

- The timer function is enabled when the timer function input (setting: 43) and the timer function output (setting: 12) are set for the multi-function input and multi-function output respectively.
- The input and output serve as general purpose I/O. Chattering of sensors, switches, contactors, etc., can be prevented by setting a delay time.
- When the timer function input **ON** time is longer than the value set for **C12-03** (Timer function ON-Delay Time), the timer function output turns **ON**.
- When the timer function input **OFF** time is longer than the value set for **C12-04** (Timer function OFF-Delay Time), the timer function output turns **OFF**.

| Parameter Code | Display | Setting Range | Factory Default Setting | Access Level |
|----------------|-----------------|---------------|-------------------------|--------------|
| C12-03 | Delay-on timer | 0.0~3000.0 | 0.0 | Adv. |
| C12-04 | Delay-off timer | 0.0~3000.0 | 0.0 | Adv. |

Maintenance Timer

The “Maintenance Timer” is a maintenance feature that will alert an operator, for example, when the bearings need to be greased. It consists of a Multi-Function output (Data 37) that becomes active when the total running time has exceeded the amount of time (in hours) programmed in parameter C12-05 and the frequency reference will be multiplied by a programmable gain (C12-06) to slow the motion down until the bearings have been greased. An alarm will also be posted on the Keypad stating “Maintenance Required”. Once the bearings have been greased, the output and alarm message can be reset by two different methods. One method is through a Multi-Function Input programmed for Maintenance Reset (H1-01 ~ 06 = 5A) and the second method is by pressing the Mode/Service (Local/Remote) button three consecutive times with no more than 2 seconds between presses. Press enter to reset timer. A message will then appear on the keypad stating that the timer has been reset. The Multi-Function Output will turn off at this time. When C12-0 = 0, the function is disabled.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|-----------------------|------------------|------------------------------|--------------|----------------------|---------------------|
| C12-05 | Maintenance Tmr | Maintenance Timer Trip Level | 0-32767 | 0 | Adv |
| C12-06 | Maintenance Gain | Speed Reference Gain | 0.00-1.00 | 0.5 | Adv |

Inching Control

Inching Control Function can be enabled by programming data 17, 18, and 19 respectively to the Multi-Function input terminals (H1-01~06). The frequency reference used during inching is determined by B1-17 (Jog Reference).



| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|--------------------|------------------------------------|---------------|---------------|--------------|
| C13-01 | Inch Run Time | Inching Control run time. | 0.00–2.55 sec | 1.00 | Adv |
| C13-02 | Repeat Delay T | Inching Control repeat delay time. | 0.00–2.55 sec | 1.00 | Adv |
| H1-01~06 | Terminal Selection | | 17-19 | | Adv |
| | 17 | Forward Inch | | | |
| | 18 | Reverse Inch | | | |
| | 19 | Inch Repeat | | | |

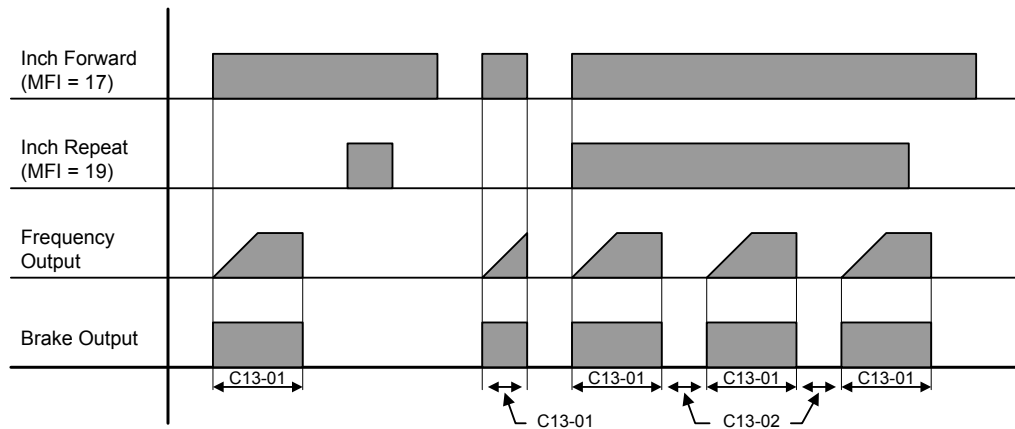


Figure 5-18: Inching Function and Inching Repeat

Index Function

Indexing allows for precise movement of the motor each time a run command is applied by the operator and the Index function is enabled by a Multi-Function Input (H1-0x = 60). This function can only be used with Traverse (A1-03 = 0) and No Load Brake (A1-03 = 2) motions in Flux Vector and any Speed Reference setting for A1-04.

The total distance (Pulses) the motor will index is determined by the following equation:

$$\text{Total distance(Pulses)} = [\text{F1-01}(\text{Pulse/Rev}) * \text{C13-04(Revs)}] + \text{C13-05(Pulses)}$$

When the Index function is turned ON, the function can also be programmed to repeat an Index as long as the Run command is enabled and by setting the Index Repeat Delay (C13-06) greater than 0.00 seconds. The Index will repeat again after the Index Repeat Delay (C13-06) time has expired. Once the motor completes the Index, the brake will either set or remain in Load Float depending on the braking sequence described below.

When an Index move is complete, a Multi-Function Output (Index Complete H2-xx = 34) can be programmed to turn ON, and will remain ON until one of the following is true:

- another directional run input is received,
- the repeat delay time has expired and the movement is repeating, or
- the Index Function is disabled.

Traverse (A1-03 = 0)

When the Index Function is turned ON in Traverse applications, the Index Brake Control (C13-12) can control the action of the brake. The following describes the brake control for each setting:

Open on Index Command (C13-12 = 0)

When the Index Function is turned ON, the brake will release and hold the position in Load Float until a run command is applied. The brake will set and normal operation will resume when the Indexing function is disabled.

Open on Each Run (C13-12 = 1)

When the Index function is turned ON, the brake will release after each run command is applied, then Index the motor. The brake will set after the Index or Index Repeat is complete, or the run command is removed.

Latch Open on Run (C13-12 = 2)

When the Index function is turned ON, the brake will release when a run command is applied, then the drive will Index the motor and will hold the position in Load Float after the Index function is complete. The drive will remain in Load Float until another run command or the Index function is turned OFF. The brake will set and normal operation will resume when the Index function is turned OFF.

No-Load Brake (NLB) Hoist (A1-03 = 2)

When the motion is No-Load Brake Hoist, the Index Brake Control (C13-12) is disabled and the action of the brake is controlled by the No-Load Brake sequence. The Index function can be enabled at any time during operation and the action of the brake is described below.

At Stop

If the Index function is turned ON while the crane is stopped, the brake will release when a run command is applied, then the drive will Index the motor and will hold the position in Load Float after the Index function is complete. The drive will remain in Load Float until another Run command or the Index function is turned OFF. When the Index function is turned OFF, the drive will set the brake according to the No-Load Brake stop sequence.

During Run

If the motor is in motion when the Index function is turned ON, the drive will decelerate to zero and hold the position in Load Float. After a Run command is applied, the drive will Index the load and hold the position in Load Float after the Index is complete. The brake is set according to the No-Load Brake stop sequence when the Index function is turned OFF.

NOTE: For best performance, enable Index after brake has released. Not recommended for double A4 applications.

NOTE: When either the Index Enable or Run Command is removed, the NLB Stop Sequence will be initiated.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|-----------------------|------------------|---|-------------------|----------------------|---------------------|
| C13-03 | Index Run Ref | Index frequency Ref. (MFI=60). | 0.01–60.00 Hz | 0.10 | Adv |
| C13-04 | Index Revs | Index motor revolutions (F1-01 PPR = 1 Rev.) | 0-65535 Rev | 0** | Adv |
| C13-05 | Index Count | Index fractional motor revolution (Setting in encoder pulses) | 0-65535 | 100** | Adv |
| C13-06 | Index Rpt Delay | Index repeat delay time (Setting of 0.00 disables Index Repeat) | 0.00-60.00 Sec | 0.00 | Adv |
| C13-07 | Index Complete | Index Complete Width | 0-32767 | 10 | Adv |
| C13-08 | Index Zsv Gain | Index Zero Servo Gain | 0-100 | 10 | Adv |
| C13-09 | Index ASR P Gain | Index ASR P Gain | 0.00-300.00 | 30 | Adv |
| C13-10 | Index ASR I Time | Index ASR Integral Time | 0.0000-10.000 Sec | 0.02 | Adv |
| C13-11 | Index Gain | Index Accel/Decel Rate Gain | 0.0-20.0 | 5.0 | Adv |
| C13-12 | Index Brake Ctrl | Configures brake behavior when indexing (traverse only) 0: Open on Index Command 1: Open on Each Run 2: Latch Open on Run | 0-2 | 0 | Adv |

** If both C13-04 and C14-05 = 0, the Index function is disabled.

Tuning

- D1 DC Injection
- D2 Automatic Slip Compensation
- D4 ASR Tuning
- D5 Torque Control
- D6 Droop Control
- D8 Dwell Function
- D9 S-Curve Acceleration/Deceleration
- D10 Carrier Frequency
- D12 Factory Tuning

DC Injection

DC Injection can be used to stop a motor whose rotational direction is uncertain at start-up.

With decel to stop enabled (B3-03=0), upon removal of the run command the IMPULSE•VG+ Series 3 drive controls motor deceleration according to the Decel Time setting, until output frequency reaches the DC Injection Braking Start Frequency (D1-01 setting). Then the IMPULSE•VG+ Series 3 drive output is turned off and DC injection current is applied to the motor. The effective DC injection time and current should be set to provide adequate stopping without excessive motor heating. The DC injection voltage is determined by the DC injection braking current and motor impedance.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|------------------|--------------------------------------|----------------|---------------|--------------|
| D1-01 | DCInj Start Freq | DC Injection braking frequency start | 0.0–10 Hz | 0.5 | Adv |
| D1-03 | DCInj Time@Start | DC Injection braking time | 0.00–10.00 sec | 0.00 | Adv |
| D1-04 | DCInj Time@Stop | DC Injection braking time at stop | 0.00–10.00 sec | 0.05 | Adv |

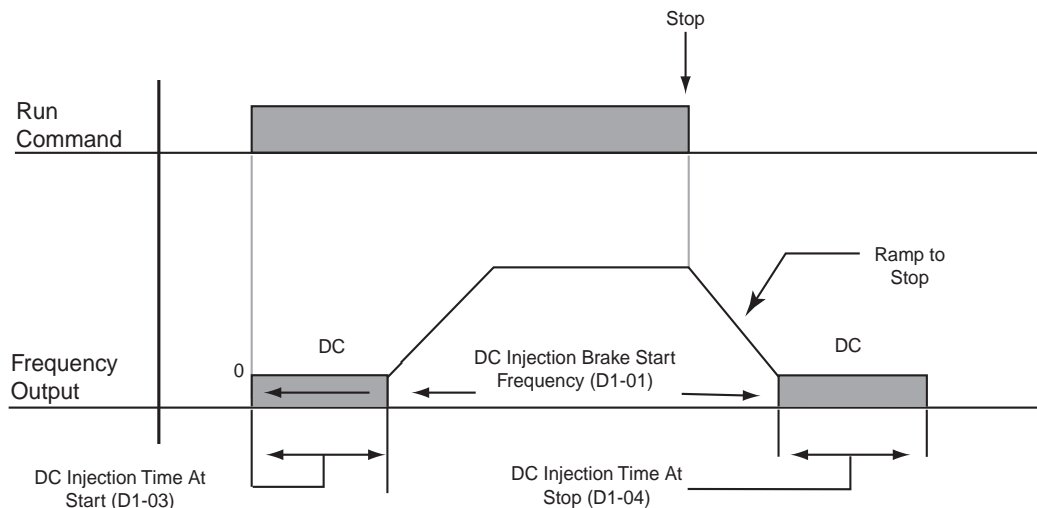


Figure 5-19: DC Braking Sequence

Automatic Slip Compensation

As the load becomes larger, the motor speed is reduced and the motor slip increases. The slip compensation function keeps the motor speed constant under varying load conditions. D2-01 sets the slip compensation gain. When the gain is “1.0”, the output frequency is increased by 1% of the E1-06 setting at rated current. A setting of “0.0” results in no slip compensation.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|------------------|-------------------------------|---------|---------------|--------------|
| D2-01 | Slip Comp Gain | Slip compensation multiplier. | 0.0–2.5 | 1.0 | Adv |
| D2-05 | Output V Lim Sel | V/F Slip Compensation | 0 - 1 | 0 | Adv |
| | 0 Disable | | | | |
| | 1 Enable | | | | |

Automatic Speed Regulator (ASR) Tuning

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|--------------|--------------------------|-------------------|---------------|--------------|
| D4-01 | ASR P Gain 1 | ASR Proportional Gain 1. | 1.00–300.00 | 30.00 | Adv |
| D4-02 | ASR I Time 1 | ASR Integral Time 1. | 0.000–10.000 sec. | 0.500 | Adv |

Parameters D4-01 and D4-02 provide adjustments to enable the optimum performance during load disturbances. The proportional gain (D4-01) adjusts the amount of instantaneous droop as a function of loss, and provides dampening from load disturbances such as speed reference change, or a change in load. The integral time (D4-02) adjusts the response time of the IMPULSE•VG+ Series 3 to the load disturbances.

NOTE: Speed control response is increased by increasing the proportional gain setting and decreasing the integral time. However, instability or hunting may occur between the IMPULSE•VG+ Series 3 and the load if D4-01 (ASR Proportional Gain) is set too high, or D4-02 (ASR Integral Time) is set too low.

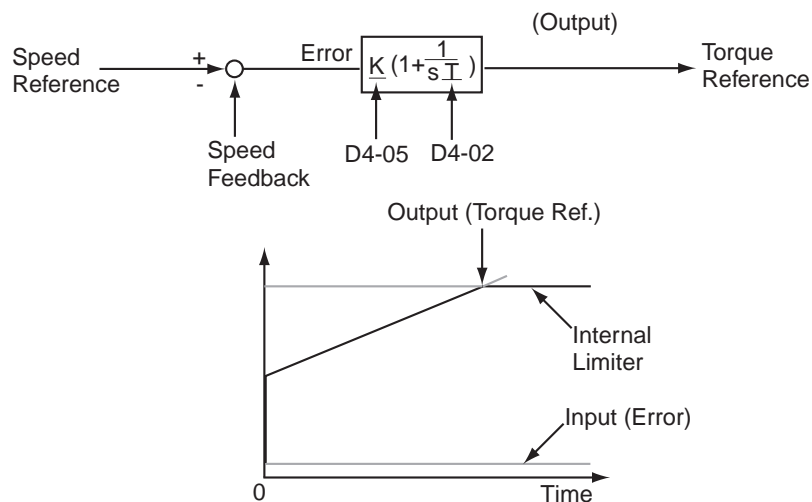


Figure 5-20: Automatic Speed Regulator (ASR) Tuning

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|--|------------------|--------------------------------|------------------|---------------|--------------|
| D4-03 | ASR P Gain 2 | ASR Proportional Gain 2. | 1.00–300.00 | 30.00 | Adv |
| D4-04 | ASR I Time 2 | ASR Integral Time 2. | 0.000–10.000 sec | 0.100 | Adv |
| D4-06 | ASR Delay Time | ASR Output Primary Delay Time. | 0.000–0.500 sec | 0.004 | Adv |
| Mechanical backlash in an application can cause secondary current (I_2) reference variations in the motor's rotor. This condition can prevent the desired adjustment of ASR parameters. The output delay time constant is used to increase the stability of the system allowing a wider setting range of ASR parameters. | | | | | |
| D4-07 | ASR Gain SW Freq | ASR Gain Switching Frequency. | 0.0–150.0 Hz | 0.0 | Adv |
| D4-08 | ASR I Limit | ASR Integral Limit. | 0–400% | 400 | Adv |

Parameter D4-03 is used as an additional proportional gain adjustment, and parameter D4-04 determines the response time for Proportional Gain 2 (D4-03).

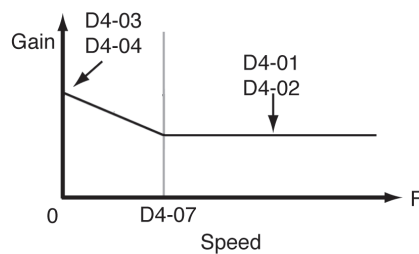


Figure 5-21: Proportional Gain

NOTE: When D4-07= “0,” proportional gain 1 (D4-01) and integral time 1 (D4-02) are selected.

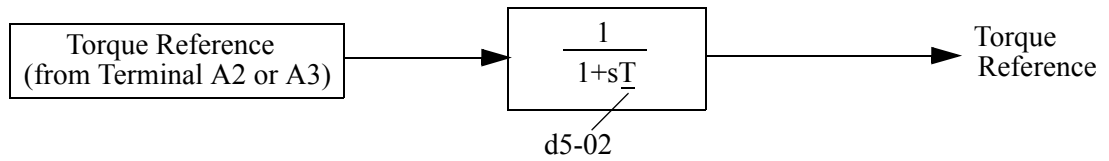
Torque Control

Please consult factory for application assistance regarding torque control. Torque control should not be applied on a vertical hoist

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|---|-------------------|---|------------|---------------|--------------|
| D5-01 | Torque Control | Determines whether Speed or Torque Control is selected. | 0~1 | 0 | Adv |
| | 0 Speed Control | Speed Control enabled with torque limit | | | |
| | 1 Torque Control* | Torque control enabled with speed limit. | | | |
| Speed/torque control selection can also be made by using a multi-function input select (H1-XX=34 speed- torque control changeover). | | | | | |
| D5-02 | Torque Ref Filter | Primary delay time for Torque Reference Input. | 0–1000msec | 0 | Adv |

* Can not set D5-01 = 1 for NLB Hoist

This function is used to avoid excessive changes in torque, which may be caused by abnormal resonance when the torque reference changes rapidly.



| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|--------------------------|--|-----------|---------------|--------------|
| D5-03 | Speed Limit Sel | Speed Limit Selection (See figure below) | 1-2 | 2 | Adv |
| | 1 <i>Analog Input</i> | | | | |
| | 2 <i>Program Setting</i> | | | | |
| D5-04 | Speed Lmt Value | Speed Limit Value (% of E1-04) | -120–120% | 105 | Adv |
| D5-05 | Speed Lmt Bias | Speed Limit Bias (% of E1-04) | 0–120% | 105 | Adv |
| D5-06 | Ref Hold Time | Speed/Torque Switching Timer | 0–1000 ms | 0 | Adv |

Speed/Torque Control Switching

Speed control or torque control can be selected “on the fly” by using the multi-function input speed/torque control selection command (H1-XX = “34”).

| Terminal Number | Parameter Number | Setting | Description |
|-----------------|------------------|---------|--|
| S8 | H1-06 | 34 | Speed/torque control selection |
| A1 | B3-01 | 1 | Frequency reference selection (terminals A1, A2 or A3) |
| | D5-03 | 1 | Speed limit selection (terminals A1, A2 or A3) |
| A3/A2 | H3-05/H3-09 | 13 | Torque reference/torque limit |

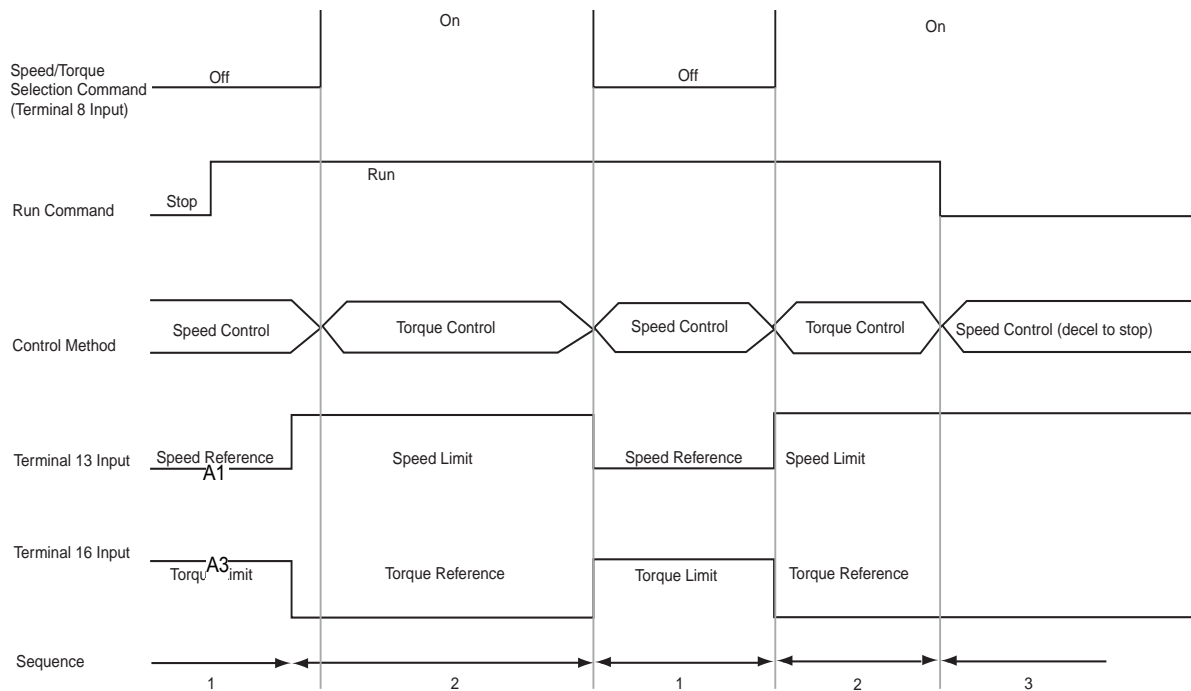


Figure 5-22: Speed/Torque Control Selection Timing Diagram

- When the speed/torque control selection contact is OFF, speed control is activated.
 - Speed reference during speed control depends on the frequency reference selection (B3-01) setting. To use terminal A1, A2, or A3 as the master frequency reference, set B3-01 to “1.”
 - Torque limit during speed control is the smaller of the absolute value of terminal A2 or A3 torque limit, or the values set in the torque limit parameters (C7-01 to C7-04) is used as the torque limit.
 - When a stop command is given during speed control, speed control is maintained as the motor decelerates to stop and the smaller of the absolute value of the terminal A3 torque limit, or the values set in the torque limit parameters (C7-01 to C7-04) is used as the torque limit.

2. When the speed/torque control selection is ON, torque control is activated.
 - *Speed limit during torque control is the master frequency reference at terminal A1, A2, or A3 when speed limit selection (D5-03) is set to “1”, and is the speed limit value (D5-04) when D5-03 = “2”, regardless of the frequency reference selection (B3-01) setting.*
 - *During torque control, the terminal A2 or A3 analog input value becomes the torque reference.*
3. By giving a stop command during torque control, operation changes to speed control automatically, and the motor decelerates to stop. The torque limit during deceleration to stop becomes the values set in the torque limit parameters (C7-01 to C7-04).

NOTE: The control mode actually changes after the speed/torque control selection command changes and the reference delay timer (D5-06) elapses. The speed reference/speed limit and the torque limit/torque reference are stored in the inverter until the time set to D5-06 elapses.

Droop Control

The Drooping function reduces the motor speed based on the load torque of the motor. The actual amount of motor speed reduction is based on the ratio of the amount of motor torque and maximum output frequency (E1-04).

The Droop Delay Time D6-02 sets the response time for the drooping function. Decreasing the Droop Delay Time will cause the response to become quicker; however, instability may occur.

| Parameter | | | | | Access |
|-----------|------------------|---|----------------|---------------|--------|
| Code | Display | Function | Range | Initial Value | Level |
| D6-01 | Droop Quantity | Sets the motor speed reduction when torque output equals 100% | 0.0 - 100.0% | 0.0 | Adv |
| D6-02 | Droop Delay Time | Sets the response time for the drooping function | 0.03 - 2.0 sec | 0.05 | Adv |

Dwell Function

The Dwell Function is used to temporarily hold the output frequency at a set reference for a set time. This function can be used when driving a motor with a heavy starting load. This pause in acceleration reduces traditionally high starting current. Enable by setting H1-01 ~ 06 to 65.

NOTE: This function should not be used for hoists.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|--------------------|---|--------------|---------------|--------------|
| D8-01 | Dwell Ref @ Start | Sets Dwell frequency reference at start. | 0.0–150.0 Hz | 0.0 | Adv |
| D8-02 | Dwell Time @ Start | Sets the time duration for the Dwell function at start. | 0.0–10.0 sec | 0.0 | Adv |
| D8-03 | Dwell Ref @ Stop | Sets dwell frequency Reference at stop. | 0.0–150.0 Hz | 0.0 | Adv |
| D8-04 | Dwell Time @ Stop | Sets the time duration for the Dwell function at stop. | 0.0–10.0 sec | 0.0 | Adv |

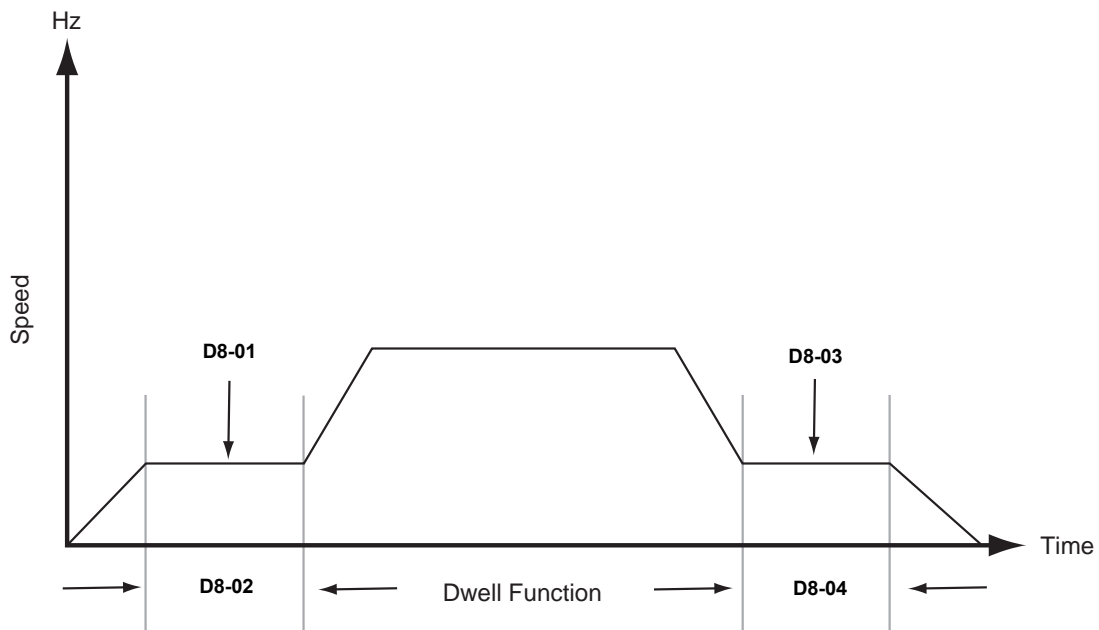


Figure 5-23: Dwell Function

S-Curve Acceleration/Deceleration

An S-Curve pattern is used to reduce shock and provide smooth transitions during machine acceleration and deceleration. S-Curve characteristic time is the time from the output frequency to the set accel/decel time. See S-Curve Characteristic timing diagrams below and on the following page.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|-------------------|----------------------------------|---------------|---------------|--------------|
| D9-01* | S-Crv Acc @ Start | Sets S-Curve time at Accel start | 0.00–2.50 sec | 0.5 | Adv |
| D9-02* | S-Crv Acc @ End | Sets S-Curve time at Accel end | 0.00–2.50 sec | 0.5 | Adv |
| D9-03* | S-Crv Dec @ Start | Sets S-Curve time Decel start | 0.00–2.50 sec | 0.5 | Adv |
| D9-04 | S-Crv Dec @ End | Sets S-Curve time at Decel end | 0.00–2.50 sec | 0.20 | Adv |

*Initial value is determined by X-Press Programming (Table 4.1 to 4.2).

The figure below shows FWD/REV run switching during deceleration to stop. The S-curve function will add time to the acceleration and deceleration. Time to accelerate from the minimum frequency to the maximum frequency (total acceleration) = B5-01 + (D9-01 + D9-02)/2.

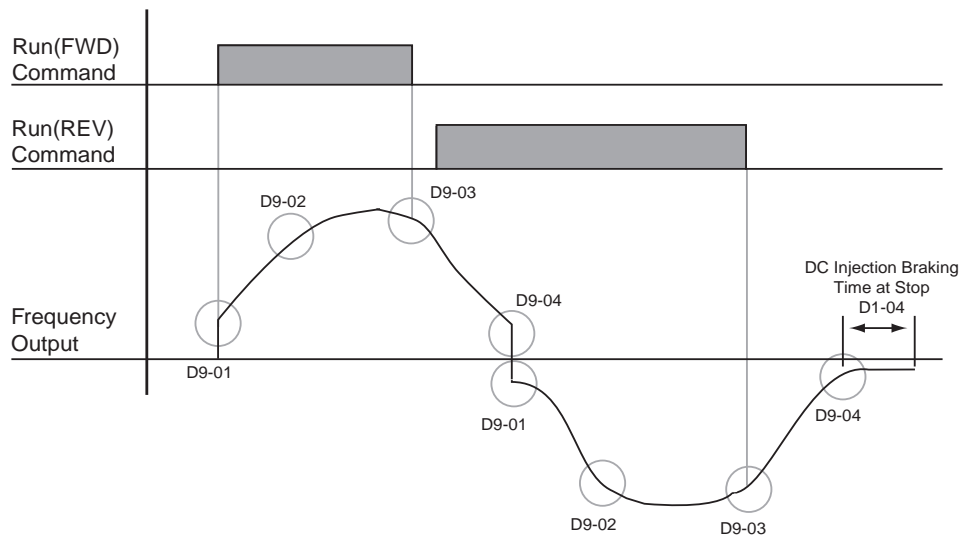


Figure 5-24: S-Curve Characteristics–FWD/REV Operation

Motor Parameters

- E1 V/F Pattern 1
- E2 Motor Set-up
- E3 Motor 2 Method
- E4 Motor 2 V/F Pattern
- E5 Motor 2 Set-up

Voltage/Frequency Pattern

| Parameter Code | Display | Function | Range | Initial ⁽¹⁾ Value | Access Level |
|----------------|---------------|--------------------|---------------------|------------------------------|--------------|
| E1-01 | Input Voltage | Sets input voltage | 155-255/ 310-510 | 230/460 | Adv |

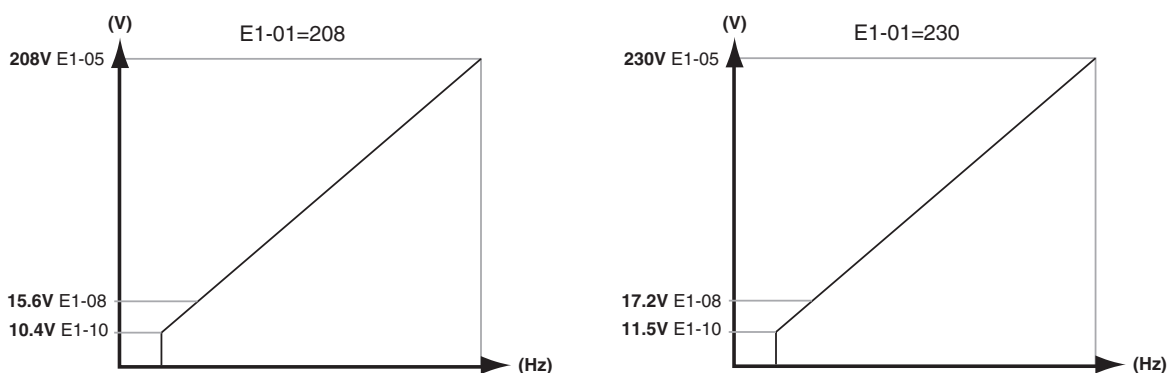


Figure 5-25: E1-01 Input Voltage

- When using flux vector control mode, the V/F pattern voltage values will be adjusted by the Auto-Tuning function.
- Factory setting is 230 (230V units) or 460 (460V units).

The setting E1-01 adjusts the overvoltage level, braking transistor turn on level and the stall prevention level during deceleration.

Table 5-5:

| Inverter Voltage | E1-01 Setting | Overvoltage Trip | | Braking Transistor | | Stall Level |
|------------------|---------------|------------------|-------|--------------------|------|-------------|
| | | Trip | Reset | On | Off | |
| 230 | 150-255 | 400V | 380V | 380V | 375V | 380V |
| 460 | ≥400 | 800V | 760V | 760V | 750V | 760V |
| 460 | <400 | 720V | 680V | 660V | 650V | 670V |

Parameter E1-01 performs the above mentioned function in all three control modes.

Table 5-6: V/F Parameters

| Parameter Code | Display | Function | Range | Initial⁽¹⁾ Value | Access Level |
|-----------------------|-----------------|-----------------------------|---------------|------------------------------------|---------------------|
| E1-04 | Max Frequency | Maximum Frequency | 40.0–150.0 Hz | 60.0 | Adv |
| E1-05 ⁽²⁾ | Max Voltage | Maximum Voltage | 0.0–510.0 V | 460 | Adv |
| E1-06 | Base Frequency | Motor Base Frequency | 0.0–150.0 Hz | 60 | Adv |
| E1-09 | Min Frequency | Minimum Frequency | 0.0–150.0 Hz | 0.0 | Adv |
| E1-11 | Mid Frequency B | Midpoint Output Frequency B | 0.0–150.0 Hz | 0.0 | Adv |
| E1-12 | Mid Voltage B | Midpoint Output Voltage B | 0.0–510.0 V | 0.0 | Adv |
| E1-13 ⁽²⁾ | Base Voltage | Motor Base Voltage | 0.0–510.0 V | 0.0 | Adv |

* Initial value determined by X-Press Programming (Table 4.1 to 4.2).

⁽¹⁾ The initial value displayed here is for 460V class drives.

⁽²⁾ For 230V class units, the value is half that of 460V class units.

Motor Set-up

E2 constants define motor parameters. Normally, the default settings for E2 constants are determined by kVA selection (O2-04). In flux vector control the E2 constants will be set automatically during auto-tuning. If the control method is V/F (A1-02=0), the motor rated current should be entered into E2-01.

If auto-tuning cannot be performed, some E2 constants can be calculated using the motor's nameplate information.

Motor rated slip frequency (E2-02) can be calculated by using the following equation:

$$f_s = f - \frac{(N * P)}{120}$$

Where... f_s : slip frequency (Hz)
 f : rated frequency (Hz)
 N : rated motor speed (rpm)
 P : number of motor poles

Motor terminal resistance E2-05 can be calculated by using the following equation:

$$r_t = r_p * \frac{273 + \left[\frac{(25^\circ C + T_i)}{2} \right]}{273 + T_i}$$

Where... r_t : motor terminal resistance
 r_p : Phase-to-Phase resistance at insulation class temperature
 T_i : insulation class temperature (°C)

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|-------------------|--|----------------|---------------|--------------|
| E2-01 | Motor Rated FLA | Motor-rated current | 0.01–1500.0 A | * | Adv |
| E2-02 | Motor Rated Slip | Motor-rated slip frequency | 0.00-20.00 Hz | * | Adv |
| E2-03 | No-Load Current | Motor no-load current | 0.0–1500.0 A | * | Adv |
| E2-04 | Number of Poles | Number of poles in motor | 2-48 | 4 | Adv |
| E2-05 | Term Resistance | Motor terminal resistance | 0.000–65.000 Ω | * | Adv |
| E2-06 | Leak Inductance | Leakage Inductance | 0.0–30.0% | * | Adv |
| E2-07 | Saturation Comp 1 | Core-Saturation Compensation Coefficient 1 | 0.00–0.50 | * | Adv |
| E2-08 | Saturation Comp 2 | Core-Saturation Compensation Coefficient 2 | 0.00–0.75 | * | Adv |
| E2-11 | Motor Rated Power | Rated output | 0.0-650 kW | * | Adv |

* Initial value is determined by O2-04 (kVA Selection)

This value is automatically set during auto tuning

Motor 2 Method

The Motor 2 method function allows one drive to control two separate motors which are coupled to separate motions. The output of the drive is switched from one motor to the other and a multi-function input (H1-XX=41 Motor 2 Select) informs the drive of which motor is being used. Special functions are disabled and become read only while in Motor 2. Those functions that are disabled include: Load Check (C5), Swift/Ultra Lift (C6), Weight Measurement (C10), Slack Cable (C11), Snap Shaft (C12), and Inching (C13). If encoder feedback is used with Motor 2 then use a PG-Z2 option card.



WARNING

Do not switch between motors when the drive's output is on as it will damage the unit!

Use multi-function output, 1E, as motor 2 switch over control.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|---|-------------------------|-------|---------------|--------------|
| E3-01 | Control Method <i>0 V/F control</i> <i>1 V/F w/PG Fdbk</i> <i>2 Open loop vector</i> <i>3 Flux Vector</i> | Motor 2 control method | 0–3 | 0 | Adv |
| E3-02 | Stopping Method <i>0 Decel to Stop</i> <i>1 Coast to Stop</i> <i>6 No load brake (E3-01 must = 3)</i> | Motor 2 Stopping Method | 0,1,6 | 1 | Adv |

Motor 2 Voltage/Frequency Pattern

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|----------------|---------------------------------------|---------------|---------------|--------------|
| E3-03 | Max Frequency | Maximum frequency for Motor 2 | 40.0–150.0 Hz | 60.0 | Adv |
| E3-04 | Max voltage | Maximum voltage for Motor 2 | 0.0–255.0 V | 230.0 | Adv |
| E3-05 | Base Frequency | Base frequency for Motor 2 | 50.0–150.0 Hz | 60.0 | Adv |
| E3-06 | Mid Frequency | Midpoint output frequency for Motor 2 | 0.0–150.0 Hz | 3.0 | Factory |
| E3-07 | Mid Voltage | Midpoint output voltage for Motor 2 | 0.0–255.0 V | 17.2 | Factory |
| E3-08 | Min Frequency | Minimum output frequency for Motor 2 | 0.0–150.0 Hz | 1.5 | Factory |
| E3-09 | Min Voltage | Minimum output voltage for Motor 2 | 0.0–255.0 V | 10.3 | Factory |

Motor 2 Set-up

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|---------------------|--|---------------|---------------|--------------|
| E4-01 | Motor Rated FLA | Motor-rated current for Motor 2 | 0.0–150.0 A | * | Adv |
| E4-02 | Motor Rated Slip | Motor-rated slip frequency for Motor 2 | 0.00–20.0 Hz | * | Adv |
| E4-03 | No Load Current | Motor no-load current for Motor 2 | 0.0–150.0 A | * | Adv |
| E4-04 | Number of Poles | Number of poles in motor | 2-48 | 4 | Adv |
| E4-05 | Terminal Resistance | Motor 2 Terminal Resistance | 0.000–65.000Ω | * | Adv |
| E4-06 | Leakage Inductance | Leakage Inductance for Motor 2 | 0.0-40% | * | Adv |
| E4-07 | Motor Rated Power | Motor 2 Rated kW | 0.40-650kW | * | Adv |

* Values automatically set at Auto Tuning

Option Card Parameters

- F1 Pulse Generator Option Set-up
- F2 Analog Input 14 Set-up
- F3 Digital Input Option Set-up
- F4 Analog Output Option Set-up
- F5 Digital Output 2 Set-up
- F6 Communication Card Set-up

Encoder (PG) Option Set-up

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|----------------------------|---|--------------------|---------------|--------------|
| F1-01 | Pulses/Rev | Sets encoder Pulses/Rev for Channel 1 | 0–60000 pulses/rev | 1024 | Adv |
| F1-02** | PG Fdbk Loss Sel | Selects stopping method or alarm output when PG line break is detected (both channels). | 0-3 | 1 | Adv |
| | 0 <i>Decel to Stop</i> | Decels to stop | | | |
| | 1 <i>Coast to Stop</i> | Immediate stop | | | |
| | 2 <i>Fast-Stop*</i> | Decel by B5-08 | | | |
| | 3 <i>Alarm Only</i> | Displayed on keypad only | | | |
| F1-03** | PG Overspeed Sel | Selects stopping method or alarm output when motor overspeed is detected (both channels). | 0-3 | 1 | Adv |
| | 0 <i>Decel to Stop</i> | Decels to stop | | | |
| | 1 <i>Coast to Stop</i> | Immediate stop | | | |
| | 2 <i>Fast-Stop*</i> | Decel by B5-08 | | | |
| | 3 <i>Alarm Only</i> | Displayed on keypad only | | | |
| F1-04** | PG Deviation Sel | Selects stopping method when PG deviation is detected. | 0-7 | 5 | Adv |
| | 0 <i>@SpdAgree-Ramp</i> | Ramp to stop by B5-02 | | | |
| | 1 <i>@SpdAgree-Coast</i> | Coast to Stop | | | |
| | 2 <i>@SpdAgree-F-Stop*</i> | Decel by B5-08 | | | |
| | 3 <i>@SpdAgree-Alm</i> | Displayed on keypad only | | | |
| | 4 <i>@Run-Ramp</i> | Ramp to stop by B5-02 | | | |
| | 5 <i>@Run-Coast</i> | Coast to Stop | | | |
| | 6 <i>@Run-Fast Stop*</i> | Decel by B5-08 | | | |
| | 7 <i>@Run-Alarm Only</i> | Displayed on keypad only | | | |
| F1-05 | PG Rotation Sel | Selects PG rotation | 0-1 | 0 | Adv |
| | 0 <i>Fwd = C.C.W.</i> | | | | |
| | 1 <i>Fwd = C.W.</i> | | | | |
| F1-06 | PG Output Ratio | PG division rate (pulse output) | 1-132 | 1 | Adv |

NOTE: *If Fast-stop is selected, the stopping time is set by B5-08 (Fast stop time)
 ** Parameters can not be changed when A1-03 = 2 (No Load Brake Hoist)

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|---|---|-------------|---------------|--------------|
| F1-08 | PG Overspd Level | Motor overspeed detection level. | 0–120% | 105 | Adv |
| F1-09 | PG Overspd Time | Motor overspeed detection time. | 0–2.0 sec | 0.0 | Adv |
| F1-10 | PG Deviate Level | Excessive speed deviation level. | 0–50% | 10 | Adv |
| F1-11 | PG Deviate Time | Excessive speed deviation time. | 0–10.0 sec | 0.3 | Adv |
| F1-12 | PG# Gear Teeth 1 | PG Reduction Ratio | 0-1000 | 0 | Adv |
| F1-13 | PG# Gear Teeth 2 | PG Reduction Ratio Ratio = $60 \times \frac{F1-13}{F1-12}$ Note: A Gear ratio of 1 will be used if either parameter = 0 | 0-1000 | 0 | Adv |
| F1-14 | PGO Detect Time | Open encoder circuit | 0.00-10.00 | 0.50 | Adv |
| F1-16 | PG Ch 2 PPR | Indicates how many pulses the drive can expect per revolution of the motor. | 1-60000 PPR | 1024 | Adv |
| F1-17 | PG Ch 2 Rotation | 0-FWD = CCW 1 - FWD = CW | 0-1 | 0 | Adv |
| F1-18 | PGO-2-S Det Time | Channel 2 open encoder circuit | 0-10.0 Sec | 0.5 Sec | Adv |
| F1-19 | PG-Z2 Output Set | PG-Z2 Output | 0-3 | 2 | Adv |
| | 0 <i>Select by MFI=41</i> | | | | |
| | 1 <i>Channel 1</i> | | | | |
| | 2 <i>Channel 2</i> | | | | |
| | 3 <i>Select by MFI=64</i> | | | | |
| F1-20 | PGO-1-H 0/1 | CH1 Hardware PGO enable/disable | 0-1 | 1 | Adv |
| | 0 <i>Disabled</i> | | | | |
| | 1 <i>Enabled</i> | | | | |
| F1-21 | PGO-2-H 0/1 | CH2 Hardware PGO enable/disable | 0-1 | 0 | Adv |
| | 0 <i>Disabled</i> | | | | |
| | 1 <i>Enabled</i> | | | | |
| F1-22 | PG-Z2 Input Sel | Option Card PG-Z2 channel select | 0-1 | 0 | Adv |
| | 0 <i>Ch1 = motor 1, Ch 2 = motor 2</i> | | | | |
| | 1 <i>Ch 2 = motor 2, Ch 2 = motor 1</i> | | | | |

* Factory setting changes based on Control Method (A1-02)

AI-14 Option Set-up

Sets CH1 to CH3 input functions when AI-14B option is connected (2CN).

When the 3CH individual input is used, parameter B3-01 is automatically set to “1” (frequency reference from control circuit terminal). The option/inverter reference selection, which is selected by a multi-function contact input (H1-XX= “1F”), is disabled when using the AI-14B option.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|-----------------|---|-------|---------------|--------------|
| F2-01 | AI-14 Input Sel | Determines whether the 3-channel input selection is individual or additional. | 0-1 | 0 | Adv |
| | 0 | 3ch Individual | | | |
| | 1 | 3ch Additional | | | |

Sets CH1 to CH3 input functions when AI-14B option is connected

| Setting | Function | CH1 (TC1 to TC4) | CH2 (TC2 to TC4) | CH3 (TC3 to TC4) |
|---------|--|---|----------------------------------|----------------------------------|
| 0 | 3-channel individual input (factory default) | Substitute for terminals A1 & AC | Substitute for terminals A2 & AC | Substitute for terminals A3 & AC |
| 1 | 3-channel additional input | Sum of CH1 to CH3 input values is used as the frequency reference value | | |

Digital Input Option Set-up

Selects the setting of the frequency reference input from the DI-08 and DI-16H option cards.

NOTE: B3-01 must be set to 3-option PCB when using these cards.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|-----------------|---|-----------|---------------|--------------|
| F3-01 | DI Option Setup | Selects the setting mode of the reference input from the DI-08 and DI-16H options | 0-7 | 7 | Adv |
| | 0 | BCD 1% | | | |
| | 1 | BCD 0.1% | | | |
| | 2 | BCD 0.01% | | | |
| | 3 | BCD 1Hz | | | |
| | 4 | BCD 0.1Hz | | | |
| | 5 | BCD 0.01Hz | | | |
| | 6 | BCD (5DG) 0.01Hz | | | |
| | | Binary | | | |
| | | DI-08: | 255/100% | | |
| | | DI-16H, 12 bit selection: | 4096/100% | | |
| | | DI-16H, 16 bit selection: | 3000/100% | | |
| | 7 | Binary | | | |
| | | Set value is displayed in decimal notation | | | |

Analog Output Option Set-up

Selects the analog output monitors for channel 1 and 2 if AO-08 and AO-12 optional card is connected to 3CN.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|--------------------------------------|--|------------|---------------|--------------|
| F4-01 | AO Ch1 Select | Analog output option Channel 1 selection | 1–50 | 2 | Adv |
| | 1 <i>Frequency Ref</i> | | | | |
| | 2 <i>Output Freq</i> | | | | |
| | 3 <i>Output Current</i> | | | | |
| | 5 <i>Motor Speed</i> | | | | |
| | 6 <i>Output Voltage</i> | | | | |
| | 7 <i>DC Bus Voltage</i> | | | | |
| | 8 <i>Output kWatts</i> | | | | |
| | 9 <i>Torque Reference</i> | | | | |
| | 15 <i>Term A1 Level</i> | | | | |
| | 16 <i>Term A2 Level</i> | | | | |
| | 17 <i>Term A3 Level</i> | | | | |
| | 18 <i>Mot SEC Current</i> | | | | |
| | 19 <i>Mot EXC Current</i> | | | | |
| | 20 <i>SFS Output</i> | | | | |
| | 21 <i>ASR Input</i> | | | | |
| | 22 <i>ASR Output</i> | | | | |
| | 23 <i>PG-Z2 CH2 Feedback</i> | | | | |
| | 24 <i>PID Feedback</i> | | | | |
| | 26 <i>Voltage Ref (Vq)</i> | | | | |
| | 27 <i>Voltage Ref (Vd)</i> | | | | |
| | 29 <i>Load Weight</i> | | | | |
| | 30 <i>SS Delta Speed</i> | | | | |
| | 31 <i>Not used</i> | | | | |
| | 32 <i>ACR (q) Output</i> | | | | |
| | 33 <i>ACR (d) Output</i> | | | | |
| | 36 <i>PID Input</i> | | | | |
| | 37 <i>PID Output</i> | | | | |
| | 38 <i>PID Setpoint</i> | | | | |
| | 41 <i>Heat Sink Temp (10V=100°C)</i> | | | | |
| | 44 <i>ASR Out w/o Filter</i> | | | | |
| | 50 <i>Hook height (10V=100%)</i> | | | | |
| F4-02 | AO Ch1 Gain | Analog output Channel 1 multiplier | 0.00-1000% | 100% | Adv |
| F4-03 | AO Ch2 Select | Analog output option Channel 2 selection (Same as F4-01) | 1–50 | 3 | Adv |
| F4-04 | AO Ch2 Gain | Analog output Channel 2 multiplier | 0.00-1000% | 50% | Adv |
| F4-05 | CH1 A0 Bias | Channel 1 bias | -110%-110% | 0.0 | Adv |
| F4-06 | CH2 A0 Bias | Channel 2 bias | -110%-110% | 0.0 | Adv |

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|--|-------------------------|-------|---------------|--------------|
| F4-07 | AO Opt Level CH1 0 0-10V DC 1 -10-10V DC | Channel 1 output signal | 0-1 | 0 | Adv |
| F4-08 | AO Opt Level CH2 0 0-10V DC 1 -10-10V DC | Channel 2 output signal | 0-1 | 0 | Adv |

Digital Output Set-up with Option Card DO-02 or DO-08

Selects the multi-function output settings for channels 1 and 2 of the DO-02C option card and channels 1 through 8 of the DO-08 option card.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|-------------------------------|--|-------|---------------|--------------|
| F5-01 | DO Ch1 Select | Determines the digital output of Channel 1 (See H2-01) | 0-FF | F | Adv |
| F5-02 | DO Ch2 Select | Determines the digital output of Channel 2 (See H2-01) | 0-FF | F | Adv |
| F5-03 | DO Ch3 Select | Determines the digital output of Channel 3 (See H2-01) | 0-FF | F | Adv |
| F5-04 | DO Ch4 Select | Determines the digital output of Channel 4 (See H2-01) | 0-FF | F | Adv |
| F5-05 | DO Ch5 Select | Determines the digital output of Channel 5 (See H2-01) | 0-FF | F | Adv |
| F5-06 | DO Ch6 Select | Determines the digital output of Channel 6 (See H2-01) | 0-FF | F | Adv |
| F5-07 | DO Ch7 Select | Determines the digital output of Channel 7 (See H2-01) | 0-FF | F | Adv |
| F5-08 | DO Ch8 Select | Determines the digital output of Channel 8 (See H2-01) | 0-FF | F | Adv |
| F5-09 | DO-08 Selection | DO-08 option card output mode selection | 0-3 | 2 | Adv |
| | 0 8 Ch Individual | | | | |
| | 1 Binary Output | | | | |
| | 2 Output per F5-01 ~ 08 | | | | |
| | 3 Serial Communication output | | | | |

Selects the multi-function output selections for the DO-08 option.

| DO-08 Output Mode Selection for F7 C&H | | | | | | |
|--|-----------------------------------|--------------------|--|--|-----------------------|--|
| Parameter F5-09 setting | Output Type | Terminals | Output Contents | | | |
| 0 | 8-Channel Individual (Fixed Data) | TD5 – TD11 | OverCurrent (SC, OC, GF) | | | |
| | | TD6 – TD11 | OverVoltage (OV) | | | |
| | | TD7 – TD11 | Drive Overload (OL2, OH, OH1) | | | |
| | | TD8 – TD11 | Fuse Blown (PUF) | | | |
| | | TD9 – TD11 | OverSpeed (OS-1, OS-2) | | | |
| | | TD10 – TD11 | Motor Overload (OL1) | | | |
| | | TD1 – TD2 | Brake Release | | | |
| | | TD3 – TD4 | Limit Switch (UL1, UL2, UL3, LL1 or LL2) | | | |
| 1 | Binary Coded | TD5 – TD11 (Bit 0) | Bit 3, 2, 1, 0 | Output | Bit 3, 2, 1, 0 | Output |
| | | | 0000 | No Fault | 1000 | EF (ALL) |
| | | TD6 – TD11 (Bit 1) | 0001 | SC, OC, GF | 1001 | CPF (ALL) |
| | | | 0010 | OV | 1010 | oL1 |
| | | | 0011 | OL2 | 1011 | BE7 |
| | | TD7 – TD11 (Bit 2) | 0100 | OH, OH1 | 1100 | UV (ALL) |
| | | | 0101 | OS-1, OS-2 | 1101 | DEV-1, DEV-2 |
| | | TD8 – TD11 (Bit 3) | 0110 | PUF | 1110 | PGO-1-S PGO-1-H PGO-2-S PGO-2-H |
| | | | 0111 | LF | 1111 | Not Used |
| | | TD9 – TD11 | Minor Fault (Alarm) | | | |
| | | TD10 – TD11 | Inverter Ready | | | |
| | | TD1 – TD2 | Brake Release | | | |
| | | TD3 – TD4 | Limit Switch (UL1, UL2, UL3, LL1 or LL2) | | | |
| 2 | 8-Channel Selectable | TD5 – TD11 | F5-01 (See H2-01 ~ 03 for output selections) | | | |
| | | TD6 – TD11 | F5-02 (See H2-01 ~ 03 for output selections) | | | |
| | | TD7 – TD11 | F5-03 (See H2-01 ~ 03 for output selections) | | | |
| | | TD8 – TD11 | F5-04 (See H2-01 ~ 03 for output selections) | | | |
| | | TD9 – TD11 | F5-05 (See H2-01 ~ 03 for output selections) | | | |
| | | TD10 – TD11 | F5-06 (See H2-01 ~ 03 for output selections) | | | |
| | | TD1 – TD2 | F5-07 (See H2-01 ~ 03 for output selections) | | | |
| | | TD3 – TD4 | F5-08 (See H2-01 ~ 03 for output selections) | | | |
| 3 | Serial Com | TD5 – TD11 | 00000001 | Through communication to register 000BH, TD1 - TD10 are independently controlled. Writing 00000100 to 000BH would turn on TD7 - TD11. (Bit 7, 6, 5, 4, 3, 2, 1, 0) | | |
| | | TD6 – TD11 | 00000010 | | | |
| | | TD7 – TD11 | 00000100 | | | |
| | | TD8 – TD11 | 00001000 | | | |
| | | TD9 – TD11 | 00010000 | | | |
| | | TD10 – TD11 | 00100000 | | | |
| | | TD1 – TD2 | 01000000 | | | |
| | | TD3 – TD4 | 10000000 | | | |

Communication Option Cards

Settings for DP-RAM option cards.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|---|---|-------|---------------|--------------|
| F6-01 | Com Bus Flt Sel <i>0 Decel to Stop</i> <i>1 Coast to Stop</i> <i>2 Fast Stop</i> <i>3 Use B3-03 Method</i> <i>4 Alarm only</i> | Stopping method at communication error. | 0-4 | 1 | Adv |
| F6-02 | EFO Detection <i>0 Always Detected</i> <i>1 Only During Run</i> | Option External Fault | 0-1 | 0 | Adv |
| F6-03 | EFO Fault Action <i>0 Decel to Stop</i> <i>1 Coast to Stop</i> <i>2 Fast Stop</i> <i>3 Use B3-03</i> <i>4 Alarm Only</i> | Option External Fault | 0-4 | 1 | Adv |
| F6-05 | Current Unit Sel <i>0 A Display</i> <i>1 100%/8192</i> | Current Unit | 0-1 | 0 | Adv |
| F6-06 | Torq Ref/Lmt Sel <i>0 Disabled</i> <i>1 Enabled</i> | Torque Reference Limit Selection | 0-1 | 0 | Adv |

Terminal Parameters

- H1 Digital Inputs
- H2 Digital Outputs
- H3 Analog Inputs
- H4 Analog Outputs
- H5 Serial Communication Set-up
- H6 Pulse Input

Digital Inputs

The IMPULSE•VG+ Series 3 has six multi-function contact inputs for the set-up of numerous functions. The following table lists the function selections for the multi-function contact inputs (terminals S3 to S8) and indicates the control modes during which each function can be enabled. An OPEO3 error will occur if a function is programmed in more than one terminal at the same time.

| Parameter Code | Display | Function | Ref Page Number | Range | Initial Value | Access Level |
|----------------|---------------------------------------|--|-----------------|-------|---------------|--------------|
| H1-01* | Terminal S3 Sel <i>(parameter)</i> | Selects the multi-function inputs. | -- | 0-73 | 0 | Adv |
| H1-02* | Terminal S4 Sel <i>(parameter)</i> | Same as H1-01 | -- | 0-73 | 1 | Adv |
| H1-03* | Terminal S5 Sel <i>(parameter)</i> | Same as H1-01 | -- | 0-73 | F | Adv |
| H1-04* | Terminal S6 Sel <i>(parameter)</i> | Same as H1-01 | -- | 0-73 | F | Adv |
| H1-05* | Terminal S7 Sel <i>(parameter)</i> | Same as H1-01 | -- | 0-73 | F | Adv |
| H1-06* | Terminal S8 Sel <i>(parameter)</i> | Same as H1-01 | -- | 0-73 | F | Adv |
| | 0 <i>Multi-Step Ref 2</i> | <i>Multi-Step Reference 2 (Use with 3A to Enable A2).</i> | 5-3 | | | |
| | 1 <i>Multi-Step Ref 3</i> | <i>Multi-Step Reference 3 (Use with 3A to Enable A3).</i> | 5-3 | | | |
| | 2 <i>Multi-Step Ref 4</i> | <i>Multi-Step Reference 4.</i> | 5-3 | | | |
| | 3 <i>Multi-Step Ref 5</i> | <i>Multi-Step Reference 5.</i> | 5-3 | | | |
| | 4 <i>Speed Hold 2</i> | <i>Hold function (2nd step of Three-Step Infinitely Variable).</i> | 4-10 | | | |
| | 5 <i>Accel Command</i> | <i>Acceleration function (2nd step of Two-Step Infinitely Variable or 3rd step of Three-Step Infinitely Variable).</i> | 4-10 | | | |
| | 6 <i>Upper Lmt 1 N/O</i> | <i>Upper Limit-SLOW DOWN; Normally Open. UL1 - blinking</i> | 5-20 | | | |
| | 7 <i>Upper Lmt 2 N/O</i> | <i>Upper Limit-STOP; Normally Open. UL2 - blinking</i> | 5-20 | | | |
| | 8 <i>Lower Lmt 1 N/O</i> | <i>Lower Limit-SLOW DOWN; Normally Open. LL1 - blinking</i> | 5-20 | | | |
| | 9 <i>Lower Lmt 2 N/O</i> | <i>Lower Limit-STOP; Normally Open. LL2 - blinking</i> | 5-20 | | | |

| Parameter Code | Display | Function | Ref Page Number | Range | Initial Value | Access Level |
|----------------|-------------------|--|-----------------|-------|---------------|--------------|
| A | Upper Lmt 1 N/C | Upper Limit–SLOW DOWN; Normally Closed. UL1 - blinking | 5-20 | | | |
| B | Upper Lmt 2 N/C | Upper Limit–STOP; Normally Closed. UL2 - blinking | 5-20 | | | |
| C | Lower Lmt 1 N/C | Lower Limit–SLOW DOWN; Normally Closed. LL1 - blinking | 5-20 | | | |
| D | Lower Limit 2 N/C | Lower Limit–STOP; Normally Closed. LL2 - blinking | 5-20 | | | |
| E | M-Speed Gain 1 | Micro-Speed Positioning Control Multiplier 1. Gain is set by parameter C2-01 (Has priority over MS 2) | 5-19 | | | |
| F | Not used | No function - terminal is disabled | -- | | | |
| 10 | M-Speed Gain 2 | Micro-Speed Positioning Control Multiplier 2. Gain is set by parameter C2-02. | 5-19 | | | |
| 11 | Load Float 1 | Load Float Hold; when input during run, Load Float will remain on indefinitely - Fref is held at 0 while MFI is ON. | -- | | | |
| 12 | Weight Lmt N.C. | Weighted Upper Limit - UL3. Stopping method determined by C3-08. | 5-20 | | | |
| 13 | Ultra/Swift Lift | Ultra/Swift Lift Enable (C6-01 = 2). Not available for traverse motion. | 5-27 | | | |
| 14 | Alt T-Lim Gain | Alternate Torque Limit Gain - C7-05. Use when Load Testing a hoist. Internal tlim * C7-05 | 5-29 | | | |
| 15 | Forward Jog | Jog Control FORWARD command. Uses B1-17 Reference | 5-3 | | | |
| 16 | Reverse Jog | Jog Control REVERSE command. Uses B1-17 Reference. | 5-3 | | | |
| 17 | Forward Inch | Inch Control | 5-46 | | | |
| 18 | Reverse Inch | Inch Control | 5-46 | | | |
| 19 | Inch Repeat | Inch Control | 5-46 | | | |
| 1A | Acc/Dec 2 | Acceleration/Deceleration Time Changeover 2 using B5-03 and B5-04 | 5-12 | | | |
| 1B | Acc/Dec 3 | Acceleration/Deceleration Time Changeover 3 using B5-12 and B5-13 | 5-13 | | | |
| 1C | Acc/Dec 4 | Acceleration/Deceleration Time Changeover 4 using B5-14 and B5-15 | 5-13 | | | |
| 1D | Digital Chngover | Analog/Digital Switch (Analog/Digital Reference Changeover; When B1-18 = 1 - If Closed = Digital). | 5-13 | | | |
| 1F | Opt/Inv Switch | Option/Inverter Selection (Frequency & Run Reference from Option Card. Closed = Option Card.). B3-01, 02 = Terminals | -- | | | |

| Parameter Code | Display | Function | Ref Page Number | Range | Initial Value | Access Level |
|----------------|------------------|--|-----------------|-------|---------------|--------------|
| 20 thru 2F | External Fault | External Fault (Desired setting is possible) Input Mode: N.O./N.C., Detection Mode: Always/ During Run | 5-78 | | | |
| 30 | Program Lockout | Program Lockout (Closed: Parameters enabled to write; Open: Parameters disabled to write other than freq. reference (U1-01)) | -- | | | |
| 31 | Local/Remote Sw | Local/Remote Changeover. Closed = Local | -- | | | |
| 32 | Ext BB N.O. | External BB N.O. - (N.O.: Baseblock by ON). | -- | | | |
| 33 | Ext BB N.C. | External BB N.C. - (N.C.: Baseblock by OFF). | -- | | | |
| 34 | Spd/Trq Chngover | Speed/Torque Control Changeover (ON: Torque Control) | 5-51 | | | |
| 35 | Load Float 2 | Load Float initiated. Manual Load Float Timed by C4-01. (Stop Method must be No Load Brake) | 5-25 | | | |
| 36 | Polarity Rev | Polarity Reversing command for External Torque Control. Closed = Reverse Polarity | -- | | | |
| 37 | ASR Gain Switch | ON: Switches to ASR Gain 2 parameters. Forces D4-07 | 5-51 | | | |
| 38 | Speed Hold 1 | (Accel/decel is stopped by ON, and frequency is held) | -- | | | |
| 39 | External OH2 | Inverter overheat prediction (OH2 is shown by ON) (Alarm only) | -- | | | |
| 3A | Trm A2/A3 Enable | Multi-function analog input (A3) Enable/Disable - (When programmed, analog input A2/A3 is enabled by ON. A2 and A3 are enabled by Multi-step Ref 1 and 2 respectively. H1-0x = 0 or 1) | -- | | | |
| 3D | Fref UP Cmd | Fref UP Cmd - (Make sure to set with DOWN command) (Used with B4-01) | 5-10 | | | |
| 3E | Fref Down Cmd | Fref DOWN Cmd - (Make sure to set with UP command) (Used with B4-01) | 5-10 | | | |
| 3F | Fault Reset | Fault Reset (Reset by ON) | -- | | | |
| 40 | Fast Stop N.O. | Fast Stop N.O. - (N.O.: Deceleration to stop by fast stop time B5-08 at ON.) | 5-13 | | | |
| 41 | Motor 2 Switch | Motor 2 Switch - Motor 2 changeover command (ON: Motor 2 selected) | 5-61 | | | |
| 42 | Fast Stop N.C. | Fast Stop N.C. - (N.C.: Deceleration to stop by fast stop time B5-08 at OFF.) | 5-13 | | | |
| 43 | Timer Enable | Function settings by C12-03, C12-04. It is set with time function output [Multi-Function Output] | 5-44 | | | |

| Parameter Code | Display | Function | Ref Page Number | Initial Value | Access Level |
|----------------|--------------------|--|-----------------|---------------|--------------|
| 45 | + Speed Cmd | ON: B4-02 frequency is added to analog frequency references | 5-11 | | |
| 46 | — Speed Cmd | ON: B4-02 frequency is subtracted from analog frequency reference | 5-11 | | |
| 47 | Analog Hold | Analog frequency reference Sample/Hold | -- | | |
| 4C | DCInj Activate | ON: DC injection braking command, once SFS reaches Zero Speed | 5-49 | | |
| 50 | Ext Spd Search 3 | OFF: Motor Base Blocked, ON: Speed Search | -- | | |
| 53 | Comm Test | Communication Test Mode - Loopback test of Modbus RS-422/485 interface | -- | | |
| 55 | Drive Enable | When programmed, must be ON in order for Inverter Ready - Generates "Can't Run - Drive Not Ready" alarm. "RDY" is displayed in upper right hand corner of LCD when drive is ready. | -- | | |
| 56 | Klixon N.O. | When Closed, Reset run command, use stopping method B3-03, display KLX - Klixon Alarm on Keypad | 5-20 | | |
| 57 | Klixon N.C. | When Open, Reset run command, stop using method B3-03, display KLX - Klixon Alarm on Keypad | 5-20 | | |
| 58 | Brake Answer back | Generates BE1, BE4, BE5, BE7 alarm or fault conditions only when programmed to MFI. (C8-04, C8-11) | 5-32 | | |
| 59 | Alt F-Ref Up Lmt | Use Alternate Upper Limit Frequency Reference B2-04 | 5-5 | | |
| 5A | Maintenance Reset | Resets Maintenance Timer (C12-05 ~ 06, U1-52) | 5-45 | | |
| 5B | BE6 Up Speed Lmt | Limits Fref to setting in C8-17 (BE6 Up Speed Limit) | 5-32 | | |
| 5C | Weight Measure | Weight Measurement by C10-01 | 5-38 | | |
| 5D | Load Float Ext | Extends C8-10 Time by adding C8-15 Time | 5-32 | | |
| 5E | M-Spd Gni + LF-E | Micro Speed Gain 1 and Load Float Extension Time (Combination of MFI "E" and 5D ON) | 5-19 | | |
| 5F | Phantom Fault N.C. | Stop motion based C3-09 but does not change Keypad display. STOP L.E.D. on JVOP blinks. | 5-20 | | |
| 60 | Index Enable | Enables indexing function (Hidden if B3-03 = 1) | 5-48 | | |
| 61 | Brake Test | Motor pushes against brake up to programmable torque setting C8-19 at programmable frequency C8-20. Disables PG Faults during this condition. | 5-32 | | |

| Parameter Code | Display | Function | Ref Page Number | Range | Initial Value | Access Level |
|----------------|---------------------|--|-----------------|-------|---------------|--------------|
| 62 | Weight Limit N.O. | (Weighted Upper Limit - UL3) - Stopping method determined by C3-08 | 5-20 | | | |
| 63 | Phantom Fault N.O. | Stops motion based C3-09 but does not change Keypad display. STOP L.E.D. on JVOP Blinks. | 5-20 | | | |
| 64 | PG Ch1 Output | Enabled to select when PG-Z2 o pt. code is present and F1-19=3. Off: TA3 = CH2, ON: CH1 = TA3 | 5-63 | | | |
| 65 | Dwell Enable | Enables/Disables Dwell Function. When H1-0x = 65H, OFF = Disabled. | 5-55 | | | |
| 66 | Load Share 0/1 | Enables/Disables Load Sharing. | 5-24 | | | |
| 67 | Hook Height Home | Used w/ C8-24 - Height Measurement function | 5-33 | | | |
| 68 | PG-Z2 Input Sel | Off: Motor 1 = CH1, On: Motor 1 = CH2 | 5-63 | | | |
| 70 | Torque Det 0/1 | When H1-0x = 70H, Overtorque/Undertorque detection is enabled and disabled by MFDI. When the input is closed, Overtorque/Undertorque detection is enabled. | 5-91 | | | |
| 71 | Test Mode 0/1 | Test Mode Disable/Enable: When MFDI 71H is closed, the control method and stopping method are changed according to the setting of L5-01 and L5-02. An internal timer is accumulated while the input is on. Motor speed is displayed at U1-05. Open: Test Mode is Disabled. Closed: Test Mode is Enabled. | 5-88 | | | |
| 73 | LL2/UL2 Bypass MFDI | Bypass limit MFDI and EPLS (7H, BH, 9H, DH, C3-12 & C3-15) | 5-21 | | | |

* Initial value is determined by X-Press Programming (Table 4.1 to 4.2).

Digital Outputs

The IMPULSE•VG+ Series 3 has three multi-function control outputs for indicating various conditions. The following table lists the function selections for the multi-function contact outputs and indicates the control modes during which each function can be enabled.

| Parameter Code | Display | Function | Reference | | Initial Value | Access Level |
|----------------|-------------------|---------------------------|-------------|---|---------------|--------------|
| | | | Page Number | Range | | |
| H2-01 | Terminal M0-M1 | Digital Output 1 Function | -- | 0–FF | 0 | Adv |
| H2-02 | Terminal M2-M3-M4 | Digital Output 2 Function | -- | 0–FF | 0 | Adv |
| H2-03 | Terminal M5 - M6 | Digital Output 3 Function | -- | 0–FF | 78 | Adv |
| | 0 | Brake Release | | Closed when voltage or frequency is output | 5-67 | |
| | 1 | Zero Speed | | Closed when below B2-02 or D1-01 | -- | |
| | 2 | Fref/Fout Agree 1 | | Output when Frequency Reference and Frequency Output agree | 5-87 | |
| | 3 | Fref/Set Agree 1 | | Output when Output Frequency Reference equals L4-01. | 5-88 | |
| | 4 | Freq Detect 1 | | Closed when output frequency is < L4-01. | 5-88 | |
| | 5 | Freq Detect 2 | | Closed when output frequency is > L4-01. | 5-88 | |
| | 6 | Inverter Ready | | Closed when an inverter is not in a fault state | -- | |
| | 7 | DC Bus Undervolt | | Closed when DC Bus voltage drops below UV trip point. | -- | |
| | 8 | BaseBlk N.O. | | Closed when the inverter is not outputting voltage. | -- | |
| | 9 | Operator Reference | | Closed when the frequency reference is input from the digital operator (02-01). | 5-97 | |
| | A | Local Operation | | Closed when the RUN command is input from the digital operator. | 5-98 | |
| | B | Trq Det 1 N.O. | | Output when torque > L6-02 | 5-91 | |
| | D | DB Overheat | | Closed when inverter displays "RH" or "RR" fault. | -- | |
| | E | Fault | | Closed during a major fault. | 6-3 | |
| | F | Not Used | | No function | | |
| | 10 | Minor Fault | | Closed during minor fault or alarm. | 6-3 | |
| | 11 | Reset Cmd Active | | Closed when a reset command is present on the terminals | -- | |
| | 12 | Timer Output | | Timer function output | 5-44 | |
| | 13 | Fref/Fout Agree 2 | | Closed when output frequency = frequency reference | 5-88 | |
| | 14 | Fref/Set Agree 2 | | Closed when output frequency = L4-03 | 5-88 | |

| Parameter Code | Display | Function | Reference Page Number | Range | Initial Value | Access Level |
|----------------|------------------|---|-----------------------|-------|---------------|--------------|
| 15 | Freq Detect 3 | Closed when output frequency is \leq L4-03 | 5-88 | | | |
| 16 | Freq Detect 4 | Closed when output frequency \geq L4-03 | 5-88 | | | |
| 17 | Trq Det 1 N.C. | Open when torque > L6-02 | 5-91 | | | |
| 18 | Trq Det 2 N.O. | Closed when torque > L6-05 | 5-92 | | | |
| 19 | Trq Det 2 N.C. | Open when torque > L6-05 | 5-92 | | | |
| 1A | Forward Dir | Closed when running FWD/UP | -- | | | |
| 1B | Reverse Dir | Closed when running REV/DOWN | -- | | | |
| 1C | Swift/Ultra Lift | Swift/Ultra Lift is active | 5-27 | | | |
| 1D | BaseBlk N.C. | During baseblock 2 | -- | | | |
| 1E | Motor 2 Selected | Closed when motor 2 changeover is input to terminals | 5-61 | | | |
| 1F | Regenerating | Regenerating | 5-29 | | | |
| 20 | Auto-Rst Attempt | Auto-Reset Enabled | 5-94 | | | |
| 21 | Overload OLI | OLI Overload fault code | 6-8 | | | |
| 22 | OH Prealarm | Closed when "OH" is displayed on keypad | 6-7 | | | |
| 23 | Torque Limit | Current Torque Limit | 5-29 | | | |
| 24 | Speed Limit | Speed Limit | -- | | | |
| 25 | Load Float | Movement C4-03 count | -- | | | |
| 26 | Run Cmd is input | During Run - ON: | -- | | | |
| 27 | Load Check Det | Load Check detected | 5-26 | | | |
| 28 | Slack Cable Det | Slack Cable Detection output | 5-41 | | | |
| 29 | Upper Limit | Closed when Upper Limit–SLOW DOWN or Upper Limit STOP is input | 5-20 | | | |
| 2A | During Run 1 | Used with Load Share | 5-24 | | | |
| 2B | Upper Limit 1 | Output during Upper Limit 1 | 5-20 | | | |
| 2C | Upper Limit 2 | Output during Upper Limit 2 | 5-20 | | | |
| 2D | Lower Limit 1 | Output during Lower Limit 1 | 5-20 | | | |
| 2E | Lower Limit 2 | Output during Lower Limit 2 | 5-20 | | | |
| 30 | Lower Limit | Closed when Lower Limit–SLOW DOWN or Lower Limit STOP is input | 5-20 | | | |
| 31 | Up/Low Lmt | Closed when Upper Limit–SLOW DOWN or Upper Limit STOP or Lower Limit–SLOW DOWN or Lower Limit STOP is input | 5-20 | | | |
| 32 | Snap Shaft | See C11-09 | 5-43 | | | |
| 33 | Weight Limit | Enabled by C10-08 | 5-38 | | | |
| 34 | Index Complete | Index move is complete | 5-47 | | | |
| 35 | Torq Proving OK | Torque Proving successful, brake is released, drive ready for F-Ref. | -- | | | |
| 36 | During Load FLT | Drive in Load Float | 5-32 | | | |
| 37 | Maintenance | Timer reaches C12-05 | 5-45 | | | |

| Parameter Code | Display | Function | Reference Page Number | Range | Initial Value | Access Level |
|-----------------------|----------------------------|---|------------------------------|--------------|----------------------|---------------------|
| 38 | <i>Spd Lim @ Tcont</i> | <i>On when in Torque Control and output frequency is at upper limit</i> | 5-51 | | | |
| 39 | <i>Drive Enable</i> | <i>Closed when drive enable is active</i> | -- | | | |
| 3E | <i>Overspeed</i> | <i>Closed when Overspeed is detected</i> | -- | | | |
| 3F | <i>Klixon</i> | <i>MFDI 56 to 57 has changed state - motor is overheating</i> | 5-20 | | | |
| 40 ~ | <i>FF Fault Annunciate</i> | <i>Closed on specified faults.</i> | 5-77 | | | |

Digital Outputs—Alarm/Fault Annunciate (H2-01~03=40)

Digital Outputs—Fault Annunciate enables you to assign a set of six fault outputs to Relay Output M3/M4 and/or Output M5/M6. In addition, you can select whether each fault output is enabled.

NOTE: Output M0/M1 can also be used for Digital Outputs—Fault Annunciate; however, it is normally assigned to a brake output.

Before you start to program this feature, you may find it convenient to first photocopy the “Binary-to-Hexadecimal Conversion Worksheet” in this section. By being able to write in the worksheet’s boxes, you will find it easier to program the feature.

Programming **Digital Outputs—Fault Annunciate** requires that you determine two 4-digit binary numbers and then convert these numbers to two 1-digit hexadecimal numbers. You enter the hexadecimal numbers when you program the drive.

To program **Digital Outputs—Fault Annunciate** (assuming you are in **Programming Mode**):

1. Press the **UP** button until

| |
|-----------------|
| Digital Outputs |
| H2-01=0 |
| TERM M0-M1 SEL |

 appears.
2. Determine the output terminal to which you want **Fault Annunciate** assigned; Terminals M0-M1, M2-M4 or M5-M6.
3. Press the

| |
|---|
| > |
|---|

 button. “01” blinks. Press the **UP** arrow button to select Relay Outputs 2 or 3.
4. Press the **DATA/ENTER** button.
5. Press the **UP** or **DOWN** button until

| |
|------------------|
| H2-XX=40 |
| Fault Annunciate |

 appears.
6. Press the **DATA/ENTER** button.

| |
|------------------|
| Fault Data Input |
| OF |

 appears.
7. From the following worksheet, select one of three fault output sets. (Each row is a set.)
Enter the one-zero combination that corresponds to the set (row) that you selected.

For example, if you selected Set 2, you would enter “1 0” in the first two columns from the left, which would represent the first two digits of the first binary number that you would convert later.

Table 5-7: Binary-to-Hexadecimal Conversion Worksheet

| | First digit from the left | | | | Second digit from the left | | | | | | | | | | |
|--------|--|--------|--|--------|--|--------|--|--------|--|--------|--|--------|--|--------|--|
| | <table border="1"><tr><td>1 or 0</td></tr></table> | 1 or 0 | <table border="1"><tr><td>1 or 0</td></tr></table> | 1 or 0 | <table border="1"><tr><td>1 or 0</td></tr></table> | 1 or 0 | <table border="1"><tr><td>1 or 0</td></tr></table> | 1 or 0 | <table border="1"><tr><td>1 or 0</td></tr></table> | 1 or 0 | <table border="1"><tr><td>1 or 0</td></tr></table> | 1 or 0 | <table border="1"><tr><td>1 or 0</td></tr></table> | 1 or 0 | <table border="1"><tr><td>1 or 0</td></tr></table> |
| 1 or 0 | | | | | | | | | | | | | | | |
| 1 or 0 | | | | | | | | | | | | | | | |
| 1 or 0 | | | | | | | | | | | | | | | |
| 1 or 0 | | | | | | | | | | | | | | | |
| 1 or 0 | | | | | | | | | | | | | | | |
| 1 or 0 | | | | | | | | | | | | | | | |
| 1 or 0 | | | | | | | | | | | | | | | |
| 1 or 0 | | | | | | | | | | | | | | | |
| Set 1 | 0 | 1 | BE8 | BE6 | BE5 | BE3 | BE2 | BE1 | | | | | | | |
| Set 2 | 1 | 0 | OT1 | OT2 | LL1 | LL2 | UL1 | UL2 | | | | | | | |
| Set 3 | 1 | 1 | SLC | BE4 | BE3 | BE2 | BE1 | BE0 | | | | | | | |


8. Determine which fault outputs should be enabled. To enable a fault output, enter 1 in the box above the fault output; otherwise, enter 0. Do this for each fault output in the set.

For example, if Set 2 is selected and LL1 and UL1=1, "1 0 0 0" and "1 0 1 0" would be the two 4-digit binary numbers.

9. Using the conversion table below, determine the 1-digit hexadecimal number for both 4-digit binary numbers.

| Binary Number | Hexadecimal Number |
|---------------|--------------------|
| 0000 | 0 |
| 0001 | 1 |
| 0010 | 2 |
| 0011 | 3 |
| 0100 | 4 |
| 0101 | 5 |
| 0110 | 6 |
| 0111 | 7 |
| 1000 | 8 |
| 1001 | 9 |
| 1010 | A |
| 1011 | B |
| 1100 | C |
| 1101 | D |
| 1110 | E |
| 1111 | F |

Continuing with the example, "1 0 0 0" and "1 0 1 0" converts to "8A."

10. Press the **UP** or **DOWN** and  button until the appropriate hexadecimal number appears for

XX on

| |
|------------------------|
| Fault Data Input XX |
|------------------------|

External Fault Response Selection

It is sometimes desirable to have at least one external fault input to the drive. To properly program a multi-function input (H1-01 to H1-06) for this purpose an external fault response must be selected. The table below shows the possible selections for an external fault response.

Table 5-8:

| External Fault Selection | | | | | | | | MFI Setting Result |
|--------------------------|---------------------|------------------|------------|-----------------------|---------------|--------------------------|------------|--------------------|
| Input Level Selection | | Detection Method | | External Fault Action | | | | |
| N.O. ⁽¹⁾ | N.C. ⁽¹⁾ | Always | During Run | Ramp to Stop | Coast to Stop | Fast-stop ⁽³⁾ | Alarm Only | |
| √ | | √ | | √ | | | | 20 |
| √ | | √ | | | √ | | | 24 ⁽²⁾ |
| √ | | √ | | | | √ | | 28 |
| √ | | √ | | | | | √ | 2C |
| √ | | | √ | √ | | | | 22 |
| √ | | | √ | | √ | | | 26 |
| √ | | | √ | | | √ | | 2A |
| √ | | | √ | | | | √ | 2E |
| | √ | √ | | √ | | | | 21 |
| | √ | √ | | | √ | | | 25 |
| | √ | √ | | | | √ | | 29 |
| | √ | √ | | | | | √ | 2D |
| | √ | | √ | √ | | | | 23 |
| | √ | | √ | | √ | | | 27 |
| | √ | | √ | | | √ | | 2B |
| | √ | | √ | | | | √ | 2F |

(1) N.O. = normally open contact; N.C. = normally closed contact

(2) Setting 24 is the factory default

(3) Uses B5-08 timer

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|---|---|-------------------------------|---------------|--------------|
| H3-08 | Term A2 Signal | Terminal A2 Signal Level Selection | 0-2 | 2 | Adv |
| | 0 0 to +10VDC (Set S1-2 Dip Switch to Off) * | | | | |
| | 1 -10 to +10VDC (Set S1-2 Dip Switch to Off) * | | | | |
| | 2 4 to 20mA | (S1-2 Dip Switch must be ON) | | | |
| H3-09 | Terminal A2 Sel | Assigns one of the following function analog input parameters to Terminal A2. | 0-3, 5, 7, 9, A, E, 10-17, 1F | 0 | Adv |
| | 0 Add to Term A1 | Auxiliary Reference | | | |
| | 1 Frequency Gain | Frequency Gain | | | |
| | 2 Aux Speed Ref 1 | | | | |
| | 3 Aux Speed Ref 2 | | | | |
| | 5 Acc/Dec T Reduct | Acceleration/Deceleration Time Reduction | | | |
| | 7 OT/UT Det Level | Overtorque Detection Level | | | |
| | 9 Ref Lower Limit | Speed Reference Lower Limit | | | |
| | A Jump Frequency | Jump Frequency | | | |
| | E Motor Temperature | Used in conjunction with L1-03, L1-04 and L1-05 | | | |
| | 10 Fwd Torque Limit | | | | |
| | 11 Rev Torque Limit | | | | |
| | 12 Regen Torque Limit | | | | |
| | 13 Torque Reference | | | | |
| | 14 Torque Comp | | | | |
| | 15 FWD/REV Torque Limit | | | | |
| 16 Load Cell | Weight input enable by C10-01=4 | | | | |
| 17 Hook Height | 10V=100.0% | | | | |
| | 1F Not Used | | | | |
| H3-10 | Terminal A2 Gain | Gain multiplier for terminal A2 analog input signal | 0000.0–1000.0% | 100.0 | Adv |
| H3-11 | Terminal A2 Bias | Bias multiplier for terminal A2 analog input signal | -100.0–100.0% | 0.0 | Adv |
| H3-12 | Filter Avg Time | Analog input filter average time | 0.00–2.00sec | 0.00 | Adv |

* Damage may otherwise result. See page 3-11 for S1 Dip Switch Location

Analog Outputs

The IMPULSE•VG+ Series 3 has two analog outputs for the external monitoring of drive conditions.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|------------------|---|---------------|---------------|--------------|
| H4-01 | Terminal FM Sel | Assigns one of the following function analog output parameters to Terminal FM | 1-50 | 2 | Adv |
| | 1 | <i>Frequency Ref</i> | | | |
| | 2 | <i>Output Freq</i> | | | |
| | 3 | <i>Output Current</i> | | | |
| | 5 | <i>Motor Speed</i> | | | |
| | 6 | <i>Output Voltage</i> | | | |
| | 7 | <i>DC Bus Voltage</i> | | | |
| | 8 | <i>Output kWatts</i> | | | |
| | 9 | <i>Torque Reference</i> | | | |
| | 15 | <i>Term A1 Level</i> | | | |
| | 16 | <i>Term A2 Level</i> | | | |
| | 17 | <i>Term A3 Level</i> | | | |
| | 18 | <i>Mot SEC Current</i> | | | |
| | 19 | <i>Mot EXC Current</i> | | | |
| | 20 | <i>SFS Output</i> | | | |
| | 21 | <i>ASR Input</i> | | | |
| | 22 | <i>ASR Output</i> | | | |
| | 23 | <i>PG-Z2 Ch2</i> | | | |
| | 24 | <i>PID Feedback</i> | | | |
| | 26 | <i>Voltage Ref (Vq)</i> | | | |
| | 27 | <i>Voltage Ref (Vd)</i> | | | |
| | 29 | <i>Load Weight</i> | | | |
| | 30 | <i>SS Delta Speed</i> | | | |
| | 31 | <i>Not used</i> | | | |
| | 32 | <i>ACR (q) Output</i> | | | |
| | 33 | <i>ACR (d) Output</i> | | | |
| | 36 | <i>PID Input</i> | | | |
| | 37 | <i>PID Output</i> | | | |
| | 38 | <i>PID Setpoint</i> | | | |
| | 41 | <i>Cooling Fin Temperature</i> | | | |
| | 44 | <i>ASR OUT w/o filter</i> | | | |
| | 50 | <i>Hook Height</i> | | | |
| H4-02 | Terminal FM Gain | Gain multiplier for Terminal FM analog output signal | 0.00–1000.0% | 100.0 | Adv |
| H4-03 | Terminal FM Bias | Bias multiplier for Terminal FM analog output signal | -110.0–110.0% | 0.0 | Adv |
| H4-04 | Terminal AM Sel | Assigns one of the above function analog output parameters to Terminal AM | (See H4-01) | 3 | Adv |
| H4-05 | Terminal AM Gain | Gain multiplier for Terminal AM analog output signal | 0.00–1000.0% | 50.0 | Adv |

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|-----------------------|--|--|---------------|----------------------|---------------------|
| H4-06 | Terminal AM Bias | Bias multiplier for Terminal AM analog output signal | -110.0–110.0% | 0.0 | Adv |
| H4-07 | AO Level Select 1 <i>0 0 to +10VDC</i> <i>1 -10 to +10VDC</i> <i>2 4 to 20 mA</i> | | 0-2 | 0 | Adv |
| H4-08 | AO Level Select 2 <i>0 0 to +10VDC</i> <i>1 -10 to +10VDC</i> <i>2 4 to 20 mA</i> | | 0-2 | 0 | Adv |

Serial Communication Set-up

The IMPULSE•VG+ Series 3 uses terminals R⁺/R⁻, S⁺/S⁻ to communicate MODBUS RTU (RS-485/422) protocol.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|--|--|---------|---------------|--------------|
| H5-01 | Serial Com Adr | Serial communication address | 0–20 | 1F | Adv |
| H5-02 | Serial Baud Rate 0 1200 Baud 1 2400 Baud 2 4800 Baud 3 9600 Baud 4 19200 Baud | Sets the baud rate | 0–4 | 3 | Adv |
| H5-03 | Serial Com Sel 0 No parity 1 Even parity 2 Odd parity | Determines the parity | 0–2 | 0 | Adv |
| H5-04 | Serial Fault Set 0 Decel to Stop 1 Coast to Stop 2 Fast-Stop 3 Alarm Only | Determines stopping method or fault at a serial fault occurrence | 0–3 | 1 | Adv |
| H5-05 | Serial Flt Dtct 0 Disabled 1 Enabled | Determines whether Serial Fault Detection is enabled | 0–1 | 1 | Adv |
| H5-06 | Transmit Wait Tim | Send waiting time | 5–65 ms | 5 | Adv |
| H5-07 | RTS Control Sel 0 Disabled (RTS is always on) 1 Enabled (RTS is ON only when sending) | RTS Control enable/disable | 0–1 | 1 | Adv |

NOTE: After changing any H5 parameter, power to the inverter must be cycled.

NOTE: After initial communication, if the inverter is not communicated with for 2 seconds, a communication fault will occur (CE Memobus ERR).

Pulse Input/Output

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|------------------------------|--|-------------------------|---------------|--------------|
| H6-01 | Pulse Input Sel | Selects the function of Pulse Input Terminal RP | 0-2 | 0 | Adv |
| | <i>0 Frequency Reference</i> | | | | |
| | <i>1 PID Feedback</i> | | | | |
| | <i>2 PID Set Point</i> | | | | |
| H6-02 | Pulse In Scaling | Number of pulses equal to the maximum output frequency | 1000-32000 | 1440 Hz | Adv |
| H6-03 | Pulse Input Gain | Sets the output level when input is 100% | 0.0-1000.0% | 100.0 | Adv |
| H6-04 | Pulse Input Bias | Sets the output level when input is ONE | -100.0-100.0% | 0.0 | Adv |
| H6-05 | Pulse In Filter | Sets the input filter time constant | 0.00-2.00 sec | 0.10 sec | Adv |
| H6-06 | Pulse Moni Sel | Selects the function of pulse output terminal MP. | 1, 2, 5, 20, 24, 31, 36 | 2 | Adv |
| H6-07 | Pulse Moni Scale | Item output by pulse monitor is selected by corresponding U1-□□ Value. | 0-32000 | 1440 Hz | Adv |

Protection Parameters

- L1 Motor Overload
- L2 Under Voltage Level
- L4 Ref Detection
- L6 Torque Detection
- L8 Hardware Protection
- L9 Automatic Reset

Motor Overload

The IMPULSE•VG+ Series 3 Drive has an electronic overload protection function (OL1) for protecting the motor from overheating. The Drive bases the protection on time, output current, and output frequency. The electronic thermal overload function is UL-recognized, so an external thermal overload relay is not required for single motor operation.

This parameter selects the motor overload curve used according to the type of motor applied.

Setting L1-01 = 1 selects a motor with limited cooling capability below rated (base) speed when running at 100% load. The OL1 function derates the motor any time it is running below base speed.

Setting L1-01 = 2 selects a motor capable of cooling itself at any speed when running at 100% load. The OL1 function derates the motor when it is running at 1/10 of its rated speed or less.

Setting L1-01 = 3 selects a motor capable of cooling itself at any speed when running at 100% load. This includes zero speed. The OL1 function does not derate the motor at any speed.

If the Drive is connected to a single motor, the motor overload protection should be enabled (L1-01 = 1, 2, 3) unless another means of preventing motor thermal overload is provided. When the electronic thermal overload function is activated, an OL1 fault occurs, shutting OFF the Drive's output, thus preventing additional overheating of the motor. The motor temperature is continually calculated as long as the Drive is powered up.

When operating several motors with one Drive, install a thermal relay on each motor and disable the motor overload protection (L1-01 = 0).

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|------------------------------|--|--------------|---------------|--------------|
| L1-01 | MOL Fault Select | Enable/disable motor overload detection. | 0-3 | 3 | Adv |
| | 0 Disabled | | | | |
| | 1 Std Fan Cooled | | | | |
| | 2 Std Blower Cooled | | | | |
| | 3 Vector Motor | | | | |
| L1-02 | MOL Time Const | Time for OL1 fault when motor current is $\geq 150\%$ of the motor rated current. | 0.1–20.0 min | 8.0 | Adv |
| L1-03 | Mtr OH Alarm Sel | Operation when the motor temperature analog input exceeds the OH3 alarm level. (1.17V) (H3-05 or 09 = E) | 0-4 | 3 | Adv |
| | 0 Decel to Stop (Alarm) | | | | |
| | 1 Coast to Stop (Alarm) | | | | |
| | 2 Fast Stop by B5-08 (Alarm) | | | | |
| | 3 Alarm Only (OH3 Flashes) | | | | |

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|--------------------------------|--|----------------|---------------|--------------|
| | 4 Stop by B3-03 Method (Alarm) | | | | |
| L1-04 | Mtr OH Fault Sel | Operation when the motor temperature analog input exceeds the OH4 fault level. (2.34V) (H3-05 or 09 = E) | 0-2 | 2 | Adv |
| | 0 Decel to Stop | | | | |
| | 1 Coast to Stop | | | | |
| | 2 Fast Stop by B5-08 | | | | |
| L1-05 | Mtr Temp Filter | Motor temperature analog input filter time constant | 0.00-10.00 sec | 0.20 | Adv |

Power Loss Ride thru

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|---|--|------------------------------|---------------|--------------|
| L2-01 | PwrL Selection 0 Disabled 1 Enabled - drive will restart if power returns within L2-02 2 CPU Power Active - drive will restart if power returns before control supply shutdown | Enables/disables the Power Loss Ride thru function | 0-2 | 0 | Adv |
| L2-02 | PwrL Ride thru t | Power Loss Ride thru time | 0.0 - 25.5 sec | ** | Adv |
| L2-03 | PwrL BaseBlock t | Output turn on delay after power resumes | 0.1 - 5.0 sec | ** | Adv |
| L2-04 | PwrL V/F Ramp t | Voltage recovery time after speed search is complete | 0.0 - 5.0 sec | ** | Adv |
| L2-05 | PUV Det Level | Under voltage fault detection level | 150 - 210VDC 300 - 420VDC | 190 380** | Adv |

** Initial value is dependent on drive size, which is determined by O2-04 (kVA Selection).

Reference Detection

The IMPULSE•VG+ Series 3 utilizes three different functions for detecting output frequency:

- When frequency agree is enabled using the multi-function contact outputs (H2-XX = “2” or “13”), the contact closes whenever the output frequency “agrees” with the frequency reference, plus or minus the speed agree detection width.
- When desired frequency agree is enabled using the multi-function contact outputs (H2-XX = “3” or “14”), the contact closes whenever the output frequency “agrees” with the speed agree detection level, plus or minus the speed agree detection width.
- When frequency detection is enabled using the multi-function contact outputs (H2-XX = “4”, “5”, “15” or “16”), the contact closes whenever the output frequency is less than or more than the speed agree detection level, depending on which detection is selected.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|-----------------|-------------------|--------------|---------------|--------------|
| L4-01 | Spd Agree Level | Speed Agree Level | 0.0–150.0 Hz | 0.0 | Adv |

Sets the detection level for the desired frequency agree 1 and frequency detection 1 and 2 functions. The set detection level is effective during both FWD and REV operation.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|-----------------|-------------------|-------------|---------------|--------------|
| L4-02 | Spd Agree Width | Speed Agree Width | 0.0–20.0 Hz | 2.0 | Adv |

Sets the detection width for frequency and desired frequency agree 1 and frequency detection 1 and 2 functions.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|-------------------|---------------------|-----------------|---------------|--------------|
| L4-03 | Speed Agree Lvl ± | Speed Agree Level ± | -150.0–150.0 Hz | 0.0 | Adv |

Sets the detection level for the desired frequency agree 2 and frequency detection 3 and 4 functions. The set detection level is effective during either FWD or REV operation, depending on the set detection level (positive value for FWD operation, negative value for REV operation).

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|---------------------|---------------------|-------------|---------------|--------------|
| L4-04 | Speed Agree Width ± | Speed Agree Width ± | 0.0–20.0 Hz | 2.0 | Adv |

Sets the detection width for frequency and desired frequency agree 2 and frequency detection 3 and 4 functions.

Test Mode

The Test Mode 0/1 by MFDI 71H is a service aid multi-function digital input (MFDI) that is intended for troubleshooting Flux Vector Control Method problems in the field. The functionality is similar to that of Motor 2, except that all motor constants are left in place so that troubleshooting of the Motor 1 data can be achieved by simply changing the control method from Flux Vector. The input can not be left on indefinitely as it will generate a fault after being on for total accumulated time of 10 minutes. At this time, the fault must be reset or power must be cycled.

When the input is “ON” (closed), the Control Method in A1-02 is temporarily overridden by the setting of L5-01. The same holds true for the stopping method. B3-03 is overridden by L5-02. All other functions for the new control method are not restricted. Certain programming may need to be done to clear up any OPE conditions that may occur as a result of the change in control method during this mode. It is up to the user to determine if a special function may cause an unsafe condition during testing. i.e. Since this feature will be used mainly for No-Load Brake type hoists, many of the inherent safety checks will become disabled. It may be desirable to disable functions such as Ultra Lift, but desirable to leave Limit Switch functions enabled. The user will need to determine what functions are being used. If unsure, it is best to ensure that the function is disabled (either by programming or MFDI is in OFF state) before running the drive/motor in this mode.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|-----------------------|--|--|--------------|----------------------|---------------------|
| L5-01 | TM Ctrl Method 0 V/F control without PG 2 Open Loop Vector | When MFDI 71H is on, this control method setting is used. A1-02 is overridden. | 0, 2 | 0 | Adv |
| L5-02 | TM Stop Method 0 Decel to Stop 1 Coast to Stop | When MFDI 71H is on, this stopping method is used. B3-03 is overridden. | 0 - 1 | 0 | Adv |

Torque Detection

The overtorque detection circuit activates when the motor load causes the motor current to exceed the overtorque detection level (L6-02). When an overtorque condition is detected, alarm signals can be sent to a multi-function output. To output an overtorque detection signal, select torque detection 1 at either of the multi-function contact outputs (H2-0x = “B” or “17”).

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|------------------|--|-------|---------------|--------------|
| L6-01 | Torque Det 1 Sel | Activates overtorque/undertorque detection and selects whether detection generates an alarm or a fault | 0-8 | 0 | Adv |
| | 0 | Disable | | | |
| | 1 | OT At Speed Agree–Alarm | | | |
| | 2 | OT At Run–Alarm | | | |
| | 3 | OT At Speed Agree–Fault | | | |
| | 4 | OT At Run–Fault | | | |
| | 5 | UT At Speed Agree–Alarm | | | |
| | 6 | UT At Run–Alarm | | | |
| | 7 | UT At Speed Agree–Fault | | | |
| | 8 | UT At Run–Fault | | | |

Table 5-9:

| Setting | Description |
|---------|---|
| 0 | Torque detection is disabled (<i>factory default</i>). |
| 1 | Overtorque detection is enabled whenever at the speed agree level (when inverter is not accelerating or decelerating). Continue running after detection (OT1 alarm). |
| 2 | Overtorque detection is enabled always. Continue running after detection (OT1 alarm). |
| 3 | Overtorque detection is enabled whenever at the speed agree level. Coast to a stop after detection (OT1 fault). |
| 4 | Overtorque detection is enabled always. Coast to a stop after detection (OT1 fault). |
| 5 | Undertorque detection is enabled whenever at the speed agree level (when inverter is not accelerating or decelerating). Continue running after detection (UT1 alarm). |
| 6 | Undertorque detection is enabled always. Continuing running after detection (UT1 alarm). |
| 7 | Undertorque detection is enabled whenever at the speed agree level. Coast to a stop after detection (UT1 fault). |
| 8 | Undertorque detection is enabled always. Coast to stop after detection (UT1 fault) |

- Note:**
- To detect overtorque/undertorque during acceleration or deceleration, set to “2” or “4” / “6” or “8”.
 - To continue operation after overtorque/undertorque detection, set to “1” or “2” / “5” or “6” During detection, the digital operator displays an “OL3” alarm (blinking).
 - To stop the inverter after an overtorque/undertorque detection fault, set to “3” or “4” / “7” or “8”. During detection, the digital operator displays an “OL3/UL3” fault.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|-----------------|---|--------------|---------------|--------------|
| L6-02 | Torq Det 1 Lvl | Sets the overtorque detection as a percentage of inverter rated current, during V/F control, and motor rated torque during vector control. | 0–300% | 150 | Adv |
| L6-03 | Torq Det 1 Time | The overtorque detection delay time inserts a delay, between the time motor current (or torque) exceeds the overtorque level (L6-02) and when the overtorque detection function is enabled. The digital operator then displays “OL3”. | 0.0–10.0 sec | 0.1 | Adv |
| L6-04 | Torq Det 2 Sel | Activates overtorque/undertorque detection, and selects whether detection generates an alarm or a fault. | 0-8 | 0 | Adv |
| | 0 | Disable | | | |
| | 1 | OT At Speed Agree–Alarm | | | |
| | 2 | OT At Run–Alarm | | | |
| | 3 | OT At Speed Agree–Fault | | | |
| | 4 | OT At Run–Fault | | | |
| | 5 | UT At Speed Agree–Alarm | | | |
| | 6 | UT At Run–Alarm | | | |
| | 7 | UT At Speed Agree–Fault | | | |
| | 8 | UT At Run–Fault | | | |

Table 5-10:

| Setting | Description |
|---------|---|
| 0 | Overtorque/undertorque detection is disabled (<i>factory default</i>). |
| 1 | Overtorque detection is enabled whenever at the speed agree level (when inverter is not accelerating or decelerating). Continue running after detection (OT2 alarm). |
| 2 | Overtorque detection is enabled always. Continue running after detection (OT2 alarm). |
| 3 | Overtorque detection is enabled whenever at the speed agree level. Coast to a stop after detection (OT2 fault). |
| 4 | Overtorque detection is enabled always. Coast to a stop after detection (OT2 fault). |
| 5 | Undertorque detection is enabled whenever at the speed agree level (when inverter is not accelerating or decelerating). Continue running after detection (UT2 alarm). |
| 6 | Undertorque detection is enabled always. Continuing running after detection (UT2 alarm). |
| 7 | Undertorque detection is enabled whenever at the speed agree level. Coast to a stop after detection (UT2 fault). |
| 8 | Undertorque detection is enabled always. Coast to stop after detection (UT2 fault) |

Overtorque detection 2 functions the same as overtorque/undertorque detection 1 (L6-01), except that “OT2/UT2” is displayed on the digital operator instead. This function is used when two types of detection are output to the multi-function output terminals.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|-----------------------|-----------------|--------------------------|--------------|----------------------|---------------------|
| L6-05 | Torq Det 2 Lvl | Torque Detection 2 Level | 0–300% | 150 | Adv |
| L6-06 | Torq Det 2 Time | Torque Detection 2 Time | 0.0–10.0 sec | 0.1 | Adv |

Hardware Protection

The IMPULSE•VG+ Series 3 comes equipped with a number of built-in functions designed to protect the inverter and its components from damage.

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|--|---|-----------|---------------|--------------|
| L8-02 | OH Pre-Alarm Lvl | Sets the heatsink temperature level for protection against overheat (OH). Note: The inverter measures heatsink temperature by an negative temperature coefficient thermistor. | 50–130°C | 95** | Adv |
| L8-03 | OH Pre-Alarm Sel 0 <i>Decel to Stop</i> 1 <i>Coast to Stop</i> 2 <i>Fast-Stop</i> 3 <i>Use B3-03 Method</i> 4 <i>Alarm Only</i> | Selects the stopping method when heatsink overheat is detected. <i>(Decel to stop using B5-02)</i> <i>(Immediate stop)</i> <i>(Decel to stop using B5-08)</i> <i>Uses programmed B3-03 Method</i> <i>(Operation continues and “OH Heatsink Overtemp” is displayed on keypad)</i> | 0–4 | 4 | Adv |
| L8-05 | PH Loss In Sel 0 <i>Disabled</i> 1 <i>Enabled</i> | Input phase loss detection | 0–1 | 1 | Adv |
| L8-07 | PH Loss Out Sel 0 <i>Disabled</i> 1 <i>1PH Loss Det</i> 2 <i>2/3PH Loss Det</i> | Output phase loss detection | 0–2 | 2 | Adv |
| L8-09 | Ground Fault Detect 0 <i>Disabled</i> 1 <i>Enabled</i> | Enables/disables ground fault detection | 0–1 | 1 | Adv |
| L8-10 | Fan On/Off Sel 0 <i>Fan On-Run Mode</i> 1 <i>Fan Always On</i> | Cooling fan operation select | 0–1 | 0 | Adv |
| L8-11 | Fan Delay Time | When L8-10 = 1, fan will operate L8-11 seconds after Run Command is removed | 0-300 sec | 60 | Adv |
| L8-12 | Ambient Temp | Adjusts Overload (OL2) Protection for high ambients | 45-60°C | 45 | Adv |
| L8-15 | OL2 Sel @ L-Spd 0 <i>Disabled</i> 1 <i>Enabled</i> | Enables/disables OL when output frequency \leq 6 Hz | 0–1 | 0 | Adv |
| L8-18 | Soft CLA Sel 0 <i>Disabled</i> 1 <i>Enabled</i> | Enables/disables the software current limit function. Limits output frequency when current exceeds 110% of rated. | 0–1 | 1 | Adv |

** Initial value is dependent on drive size, which is determined by O2-04 (kVA selection)

Automatic Reset

When a fault occurs during operation, the IMPULSE•VG+ Series 3 can be programmed for an auto restart operation to automatically reset the fault.

| Parameter Code | Display | Function | Range | Initial Value | Level Access |
|----------------|---|--|---------------|---------------|--------------|
| L9-01 | Reset Select 0 Disabled 1 Enabled | Activates the fault auto-reset function. | 0-1 | 1 | Adv |
| L9-02 | Reset Attempts | Sets the number of reset attempts. Reset attempt counter is returned to zero if no faults occur within a ten minute period. | 0–10 | 3 | Adv |
| L9-03 | Reset Time | Sets the reset starting time | 0.5–180.0 sec | 0.5 | Adv |
| L9-04* | Reset Flt Sel 1 | Reset Fault Select 1. | 0000–FFFF | 0001 | Adv |
| L9-05* | Reset Flt Sel 2 | Reset Fault Select 2. | 0000–FFFF | E000 | Adv |
| L9-06 | FLT Contact Sel 0 No FLT Relay 1 FLT Relay active | Fault contact operation during reset attempts | 0-1 | 0 | Adv |

* To program constant L9-04 and L9-05, refer to the example on the following page and follow steps 1 through 4:

1. Sign 1 to each fault code that you wish to enable the auto reset.
2. Sign 0 to each fault code that you wish to disable the auto reset.
3. Convert all Digits (1 to 4) from binary to hex.
4. Program L9-04 and L9-05 by entering the hex number obtained from step 3.

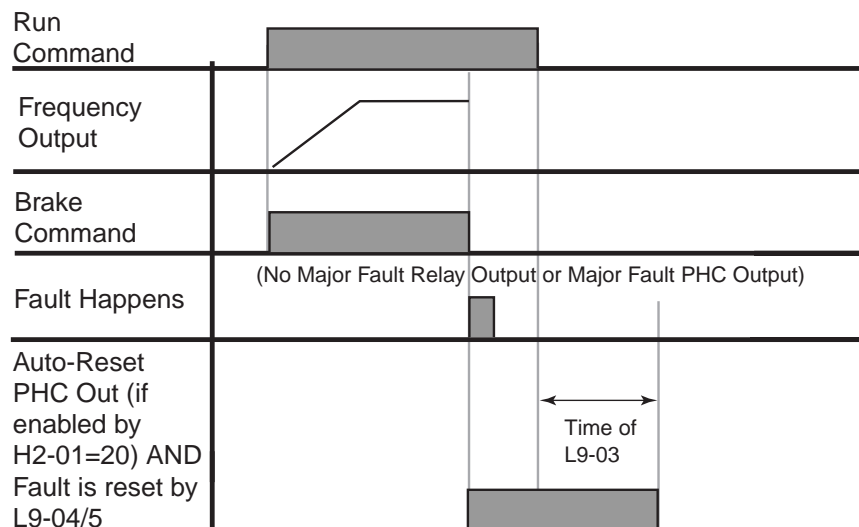


Figure 5-26: Automatic Fault Reset

Example:

Enable auto-reset for UV1, OS and CE faults.

Table 5-11:

| | Digit 4 | Digit 3 | Digit 2 | Digit 1 |
|--------|-------------------------------|-------------------------------|----------------------------------|-------------------------------|
| HEX | 2 | 0 | 0 | 1 |
| Binary | 0 0 1 0 | 0 0 0 0 | 0 0 0 0 | 0 0 0 1 |
| L9-04 | E - - - F - - - O - - - | L P U U F F T T 1 2 | O S O G H C V F 1 | O U U U C V V V 3 2 1 |
| HEX | 0 | 0 | 8 | 0 |
| Binary | 0 0 0 0 | 0 0 0 0 | 1 0 0 0 | 0 0 0 0 |
| L9-05 | B B B F E E E b 1 2 3 L | O O O O L L t T 1 2 1 2 | C C E E E A F F L 8 7 L | E E E E F F F F 6 5 4 3 |

Table 5-12:

| L9-04 | Binary | HEX |
|---------|--------|-----|
| Digit 4 | 0010 | 2 |
| Digit 3 | 0000 | 0 |
| Digit 2 | 0000 | 0 |
| Digit 1 | 0001 | 1 |

Table 5-13:

| Binary Number | Hexadecimal Number |
|---------------|--------------------|
| 0000 | 0 |
| 0001 | 1 |
| 0010 | 2 |
| 0011 | 3 |
| 0100 | 4 |
| 0101 | 5 |
| 0110 | 6 |
| 0111 | 7 |
| 1000 | 8 |
| 1001 | 9 |
| 1010 | A |
| 1011 | B |
| 1100 | C |
| 1101 | D |
| 1110 | E |
| 1111 | F |

Operator Parameters

- O1 Monitor Selection
- O2 Keypad Key Selection
- O3 Clear History
- O4 Copy Parameters

Monitor Selection

The top level in the operation mode allows the viewing of four monitor variables. They are Fref, Fout, Iout, and User-Selected monitor. This user-selected monitor can be selected from the following table. See Monitor Parameters table on page 5-102 for available monitors by control method

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|---------------------|---|-------|---------------|--------------|
| O1-01 | User Monitor Sel | Assigns one of the following monitor parameter as user-selected monitor. Set O1-02 = 4 to use O1-01. | 4-53 | 6 | Adv |
| | 4 Control Method | | | | |
| | 5 Motor Speed | | | | |
| | 6 Output Voltage | | | | |
| | 7 DC Bus Voltage | | | | |
| | 8 Output kWatts | | | | |
| | 9 Torque Reference | | | | |
| | 10 Input Term Sts | | | | |
| | 11 Output Term Sts | | | | |
| | 12 Int Ctl Sts 1 | | | | |
| | 13 Elapsed Time | | | | |
| | 14 FLASH ID | | | | |
| | 15 Term A1 Level | | | | |
| | 16 Term A2 Level | | | | |
| | 17 Term A3 Level | | | | |
| | 18 Mot SEC Current | | | | |
| | 19 Mot EXC Current | | | | |
| | 20 SFS Output | | | | |
| | 21 ASR Input | | | | |
| | 22 ASR Output | | | | |
| | 23 PG-Z2 ch 2 | | | | |
| | 24 PID Feedback | | | | |
| | 25 G5IN4 Reference | | | | |
| | 26 Voltage Ref (Vq) | | | | |
| | 27 Voltage Ref (Vd) | | | | |
| | 28 CPU ID | | | | |
| | 29 Load Weight | | | | |
| | 30 SS Delta Speed | | | | |
| | 32 ACR(q) Output | | | | |
| | 33 ACR(d) Output | | | | |
| | 34 OPE Detected | | | | |

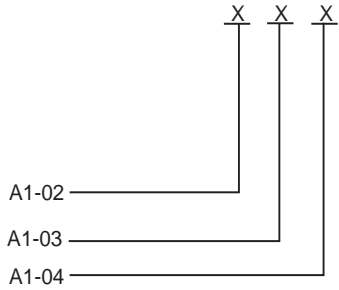
| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|------------------|--|---------|---------------|--------------|
| | 36 | PID Input | | | |
| | 37 | PID Output | | | |
| | 38 | PID Setpoint | | | |
| | 39 | Transmit Err | | | |
| | 40 | Fan Elapsed Time | | | |
| | 41 | Actual Fin Temp | | | |
| | 44 | ASR OUT w/o Fil | | | |
| | 50 | Hook Height | | | |
| | 51 | Motor Revolution | | | |
| | 52 | Maintenance Timer | | | |
| | 53 | Index Count | | | |
| O1-02 | Power-On Monitor | Selects the monitor to be displayed on the digital operator immediately after the power supply is turned on. | 1-4 | 2 | Adv |
| | 1 | Frequency Ref (U1-01) | | | |
| | 2 | Output Freq (U1-02) | | | |
| | 3 | Output Current (U1-03) | | | |
| | 4 | User Monitor (O1-01) | | | |
| O1-03 | Display Scaling | Units for parameters and monitor related to frequency reference and output frequency can be scaled as shown below. | 0-39999 | 0 | Adv |

Table 5-14:

| Setting (O1-03) | Description |
|---|--|
| 00000 | Unit: 0.01Hz (factory default) |
| 00001 | Unit: 0.01% |
| 00002 to 00039 | Unit: rpm (set O1-03 equal to the number of motor poles) |
| 00040 to 39999 (user-selected units) | Digits: <u>5th</u> <u>4th</u> <u>3rd</u> <u>2nd</u> <u>1st</u> 0 0 0 0 0 The first through fourth digits determine the set value at 100% output frequency. Decimal point position is set by the fifth digit as follows: 5th digit = 0: displayed as 0000 5th digit = 1: displayed as 000.0 5th digit = 2: displayed as 00.00 5th digit = 3: displayed as 0.000 Example 1 If 100% output frequency is equal to 200.0 units: Set O1-03="12000"; 100% of this reference is displayed as 200.0 and 60% of this reference is displayed as 120.0. Example 2 If 100% output frequency is equal to 65.00: Set O1-03="26500"; 60% of this reference is displayed as 39.00. |

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|-------------------------------------|--|-------|---------------|--------------|
| O1-04 | Display Units 0) Hertz 1) RPM | Setting units for E1-04, E1-06, and E1-09. | 0, 1 | 0 | Adv |
| O1-05 | LCD Contrast | Adjusts brightness of the keypad display | 0-5 | 3 | Adv |

Keypad Key Selection

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|--|--|----------------|---------------|--------------|
| O2-01 | Mode/Service Key 0 <i>Mode/Service</i> | Pressing the Mode/Service Key once displays “Call ESI Service” 866-624-7378. Pressing the Mode/Service Key a second time:  | 0–1 | 0 | Adv |
| | 1 <i>Local/Remote</i> | Local/remote key is enabled depressing the Mode/Service key switches operation command between the digital operator and the settings of B3-01 and B3-02. | | | |
| O2-02 | Oper Stop Key 0 <i>Coast to Stop</i> 1 <i>Decel to Stop</i> 2 <i>Use B3-03 Method</i> | Selects the action when the digital stop key is pressed. (Immediate stop) | 0–2 | 0 | Adv |
| O2-03 | User Defaults 0 <i>No Change</i> 1 <i>Set Defaults</i> 2 <i>Clear all</i> | Memorizes up to 50 modified parameters. User defaults can be restored by setting A1 - 05= “1110”. Clear user defaults. | 0–2 | 0 | Adv |
| O2-04 | Inverter Model # 0 <i>20P4</i> 1 <i>20P7</i> 2 <i>21P5</i> 3 <i>22P2</i> 4 <i>23P7</i> 5 <i>25P5</i> 6 <i>27P5</i> 7 <i>2011</i> 8 <i>2015</i> 9 <i>2018</i> A <i>2022</i> B <i>2030</i> | Determines the model number of the drive, which is based on the kVA rating. The following in this column are Magnetek model numbers. Not used. Not used. 2007-FVG+S3 2009-FVG+S3 2015-FVG+S3 2023-FVG+S3 2031-FVG+S3 2045-FVG+S3 2058-FVG+S3 2071-FVG+S3 2085-FVG+S3 Not Used. | 0–F, 10, 20–37 | kVA dependent | Adv |

| | | | | | |
|-------|------------------|--|---------|---|---|
| | C 2037 | 2145-FVG+S3 | | | |
| | D 2045 | Not Used | | | |
| | E 2055 | 2215-FVG+S3 | | | |
| | F 2075 | 2283-FVG+S3 | | | |
| | 10 2090 | 2346-FVG+S3 | | | |
| | 20 40P4 | 4001-FVG+S3 | | | |
| | 21 40P7 | 4002-FVG+S3 | | | |
| | 22 41P5 | 4003-FVG+S3 | | | |
| | 23 42P2 | 4005-FVG+S3 | | | |
| | 24 43P7 | Not Used | | | |
| | 25 44P0 | 4008-FVG+S3. | | | |
| | 26 45P5 | 4012-FVG+S3 | | | |
| | 27 47P5 | 4017-FVG+S3 | | | |
| | 28 4011 | 4024-FVG+S3 | | | |
| | 29 4015 | 4031-FVG+S3 | | | |
| | 2A 4018 | 4039-FVG+S3 | | | |
| | 2B 4022 | 4045-FVG+S3 | | | |
| | 2C 4030 | 4060-FVG+S3 | | | |
| | 2D 4037 | 4075-FVG+S3 | | | |
| | 2E 4045 | 4091-FVG+S3 | | | |
| | 2F 4055 | 4112-FVG+S3 | | | |
| | 30 4075 | 4150-FVG+S3 | | | |
| | 31) 4090 | 4180-FVG+S3 | | | |
| | 32 4110 | Not Used. | | | |
| | 33) 4132 | 4260-FVG+S3 | | | |
| | 34 4160 | 4304-FVG+S3 | | | |
| | 35 4185 | 4370-FVG+S3 | | | |
| | 36 4220 | 4477-FVG+S3 | | | |
| | 37 4300 | 4590-FVG+S3 | | | |
| O2-05 | Operator M.O.P | Selects whether the ENTER key is used when the frequency reference is set by the digital operator. The digital operator can simulate a motor operated potentiometer (M.O.P.) by setting this parameter. | 0-1 | 0 | Adv |
| | 0 Disabled | ENTER Key Required | | | <i>Note: This feature cannot be used in conjunction with infinitely variable speed control.</i> |
| | 1 Enabled | ENTER Key Not Required | | | |
| O2-06 | Oper Detection | If the digital operator is disconnected from the inverter. This parameter selects whether the inverter detects this condition. The operator is only detected when the inverter is being commanded locally. | 0-1 | 1 | Adv |
| | 0 Disabled | | | | |
| | 1 Enabled | | | | |
| O2-07 | Elapsed Time Set | Viewable by U1-13 | 0-65535 | 0 | Adv |
| O2-08 | Elapsed Time Run | Defines the operation time that accumulates in the timer. | 0-1 | 1 | Adv |
| | 0 Power-On Time | | | | |
| | 1 Running Time | | | | |
| O2-10 | Fan ON Time Set | Sets the initial fan operation timer value displayed in U1-40 | 0-65535 | 0 | Adv |

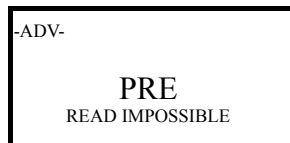
Clear History

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|-------------------|--------------------------------|--------|---------------|--------------|
| O3-01 | Flt Trace Clear | Clears fault history | 0 to 1 | 0 | Adv |
| | 0 Not Clear | | | | |
| | 1 Clear U2/U3 | | | | |
| O3-02 | Count Hist Clear | Clears count history. | 0 to 3 | 0 | Adv |
| | 0 Not Clear | | | | |
| | 1 AC Count Clr | Clears AC operations (U3-09). | | | |
| | 2 OL/LC Count Clr | Clears OL/LC (U3-10). | | | |
| | 3 Both Count Clr | Clears Both (U3-09 and U3-10). | | | |

Copy Function

| Parameter Code | Display | Function | Range | Initial Value | Access Level |
|----------------|-------------------|--------------------------------|-------|---------------|--------------|
| O4-01 | Copy Function Sel | Copy parameters to/from keypad | 0-3 | 0 | Adv |
| | 0 Copy Select | | | | |
| | 1 Inv → OP Read | | | | |
| | 2 OP → Inv Write | | | | |
| | 3 OP ↔ Inv Verify | | | | |
| O4-02 | Read Allowable | Enables/disables copy function | 0-1 | 1 | Adv |
| | 0 Disabled | | | | |
| | 1 Enabled | | | | |

The digital operator has parameter COPY capabilities via built-in non-volatile memory. The digital operator can READ all of the parameters in the Drive and store them for later, and then WRITE back to the Drive or into a Drive with the same product code and software number. In order to read the parameter values and store them into the digital operator, select O4-02 = "1: Enabled". If you attempt to READ the data, which overwrites any previously stored data, without first setting O4-02 = "1: Enabled," you will get the following error:

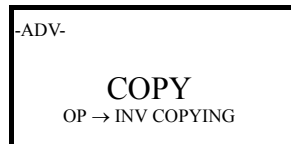


After setting O4-02 = "1: Enabled," it is possible to store parameter values in the digital operator by setting O4-01 = 1 (INV → OP READ).

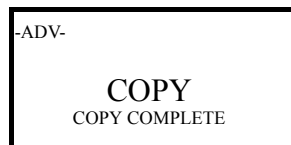
A successful READ of the parameter values will display:



An error may occur while saving the parameter values to the digital operator's memory. If an error is displayed, press any key to cancel the error display and return to parameter O4-01. Error displays and their meanings are covered in Chapter 6: Troubleshooting of the IMPULSE•VG+ Series 3 Users Manual. To COPY the parameter values into a Drive, set O4-01 = 2 (OP → INV WRITE). During the writing of the parameter values into the Drive, the digital operator will display:



A successful COPY of the parameter values will display:



An error may occur while writing the parameter values to the Drive. If an error is displayed, press any key to cancel the error display and return to parameter O4-01. Error displays and their meanings are covered in Chapter 6: Troubleshooting of the IMPULSE•VG+ Series 3.

It is possible to compare the parameter values stored in the digital operator with the parameter values currently in the Drive by using the VERIFY function. This VERIFY function should not be confused with the "-VERIFY-" that is displayed on the digital operator when viewing the "Modified Constants" menu. To VERIFY the parameter values in the Drive as compared with those stored in the digital operator, set O4-01 = 3 (OP ↔ INV VERIFY). During the comparing of the parameter values into the drive the digital operator will display:



A successful VERIFY of the parameter values will display:



If all the parameters stored in the digital operator do not match those programmed in the Drive, the digital operator displays the following:



The digital operator will not display which parameters did not match, only that the verification found discrepancies in some parameter values.

NOTE: In order to properly use the COPY or VERIFY functions, the following Drive specifications must be identical between the Drive that the parameters were read from and the Drive that the parameters are written to:

Model Number (e.g. 4001-FVG+S3)

Software Number (e.g. 8001.x as known as FLASH ID)

Monitor Parameters

| Parameter Code | Display | Function | Units |
|----------------|------------------------|---|---------|
| Monitor | | | |
| U1-01 | Frequency Ref | Frequency Reference | Hz |
| U1-02 | Output Frequency | Inverter Output Frequency | Hz |
| U1-03 | Output Current | Inverter Output Current | A |
| U1-04 | Control Method | Displays the value of A1-02 | -- |
| U1-05 | Motor Speed | Motor Speed | Hz |
| U1-06 | Output Voltage | Inverter Output Voltage (Reference) | V |
| U1-07 | DC Bus Voltage | DC Bus Voltage (Measured) | V |
| U1-08 | Output Hp | Inverter Output Power (Calculated) | Hp |
| U1-09 | Torque Reference | Torque Reference (Internal) | % |
| U1-10 | Input Term Sts | Input Terminal Status (See figure 5-27 for a detailed description.) | -- |
| U1-11 | Output Term Sts | Output Terminal Status (See figure 5-27 for a detailed description.) | -- |
| U1-12 | Int Ctl Sts 1 | Operation Status (See figure 5-27 for a detailed description.) | -- |
| U1-13 | Elapsed Time | Elapsed Time. See O2-07 and O2-08. | hours |
| U1-14 | Flash ID | Flash ROM software ID number | -- |
| U1-15 | Terminal A1 Level | External Terminal input level | V |
| U1-16 | Terminal A2 Level | External Terminal input level | V/mA |
| U1-17 | Terminal A3 Level | External Terminal input level | V |
| U1-18 | Mot SEC Current | Motor secondary current (Iq). | A |
| U1-19 | Mot EXC Current | Motor excitation current (Id). | A |
| U1-20 | SFS Output | Primary freq. after the SFS | Hz |
| U1-21 | ASR Input | Monitors the input to the speed regulator. 100%=FMAX | % |
| U1-22 | ASR Output | Monitors the output from the speed regulator. The motor's secondary current corresponds to 100%. | % |
| U1-23 | PG-Z2 ch 2 | Monitors the speed feedback from option card PG-Z2, channel 2 (when used) | Hz |
| U1-24 | PID Feedback | PID feedback signal level | % |
| U1-25 | G5IN4 Reference | See page 5-34. | Hex |
| U1-26 | Voltage Reference (Vq) | Motor secondary voltage reference | V |
| U1-27 | Voltage Reference (Vd) | Motor excitation voltage reference | V |
| U1-28 | CPU ID | CPU software ID number | -- |
| U1-29 | Load Weight | Monitors load weight when C10-01 is enabled | tons |
| U1-30 | SS Delta Speed | Snap Shaft Delta Speed between Ch1 and Ch 2 after gear ratio | Hz |
| U1-32 | ACR (q) Output | | % |
| U1-33 | ACR (d) Output | | % |
| U1-34 | OPE Detected | | const # |
| U1-35 | Zero Servo Pulse | 4 times pulses of movement during Load Float | -- |
| U1-36 | PID Input | | % |
| U1-37 | PID Output | | % |
| U1-38 | PID Set Point | | % |

| Parameter Code | Display | Function | Units | | | | | | | | | | | | | | | | |
|----------------|-------------------|---|----------------|--------------|----------|-------------------|-----------|---|---|---|----------|----------|---------------|----------------|--------------|----------|-------------------|-----------|----|
| U1-39 | Transmit Error | <table border="1" style="margin-left: auto; margin-right: auto;"> <tr> <td>0</td> <td>1</td> <td>1</td> <td>1</td> <td>1</td> <td>0</td> <td>1</td> <td>1</td> </tr> <tr> <td style="text-align: center;">Not used</td> <td style="text-align: center;">Time out</td> <td style="text-align: center;">Framing error</td> <td style="text-align: center;">Over run error</td> <td style="text-align: center;">Parity error</td> <td style="text-align: center;">Not used</td> <td style="text-align: center;">Data Length error</td> <td style="text-align: center;">CRC error</td> </tr> </table> | 0 | 1 | 1 | 1 | 1 | 0 | 1 | 1 | Not used | Time out | Framing error | Over run error | Parity error | Not used | Data Length error | CRC error | -- |
| 0 | 1 | 1 | 1 | 1 | 0 | 1 | 1 | | | | | | | | | | | | |
| Not used | Time out | Framing error | Over run error | Parity error | Not used | Data Length error | CRC error | | | | | | | | | | | | |
| U1-40 | Fan Elapsed Time | | Hr | | | | | | | | | | | | | | | | |
| U1-41 | Actual Fin Temp | | °C | | | | | | | | | | | | | | | | |
| U1-44 | ARSR Out w/o Fil | | % | | | | | | | | | | | | | | | | |
| U1-49 | Occupation Rate | CPU Utilization | % | | | | | | | | | | | | | | | | |
| U1-50 | Hook Height | | % | | | | | | | | | | | | | | | | |
| U1-51 | Motor Revolution | # of Revs after Home | Rev | | | | | | | | | | | | | | | | |
| U1-52 | Maintenance Timer | Hours since last timer reset | Hr | | | | | | | | | | | | | | | | |
| U1-53 | Index Count | Number of encoder pulses the shaft has moved since the beginning of a new Index command in quadrature. | -- | | | | | | | | | | | | | | | | |
| U1-60 | PG CH1 Count | Displays the raw pulse count for PG Channel 1 | Pulses | | | | | | | | | | | | | | | | |
| U1-61 | PG CH2 Count | Displays the raw pulse count for PG Channel 2 | Pulses | | | | | | | | | | | | | | | | |
| U1-66 | BE6 Pulse Count | Displays the amount of shaft movement during the BE6 detection time | Pulses | | | | | | | | | | | | | | | | |

Fault Trace

| | | | |
|-------|---------------------|--|-------|
| U2-01 | Current Fault | Display the most current fault detected before being reset | -- |
| U2-02 | Last Fault | Displays most recent fault after being reset (same as U3-01) | -- |
| U2-03 | Frequency Reference | Freq ref when fault was detected | Hz |
| U2-04 | Output Frequency | Output freq when fault was detected | Hz |
| U2-05 | Output Current | Output current when fault was detected | A |
| U2-06 | Motor Speed | Motor Speed when the “Last Fault” occurred | RPM |
| U2-07 | Output Voltage | Output voltage when fault was detected | V |
| U2-08 | DC Bus Voltage | DC Bus voltage when fault was detected | V |
| U2-09 | Output kWatts | Output power when fault was detected | kW |
| U2-10 | Torque Reference | Torque Reference when the “Last Fault” occurred | -- |
| U2-11 | Input Terminal Sts | Input terminal status when fault was detected | -- |
| U2-12 | Output Terminal Sts | Output terminal status when fault was detected | -- |
| U2-13 | Inverter Status | Inverter status before fault was detected | -- |
| U2-14 | Elapsed Time | Elapsed time when fault was detected | hours |

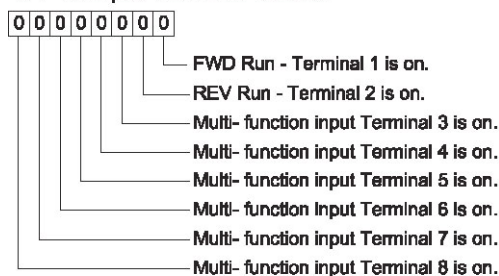
Fault History

| | | | |
|-------|-----------------|---------------------------------------|-----|
| U3-01 | Last Fault | Displays most recent fault detected | -- |
| U3-02 | Fault Message 2 | 2nd most recent fault | -- |
| U3-03 | Fault Message 3 | 3rd most recent fault | -- |
| U3-04 | Fault Message 4 | 4th most recent fault | -- |
| U3-05 | Elapsed Time 1 | Elapsed time of most recent fault | hrs |
| U3-06 | Elapsed Time 2 | Elapsed time of 2nd most recent fault | hrs |
| U3-07 | Elapsed Time 3 | Elapsed time of 3rd most recent fault | hrs |
| U3-08 | Elapsed Time 4 | Elapsed time of 4th most recent fault | hrs |
| U3-09 | Fault Message 5 | 5th most recent fault | -- |
| U3-10 | Fault Message 6 | 6th most recent fault | -- |
| U3-11 | Fault Message 7 | 7th most recent fault | -- |

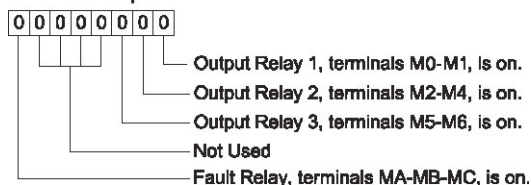
| Parameter | | | |
|------------------|------------------------|--|--------------|
| Code | Display | Function | Units |
| U3-12 | Fault Message 8 | 8th most recent fault | -- |
| U3-13 | Fault Message 9 | 9th most recent fault | -- |
| U3-14 | Fault Message 10 | 10th most recent fault | -- |
| U3-15 | Elapsed Time 5 | Elapsed time of 5th most recent fault | hrs |
| U3-16 | Elapsed Time 6 | Elapsed time of 6th most recent fault | hrs |
| U3-17 | Elapsed Time 7 | Elapsed time of 7th most recent fault | hrs |
| U3-18 | Elapsed Time 8 | Elapsed time of 8th most recent fault | hrs |
| U3-19 | Elapsed Time 9 | Elapsed time of 9th most recent fault | hrs |
| U3-20 | Elapsed Time 10 | Elapsed time of 10th most recent fault | hrs |
| U3-21 | Accumulated Operations | Counts Fwd or Rev Run commands | -- |
| U3-22 | U3-21 Rollovers | Increments when U3-21 reaches 65535, U3-21 is then set to zero | -- |
| U3-23 | OL/LC Count | Counts OL1, OL2 and LC faults | -- |

Note: Faults such as CPF00, CPF01, CPF02, CPF03, UV1 and UV2 are not stored in fault history.

U1-10 Input Terminal Status



U1-11 Output Terminal Status



U1-12 Operation Status

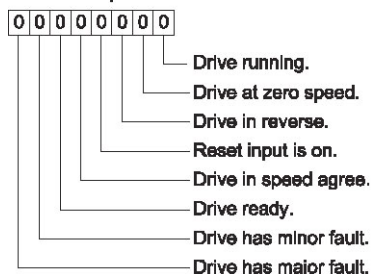


Figure 5-27: Status

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chapter **6**

**Troubleshooting
IMPULSE•VG+ Series 3**

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Troubleshooting the Drive

In this troubleshooting section, “*check*,” means *investigating whether an item is functioning and in an acceptable physical condition, and then taking corrective action (adjusting, fixing, replacing, etc.) as necessary*. In the Corrective Action column, you may not have to perform all of the steps to correct the problem.

Maintenance and Inspection

This section describes basic maintenance and inspection procedures for the IMPULSE•VG+Series 3.

| Component | Check | Corrective Action |
|---|--|--|
| External terminals, connectors, mounting screws, etc. | Loose screws or connectors | Securely tighten. |
| Heatsink | Build-up of dust and dirt | Blow with dry, compressed air (57-86 psi). |
| Printed Circuit Board (PCB) | Accumulation of conductive dust or oil | Blow with dry, compressed air (57-86 psi). If dust and oil cannot be removed, replace the board. |
| Cooling Fan | Abnormal noise and vibration | Clean or replace the fan. |
| Power Components | Accumulation of dust or dirt | Blow with dry, compressed air (57-86 psi). |

Alarm and Fault classes are described as follows:

- Major Fault: Brake is set, operation indicator lights flash, fault is displayed on keypad and fault contact output (terminals MA, MB, & MC) are activated. The reset key must be pressed, a multi-function input set for fault reset or power must be cycled in order to continue operation.
- Fault (minor): Brake is set, RUN Led flashes until run command is removed, fault is displayed on keypad, fault contact output (terminals MA, MB, & MC) are not activated. The reset key does not need to be pressed. The drive will attempt to run again at the next run command.
- Alarm (Warning): Operation continues, fault is displayed on the keypad, fault contact output (terminals MA, MB and MC) are not activated.

Motor Faults and Corrective Actions

| Symptom | Corrective Action |
|--|---|
| Analog frequency reference is not stable. (drifting) | 1. Stabilize the analog source. 2. Increase B2-02. 3. Increase B5-01, -02. |
| No motor rotation. | 1. Verify that power is on (Charge LED). 2. Verify that the keypad display is not showing a fault. 3. Verify that the run command is input to the drive (U1-10). 4. Motor stalled due to excessive load. |
| Motor rotation is in the wrong direction. | 1. Verify FWD/REV or UP/DN is correct at the interface card. 2. Match wiring to the phase order of the motor leads T1, T2, T3. |

| Symptom | Corrective Action |
|---|--|
| Motor rotates, but at minimum speed only. | <ol style="list-style-type: none"> 1. Check wiring of speed inputs. 2. Verify speed reference setting (A1-04). 3. Verify reference and run source settings are correct (B3-01, -02). 4. Verify reference priority setting (B1-18). |
| Motor RPM too high or too low. | <ol style="list-style-type: none"> 1. Compare motor nameplate specifications with E1 parameter. 2. Check maximum frequency setting (E1-04). 3. Check minimum frequency setting (E1-09). |

Drive Faults, Alarms and Indicators

| Fault Code | Fault or Indicator Name/Description | Corrective Action |
|---|--|--|
| BB (flashing) Base Block | External Base Block Indicator. The flashing base block signal is the result of a multi-function input in the terminal strip. The base block indicates that the drive's IGBTs have been disabled. The motor will begin coasting when the base block input is received. If a RUN command is still present when the BB signal is removed, the output voltage will be restored to the previous operating level and operation will continue at the previously commanded frequency. | <ol style="list-style-type: none"> 1. Check constants H1-01 through H1-06 for proper programming. 2. Check terminal status. (U1-10) |
| BE0 (flashing) Brake Ans Lost | Brake answer back signal is lost during run. While running, the multi-function input brake answer back is lost. | <ol style="list-style-type: none"> 1. Check brake answer back circuit. 2. Check terminal status. (U1-10) |
| BE1 Rollback detect | Torque Proving Fault. The BE1 fault indicates that the drive has released the brake, but not started to accelerate the motor when it detects excessive encoder feedback. A BE1 fault will occur if the pulses received during the BE1 detection time (C8-04) are greater than the expected number of pulses (C8-05). | <ol style="list-style-type: none"> 1. Please reference troubleshooting encoder related faults on page 6-14. |
| BE2 No Current | Torque Proving Fault. Before the brake is released, the drives current/torque did not reach Initial Brake Release Torque level (C8-16) within the IFB OK timer (C8-02). | <ol style="list-style-type: none"> 1. Ensure the motor has been Auto-tuned successfully. 2. Confirm that the holding brake is closed. 3. If a power limit switch is used, ensure that the switch is closed. 4. Decrease the values of C8-01 and C8-02 to no less than 0.5 seconds. <i>NOTE:</i> the values of C8-01 and C8-02 should always remain equal. 5. Decrease the value of C4-02 to no less than 5. 6. Decrease the value of C8-16 to no less than 50. |
| BE3 Brake Release NG | Torque Proving Fault. The BE3 fault indicates that the drive has released the brake and commanded the drive to run, but it has not detected the expected encoder feedback. A BE3 fault will occur if the pulses received during the BE3 detection time (C8-06) are less than the expected number of pulses (C8-07). | <ol style="list-style-type: none"> 1. Please reference encoder related faults on page 6-12. |

| Fault Code | Fault or Indicator Name/Description | Corrective Action |
|---|---|--|
| BE4 (flashing) Brake Answer 1 | Brake Answer-Back, Brake not Released. At Start, Brake Answer-back is not input within predetermined time (C8-04) after electric brake release command is output—Electric brake not released. | <ol style="list-style-type: none"> 1. Check brake answer back circuit. 2. Increase the value of C8-04. 3. Check terminal status (U1-10). |
| BE5 (flashing) Brake Answer 2 | Brake Answer-Back At Stop. At Stop, Brake Answer-back signal is not removed within predetermined time (C8-11) after electric brake release command is removed—Electric brake not closed. | <ol style="list-style-type: none"> 1. Check brake answer back circuitries 2. Increase the value of C8-11 time. |
| BE6 (flashing) Brake Stop Alarm | Brake Proving Alarm. The BE6 alarm indicates that the drive has commanded the brake to set but it has detected more than the expected encoder feedback. A BE6 alarm will occur if the number of pulses received during the BE6 detection time (C8-12) is greater than the expected number of pulses (C8-13). | <ol style="list-style-type: none"> 1. Please reference troubleshooting encoder related faults on page 6-15. |
| BE7 Brake Welded | Brake Answer-Back Major Fault. At Power Up, Brake Answer-Back is on - Electric brake not closed. | <ol style="list-style-type: none"> 1. Check if brake is closed. 2. Check brake answer back circuitry. |
| BUS Option Com Err | Option Card Communication Error. Communication to the option card was lost. | <ol style="list-style-type: none"> 1. Check all connections. |
| CALL (flashing) SI-F/G Com Call | Serial Communication Transmission Error. Control data is not received correctly after power supply is turned ON for 2 sec. | <ol style="list-style-type: none"> 1. Check serial device connections. 2. Ensure drive is properly programmed for serial communication. |
| Can't Run Drive not ready | User is trying to give a run command without first Enable Drive Enable Multi-Function input or Fwd or Rev input are present at power up. | <ol style="list-style-type: none"> 1. Turn on Drive Enable Multi-function input. 2. Check H1-01 to H1-06 programming. 3. Change B3-10 to allow run at power up. |
| CE Memobus Com Err | Communication Error. Serial communications disruption. | <ol style="list-style-type: none"> 1. Check serial connections (6 CN). 2. Check H5-01 through H5-05 for proper programming. |
| CPF00 Com-Err (OP&INV) | <p>Control Circuit Fault 1— Keypad Transmission.</p> <p>Because of external noise, excessive vibration or shock, or component failure (including RAM and PROM), one or both of the following occurs:</p> <ul style="list-style-type: none"> • Transmission between the inverter and keypad cannot be established 5 sec after power-up. • External RAM of CPU is defective. | <ol style="list-style-type: none"> 1. Check the keypad connection. 2. Replace keypad. 3. Replace Control board. |
| CPF01 Com-Err (OP&INV) | Control Circuit Fault 2—Keypad Transmission. After initial power-up, communication between the inverter and keypad was interrupted for more than 2 seconds. | <ol style="list-style-type: none"> 1. Check keypad connection. 2. Cycle Power 3. Replace keypad 4. Replace Control board. |
| CPF02 BB Circuit Err | Base Block Circuit Fault. Base block circuit fault at power-up. | <ol style="list-style-type: none"> 1. Cycle power. 2. Ensure that the control board terminals are shielded from electrical noise. 3. Replace Control board. |
| CPF03 EEPROM Err | EEPROM Fault. Invalid data found in the EEPROM. | <ol style="list-style-type: none"> 1. Cycle power. 2. Ensure that the control board terminals are shielded from electrical noise. 3. Replace Control board. |

| Fault Code | Fault or Indicator Name/Description | Corrective Action |
|---|---|--|
| CPF04 Internal A/D Err | Internal A/D Converter Fault. CPU internal analog-digital converter fault. | <ol style="list-style-type: none"> 1. Cycle power. 2. Ensure that the control board terminals are shielded from electrical noise. 3. Replace Control board. |
| CPF05 External A/D Err | External A/D Converter Fault. CPU external analog-digital converter fault. | <ol style="list-style-type: none"> 1. Cycle power. 2. Ensure that the control board terminals are shielded from electrical noise. 3. Replace Control board. |
| CPF06 Option Error | Option Card Fault. Optional card has disconnected or failed. | <ol style="list-style-type: none"> 1. Power down. 2. Verify proper installation of all option cards. |
| CPF10 ASIC-ERR | ASIC Version Fault 10. . | <ol style="list-style-type: none"> 1. Cycle power. 2. Replace the drive. |
| CPF20 Option A/D Error | Control Circuit Fault 20 — AI-14. Analog-to-digital converter fails or analog speed reference error. | <ol style="list-style-type: none"> 1. Power down. 2. Verify proper installation of AI-14B. 3. Replace AI-14B card. |
| CPF21 Option CPU Down | Control Circuit Fault 21 — CPU on Optional Card. CPU on an installed optional card fails. | <ol style="list-style-type: none"> 1. Power down. 2. Verify proper installation of Option card. 3. Replace card. |
| CPF22 Option Type Err | Control Circuit Fault 22 — Optional Card Code. Optional card code is not compatible with the inverter. | <ol style="list-style-type: none"> 1. Power down. 2. Verify proper card. 3. Verify proper installation of Option card. 4. Replace card. |
| CPF23 Option DPRAM Err | Control Circuit Fault 23 — DP-RAM. DP-RAM on an installed optional card failed. | <ol style="list-style-type: none"> 1. Power down. 2. Remove any inputs to card. 3. Verify proper installation of Option card. 4. Replace card. |
| Dev Speed Deviation | Speed Deviation Fault. Occurs when the deviation of the speed reference and speed feedback exceeds the regulation level, F1-10 for the time F1-11. | <ol style="list-style-type: none"> 1. Please reference troubleshooting encoder related faults on page 6-12. |
| EF (<i>flashing</i>) External Fault | Both FORWARD/UP and REVERSE/DOWN commands are input at same time for 500 msec or longer. | <ol style="list-style-type: none"> 1. Check control input wiring. 2. Check the sequence of operation. |
| EF0 Optional External Fault | External fault input from communication option card. | <ol style="list-style-type: none"> 1. Check communication option card connection and signals. |
| EF3 External Fault 3 | External fault occurs on Terminal S3. | <ol style="list-style-type: none"> 1. Check constant H1-01 for proper programming. 2. Check the condition of the input terminal S3. |
| EF4 External Fault 4 | External fault occurs on Terminal S4. | <ol style="list-style-type: none"> 1. Check constant H1-02 for proper programming. 2. Check the condition of the input terminal S4. |
| EF5 External Fault 5 | External fault occurs on Terminal S5 external control circuit. | <ol style="list-style-type: none"> 1. Check constant H1-03 for proper programming. 2. Check the condition of the input terminal S5. |

| Fault Code | Fault or Indicator Name/Description | Corrective Action |
|--|--|---|
| EF6 External Fault 6 | External fault occurs on Terminal S6 external control circuit | 1. Check constant H1-04 for proper programming. 2. Check the condition of the input terminal S6. |
| EF7 External Fault 7 | External fault occurs on Terminal S7 external control circuit. | 1. Check constant H1-05 for proper programming. 2. Check the condition of the input terminal S7. |
| EF8 External Fault 8 | External fault occurs on Terminal S8 external control circuit. | 1. Check constant H1-06 for proper programming. 2. Check the condition of the input terminal S8. |
| ERR EEPROM R/W Err | EEPROM Read/Write Fault. EEPROM internal data did not match when initializing the parameter. | 1. Cycle Power. 2. User initialize (A1-05=1110). 3. Replace Control board. |
| Fbl Feedback Loss | PID Feedback Loss. Occurs when PID Feedback loss is detected by D7-13. | 1. Verify drive is programmed to receive the feedback signal. |
| GF Ground Fault | During operation, the inverter sums the currents of all three motor phases. Ideally, the sum should always equal zero. If the sum is greater than 50% of the inverter rated output current, a GF occurs. | 1. Disconnect motor from drive and check it for shorts using a megger. 2. Ensure that R/C Surge Suppressors are used across all brake contactor coils to prevent disturbance by electrical transients. |
| KLX Klixon | Klixon Circuit Alarm. Input by MFI data 56 or 57 but not both. | 1. Check Motor for Overtemp. 2. Check Klixon Circuit. |
| LC Load Check Err | Load Check Fault. Load is greater than specified amount. | 1. Reduce Load. 2. Check Load Check sequence set-up. (C5-XX). |
| LF Output Phase Loss | An open phase occurred at the inverter output. | 1. Check for broken wires in output cable. 2. Check for open winding in the motor. 3. Check for loose terminals |
| LL1 (flashing) Lower Limit 1 Err | Lower Limit 1—SLOW DOWN Indicator. Lower Limit 1—SLOW DOWN is input (switch status is changed). | 1. May not require corrective action. 2. Check the Limit Switches position. 3. Check the Limit Switches condition. |
| LL2 (flashing) Lower Limit 2 Err | Lower Limit 2—STOP Indicator. Lower Limit 2—STOP is input (switch status is changed). | 1. May not require corrective action. 2. Check the Limit Switches position. 3. Check the Limit Switches condition. |
| MNT Maintenance Req'd | Maintenance Required Alert. Running time has exceeded C12-05 | 1. Reset timer by MFI=5A or depress Mode/Service key three times and enter within 2 seconds. |
| OC Over Current | Output current exceeds 200% of inverter rated output current. | 1. Check for a phase-to-phase short in the motor or wiring using a megger. 2. Extend the acceleration/deceleration time. 3. Check torque limit setting. 4. Please reference troubleshooting encoder related faults on page 6-12. |
| OH (flashing) Heatsnk Over temp | Overheat Pre-Alarm. Heatsink is overheating. The temperature of the inverters heatsink exceeded the setting in L8-02. | 1. The inverter cooling fan has stopped. 2. Reduce the ambient temperature. |

| Fault Code | Fault or Indicator Name/Description | Corrective Action |
|-------------------------------------|---|---|
| OH1 Heatsink MaxTemp | Overheat Fault. There are two situations that result in an overheat fault. The first occurs when the measured heat sink exceeded 105°C. The second is a result of a fault in the internal 24VDC cooling fan. | <ol style="list-style-type: none"> 1. Ensure that the heat sink cooling fans are functioning. 2. Ensure that the heat sink is free from dirt and debris. |
| OH2 (flashing) Overheat 2 | Overheat Alarm. Signal is input by external terminal. H1-XX=39 | <ol style="list-style-type: none"> 3. Ensure that the inverter's ambient temperature is within specification. 4. Replace the 24VDC fan 5. Replace the heat sink thermistor(s) |
| OH3 Motor Overheat 1 | Motor Overheating 1. Thermistor analog input detected motor overheating. See L1-03 | <ol style="list-style-type: none"> 1. Check the motor rated current value, E2-01. 2. Increase cycle time or reduce the load. |
| OH4 Motor Overheat 2 | Motor Overheating 2. Thermistor analog input detected motor overheating. See L1-04 | |
| OL1 Motor Overloaded | Motor Overload Fault. Inverter output exceeded the motor overload level. | <ol style="list-style-type: none"> 1. Ensure drive is programmed with proper motor full load Amps (E2-01). 2. Reduce the load. |
| OL2 INV Overload | Inverter Overload Fault. Inverter output exceeded the inverter overload level. | <ol style="list-style-type: none"> 1. Reduce the load. 2. Extend the acceleration time. |
| OT1 Overtorque Det 1 | Overtorque Detection Level 1 Fault. Defined by L6-02. Alarm defined by L6-01. | <ol style="list-style-type: none"> 1. Check for proper programming for L6-XX constant. |
| OT2 Overtorque Det 2 | Overtorque Detection Level 2 Fault. Defined by L6-05. Alarm defined by L6-04. | <ol style="list-style-type: none"> 1. Check for proper programming for L6-XX constant. |
| OPE01 kVA Selection | kVA Setting Fault. Inverter kVA setting range is incorrect. | <ol style="list-style-type: none"> 1. Check 02-04 constant for proper kVA. |
| OPE02 Limit | Setting Out of Range. Parameter setting is out of range. | <ol style="list-style-type: none"> 1. With the fault displayed on the keypad, press the DATA/ENTER key to reveal the "Out of Range" parameter via the U1-34 monitor. 2. Verify that E2-03 is < E2-01. 3. Verify E1-05 is within range. 4. Compare Modified constants with defaults. 5. Cycle Power. |
| OPE03 Terminal | Multi-Function Input Setting Fault. Set values other than "F" and "FF" are duplicated. | <ol style="list-style-type: none"> 1. Check the settings for H1-01 to H1-06, verify that the same input is not used twice. |
| OPE05 Sequence Select | Sequence Select Setting Fault. B3-01=3 and no option is plugged in. | <ol style="list-style-type: none"> 1. Check the function selection or plug in optional card. |
| OPE06 PG Opt Missing | Missing PG Card. A closed loop control method was selected, and the required PG feedback card is not installed. | <ol style="list-style-type: none"> 1. Install the required option card. 2. Remove power and reset the option card. 3. Check the A1-02, control method, program setting |
| OPE07 Analog Selection | Multi-Function Analog Input Setting Fault. H3-05 and H3-09 multi-Function analog input settings are set to the same value. | <ol style="list-style-type: none"> 1. Check the function selections. |

| Fault Code | Fault or Indicator Name/Description | Corrective Action |
|---|--|--|
| OPE08 Terminal | Selection Parameter error. A parameter has been changed that is not available in the present control method. | <ol style="list-style-type: none"> 1. Undo the last parameter change (if known) 2. Scroll through modified constants for obvious setting errors. 3. Perform a user initialize (A1-05=1110) CAUTION: All settings will be restored to the factory defaults. |
| OPE10 V/F Ptrn Setting | V/F Parameter Setting Error. | 1. Check Parameters E1-04 to E1-11. |
| OPE11 Carrier Frq/On-Delay | Carrier Frequency Parameter Error. | 1. Check Parameters D10-01 to D10-05. |
| OPE18 Weight Measure | C10-05 or C10-06 Setting Error. | 1. Satisfy condition C10-05 > C10-06 |
| OPE19 Stp-Mthd & Ctrl | Incompatible Setting of Stopping Method and Control Method. | 1. Satisfy B3-03 \geq 6 and A1-02 \leq 1. |
| OPE21 2 Channel Missing | Option Card PG-Z2 or PG-W2 is missing when C11-08 is Enabled. | 1. Install correct option card. |
| OPE22 Ctrl & Motion | Incompatible Setting of Motion and Control Mode. | 1. Satisfy A1-02 \leq 1 and A1-03 \geq 2. |
| OPE23 Load Check | Load Check setting error. | 1. Check C5-04 < C5-07 < C5-09. |
| OPE24 Slack Cable | Slack Cable setting error. | 1. Check C11-04 < C11-06 and C11-05 > C5-07. |
| OPR Oper Disconnect | Keypad Disconnected. The keypad is removed while the inverter is running, and the run command was initiated via the keypad RUN key. | <ol style="list-style-type: none"> 1. Secure the keypad. 2. Verify O2-06 setting. |
| OS-1, OS-2 Over Speed | Overspeed Fault. The motor has exceeded the programmed detection level and time. This is typically caused by an overshoot condition due to an over-responsive ASR loop. If the drive is programmed to flux vector "torque control" mode, and no load is present, an overspeed fault will typically occur. | <ol style="list-style-type: none"> 1. Check the Automatic Speed Regulator settings, D4 sub group. 2. Check setting of F1-08, F1-09. 3. Verify proper encoder PPR setting, F1-01. |
| OV DC Bus Overvolt | Overvoltage Fault. The main circuit direct current voltage exceeded the overvoltage level. Detection level: 230V class—approx. 400VDC 460V class—approx. 800VDC | <ol style="list-style-type: none"> 1. Extend the deceleration time. 2. Check for proper DBU operation. 3. Check the resistor. 4. Check the line voltage. |
| OV (flashing) DC Bus Overvolt | Overvoltage Fault. Overvoltage occurs during stop. Main circuit DC voltage rises above the detection level while the drive output is off. Detection level: 410VAC or more for 230VAC, 820VAC or more for 460VAC. | 1. Check the line voltage. |
| PF Input Pha Loss | Input Phase Loss Fault. Inverter input power supply has open phase. | <ol style="list-style-type: none"> 1. Check the line voltage and fuses. 2. Remove power. 3. Re-tighten the input terminal screws. |
| PGO-1 PG Open Ch1 | Pulse Generator Channel 1 Fault. PGO-1-S, software detected fault. PGO-1-H, hardware detected fault | <ol style="list-style-type: none"> 1. Check for proper direction of encoder feedback. 2. Please reference troubleshooting encoder related faults on page 6-12. |

| Fault Code | Fault or Indicator Name/Description | Corrective Action |
|---|--|--|
| PGO-2 PG Open 2 (Applies only with PG-Z2 Option Card) | Pulse Generator Channel 2 Fault. PGO-2-S, software detected fault. PGO-2-H, hardware detected fault | <ol style="list-style-type: none"> 1. Check for proper direction of encoder feedback. 2. Please reference troubleshooting encoder related faults on page 6-12. |
| PUF DC Bus Fuse Open | DC Bus Fuse Open Fault. The DC fuse is open. | <ol style="list-style-type: none"> 1. Check for damaged transistor. 2. Check load-side short circuit. 3. Check grounding. <p><i>Do not replace an open DC bus fuse until the cause of failure has been corrected; non-warranty, damage to the drive may result. Refer to the "Power Section Check".</i></p> |
| RR DynBrk Transistr | Braking Transistor Fault. Internal Braking transistor failed. | <ol style="list-style-type: none"> 1. Verify that the external braking resistor is connected to the proper terminals. 2. Confirm that the proper resistor is installed. 3. Check for a short circuit across the braking resistor. |
| SC Short Circuit | Short Circuit Fault. The inverter has detected an output short circuit condition. | <ol style="list-style-type: none"> 1. Disconnect the motor from the inverter. 2. Check for a short circuit in the motor or wiring using a megger. |
| SLC Slack Cable Detection | Slack Cable Fault. A hoist slack cable condition occurred. | <ol style="list-style-type: none"> 1. May not require corrective action. 2. Check proper programming of Slack Cable Detection (C11-XX). |
| SNAP Snapped Shaft | Snapped Shaft Fault. A drive train discontinuity has been detected. | <ol style="list-style-type: none"> 1. Check for loose or broken coupling. 2. Check for loose encoder(s). 3. Check for broken shaft. |
| SVE Load Float Fault | Load Float Fault. Motor revolutions exceed value in C8-26 during load float. | <ol style="list-style-type: none"> 1. Check to verify shaft is not rotating during load float. Ensure load is not greater than capacity. 2. Check torque limit settings (C7-XX). 3. Check encoder signal. |
| TEST Exit Test Mode | MFDI 71H exceeded the allowable amount of time. | <ol style="list-style-type: none"> 1. Ensure the test mode MFDI is OFF. 2. Reset the fault (Fault Reset MFDI, Keypad, or cycle power) 3. Ensure that test mode is not used for normal operation. |
| UL1 Upper Limit 1 Err | Upper Limit 1—SLOW DOWN Indicator. Upper Limit 1—SLOW DOWN switch status is changed. | <ol style="list-style-type: none"> 1. May not require corrective action. 2. Check the limit switches location. 3. Check the limit switches condition. |
| UL2 Upper Limit 2 Err | Upper Limit 2—STOP Indicator. Upper Limit 2—STOP switch status is changed. | <ol style="list-style-type: none"> 1. May not require corrective action. 2. Check the limit switches location. 3. Check the limit switches condition. |
| UL3 Upper Limit 3 Err | Upper Limit 3—Weighted Stop. Upper Limit weighted limit switch tripped. | <ol style="list-style-type: none"> 1. May not require corrective action. 2. Check the position of the Limit Switch. 3. Check the condition of the Limit Switch. 4. Check the conditions of/for terminal H1-XX (U1-10) |
| UT1 Undertorque Det 1 | Undertorque Detection 1. The current is less than L6-02 for more than L6-03. | <ol style="list-style-type: none"> 1. Check settings. 2. Check motor coupling. |

| Fault Code | Fault or Indicator Name/Description | Corrective Action |
|---------------------------------|---|--|
| UT2 Undertorque Det 2 | Undertorque Detection 2. The current is less than L6-05 for more than L6-06. | <ol style="list-style-type: none"> 1. Check settings. 2. Check motor coupling. |
| UV DC Bus Undervolt | Undervoltage Fault. Undervoltage status occurs for more than 2 sec during STOP. Input voltage drops below 190V DC or less for 230V AC class, 380V DC or less for 460V AC class. | <ol style="list-style-type: none"> 1. Check the power source wiring. 2. Replace any bad branch fuses. 3. Check collector system. |
| UV1 DC Bus Undervolt | Undervoltage 1 Fault. Undervoltage status occurs for more than 2 sec during RUN command. Input voltage drops below 190V DC or less for 230V AC class, 380V DC or less for 460V AC class. | <ol style="list-style-type: none"> 1. Check power supply wiring. 2. Correct the line voltage. 3. Check collector system. |
| UV2 CTL PS Undervolt | Undervoltage 2 Fault. The inverter detected a loss of the 24V logic power supply voltage. | <ol style="list-style-type: none"> 1. Check power supply wiring. 2. Correct the line voltage. 3. Check collector system. |
| UV3 MC Answerback | MC Fault. The pre-charge contactor opened during operation. | <ol style="list-style-type: none"> 1. Check power supply wiring. 2. Correct the line voltage. 3. Check collector system. 4. Wait 30-45 seconds before restarting drive after auto shut down. |

Troubleshooting Encoder Related Faults

The faults in this section may involve the encoder feedback system. During system startup, these faults are often caused by parameters that need to be adjusted. However, after the system has been running for some time without a fault, this usually indicates a problem with the physical system and adjusting the parameters should only be done after the physical system has been inspected.

Fault Code: Dev-1, Dev-2 Speed Deviation

Definition

Speed deviation faults mean that the drive output is not following the commanded speed reference. This is possible if there is not enough torque available to follow the internal speed reference. Therefore, speed deviations will typically occur when the drive is at its programmed torque limit. In addition, if the drive receives erratic, or missing, encoder pulses, speed deviations are also possible. If the initial drive tuning and start-up of the system was successfully completed and the crane has been in operation without any faults, then the occurrence of this fault most likely indicates that something mechanical with the system has changed or drive parameters were changed (i.e., failed encoder, load snag, crane overload, change in acceleration or deceleration times, etc.).

Corrective Action

1. Do **NOT** continue to operate the hoist.
NOTE: Continued attempts to operate the hoist with speed deviation faults occurring can result in loss of control of the load under certain circumstances.
2. As a precaution the load float time, parameter C8-10 should be set to zero until the source of the speed deviation fault has been determined and corrected.
3. Verify if the load has snagged or if there is a load on the hook that exceeds capacity.
4. Check the alignment of the encoder pulse wheel with the sensor head, or the encoder shaft coupling (depending on the type of encoder used). If the pulse wheel is misaligned or the shaft coupling is loose the drive will get erratic pulse signals or no signals at all causing a speed deviation fault or PGO (Pulse Generator Open) fault. Repairs to the encoder wheel or shaft coupling should be made immediately before again attempting to operate the hoist.
5. If the encoder appears to have no mechanical problems, the encoder cable should be checked for damage and replaced if a problem is found.
 - 5.1 Each of the encoder wires should be checked for continuity.
 - 5.2 The wires should be checked for shorts between any two wires.
 - 5.3 The wires should be checked for shorts to the shield or ground.
 - 5.4 Visually inspect the cable for damage that may be causing intermittent problems.
6. If the encoder feedback system checks out mechanically and electrically, then the last physical check to make is for something in the mechanical system that might be resisting normal operation. One example may be the brake is not opening fully and is causing enough drag to prevent the system from operating at commanded speed.

7. If the encoder feedback system checks out and no other mechanical problems can be found, then something must have changed in the control system.
 - 7.1 Check if the acceleration or deceleration times have been changed (B5-01, B5-02, or C1-02).
 - 7.2 Check if a function that provides an alternate acceleration or deceleration rate has been enabled or changed. (Quick Stop, Reverse Plug Simulation, Accel/Decel Time 2)If one of these times is too short, causing torque limited acceleration or deceleration, then the times should be extended.
8. If none of the above steps has identified a valid problem(s), only then should the speed deviation detection levels be adjusted.

NOTE: The reaction time necessary to stop a load is limited to the lift of the hoist and the response time of the hoist brakes. It is desirable to have as fast a fault reaction time as possible without causing nuisance trips.)
9. Increase Encoder Excessive Speed Deviation Level to no more than 30 (F1-10).
10. After the corrective action has been taken and the fault no longer occurs then the load float time, C8-10, can be set back to its initial value.

Fault Code: PGO–Pulse Generator Signal Fault

Definition

The pulse generator signal missing fault indicates that the drive has detected a problem with encoder feedback. This fault will typically occur if the drive doesn't receive any encoder feedback pulses while it is commanded to run or encoder wiring has a discontinuity.

Corrective Action

1. Do **NOT** continue to operate the hoist.

NOTE: Continued attempts to operate the hoist with PGO faults occurring can result in loss of control of the load under certain circumstances.
2. As a precaution, the load float time, parameter C8-10, should be set to zero until the source of the PGO Fault has been determined and corrected. Disable PGO hardware detection with F1-20 or F1-21.
3. Check the alignment of the encoder pulse wheel with the sensor head, the encoder shaft coupling (depending on the type of encoder used), or check for a failed encoder sensor head. If one of these conditions exists the drive will get erratic pulse signals or no signal at all causing a speed deviation fault or PGO fault. Repairs to the encoder wheel or shaft coupling should be made immediately before attempting to operate the hoist again.
4. If the encoder appears to have no mechanical problems, the encoder cable should be checked for damage and replaced if a problem is found.
 - 4.1 Each of the encoder wires should be check for continuity.
 - 4.2 The wires should be checked for shorts between any two wires.
 - 4.3 The wires should be checked for shorts to the shield or ground.
 - 4.4 Visually inspect the cable for damage that may be causing intermittent problems.
5. If the encoder feedback system checks out, then check for physical obstruction to motor rotation such as brake failing to open.

6. After corrective action has been taken and the fault no longer occurs then the load float time, C8-10, can be set back to initial value.

Fault Code: BE1–Torque Proving Fault

Definition

The BE1 fault indicates that the drive has released the brake, but has not started to accelerate the motor when it detects more than the expected encoder feedback. A BE1 fault will occur if the pulses received during the BE1 detection time (C8-04) are greater than the expected number of pulses (C8-05). This is typically caused by the drive/motor have insufficient torque to suspend the load.

Correction Action

1. Check the encoder cable for damage and proper grounding. Replace it if a problem is found.
 - 2.1 Each of the encoder signals should be checked for excessive noise.
 - 2.2 The shielded encoder cable should be properly grounded.
 - 2.3 Visually inspect the cable for damage that may be causing intermittent problems.
2. Check the alignment of the encoder pulse wheel with the sensor head, or the encoder shaft coupling (Depending on the type of encoder used). If the pulse wheel is misaligned or the shaft coupling is loose the drive may get erratic pulse signals possibly causing a BE1 fault. Repairs to the encoder wheel or shaft coupling should be made immediately before again attempting to operate the hoist.
3. If none of the above steps has identified a valid problem(s), only then should the BE1 detection parameters be adjusted.

NOTE: It is desirable to have as fast a fault reaction time as possible without causing nuisance trips.
4. Increase C8-05 to no more than 800.

Fault Code: BE3–Brake Release Fault

Definition

The BE3 fault indicates that the drive has released the brake and commanded the drive to run, but has not detected the expected encoder feedback. A BE3 fault will occur if the pulses received during the BE3 detection time (C8-06) are less than the expected number of pulses (C8-07).

NOTE: Depending on the condition of the crane and control system, the load may drift during the BE3 detection time until the brake is again set. If giving a run command, the BE3 fault should be detected before a PGO fault would be detected.

Corrective Action

1. Check the brake for proper operation. If the brake does not open the drive will not see the proper number of encoder pulses returned and will post this fault.
2. Check the alignment of the encoder pulse wheel with the sensor head, or the encoder shaft coupling (depending on the type of encoder used). If the pulse wheel is misaligned or the shaft coupling is loose the drive will get erratic pulse signals or no signals at all possibly causing a BE3 fault. Repairs to the encoder wheel or shaft coupling should be made immediately before again attempting to operate the hoist.

3. If the encoder appears to have no mechanical problems, the encoder cable should be checked for damage and replaced if a problem is found.
 - 4.1 Each of the encoder wires should be checked for continuity.
 - 4.2 The wires should be checked for shorts between any two wires.
 - 4.3 The wires should be checked for shorts to the shield or ground.
 - 4.4 Visually inspect the cable for damage that may be causing intermittent problems.
4. If none of the above steps has identified a valid problem(s), only then should the BE3 detection parameters be adjusted.

NOTE: It is desirable to have as fast a fault reaction time as possible without causing nuisance trips.
5. Ensure that C8-04 is equal to the brake's mechanical delay time.
6. Increase the value of C8-06 to no more than 1 second.
7. Decrease the value of C8-07 to no less than 10.

Fault Code: BE6—Brake Proving Alarm

Definition

The BE6 alarm indicates that the drive has commanded the brake to set but it has detected more than the expected encoder feedback. A BE6 alarm will occur if the number of pulses received during the BE6 detection time (C8-12) is greater than the expected number of pulses (C8-13).

NOTE: This fault typically indicates a failed brake. Power should NOT be removed while this fault is active and the load should be moved to a safe location and lowered before proceeding with any corrective action.

Corrective Action

1. Check the brake for proper operation and adjustment. If the brake does not set, is improperly adjusted or is excessively worn, it may not be able to hold the load. This will allow the encoder pulses received during the detection time to exceed the set point.
2. Check the encoder cable for damage and proper grounding. Replace it if a problem is found.
 - 3.1 Each of the encoder signals should be checked for excessive noise.
 - 3.2 The shielded encoder cable should be properly grounded.
 - 3.3 Visually inspect the cable for damage that may be causing intermittent problems.
3. Check the alignment of the encoder pulse wheel with the sensor head, or the encoder shaft coupling (Depending on the type of encoder used). If the pulse wheel is misaligned or the shaft coupling is loose the drive may get erratic pulse signals possibly causing a BE6 fault. Repairs to the encoder wheel or shaft coupling should be made immediately before again attempting to operate the hoist.
4. If none of the above steps has identified a valid problem(s), only then should the BE6 detection parameters be adjusted.

NOTE: It is desirable to have as fast a fault reaction time as possible without causing nuisance trips.
5. Ensure that C8-11 is equal to the brake's mechanical delay time.

6. Increase the value of C8-13.

Fault Code: OC–Over Current Fault

Definition

An over current fault is caused if the output current exceeds 200% of the inverter rated output current. This fault can be caused by short circuits in the wiring or in the motor, and it can also be caused by parameters that are not adjusted properly. One other cause of this alarm could be erratic or no encoder feedback. In the last instance, the drive is trying to command the motor to hold a position, but due to the encoder problem, is unable to find the correct position. This would cause the drive to increase current output to the motor in an attempt to correct the position until an over current fault occurs.

Corrective Action

1. Check the motor wiring and the motor itself for a short between phases.
2. Check the alignment of the encoder pulse wheel with the sensor head, or the encoder shaft coupling (depending on the type of encoder used). If the pulse wheel is misaligned or the shaft coupling is loose the drive will get erratic pulse signals or no signals at all possibly causing an OC fault. Repairs to the encoder wheel or shaft coupling should be made immediately before again attempting to operate the hoist.
3. If the encoder appears to have no mechanical problems, the encoder cable should be checked for damage and replaced if a problem is found.
 - 3.1 Each of the encoder wires should be check for continuity.
 - 3.2 The wires should be checked for shorts between any two wires.
 - 3.3 The shield should be check for proper grounding.
 - 3.4 The wires should be checked for shorts to the shield or ground.
 - 3.5 Visually inspect the cable for damage that may be causing intermittent problems.
4. If none of the above steps has identified a valid problem(s), check if any of the torque limit parameters (C7-01 to C7-04) have been changed. If these parameters have been changed to allow a higher torque value, it could cause overcurrent trips.

NOTE: Changing these parameters could also induce speed deviation or overload faults. Only a trained technician should modify these parameters. It is desirable to have as fast a fault reaction time as possible without causing nuisance trips.

Fault Display and Corrective Actions at Auto-tuning

The following are fault displays and corrective actions at auto-tuning. If any of the following faults are found, the digital operator displays that fault contents; the motor coasts to stop if it is under operation. Fault contact output or minor fault contact output does not operate.

| Fault Display | Fault or Indicator Name/Description | Corrective Action |
|-----------------------------|---|--|
| Er-01 Fault | Motor Data Fault. Motor data input fault for auto-tuning. Relationship between motor output and motor rated current fault. Relationship between input motor rated current and set no-load current fault (at vector control mode and line-to-line resistance tuning.) | <ul style="list-style-type: none"> • Check input data. • Check inverter and motor capacity • Check motor rated current and no-load current. |
| Er-02 Minor Fault | Alarm. The minor fault is detected during auto-tuning. | <ul style="list-style-type: none"> • Check input data. • Check wirings • Check load. |
| Er-03 STOP Key | STOP Key Input. The stop key is pressed during auto-tuning. | |
| Er-04 Resistance | Line to Line Resistance Fault. Auto-tuning is not completed within the expected time. The auto-tuning is outside the parameter setting. | <ul style="list-style-type: none"> • Check input data. |
| Er-05 No-Load Current | No-load Current Fault. Auto-tuning is not completed within the expected time. The auto-tuning is outside the parameter setting. | <ul style="list-style-type: none"> • Check motor wiring. • If a motor and a load are connected, disconnect the motor from machinery system. |
| Er-08 Rated Slip | Rated Slip Fault. Auto-tuning is not completed within the expected time. The auto-tuning is outside the parameter setting. | |
| Er-09 Accelerate | Acceleration Fault. The motor did not accelerate at the expected time. | <ul style="list-style-type: none"> • Increase B5-01 (acceleration time). • If C7-01 and C7-02 (torque limit value) are decreased, increase values. • If a motor and a load are connected, separate the motor from the load. |
| Er-11 Motor Speed | Motor Speed Fault (Rotation type tuning only). The motor speed was over 100% at auto-tuning (vector control without PG only). | <ul style="list-style-type: none"> • Increase B5-01 (acceleration time). • If a motor and a load are connected, separate the motor from the load. |
| Er-12 I.det.Circuit | Current Detection Fault. Current exceeded the motor rated current. | <ul style="list-style-type: none"> • Release brake. • Check for open motor lead. |
| Er-13 Leakage Inductance | Leakage Inductance Fault. Auto-tuning did not finish within the set time. | <ul style="list-style-type: none"> • Check the T1 parameters. • Check motor wiring. |
| End 1 V/F Oversetting | Excess V/F setting * (Rotation type tuning only). The torque reference exceeded 100% and no load current exceeded 70%. | <ul style="list-style-type: none"> • Check the T1 parameters. • Disconnect the motor from the load. |
| End 2 Saturation | Motor Iron Core Saturation Coefficient Fault (Rotation type tuning only) Since the motor iron core saturation coefficient could not be auto-tuned within the set time, tentative value is set in the iron core saturation coefficient. | <ul style="list-style-type: none"> • Check the T1 parameters. • Check motor wiring. • Disconnect the motor from the load |
| End 3 Rated FLA Alm | Rated Current Set Alarm. Motor current during tuning was greater than the set value. | <ul style="list-style-type: none"> • Check E2-01. |

NOTE: * Excessive V/F set value, motor iron core saturation coefficient fault, and rated current set alarm are displayed after the auto tuning is completed.

Power Section Check



WARNING

Do NOT touch any circuit components while AC main power is on or immediately after the main AC power is disconnected from the unit. You must wait until the red “CHARGE” lamp is extinguished. It may take as long as 10 minutes for the charge on the main DC bus capacitors to drop to a safe level. Failure to adhere to this warning could result in serious injury.

Power Off Checks

To perform a power section check, remove the drive's main and control wiring from the terminal strips. Obtain reading as specified in the table on the next page, and ensure that the reading falls within the normal reading range.

Test equipment - Analog Ohmmeter set R x 1 scale or digital multimeter set to the diode check.

| Device | VOM (on RX1 Scale) | | Normal Reading (Analog Meter) | Normal Reading (Digital Meter) |
|---|--------------------|----------------------|--|---|
| | Positive Lead | Negative Lead | | |
| Input Rectifier Bridge *1 | L1 | + | 7-100 Ω | Approximately 0.5 V |
| | L2 | + | | |
| | L3 | + | | |
| | - | L1 | | |
| | - | L2 | | |
| | - | L3 | | |
| | L1 | - | Infinite Ω | OL Displayed |
| | L2 | - | | |
| | L3 | - | | |
| | + | L1 | | |
| | + | L2 | | |
| | + | L3 | | |
| Bus Capacitors | + | - | Observe gradually increasing resistance | Observe gradually increasing voltage to OL |
| Pre-charge Resistor | - | Across the Resistors | 100 Ω or less | - |
| Output Transistors *2 *3 | T1 | + | 7-100 Ω | Approximately 0.5V |
| | T2 | + | | |
| | T3 | + | | |
| | - | T1 | | |
| | - | T2 | | |
| | - | T3 | | |
| | T1 | - | Infinite Ω | OL Displayed |
| | T2 | - | | |
| | T3 | - | | |
| | + | T1 | | |
| | + | T2 | | |
| | + | T3 | | |
| Braking Diode (2006-2033) (4001-4039) | B2 | B1 | 10 Ω | 0.5 V |
| | B1 | B2 | Infinite Ω | OL Displayed |
| | B2 | - | Infinite Ω | OL Displayed |
| | - | B2 | Infinite Ω | OL Displayed |

1. "+" could be any one of three (+) terminals which are labeled as $\oplus 1$, $\oplus 2$, and $\oplus 3$.
2. If the bus fuse is blown you must install a jumper across the fuse terminals to get accurate resistance measurements.
3. If the pre-charge resistor is open, you will read infinite Ω between + and any output terminal unless you install a temporary jumper across the resistor.

a p p e n d i x **A**

**IMPULSE•VG+ Series 3
Parameter Listing**

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IMPULSE•VG+ Series 3 Parameter Listing

| No. | Parameter Name. | Factory | Ref Page#. |
|----------------|-------------------------|---------|------------|
| A1-01 | Access Level | 2 | 4-9 |
| A1-02 | Control Method | 3 | 4-9 |
| A1-03 | Motion | -- | 4-10 |
| A1-04 | Speed Ref | 1 | 4-10 |
| A1-05 | Initialize Parameters | 0 | 4-13 |
| A1-06 | Password 1 | 0 | 4-13 |
| A1-07 | Select Password 1 | 0 | 4-13 |
| A2-01 to A2-32 | User Parameters | -- | 4-13 |
| B1-01 | Reference 1 | 15.00* | 5-3 |
| B1-02 | Reference 2 | 30.00* | 5-3 |
| B1-03 | Reference 3 | 60.00* | 5-3 |
| B1-04 | Reference 4 | 0.00* | 5-3 |
| B1-05 | Reference 5 | 0.00* | 5-3 |
| B1-06 | Reference 6 | 0.00* | 5-3 |
| B1-07 | Reference 7 | 0.00* | 5-3 |
| B1-08 | Reference 8 | 0.00* | 5-3 |
| B1-09 | Reference 9 | 0.00* | 5-3 |
| B1-10 | Reference 10 | 0.00* | 5-3 |
| B1-11 | Reference 11 | 0.00* | 5-3 |
| B1-12 | Reference 12 | 0.00* | 5-3 |
| B1-13 | Reference 13 | 0.00* | 5-3 |
| B1-14 | Reference 14 | 0.00* | 5-3 |
| B1-15 | Reference 15 | 0.00* | 5-3 |
| B1-16 | Reference 16 | 0.00* | 5-3 |
| B1-17 | Jog Reference | 6.00* | 5-3 |
| B1-18 | Ref Priority | 0* | 5-3 |
| B2-01 | Ref Upper Limit | 100.0* | 5-5 |
| B2-02 | Ref Lower Limit | 0.0 | 5-5 |
| B2-03 | Ref 1 Lower Limit | 0.0* | 5-5 |
| B2-04 | Alt Upper Limit | 100.0 | 5-5 |
| B3-01 | Reference Source | 1 | 5-6 |
| B3-02 | Run Source | 1 | 5-6 |
| B3-03 | Stopping Method | 6* | 5-7 |
| B3-04 | Reverse Motor Direction | 0 | 5-9 |
| B3-05 | Zero-Speed Operation | 0 | 5-9 |
| B3-06 | Control Input Scans | 1 | 5-10 |
| B3-07 | Local/Remote Run Select | 0 | 5-10 |
| B3-08 | Run Command at Program | 0 | 5-10 |
| B3-10 | Allow Run at Power Up | 0 | 5-10 |

* Initial value set by X-Press Programming

** Initial value dependant on drive size, which is determined by O2-04 (kVA Selection).

*** Value is automatically set during auto tuning.

| No. | Parameter Name. | Factory | Ref Page#. |
|-------|-----------------------------|---------|------------|
| B4-01 | MOP Ref Memory | 0 | 5-10 |
| B4-02 | Trim Control Level | 10 | 5-11 |
| B5-01 | Acceleration Time 1 | 5.0* | 5-12 |
| B5-02 | Deceleration Time 1 | 3.0* | 5-12 |
| B5-03 | Acceleration Time 2 | 2.0 | 5-12 |
| B5-04 | Deceleration Time 2 | 2.0 | 5-12 |
| B5-05 | Acceleration Time N Change | 2.0 | 5-13 |
| B5-06 | Deceleration Time N Change | 2.0 | 5-13 |
| B5-07 | Hoist 2 Stop Decel | 0.3 | -- |
| B5-08 | Fast Stop Time | 0.5 | 5-13 |
| B5-09 | Accel/Decel Units | 1 | 5-13 |
| B5-10 | Accel/Decel Switch Freq | 120.0 | 5-13 |
| B5-11 | Switch Freq Compare | 1 | 5-13 |
| B5-12 | Accel Time 3 | 3.0 | 5-13 |
| B5-13 | Decel Time 3 | 3.0 | 5-13 |
| B5-14 | Accel Time 4 | 3.0 | 5-13 |
| B5-15 | Decel Time 4 | 3.0 | 5-13 |
| B6-05 | Speed Search delay | 0.2 | 5-14 |
| B8-01 | Jump Frequency 1 | 0.0 | 5-15 |
| B8-02 | Jump Frequency 2 | 0.0 | 5-15 |
| B8-03 | Jump Frequency 3 | 0.0 | 5-15 |
| B8-04 | Jump Bandwidth | 1.0 | 5-15 |
| C1-01 | Quick Stop Enable/Disable | 1* | 5-17 |
| C1-02 | Quick Stop Time | 1.0 | 5-17 |
| C1-03 | Reverse Plug Enable/Disable | 0 | 5-18 |
| C1-04 | Reverse Plug Decel Time | 2.0 | 5-18 |
| C1-05 | Reverse Plug Accel Time | 2.0 | 5-18 |
| C2-01 | Micro Speed Gain 1 | 1.00 | 5-19 |
| C2-02 | Micro Speed Gain 2 | 1.00 | 5-19 |
| C3-01 | Upper Limit 1 Speed | 6.00 | 5-20 |
| C3-02 | Upper Limit 1 Decel Time | 1.0 | 5-20 |
| C3-03 | Upper Limit 2 Decel Time | 1.0 | 5-20 |
| C3-04 | Lower Limit 1 Speed | 6.00 | 5-20 |
| C3-05 | Lower Limit 1 Decel Time | 1.0 | 5-20 |
| C3-06 | Lower Limit 2 Decel Time | 1.0 | 5-20 |
| C3-07 | Stopping Method @ LL2/UL2 | 2* | 5-20 |
| C3-08 | UL3 Stopping Method | 4 | 5-20 |
| C3-09 | Phantom Stopping Method | 1 | 5-20 |
| C3-10 | Load Share—enable/disable | 0 | 5-20 |
| C3-11 | Klixon Action | 0 | 5-20 |
| C3-12 | UL2 Revolutions | 0 | 5-21 |
| C3-13 | UL1 Revolutions | 0 | 5-21 |

* Initial value set by X-Press Programming

** Initial value dependant on drive size, which is determined by O2-04 (kVA Selection).

*** Value is automatically set during auto tuning.

| No. | Parameter Name. | Factory | Ref Page#. |
|-------|---|-----------|------------|
| C3-14 | LL1 Revolutions | 0 | 5-21 |
| C3-15 | LL2 Revolutions | 0 | 5-21 |
| C4-01 | Load Float Time 2 | 10 | 5-25 |
| C4-02 | Load Float Gain | ** | 5-25 |
| C4-03 | Load Float Count | 10 | 5-25 |
| C5-01 | Load Check Enable/Disable | 0 | 5-26 |
| C5-02 | Load Check Alarm Action | 4 | 5-26 |
| C5-03 | Min Torque Reference | 60% | 5-26 |
| C5-04 | Look Speed 1 | 6 | 5-26 |
| C5-05 | Current/Torque Reference for Look Speed 1 | 160 | 5-26 |
| C5-07 | Look Speed 2 | 20 | 5-26 |
| C5-08 | Current/Torque Reference for Look Speed 2 | 160 | 5-26 |
| C5-09 | Look Speed 3 | 40 | 5-26 |
| C5-10 | Current/Torque Reference for Look Speed 3 | 160 | 5-26 |
| C5-11 | Current Ref for > Look Speed 3 | 160 | 5-26 |
| C5-12 | Load Check Setting Time | 1.00 | 5-26 |
| C5-13 | Load Check Test Time | 0.25 | 5-26 |
| C5-14 | Load Check Fault Speed | 6.0 | 5-26 |
| C6-01 | Ultra Lift Enable/Disable | 0 | 5-28 |
| C6-02 | Ultra Lift Forward Speed | 60 | 5-28 |
| C6-03 | Ultra Lift Reverse Speed | 60 | 5-28 |
| C6-04 | Ultra Lift Forward Torque | 50 | 5-28 |
| C6-05 | Ultra Lift Reverse Torque | 30 | 5-28 |
| C6-06 | Ultra Lift Enabling Speed | 59.0 | 5-28 |
| C6-07 | Ultra Lift Delay Time | 2.0 | 5-28 |
| C6-08 | SFS Acceleration Gain | 1.0 | 5-28 |
| C6-09 | Normal Overspeed Level | 60 | 5-28 |
| C7-01 | Forward Torque Limit | 150 | 5-29 |
| C7-02 | Reverse Torque Limit | 150 | 5-29 |
| C7-03 | Forward Regen Torque Limit | 180 | 5-29 |
| C7-04 | Reverse Regen Torque Limit | 180 | 5-29 |
| C7-05 | Torque Limit Gain by MFI | 1.25 | 5-29 |
| C7-08 | Trav Trq Limiter | 0 | 5-29 |
| C7-09 | Limiter Freq | 2.0 | 5-29 |
| C8-01 | Torque Compensation Time | 1.0/1.5** | 5-31 |
| C8-02 | Current Feedback OK Timer | 1.0/1.5** | 5-31 |
| C8-03 | Minimum Brake Release Torque | 10 | 5-31 |
| C8-04 | Roll Back/BE4 Timer | 0.30 | 5-32 |
| C8-05 | Roll Back Count | 800 | 5-32 |
| C8-06 | BE3/Alternate Rev Torque Time | 0.30 | 5-32 |
| C8-07 | BE3 Detect Count | 10 | 5-32 |
| C8-08 | Alternate Reverse Torque Limit | 25 | 5-32 |

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*** Value is automatically set during auto tuning.

| No. | Parameter Name. | Factory | Ref Page#. |
|------------|----------------------------------|----------------|-------------------|
| C8-09 | Zero Speed Level | 1 | 5-32 |
| C8-10 | Load Float Time | 10 | 5-32 |
| C8-11 | Brake Delay Time/BE5 Timer | 0.7 | 5-32 |
| C8-12 | BE6 Detect Time | 5.0 | 5-32 |
| C8-13 | BE6 Maximum Count | 250 | 5-32 |
| C8-14 | Brake Hold Speed | 0.0 | 5-32 |
| C8-15 | Load Float Extension Time by MFI | 10 | 5-32 |
| C8-16 | Initial Brake Release Torque | 100 | 5-32 |
| C8-17 | BE6 Up Speed | 6.00 | 5-32 |
| C8-19 | Brake Test Torque | 125 | 5-32 |
| C8-20 | Brake Test Speed | 6 | 5-32 |
| C8-21 | Height Measure | 10000 | 5-32 |
| C8-24 | Hook Height Home | 0 | 5-33 |
| C8-25 | Hook Height Out | 0 | 5-33 |
| C8-26 | Load Float Fault Revolutions | 4 | 5-33 |
| C9-01 | G5IN4 Enable/Disable | 0 | 5-34 |
| C9-02 | G5IN4 Setup | 0 | 5-35 |
| C9-03 | DIO Terminal 1 | 0F | 5-34 |
| C9-04 | DIO Terminal 2 | 0F | 5-34 |
| C9-05 | DIO Terminal 3 | 0F | 5-34 |
| C9-06 | DIO Terminal 4 | 0F | 5-34 |
| C9-07 | DIO Terminal 5 | 0F | 5-34 |
| C9-08 | DIO Terminal 6 | 0F | 5-34 |
| C10-01 | Load Weight Enable/Disable | 0 | 5-38 |
| C10-02 | Torque Output Primary Delay | 200 | 5-38 |
| C10-03 | Load Weight Display Hold | 0 | 5-38 |
| C10-04 | Load Weight Conversion | 0 | 5-38 |
| C10-05 | Full Load Torque Output | 100.0 | 5-38 |
| C10-06 | No Load Torque Output | 20.0 | 5-38 |
| C10-07 | Unit Display | 0 | 5-38 |
| C10-08 | Weight Limit Output | 125 | 5-38 |
| C11-01 | Slack Cable Enable/Disable | 0 | 5-41 |
| C11-02 | Action at Slack Cable | 2 | 5-41 |
| C11-03 | Slack Cable Detection Torque | 30 | 5-42 |
| C11-04 | Slack Cable Detect Speed 1 | 2 | 5-42 |
| C11-05 | Slack Cable Delay Time 1 | 0.50 | 5-42 |
| C11-06 | Slack Cable Detect Speed 2 | 60 | 5-42 |
| C11-07 | Slack Cable Delay Time 2 | 0.10 | 5-42 |
| C11-08 | Snap Shaft enable/disable | 0 | 5-43 |
| C11-09 | Action at Snap Shaft | 0 | 5-43 |
| C11-10 | Snap Shaft Delta Speed | 1.0 | 5-43 |
| C11-11 | Snap Shaft Delay Time | 250 | 5-43 |

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| No. | Parameter Name. | Factory | Ref Page#. |
|------------|-----------------------------------|----------------|-------------------|
| C11-12 | Snap Shaft Gear Ratio Numerator | 10000 | 5-43 |
| C11-13 | Snap Shaft Gear Ratio Denominator | 10000 | 5-43 |
| C12-01 | Brake Jog Delay | 0.0 | 5-44 |
| C12-02 | Brake Run Delay | 1.1 | 5-44 |
| C12-03 | Delay-ON Timer | 0.0 | 5-44 |
| C12-04 | Delay-OFF Timer | 0.0 | 5-44 |
| C12-05 | Maintenance Timer | 0 | 5-45 |
| C12-06 | Maintenance Speed Gain | 0.5 | 5-45 |
| C13-01 | Inch Run Time | 1.00 | 5-46 |
| C13-02 | Repeat Delay Timer | 1.00 | 5-46 |
| C13-03 | Index Run Reference | 0.10 | 5-48 |
| C13-04 | Index Revolutions | 0 | 5-48 |
| C13-05 | Index Counts | 100 | 5-48 |
| C13-06 | Index Repeat Delay | 0.00 | 5-48 |
| C13-07 | Index Complete | 10 | 5-48 |
| C13-08 | Index Load Float Gain | 10 | 5-48 |
| C13-09 | Index ASR P Gain | 30 | 5-48 |
| C13-10 | Index ASR I Gain | 0.02 | 5-48 |
| C13-11 | Index Accel/Decel Rate Gain | 5.0 | 5-48 |
| C13-12 | Index Brake Ctrl | 0 | 5-48 |
| D1-01 | DC Injection Start Frequency | 0.5 | 5-49 |
| D1-03 | DC Injection Time @ Start | 0.00 | 5-49 |
| D1-04 | DC Injection Time @ Stop | 0.05 | 5-49 |
| D2-01 | Slip Compensation Gain | 1.0 | 5-50 |
| D2-05 | Output Voltage Compensation | 0 | 5-50 |
| D4-01 | ASR P Gain 1 | 30.00 | 5-50 |
| D4-02 | ASR I Time 1 | 0.500 | 5-50 |
| D4-03 | ASR P Gain 2 | 30.00 | 5-51 |
| D4-04 | ASR I Time 2 | 0.100 | 5-51 |
| D4-06 | ASR Delay Time | 0.004 | 5-51 |
| D4-07 | ASR Gain Switch Frequency | 0.0 | 5-51 |
| D4-08 | ASR I Limit | 400 | 5-51 |
| D5-01 | Torque Control Select | 0 | 5-51 |
| D5-02 | Torque Reference Filter | 0 | 5-51 |
| D5-03 | Speed Limit Select | 2 | 5-52 |
| D5-04 | Speed Limit Value | 105 | 5-52 |
| D5-05 | Speed Limit Bias | 105 | 5-52 |
| D5-06 | Reference Hold Time | 0 | 5-52 |
| D6-01 | Droop Quantity | 0.0 | 5-54 |
| D6-02 | Droop Delay Time | 0.05 | 5-54 |
| D8-01 | Dwell Reference @ Start | 0.0 | 5-55 |
| D8-02 | Dwell Time @ Start | 0.0 | 5-55 |

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| No. | Parameter Name. | Factory | Ref Page#. |
|-------|----------------------------|-----------|------------|
| D8-03 | Dwell Reference @ Stop | 0.0 | 5-55 |
| D8-04 | Dwell Time @ Stop | 0.0 | 5-55 |
| D9-01 | S-Curve Accel @ Start | 0.5* | 5-56 |
| D9-02 | S-Curve Accel @ End | 0.5* | 5-56 |
| D9-03 | S-Curve Decel @ Start | 0.5* | 5-56 |
| D9-04 | S-Curve Decel @ Stop | 0.20 | 5-56 |
| E1-01 | Input Voltage | 230/460** | 5-57 |
| E1-04 | Max Frequency | 60.0 | 5-58 |
| E1-05 | Max Voltage | 460 | 5-58 |
| E1-06 | Base Frequency | 60 | 5-58 |
| E1-09 | Min Frequency | 0.0 | 5-58 |
| E1-11 | Mid Frequency B | 0.0 | 5-58 |
| E1-12 | Mid Voltage B | 0.0 | 5-58 |
| E1-13 | Base Voltage | 0.0 | 5-58 |
| E2-01 | Motor Rated Full Load Amps | ** | 5-59 |
| E2-02 | Motor Rated Slip | ** | 5-59 |
| E2-03 | No load current | ** | 5-59 |
| E2-04 | Number of Poles | 4 | 5-59 |
| E2-05 | Terminal Resistance | ** | 5-59 |
| E2-06 | Leakage Inductance | ** | 5-59 |
| E2-07 | Saturation Compensation 1 | ** | 5-59 |
| E2-08 | Saturation Compensation 2 | ** | 5-59 |
| E2-11 | Motor Rated Power | ** | 5-59 |
| E3-01 | Motor 2 Control Method | 0 | 5-60 |
| E3-02 | Motion 2 | 1 | 5-60 |
| E3-03 | Motor 2 Max Frequency | 60.0 | 5-60 |
| E3-04 | Motor 2 Max Voltage | 230.0 | 5-60 |
| E3-05 | Motor 2 Base Frequency | 60.0 | 5-60 |
| E3-06 | Motor 2 Mid Frequency | 3.0 | 5-60 |
| E3-07 | Motor 2 Mid Voltage | 17.2 | 5-60 |
| E3-08 | Motor 2 Min Frequency | 1.5 | 5-60 |
| E3-09 | Motor 2 Min Voltage | 10.3 | 5-60 |
| E4-01 | Motor 2 FLA | ** | 5-61 |
| E4-02 | Motor 2 Slip | ** | 5-61 |
| E4-03 | Motor 2 NLA | ** | 5-61 |
| E4-04 | Motor 2 Poles | 4 | 5-61 |
| E4-05 | Motor 2 Term Resistance | ** | 5-61 |
| E4-06 | Motor 2 Leak Inductance | ** | 5-61 |
| E4-07 | Motor 2 Rated Power | ** | 5-61 |
| F1-01 | PG Pulses/Revolution | 1024 | 5-62 |
| F1-02 | PG Feedback Loss Select | 1 | 5-62 |
| F1-03 | PG OverSpeed Select | 1 | 5-62 |

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*** Value is automatically set during auto tuning.

| No. | Parameter Name. | Factory | Ref Page#. |
|-------|---------------------------------------|---------|------------|
| F1-04 | Action @ PG Deviation Select | 5 | 5-62 |
| F1-05 | PG Rotation Select | 0 | 5-62 |
| F1-06 | PG Output Ratio | 1 | 5-62 |
| F1-08 | PG OverSpeed Level | 105 | 5-63 |
| F1-09 | PG OverSpeed Time | 0.0 | 5-63 |
| F1-10 | PG Deviate Level | 10 | 5-63 |
| F1-11 | PG Deviate Time | 0.3 | 5-63 |
| F1-12 | PG# Gear Teeth 1 | 0 | 5-63 |
| F1-13 | PG# Gear Teeth 2 | 0 | 5-63 |
| F1-14 | PGO Detect Time | 0.50 | 5-63 |
| F1-16 | Pulse PPR Channel 2 | 1024 | 5-63 |
| F1-17 | PG Channel 2 Rotation | 0 | 5-63 |
| F1-18 | PGO Ch 2 Detect Time | 0.5 | 5-63 |
| F1-19 | PG-Z2 Output Select | 2 | 5-63 |
| F1-20 | PGO Ch1 enable/disable | 1 | 5-63 |
| F1-21 | PGO Ch2 enable/disable | 0 | 5-63 |
| F1-22 | PG-Z2 Input Select | 0 | 5-63 |
| F2-01 | AI-14 Input Select | 0 | 5-64 |
| F3-01 | Digital Input Setup | 7 | 5-64 |
| F4-01 | Analog Out Channel 1 Select | 2 | 5-65 |
| F4-02 | Analog Out Channel 1 Gain | 100 | 5-65 |
| F4-03 | Analog Out Channel 2 Select | 3 | 5-65 |
| F4-04 | Analog Out Channel 2 Gain | 50 | 5-65 |
| F4-05 | Analog Out Channel 1 bias | 0.0 | 5-65 |
| F4-06 | Analog Out Channel 2 bias | 0.0 | 5-65 |
| F4-07 | Channel 1 output signal | 0 | 5-66 |
| F4-08 | Channel 2 output signal | 0 | 5.66 |
| F5-01 | Digital Out Channel 1 Select | F | 5-66 |
| F5-02 | Digital Out Channel 2 Select | F | 5-66 |
| F5-03 | Digital Out Channel 3 Select | F | 5-66 |
| F5-04 | Digital Out Channel 4 Select | F | 5-66 |
| F5-05 | Digital Out Channel 5 Select | F | 5-66 |
| F5-06 | Digital Out Channel 6 Select | F | 5-66 |
| F5-07 | Digital Out Channel 7 Select | F | 5-66 |
| F5-08 | Digital Out Channel 8 Select | F | 5-66 |
| F5-09 | Digital Output Selection | 2 | 5-66 |
| F6-01 | Com Fault Stop Method | 1 | 5-68 |
| F6-02 | Option External Fault (EFO) Detection | 0 | 5-68 |
| F6-03 | Option External Fault (EFO) Action | 1 | 5-68 |
| F6-05 | Current Unit Selection | 0 | 5-68 |
| F6-06 | Torque Reference Limit Selection | 0 | 5-68 |
| H1-01 | Terminal 3 Select | 0* | 5-69 |
| H1-02 | Terminal 4 Select | 1* | 5-69 |

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| No. | Parameter Name. | Factory | Ref Page#. |
|------------|------------------------------|----------------|-------------------|
| H1-03 | Terminal 5 Select | F* | 5-69 |
| H1-04 | Terminal 6 Select | F* | 5-69 |
| H1-05 | Terminal 7 Select | F* | 5-69 |
| H1-06 | Terminal 8 Select | F* | 5-69 |
| H2-01 | Terminal M0/M1 Select | 0* | 5-74 |
| H2-02 | Terminal M2/M3/M4 Select | 0* | 5-74 |
| H2-03 | Terminal M5/M6 Select | 78* | 5-74 |
| H3-01 | Terminal A1 Signal | 0* | 5-80 |
| H3-02 | Terminal A1 Gain | 100.0 | 5-80 |
| H3-03 | Terminal A1 Bias | 0.0 | 5-80 |
| H3-04 | Terminal A3 Signal | 0 | 5-80 |
| H3-05 | Terminal A3 Select | 1F* | 5-80 |
| H3-06 | Terminal A3 Gain | 100.0 | 5-80 |
| H3-07 | Terminal A3 Bias | 0.0 | 5-80 |
| H3-08 | Terminal A2 Signal | 2 | 5-81 |
| H3-09 | Terminal A2 Select | 0 | 5-81 |
| H3-10 | Terminal A2 Gain | 100.0 | 5-81 |
| H3-11 | Terminal A2 Bias | 0.0 | 5-81 |
| H3-12 | Filter Average Time | 0.00 | 5-81 |
| H4-01 | Terminal FM Select | 2 | 5-82 |
| H4-02 | Terminal FM Gain | 100.0 | 5-82 |
| H4-03 | Terminal FM Bias | 0.0 | 5-82 |
| H4-04 | Terminal AM Select | 3 | 5-82 |
| H4-05 | Terminal AM Gain | 50.0 | 5-82 |
| H4-06 | Terminal AM Bias | 0.0 | 5-83 |
| H4-07 | Analog Out Level Select 1 | 0 | 5-83 |
| H4-08 | Analog Out Level Select 2 | 0 | 5-83 |
| H5-01 | Serial Comm Address | 1F | 5-84 |
| H5-02 | Serial Baud Rate | 3 | 5-84 |
| H5-03 | Serial Communication Parity | 0 | 5-84 |
| H5-04 | Action @ Serial Fault Select | 1 | 5-84 |
| H5-05 | Serial Fault Enable/Disable | 1 | 5-84 |
| H5-06 | Transmit Wait Time | 5 | 5-84 |
| H5-07 | RTS Control Select | 1 | 5-84 |
| H6-01 | Pulse Input Select | 0 | 5-85 |
| H6-02 | Pulse Input Scaling | 1440 | 5-85 |
| H6-03 | Pulse Input Gain | 100.0 | 5-85 |
| H6-04 | Pulse Input Bias | 0.0 | 5-85 |
| H6-05 | Pulse Input Filter | 0.10 | 5-85 |
| H6-06 | Pulse Monitor Selection | 2 | 5-85 |
| H6-07 | Pulse Monitor Scale | 1440 | 5-85 |
| L1-01 | Motor Overload Fault Select | 3 | 5-86 |

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| No. | Parameter Name. | Factory | Ref Page#. |
|-------|-------------------------------------|-----------|------------|
| L1-02 | Motor Overload Time Constant | 8.0 | 5-86 |
| L1-03 | Motor Overheat Alarm Select | 3 | 5-86 |
| L1-04 | Motor Overheat Fault Select | 2 | 5-87 |
| L1-05 | Motor Temperature Input Filter | 0.20 | 5-87 |
| L2-01 | Power Loss Ride Thru Enable/Disable | 0 | 5-87 |
| L2-02 | Power Loss Ride Thru Time | ** | 5-87 |
| L2-03 | Power Loss Base Block Time | ** | 5-87 |
| L2-04 | Power Loss Voltage Recovery Time | ** | 5-87 |
| L2-05 | Under Voltage Fault Level | 190/380** | 5-87 |
| L3-04 | Stall Prevention Decel Select | 0 | -- |
| L4-01 | Speed Agree Level | 0.0 | 5-88 |
| L4-02 | Speed Agree Width | 2.0 | 5-88 |
| L4-03 | Speed Agree Level +/- | 0.0 | 5-88 |
| L4-04 | Speed Agree Width +/- | 2.0 | 5-88 |
| L5-01 | TM Ctrl Method | 0 | 5-89 |
| L5-02 | TM Stop Method | 0 | 5-89 |
| L6-01 | Torque Detection 1 Select | 0 | 5-90 |
| L6-02 | Torque Detection 1 Level | 150 | 5-91 |
| L6-03 | Torque Detection1 Time | 0.1 | 5-91 |
| L6-04 | Torque Detection 2 Select | 0 | 5-91 |
| L6-05 | Torque Detection 2 Level | 150 | 5-92 |
| L6-06 | Torque Detection 2 Time | 0.1 | 5-92 |
| L8-02 | Over Heat Pre-Alarm Level | 95** | 5-93 |
| L8-03 | Over Heat Pre-Alarm Select | 4 | 5-93 |
| L8-05 | Input Phase Loss Detection | 1 | 5-93 |
| L8-07 | Output Phase Loss Detection | 2 | 5-93 |
| L8-09 | Ground Fault Detection | 1 | 5-93 |
| L8-10 | Fan on/off Selection | 0 | 5-93 |
| L8-11 | Fan Delay Time | 60 | 5-93 |
| L8-12 | Ambient Temperature | 45 | 5-93 |
| L8-15 | OL2 Selection at Low Speed | 0 | 5-93 |
| L8-18 | Software Current Limit | 1 | 5-93 |
| L9-01 | Auto Reset Enable/Disable | 1 | 5-94 |
| L9-02 | Reset Attempts | 3 | 5-94 |
| L9-03 | Reset Time | 0.5 | 5-94 |
| L9-04 | Reset Fault Select 1 | 0001 | 5-94 |
| L9-05 | Reset Fault Select 2 | E000 | 5-94 |
| L9-06 | Fault Contact Operation at Reset | 0 | 5-94 |
| O1-01 | User Monitor Select | 6 | 5-96 |
| O1-02 | Power On Monitor | 2 | 5-97 |
| O1-03 | Display Scaling | 0 | 5-97 |
| O1-04 | Display Units | 0 | 5-97 |

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| No. | Parameter Name. | Factory | Ref Page#. |
|------------|---|----------------|-------------------|
| O1-05 | LCD Contrast | 3 | 5-97 |
| O2-01 | Mode/Service Key | 0 | 5-98 |
| O2-02 | Operator Stop Key | 0 | 5-98 |
| O2-03 | User Defaults | 0 | 5-98 |
| O2-04 | Drive Model # | ** | 5-98 |
| O2-05 | Operator MOP | 0 | 5-99 |
| O2-06 | Operator Detection | 1 | 5-99 |
| O2-07 | Elapsed Time Set | 0 | 5-99 |
| O2-08 | Elapsed Time Run | 1 | 5-99 |
| O2-10 | Fan on Time Setting | 0 | 5-99 |
| O3-01 | Fault Trace Clear | 0 | 5-100 |
| O3-02 | Count History Clear | 0 | 5-100 |
| O4-01 | Copy Function Select | 0 | 5-100 |
| O4-02 | Copy Function enable/disable | 1 | 5-100 |
| T1-00 | Select Motor | 1 | 4-14 |
| T1-01 | Tuning Mode Sel | 0 | 4-14 |
| T1-02 | Mtr Rated Power | ** | 4-14 |
| T1-03 | Rated Voltage | ** | 4-14 |
| T1-04 | Rated Current | ** | 4-14 |
| T1-05 | Rated Frequency | 60.0 | 4-14 |
| T1-06 | Number of Poles | 4 | 4-14 |
| T1-07 | Rated Speed | 1750 | 4-14 |
| T1-08 | PG Pulses/Rev | 1024 | 4-14 |
| U1-01 | Frequency Reference | -- | 5-103 |
| U1-02 | Output Frequency | -- | 5-103 |
| U1-03 | Output Current | -- | 5-103 |
| U1-04 | Control Method | -- | 5-103 |
| U1-05 | Motor Speed | -- | 5-103 |
| U1-06 | Output Voltage | -- | 5-103 |
| U1-07 | DC Bus Voltage | -- | 5-103 |
| U1-08 | Output Hp | -- | 5-103 |
| U1-09 | Torque Reference | -- | 5-103 |
| U1-10 | Input Terminal Status | -- | 5-103 |
| U1-11 | Output Terminal Status | -- | 5-103 |
| U1-12 | Inverter Control Status 1 | -- | 5-103 |
| U1-13 | Elapsed Time | -- | 5-103 |
| U1-14 | Flash ROM Software ID Number and Revision | -- | 5-103 |
| U1-15 | Terminal A1 Level | -- | 5-103 |
| U1-16 | Terminal A2 Level | -- | 5-103 |
| U1-17 | Terminal A3 Level | -- | 5-103 |
| U1-18 | Motor Secondary Current | -- | 5-103 |
| U1-19 | Motor Excitation Current | -- | 5-103 |
| U1-20 | SFS Output | -- | 5-103 |

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| No. | Parameter Name. | Factory | Ref Page#. |
|------------|---|----------------|-------------------|
| U1-21 | ASR Input | -- | 5-103 |
| U1-22 | ASR Output | -- | 5-103 |
| U1-23 | PG Channel 2 Speed | -- | 5-103 |
| U1-24 | PID Feedback | -- | 5-103 |
| U1-25 | G5IN4 Monitor | -- | 5-103 |
| U1-26 | Voltage Reference (Vq) | -- | 5-103 |
| U1-27 | Voltage Reference (Vd) | -- | 5-103 |
| U1-28 | CPU ID | -- | 5-103 |
| U1-29 | Load Weight | -- | 5-103 |
| U1-30 | Snap Shaft Delta Speed | -- | 5-103 |
| U1-32 | ACR (q) Output | -- | 5-103 |
| U1-33 | ACR (d) Output | -- | 5-103 |
| U1-34 | OPE Detected | -- | 5-103 |
| U1-35 | Zero Servo Pulses | -- | 5-103 |
| U1-36 | PID Input | -- | 5-103 |
| U1-37 | PID Output | -- | 5-103 |
| U1-38 | PID Setpoint | -- | 5-103 |
| U1-39 | Communication Transmit Error | -- | 5-104 |
| U1-40 | Fan Elapsed Time | -- | 5-104 |
| U1-41 | Actual Heat Sink Temperature | -- | 5-104 |
| U1-44 | ASR out w/o Filter | -- | 5-104 |
| U1-49 | CPU Utilization Rate | -- | 5-104 |
| U1-50 | Hook Height | -- | 5-104 |
| U1-51 | Motor Revolutions after UL2 | -- | 5-104 |
| U1-52 | Maintenance Timer Elapsed Time | -- | 5-104 |
| U1-53 | Index Counts (Counts DIV BY SIGN F1-01 = # of Revs) | -- | 5-104 |
| U1-60 | PG CH1 Count | -- | 5-104 |
| U1-61 | PG CH2 Count | -- | 5-104 |
| U1-66 | BE6 Pulse Count | -- | 5-104 |
| U2-01 | Current Fault | -- | 5-104 |
| U2-02 | Last Fault | -- | 5-104 |
| U2-03 | Frequency Reference | -- | 5-104 |
| U2-04 | Output Frequency | -- | 5-104 |
| U2-05 | Output Current | -- | 5-104 |
| U2-06 | Motor Speed | -- | 5-104 |
| U2-07 | Output Voltage | -- | 5-104 |
| U2-08 | DC Bus Voltage | -- | 5-104 |
| U2-09 | Output kWatts | -- | 5-104 |
| U2-10 | Torque Reference | -- | 5-104 |
| U2-11 | Input Terminal Status | -- | 5-104 |
| U2-12 | Output Terminal Status | -- | 5-104 |
| U2-13 | Inverter Status | -- | 5-104 |

* Initial value set by X-Press Programming

** Initial value dependant on drive size, which is determined by O2-04 (kVA Selection).

*** Value is automatically set during auto tuning.

| No. | Parameter Name. | Factory | Ref Page#. |
|------------|------------------------|----------------|-------------------|
| U2-14 | Elapsed Time | -- | 5-104 |
| U3-01 | Last Fault | -- | 5-104 |
| U3-02 | Fault Message 2 | -- | 5-104 |
| U3-03 | Fault Message 3 | -- | 5-104 |
| U3-04 | Fault Message 4 | -- | 5-104 |
| U3-05 | Elapsed Time 1 | -- | 5-104 |
| U3-06 | Elapsed Time 2 | -- | 5-104 |
| U3-07 | Elapsed Time 3 | -- | 5-104 |
| U3-08 | Elapsed Time 4 | -- | 5-104 |
| U3-09 | Fault Message 5 | -- | 5-104 |
| U3-10 | Fault Message 6 | -- | 5-104 |
| U3-11 | Fault Message 7 | -- | 5-104 |
| U3-12 | Fault Message 8 | -- | 5-105 |
| U3-13 | Fault Message 9 | -- | 5-105 |
| U3-14 | Fault Message 10 | -- | 5-105 |
| U3-15 | Elapsed Time 5 | -- | 5-105 |
| U3-16 | Elapsed Time 6 | -- | 5-105 |
| U3-17 | Elapsed Time 7 | -- | 5-105 |
| U3-18 | Elapsed Time 8 | -- | 5-105 |
| U3-19 | Elapsed Time 9 | -- | 5-105 |
| U3-20 | Elapsed Time 10 | -- | 5-105 |
| U3-21 | AC Operations | -- | 5-105 |
| U3-22 | U3-21 Rollovers | -- | 5-105 |
| U3-23 | OL/LC Count | -- | 5-105 |

* Initial value set by X-Press Programming

** Initial value dependant on drive size, which is determined by O2-04 (kVA Selection).

*** Value is automatically set during auto tuning.