User's manual ACS355 drives



List of related manuals

Drive manuals and guides	Code (English)
ACS355 user's manual	3AUA0000066143
ACS355 drives with IP66/67 / UL Type 4x enclosure supplement	3AUA0000066066
ACS355 quick installation guide	3AUA0000092940
ACS355 common DC application guide	3AUA0000070130
Option manuals and guides	
FCAN-01 CANopen adapter module user's manual	3AFE68615500
FDNA-01 DeviceNet adapter module user's manual	3AFE68573360
FECA-01 EtherCAT® adapter module user's manual	<i>3AUA0000068940</i>
FENA-01/-11 Ethernet adapter module user's manual	3AUA0000093568
FLON-01 LONWORKS® adapter module user's manual	3AUA0000041017
FMBA-01 Modbus adapter module user's manual	3AFE68586704
FPBA-01 PROFIBUS DP adapter module user's manual	3AFE68573271
FRSA-00 RS-485 adapter board user's manual	3AFE68640300
MFDT-01 FlashDrop user's manual	3AFE68591074
MPOT-01 potentiometer module instructions for installation and use	3AFE68591082
MREL-01 output relay module user's manual	3AUA0000035974
MTAC-01 pulse encoder interface module user's manual	3AFE68591091
MUL1-R1 installation instructions for ACS150, ACS310, ACS320, ACS350 and ACS355	3AFE68642868
MUL1-R3 installation instructions for ACS310, ACS320, ACS350 and ACS355	3AFE68643147
MUL1-R4 installation instructions for ACS310, ACS320, ACS350 and ACS355	3AUA0000025916
SREA-01 Ethernet adapter module quick start-up guide	3AUA0000042902
SREA-01 Ethernet adapter module user's manual	3AUA0000042896
ACS355 and AC500-eCo application guide	2CDC125152M0201
AC500-eCo PLC and ACS355 quick installation guide	2CDC125145M0201

Maintenance manuals and guides

Guide for capacitor reforming in ACS50, ACS55, ACS150, 3AFE68735190 ACS310, ACS350, ACS355, ACS550, ACH550 and R1-R4 OINT/SINT boards

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

User's manual

ACS355

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Safety

What this chapter contains

The chapter contains safety instructions which you must follow when installing, operating and servicing the drive. If ignored, physical injury or death may follow, or damage may occur to the drive, motor or driven equipment. Read the safety instructions before you work on the drive.



Use of warnings

Warnings caution you about conditions which can result in serious injury or death and/or damage to the equipment, and advise on how to avoid the danger. The following warning symbols are used in this manual:



Electricity warning warns of hazards from electricity which can cause physical injury and/or damage to the equipment.



General warning warns about conditions, other than those caused by electricity, which can result in physical injury and/or damage to the equipment.

Safety in installation and maintenance

These warnings are intended for all who work on the drive, motor cable or motor.

Electrical safety



WARNING! Ignoring the following instructions can cause physical injury or death, or damage to the equipment.

Only qualified electricians are allowed to install and maintain the drive!

 Never work on the drive, motor cable or motor when input power is applied. After disconnecting the input power, always wait for 5 minutes to let the intermediate circuit capacitors discharge before you start working on the drive, motor or motor cable.

Always ensure by measuring with a multimeter (impedance at least 1 Mohm) that

- 1. there is no voltage between the drive input phases U1, V1 and W1 and the ground
- 2. there is no voltage between terminals BRK+ and BRK- and the ground.
- Do not work on the control cables when power is applied to the drive or to the
 external control circuits. Externally supplied control circuits may carry dangerous
 voltage even when the input power of the drive is switched off.
- Do not make any insulation or voltage withstand tests on the drive.
- Disconnect the internal EMC filter when installing the drive on an IT system (an ungrounded power system or a high-resistance-grounded [over 30 ohms] power system), otherwise the system will be connected to ground potential through the EMC filter capacitors. This may cause danger or damage the drive. See page 50.
 Note: When the internal EMC filter is disconnected, the drive is not EMC compatible without an external filter.
- Disconnect the internal EMC filter when installing the drive on a corner-grounded TN system, otherwise the drive will be damaged. See page 50. Note: When the internal EMC filter is disconnected, the drive is not EMC compatible without an external filter.
- All ELV (extra low voltage) circuits connected to the drive must be used within a
 zone of equipotential bonding, ie within a zone where all simultaneously
 accessible conductive parts are electrically connected to prevent hazardous
 voltages appearing between them. This is accomplished by a proper factory
 grounding.

Note:

 Even when the motor is stopped, dangerous voltage is present at the power circuit terminals U1, V1, W1 and U2, V2, W2 and BRK+ and BRK-.



Permanent magnet synchronous motor drives

These are additional warnings concerning permanent magnet synchronous motor drives. Ignoring the instructions can cause physical injury or death, or damage to the equipment.

WARNING! Do not work on the drive when the permanent magnet synchronous motor is rotating. Also, when the supply power is switched off and the inverter is stopped, a rotating permanent magnet synchronous motor feeds power to the intermediate circuit of the drive and the supply connections become live.

Before installation and maintenance work on the drive:

- Stop the motor.
- Ensure that there is no voltage on the drive power terminals according to step 1 or 2, or if possible, according to the both steps.
 - 1. Disconnect the motor from the drive with a safety switch or by other means. Measure that there is no voltage present on the drive input or output terminals (U1, V1, W1, U2, V2, W2, BRK+, BRK-).
 - 2. Ensure that the motor cannot rotate during work. Make sure that no other system, like hydraulic crawling drives, is able to rotate the motor directly or through any mechanical connection like felt, nip, rope, etc. Measure that there is no voltage present on the drive input or output terminals (U1, V1, W1, U2, V2, W2, BRK+, BRK-). Ground the drive output terminals temporarily by connecting them together as well as to the PE.



General safety



WARNING! Ignoring the following instructions can cause physical injury or death, or damage to the equipment.

- The drive is not field repairable. Never attempt to repair a malfunctioning drive; contact your local ABB representative or Authorized Service Center for replacement.
- Make sure that dust from drilling does not enter the drive during the installation. Electrically conductive dust inside the drive may cause damage or lead to malfunction.
- Ensure sufficient cooling.



Safe start-up and operation

These warnings are intended for all who plan the operation, start up or operate the drive.

Electrical safety

Permanent magnet synchronous motor drives

These warnings concern permanent magnet synchronous motor drives. Ignoring the instructions can cause physical injury or death, or damage to the equipment.

WARNING! It is not recommended to run the permanent magnet synchronous motor over 1.2 times the rated speed. Motor overspeed may lead to overvoltage which may permanently damage the drive.

General safety



WARNING! Ignoring the following instructions can cause physical injury or death, or damage to the equipment.



- Before adjusting the drive and putting it into service, make sure that the motor and all driven equipment are suitable for operation throughout the speed range provided by the drive. The drive can be adjusted to operate the motor at speeds above and below the speed provided by connecting the motor directly to the power line.
- Do not activate automatic fault reset functions if dangerous situations can occur. When activated, these functions will reset the drive and resume operation after a fault.
- Do not control the motor with an AC contactor or disconnecting device (disconnecting means); use instead the control panel start and stop keys 🔷 and (I/O or fieldbus). The maximum allowed number of charging cycles of the DC capacitors (ie power-ups by applying power) is two per minute and the maximum total number of chargings is 15 000.

Note:

- If an external source for start command is selected and it is ON, the drive will start immediately after an input voltage break or fault reset unless the drive is configured for 3-wire (a pulse) start/stop.
- When the control location is not set to local (LOC not shown on the display), the stop key on the control panel will not stop the drive. To stop the drive using the control panel, first press the LOC/REM key (26) and then the stop key (36).



Introduction to the manual

What this chapter contains

The chapter describes applicability, target audience and purpose of this manual. It describes the contents of this manual and refers to a list of related manuals for more information. The chapter also contains a flowchart of steps for checking the delivery, installing and commissioning the drive. The flowchart refers to chapters/sections in this manual.

Applicability

The manual is applicable to the ACS355 drive firmware version 5.060 or later. See parameter 3301 FIRMWARE on page 260.

Target audience

The reader is expected to know the fundamentals of electricity, wiring, electrical components and electrical schematic symbols.

The manual is written for readers worldwide. Both SI and imperial units are shown. Special US instructions for installations in the United States are given.

Purpose of the manual

This manual provides information needed for planning the installation, installing, commissioning, using and servicing the drive.

Contents of this manual

The manual consists of the following chapters:

- Safety (page 17) gives safety instructions you must follow when installing, commissioning, operating and servicing the drive.
- Introduction to the manual (this chapter, page 21) describes applicability, target audience, purpose and contents of this manual. It also contains a guick installation and commissioning flowchart.
- Operation principle and hardware description (page 27) describes the operation principle, layout, power connections and control interfaces, type designation label and type designation information in short.
- *Mechanical installation* (page 33) tells how to check the installation site, unpack, check the delivery and install the drive mechanically.
- Planning the electrical installation (page 39) tells how to check the compatibility of the motor and the drive and select cables, protections and cable routing.
- *Electrical installation* (page 49) tells how to check the insulation of the assembly and the compatibility with IT (ungrounded) and corner-grounded TN systems as well as connect power cables and control cables.
- Installation checklist (page 59) contains a checklist for checking the mechanical and electrical installation of the drive.
- Start-up, control with I/O and ID run (page 61) tells how to start up the drive as well as how to start, stop, change the direction of the motor rotation and adjust the motor speed through the I/O interface.
- Control panels (page 75) describes the control panel keys, LED indicators and display fields and tells how to use the panel for control, monitoring and changing the settings.
- Application macros (page 111) gives a brief description of each application macro together with a wiring diagram showing the default control connections. It also explains how to save a user macro and how to recall it.
- *Program features* (page 125) describes program features with lists of related user settings, actual signals, and fault and alarm messages.
- Actual signals and parameters (page 181) describes actual signals and parameters. It also lists the default values for the different macros.
- Fieldbus control with embedded fieldbus (page 311) tells how the drive can be controlled by external devices over a communication network using embedded fieldbus.
- Fieldbus control with fieldbus adapter (page 337) tells how the drive can be controlled by external devices over a communication network using a fieldbus adapter.
- Fault tracing (page 347) tells how to reset faults and view fault history. It lists all alarm and fault messages including the possible cause and corrective actions.
- Maintenance and hardware diagnostics (page 367) contains preventive

maintenance instructions and LED indicator descriptions.

- Technical data (page 371) contains technical specifications of the drive, eg ratings, sizes and technical requirements as well as provisions for fulfilling the requirements for CE and other marks.
- Dimension drawings (page 391) shows dimension drawings of the drive.
- Appendix: Resistor braking (page 401) tells how to select the brake resistor.
- Appendix: Extension modules (page 405) describes common features and mechanical installation of the optional extension modules: MPOW-01 auxiliary power extension module, MTAC-01 pulse encoder interface module and MREL-01 output relay module. Specific features and electrical installation for the MPOW-01 are also described; for information on the MTAC-01 and MREL-01, refer to the corresponding user's manual.
- Appendix: Safe torque off (STO) (page 411) describes STO features, installation and technical data.
- Appendix: Permanent magnet synchronous motors (PMSMs) (page 417) describes the parameter settings needed for permanent magnet synchronous motors.
- Further information (inside of the back cover, page 421) tells how to make product and service inquiries, get information on product training, provide feedback on ABB Drives manuals and how to find documents on the Internet.

Related documents

See *List of related manuals* on page 2 (inside of the front cover).

Categorization by frame size

The ACS355 is manufactured in frame sizes R0...R4. Some instructions and other information which only concern certain frame sizes are marked with the symbol of the frame size (R0...R4). To identify the frame size of your drive, see the table in section Ratings on page 372.

Quick installation and commissioning flowchart

Task	See
Identify the frame size of your drive: R0R4.	Operation principle and hardware description: Type designation key on page 31 Technical data: Ratings on page 372
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	-
Install the drive on a wall or in a cabinet.	Mechanical installation on page 33
	-
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Check the insulation of the input cable and the motor and the motor cable.	Electrical installation: Checking the insulation of the assembly on page 49
	-
Connect the power cables.	Electrical installation: Connecting the power cables on page 51
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Connect the control cables.	Electrical installation: Connecting the control cables on page 53
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Check the installation.	Installation checklist on page 59
Commission the drive.	Start-up, control with I/O and ID run on page
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Terms and abbreviations

Term/abbreviation	Explanation
ACS-CP-A	Assistant control panel, advanced operator keypad for communication with the drive
ACS-CP-C	Basic control panel, basic operator keypad for communication with the drive
ACS-CP-D	Assistant control panel for Asian languages, advanced operator keypad for communication with the drive
Brake chopper	Conducts the surplus energy from the intermediate circuit of the drive to the brake resistor when necessary. The chopper operates when the DC link voltage exceeds a certain maximum limit. The voltage rise is typically caused by deceleration (braking) of a high inertia motor.
Brake resistor	Dissipates the drive surplus braking energy conducted by the brake chopper to heat. Essential part of the brake circuit. See <i>Brake chopper</i> .
Capacitor bank	See DC link capacitors.
Control board	Circuit board in which the control program runs.
CRC	Cyclic redundancy check
DC link	DC circuit between rectifier and inverter
DC link capacitors	Energy storage which stabilizes the intermediate circuit DC voltage.
DCU	Drive control unit
Drive	Frequency converter for controlling AC motors
EMC	Electromagnetic compatibility
EFB	Embedded fieldbus
FBA	Fieldbus adapter
FCAN	Optional CANopen adapter module
FDNA	Optional DeviceNet adapter module
FECA	Optional EtherCAT adapter module
FENA	Optional Ethernet adapter module for EtherNet/IP, Modbus TCP and PROFINET IO protocols
FLON	Optional LONWORKS® adapter module
FMBA	Optional Modbus RTU adapter module
FPBA	Optional PROFIBUS DP adapter module
Frame (size)	Refers to drive physical size, for example R1 and R2. To determine the frame size of a drive, refer to the rating table in chapter <i>Technical data</i> on page <i>371</i> .
FRSA	RSA-485 adapter board
I/O	Input/Output
ID run	Identification run
IGBT	Insulated gate bipolar transistor
Intermediate circuit	See DC link.
Inverter	Converts direct current and voltage to alternating current and voltage.

Term/abbreviation	Explanation
IT system	Type of supply system that has no (low-impedance) connection to ground/earth.
LRFI Series of optional EMC filters	
LSW	Least significant word
Macro	Pre-defined default values of parameters in drive control program. Each macro is intended for a specific application. See <i>Parameter</i> .
MFDT-01	FlashDrop, a tool for configuring an unpowered drive
MPOT	Potentiometer module
MPOW	Auxiliary power extension module
MREL	Relay output module
MSW	Most significant word
MTAC	Pulse encoder interface module
MUL1-R1	Option kit for R1 frame sizes for compliance with NEMA 1
MUL1-R3	Option kit for R3 frame sizes for compliance with NEMA 1
MUL1-R4	Option kit for R4 frame sizes for compliance with NEMA 1
Parameter	User-adjustable operation instruction to the drive, or signal measured or calculated by the drive
PLC	Programmable logic controller
PMSM	Permanent magnet synchronous motor
PROFIBUS, PROFIBUS DP, PROFINET IO	Registered trademarks of PI - PROFIBUS & PROFINET International
R1, R2,	Frame (size)
RCD	Residual current device
Rectifier	Converts alternating current and voltage to direct current and voltage.
RFI	Radio-frequency interference
RTU	Remote terminal unit
SIL	Safety integrity level. See Appendix: Safe torque off (STO) on page 411.
SREA-01	Ethernet adapter module
STO	Safe torque off. See Appendix: Safe torque off (STO) on page 411.
TN system	Type of supply system that provides a direct connection to ground/earth.



Operation principle and hardware description

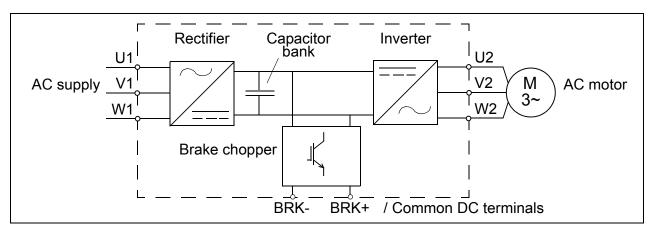
What this chapter contains

The chapter briefly describes the operation principle, layout, type designation label and type designation information. It also shows a general diagram of power connections and control interfaces.

Operation principle

The ACS355 is a wall or cabinet mountable drive for controlling asynchronous AC induction motors and permanent magnet synchronous motors.

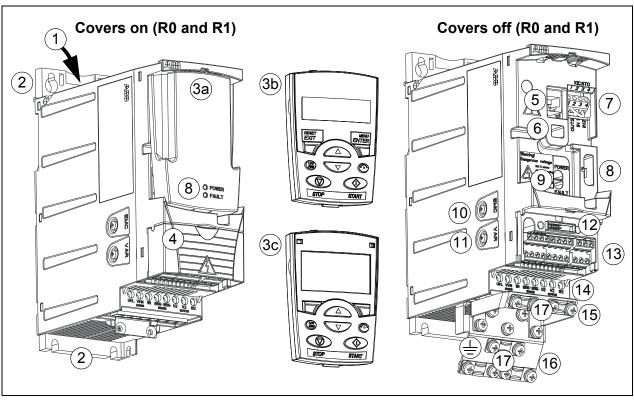
The figure below shows the simplified main circuit diagram of the drive. The rectifier converts three-phase AC voltage to DC voltage. The capacitor bank of the intermediate circuit stabilizes the DC voltage. The inverter converts the DC voltage back to AC voltage for the AC motor. The brake chopper connects the external brake resistor to the intermediate DC circuit when the voltage in the circuit exceeds its maximum limit.



Product overview

Layout

The layout of the drive is presented below. The construction of the different frame sizes R0...R4 varies to some extent.

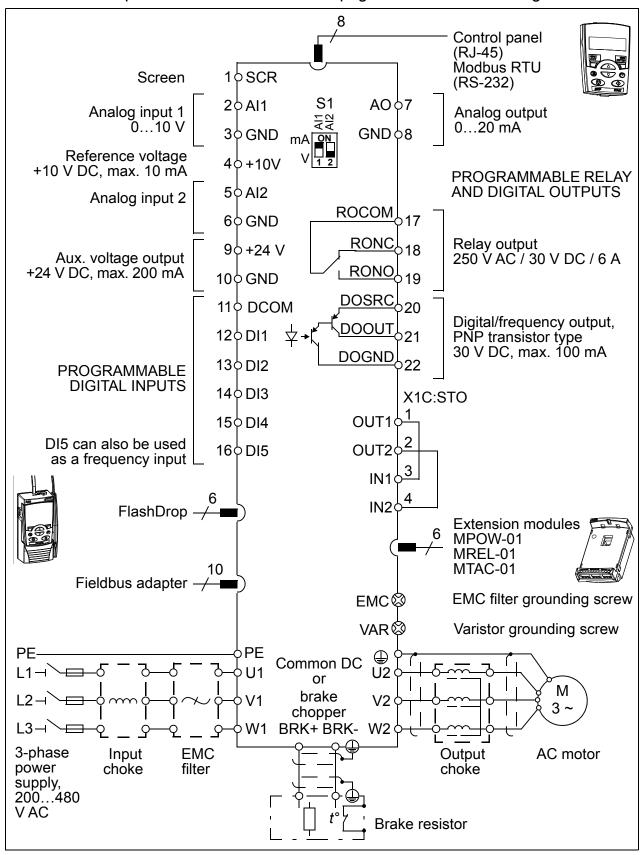


1	Cooling outlet through top cover
	Mounting holes
3	Panel cover (a) / basic control panel (b) /
	assistant control panel (c)
4	Terminal cover (or optional potentiometer
	unit MPOT-01)
	Panel connection
6	Option connection
	STO (Safe torque off) connection
	FlashDrop connection
9	Power OK and Fault LEDs. See section
	LEDs on page 370.

10	EMC filter grounding screw (EMC).
10	Note: The screw is on the front in frame
	size R4.
11	Varistor grounding screw (VAR)
12	Fieldbus adapter (serial communication)
	connection
13	I/O connections
14	Input power connection (U1, V1, W1),
	brake resistor connection (BRK+, BRK-)
	and motor connection (U2, V2, W2).
15	I/O clamping plate
16	Clamping plate
17	Clamps

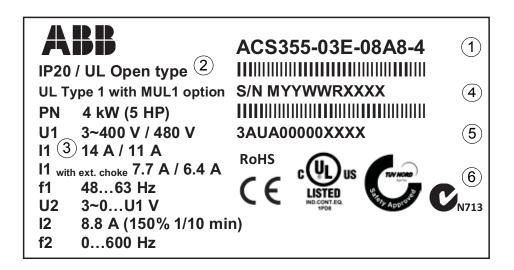
Overview of power and control connections

The diagram gives an overview of connections. I/O connections are parameterable. See chapter Application macros on page 111 for I/O connections for the different macros and chapter *Electrical installation* on page 49 for installation in general.



Type designation label

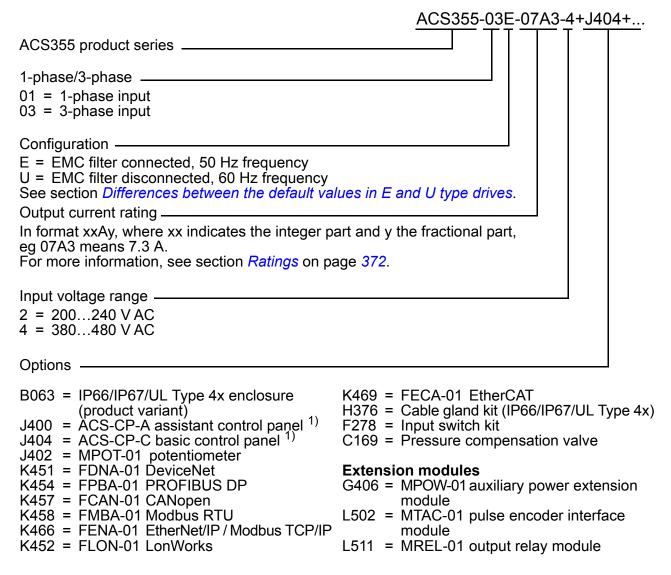
The type designation label is attached to the left side of the drive. An example label and explanation of the label contents are shown below.



1	Type designation, see section <i>Type designation key</i> on page <i>31</i>		
2	Degree of protection by enclosure (IP and UL/NEMA)		
3	Nominal ratings, see section <i>Ratings</i> on page 372.		
4	Serial number of format MYYWWRXXXX, where		
	M:	Manufacturer	
	YY:	10, 11, 12, for 2010, 2011, 2012,	
	WW:	01, 02, 03, for week 1, week 2, week 3,	
	R:	A, B, C, for product revision number	
	XXXX:	Integer starting every week from 0001	
5	ABB MRP code of the drive		
6	CE marking and C-Tick, C-UL US, RoHS and TÜV NORD marks (the label of your drive		
	shows the valid markings)		

Type designation key

The type designation contains information on the specifications and configuration of the drive. You find the type designation on the type designation label attached to the drive. The first digits from the left express the basic configuration, for example ACS355-03E-07A3-4. The optional selections are given after that, separated by + signs, for example +J404. The explanations of the type designation selections are described below.



1) The ACS355 is compatible with panels that have the following panel revisions and panel firmware versions. To find out the revision and firmware version of your panel, see page 76.

Panel type	Type code	Panel revision	Panel firmware version
Basic control panel	ACS-CP-C	M or later	1.13 or later
Assistant control panel	ACS-CP-A	F or later	2.04 or later
Assistant control panel (Asia)	ACS-CP-D	Q or later	2.04 or later

Note that unlike the other panels, the ACS-CP-D is ordered with a separate material code.

32	Operation principle and hardware description

Mechanical installation

What this chapter contains

The chapter tells how to check the installation site, unpack, check the delivery and install the drive mechanically.

Checking the installation site

The drive may be installed on the wall or in a cabinet. Check the enclosure requirements for the need to use the NEMA 1 option in wall installations (see chapter Technical data on page 371).

The drive can be installed in three different ways, depending on the frame size:

- a) back mounting (all frame sizes)
- b) side mounting (frame sizes R0...R2)
- c) DIN rail mounting (all frame sizes).

The drive must be installed in an upright position.

Check the installation site according to the requirements below. Refer to chapter *Dimension drawings* on page 391 for frame details.

Requirements for the installation site

Operation conditions

See chapter *Technical data* on page 371 for the allowed operation conditions of the drive.

Wall

The wall should be as close to vertical and even as possible, of non-flammable material and strong enough to carry the weight of the drive.



Floor

The floor/material below the installation should be non-flammable.

Free space around the drive

The required free space for cooling above and below the drive is 75 mm (3 in). No free space is required on the sides of the drive, so drives can be mounted immediately next to each other.

Required tools

To install the drive, you need the following tools:

- screwdrivers (as appropriate for the mounting hardware used)
- wire stripper
- tape measure
- drill (if the drive will be installed with screws/bolts)
- mounting hardware: screws or bolts (if the drive will be installed with screws/bolts). For the number of screws/bolts, see With screws on page 36.



Unpacking

The drive (1) is delivered in a package that also contains the following items (frame size R1 shown in the figure):

- plastic bag (2) including clamping plate (also used for I/O cables in frame sizes R3 and R4), I/O clamping plate (for frame sizes R0...R2), fieldbus option ground plate, clamps and screws
- panel cover (3)
- mounting template, integrated into the package (4)
- user's manual (5)
- possible options (fieldbus, potentiometer, extension module, all with instructions, basic control panel or assistant control panel).



Checking the delivery

Check that there are no signs of damage. Notify the shipper immediately if damaged components are found.

Before attempting installation and operation, check the information on the type designation label of the drive to verify that the drive is of the correct type. See section Type designation label on page 30.



Installing

The instructions in this manual cover drives with the IP20 degree of protection. To comply with NEMA 1, use the MUL1-R1, MUL1-R3 or MUL1-R4 option kit, which is delivered with multilingual installation instructions (3AFE68642868, 3AFE68643147 or 3AUA0000025916, respectively).

To obtain a higher degree of protection, the drive must be installed inside a cabinet. If there are sand, dust or other impurities in the operating environment, a typical minimum requirement for the installation cabinet is IP54 degree of protection.

Install the drive

Install the drive with screws or on a DIN rail as appropriate.

Note: Make sure that dust from drilling does not enter the drive during the installation.

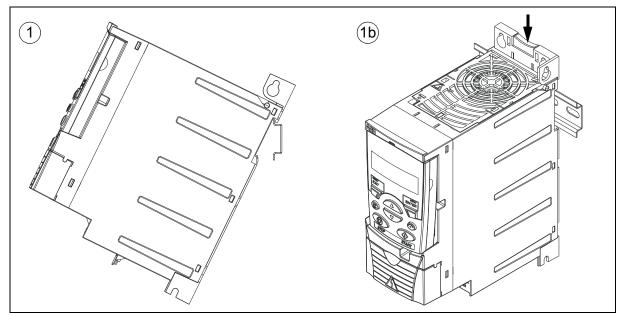
With screws

- 1. Mark the hole locations using for example the mounting template cut out from the package. The locations of the holes are also shown in the drawings in chapter Dimension drawings on page 391. The number and location of the holes used depend on how the drive is installed:
 - a) back mounting (frame sizes R0...R4): four holes
 - b) side mounting (frame sizes R0...R2): three holes; one of the bottom holes is located in the clamping plate.
- 2. Fix the screws or bolts to the marked locations.
- Position the drive onto the screws on the wall.
- 4. Tighten the screws in the wall securely.



On DIN rail

1. Click the drive to the rail. To detach the drive, press the release lever on top of the drive (1b).

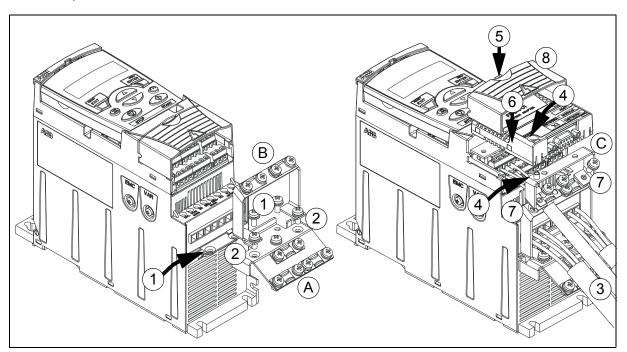




Fasten clamping plates

Note: Make sure that you do not throw the clamping plates away as they are required for proper grounding of the power and control cables as well as the fieldbus option.

- 1. Fasten the clamping plate (A) to the plate at the bottom of the drive with the provided screws.
- 2. For frame sizes R0...R2, fasten the I/O clamping plate (B) to the clamping plate with the provided screws.





Attach the optional fieldbus module

- 1. Connect the power and control cables as instructed in chapter *Electrical* installation on page 49.
- 2. Place the fieldbus module on the option ground plate (C) and tighten the grounding screw on the left corner of the fieldbus module. This fastens the module to the option ground plate (C).
- 3. If the terminal cover is not already removed, push the recess in the cover and simultaneously slide the cover off the frame.
- 4. Snap the fieldbus module attached to the option ground plate (C) in position so that the module is plugged to the connection on the drive front and the screw holes in the option ground plate (C) and the I/O clamping plate (B) are aligned.
- 5. Fasten the option ground plate (C) to the I/O clamping plate (B) with the provided screws.
- 6. Slide the terminal cover back in place.



Planning the electrical installation

What this chapter contains

The chapter contains the instructions that you must follow when checking the compatibility of the motor and drive, and selecting cables, protections, cable routing and way of operation for the drive.

Note: The installation must always be designed and made according to applicable local laws and regulations. ABB does not assume any liability whatsoever for any installation which breaches the local laws and/or other regulations. Furthermore, if the recommendations given by ABB are not followed, the drive may experience problems that the warranty does not cover.

Implementing the AC power line connection

See the requirements in section *Electric power network specification* on page 381. Use a fixed connection to the AC power line.



WARNING! As the leakage current of the device typically exceeds 3.5 mA, a fixed installation is required according to IEC 61800-5-1.

Using an input choke

An input choke is required in case of unstable supply networks. An input choke can also be used for decreasing the input current.

Selecting the supply disconnecting device (disconnecting means)

Install a hand-operated supply disconnecting device (disconnecting means) between the AC power source and the drive. The disconnecting device must be of a type that can be locked to the open position for installation and maintenance work.

European union

To meet the European Union Directives, according to standard EN 60204-1, Safety of Machinery, the disconnecting device must be one of the following types:

- a switch-disconnector of utilization category AC-23B (EN 60947-3)
- a disconnector having an auxiliary contact that in all cases causes switching devices to break the load circuit before the opening of the main contacts of the disconnector (EN 60947-3)
- a circuit breaker suitable for isolation in accordance with EN 60947-2.

Other regions

The disconnecting device must conform to the applicable safety regulations.

Checking the compatibility of the motor and drive

Check that the 3-phase AC induction motor and the drive are compatible according to the rating table in section *Ratings* on page 372. The table lists the typical motor power for each drive type.

Only one permanent magnet synchronous motor can be connected to the inverter output.

Checking the compatibility of the drive when multiple motors are connected to the drive

The drive is selected based on the sum of the connected motor powers. Typically, overdimensioning of the drive and the use of external output chokes is recommended.

When one drive controls several motors, only scalar control is possible. Motor parameters (P_N, I_{2N}) are given as the sum of the nominal values of the motors. Nominal speed is given as an average of the motors. It is recommended to limit the maximum current according to the actual need and it should not exceed 1.1 \cdot I_{2N} (parameter 2003 MAX CURRENT).

When multiple motors are connected, the sum of the output cable lengths must not exceed the maximum allowed cable length (see *Maximum recommended motor* cable length on page 382). If motor contactors are used, switching the contactors during run is not recommended.

When more than 4 motors need to be controlled by one drive, contact your local ABB representative.

Selecting the power cables

General rules

Dimension the input power and motor cables according to local regulations.

- The input power and the motor cables must be able to carry the corresponding load currents. See section *Ratings* on page 372 for the rated currents.
- The cable must be rated for at least 70 °C (158 °F) maximum permissible temperature of the conductor in continuous use. For US, see section Additional US requirements on page 43.
- The conductivity of the PE conductor must be equal to that of the phase conductor (same cross-sectional area).
- 600 V AC cable is accepted for up to 500 V AC.
- Refer to chapter *Technical data* on page 371 for the EMC requirements.

A symmetrical shielded motor cable (see the figure below) must be used to meet the EMC requirements of the CE and C-Tick marks.

A four-conductor system is allowed for input cabling, but a shielded symmetrical cable is recommended.

Compared to a four-conductor system, the use of a symmetrical shielded cable reduces electromagnetic emission of the whole drive system as well as motor bearing currents and wear.

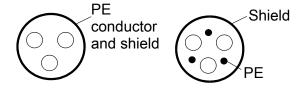
Alternative power cable types

Power cable types that can be used with the drive are presented below.

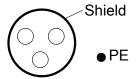
Motor cables

(recommended for input cables also)

Symmetrical shielded cable: three phase conductors, a concentric or otherwise symmetrically constructed PE conductor and a shield

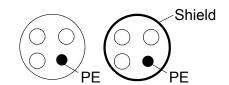


Note: A separate PE conductor is required if the conductivity of the cable shield is not sufficient for the purpose.



Allowed as input cables

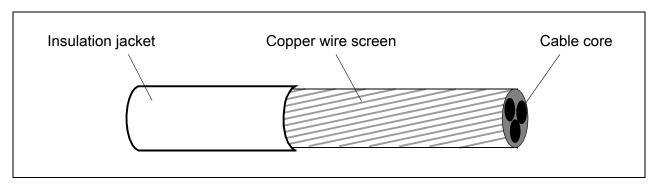
A four-conductor system: three phase conductors and a protective conductor



Motor cable shield

To function as a protective conductor, the shield must have the same cross-sectional area as the phase conductors when they are made of the same metal.

To effectively suppress radiated and conducted radio-frequency emissions, the shield conductivity must be at least 1/10 of the phase conductor conductivity. The requirements are easily met with a copper or aluminum shield. The minimum requirement of the motor cable shield of the drive is shown below. It consists of a concentric layer of copper wires. The better and tighter the shield, the lower the emission level and bearing currents.



Additional US requirements

Type MC continuous corrugated aluminum armor cable with symmetrical grounds or shielded power cable is recommended for the motor cables if metallic conduit is not used.

The power cables must be rated for 75 °C (167 °F).

Conduit

Where conduits must be coupled together, bridge the joint with a ground conductor bonded to the conduit on each side of the joint. Bond the conduits also to the drive enclosure. Use separate conduits for input power, motor, brake resistors and control wiring. Do not run motor wiring from more than one drive in the same conduit.

Armored cable / shielded power cable

Six-conductor (three phases and three ground) type MC continuous corrugated aluminum armor cable with symmetrical grounds is available from the following suppliers (trade names in parentheses):

- Anixter Wire & Cable (Philsheath)
- BICC General Corp (Philsheath)
- Rockbestos Co. (Gardex)
- Oaknite (CLX).

Shielded power cable is available from the following suppliers:

- Belden
- LAPPKABEL (ÖLFLEX)
- Pirelli.

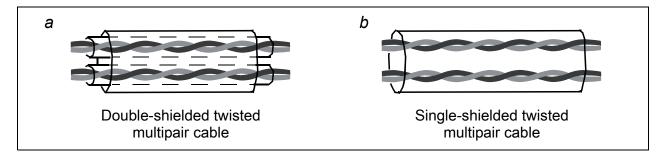
Selecting the control cables

General rules

All analog control cables and the cable used for the frequency input must be shielded.

Use a double-shielded twisted pair cable (Figure a, for example JAMAK by Draka NK Cables) for analog signals. Employ one individually shielded pair for each signal. Do not use common return for different analog signals.

A double-shielded cable is the best alternative for low-voltage digital signals, but a single-shielded or unshielded twisted multipair cable (Figure b) is also usable. However, for frequency input, always use a shielded cable.



Run analog and digital signals in separate cables.

Relay-controlled signals, providing their voltage does not exceed 48 V, can be run in the same cables as digital input signals. It is recommended that the relay-controlled signals are run as twisted pairs.

Never mix 24 V DC and 115/230 V AC signals in the same cable.

Relay cable

The cable type with braided metallic screen (for example ÖLFLEX by LAPPKABEL) has been tested and approved by ABB.

Control panel cable

In remote use, the cable connecting the control panel to the drive must not exceed 3 m (10 ft). The cable type tested and approved by ABB is used in control panel option kits.

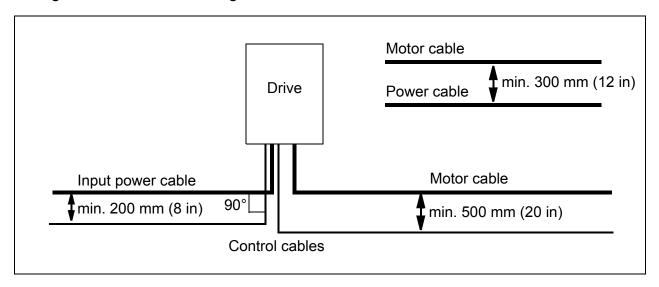
Routing the cables

Route the motor cable away from other cable routes. Motor cables of several drives can be run in parallel installed next to each other. It is recommended that the motor cable, input power cable and control cables are installed on separate trays. Avoid long parallel runs of motor cables with other cables to decrease electromagnetic interference caused by the rapid changes in the drive output voltage.

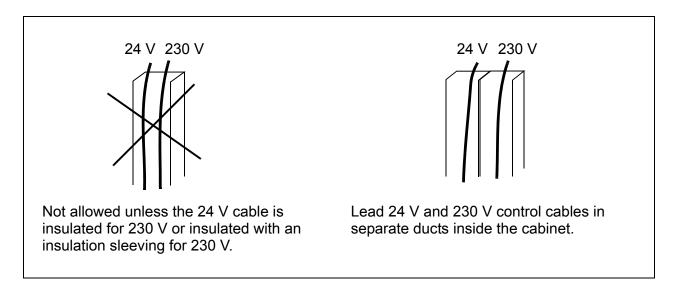
Where control cables must cross power cables make sure that they are arranged at an angle as near to 90 degrees as possible.

The cable trays must have good electrical bonding to each other and to the grounding electrodes. Aluminum tray systems can be used to improve local equalizing of potential.

A diagram of the cable routing is shown below.



Control cable ducts



Protecting the drive, input power cable, motor and motor cable in short-circuit situations and against thermal overload

Protecting the drive and input power cable in short-circuit situations

Arrange the protection according to the following guidelines.

Circuit diagram	Short-circuit protection
Distribution Input cable Drive board 1)	Protect the drive and input cable with fuses. See footnote 1).

¹⁾ Size the fuses according to instructions given in chapter *Technical data* on page 371. The fuses will protect the input cable in short-circuit situations, restrict drive damage and prevent damage to adjoining equipment in case of a short-circuit inside the drive.

Protecting the motor and motor cable in short-circuit situations

The drive protects the motor and motor cable in a short-circuit situation when the motor cable is dimensioned according to the nominal current of the drive. No additional protection devices are needed.

Protecting the drive, motor cable and input power cable against thermal overload

The drive protects itself and the input and motor cables against thermal overload when the cables are dimensioned according to the nominal current of the drive. No additional thermal protection devices are needed.

WARNING! If the drive is connected to multiple motors, a separate thermal overload switch must be used for protecting each cable and motor. These devices may require a separate fuse to cut off the short-circuit current.

Protecting the motor against thermal overload

According to regulations, the motor must be protected against thermal overload and the current must be switched off when overload is detected. The drive includes a motor thermal protection function that protects the motor and switches off the current when necessary. It is also possible to connect a motor temperature measurement to the drive. The user can tune both the thermal model and the temperature measurement function further by parameters.

The most common temperature sensors are:

- motor sizes IEC 180...225: thermal switch (for example Klixon)
- motor sizes IEC 200...250 and larger: PTC or Pt100.

For more information on the thermal model, see section *Motor thermal protection* on page 150. For more information on the temperature measurement function, see section Motor temperature measurement through the standard I/O on page 160.

Implementing the Safe torque off (STO) function

See Appendix: Safe torque off (STO) on page 411.

Using residual current devices (RCD) with the drive

ACS355-01x drives are suitable to be used with residual current devices of Type A, ACS355-03x drives with residual current devices of Type B. For ACS355-03x drives, other measures for protection in case of direct or indirect contact, such as separation from the environment by double or reinforced insulation or isolation from the supply system by a transformer, can also be applied.

Using a safety switch between the drive and the motor

It is recommended to install a safety switch between the permanent magnet synchronous motor and the drive output. This is needed to isolate the motor from the drive during maintenance work on the drive.

Implementing a bypass connection

WARNING! Never connect the supply power to the drive output terminals U2, V2 and W2. Power line voltage applied to the output can result in permanent damage to the drive.

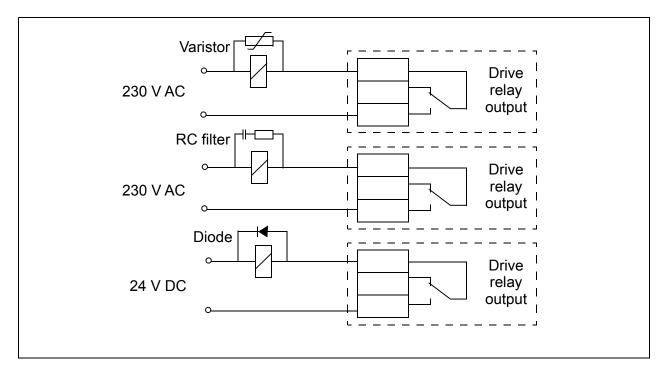
If frequent bypassing is required, employ mechanically connected switches or contactors to ensure that the motor terminals are not connected to the AC power line and drive output terminals simultaneously.

Protecting the contacts of relay outputs

Inductive loads (relays, contactors, motors) cause voltage transients when switched off.

Equip inductive loads with noise attenuating circuits (varistors, RC filters [AC] or diodes [DC]) in order to minimize the EMC emission at switch-off. If not suppressed, the disturbances may connect capacitively or inductively to other conductors in the control cable and form a risk of malfunction in other parts of the system.

Install the protective component as close to the inductive load as possible. Do not install protective components at the I/O terminal block.





Electrical installation

What this chapter contains

The chapter tells how to check the insulation of the assembly and the compatibility with IT (ungrounded) and corner-grounded TN systems as well as connect power cables and control cables.

WARNING! The work described in this chapter may only be carried out by a qualified electrician. Follow the instructions in chapter Safety on page 17. Ignoring the safety instructions can cause injury or death.

Make sure that the drive is disconnected from the input power during installation. If the drive is already connected to the input power, wait for 5 minutes after disconnecting the input power.

Checking the insulation of the assembly

Drive

Do not make any voltage tolerance or insulation resistance tests (for example hi-pot or megger) on any part of the drive as testing can damage the drive. Every drive has been tested for insulation between the main circuit and the chassis at the factory. Also, there are voltage-limiting circuits inside the drive which cut down the testing voltage automatically.

Input power cable

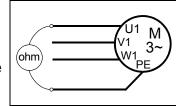
Check the insulation of the input power cable according to local regulations before connecting to the drive.



Motor and motor cable

Check the insulation of the motor and motor cable as follows:

- 1. Check that the motor cable is connected to the motor and disconnected from the drive output terminals U2, V2 and W2.
- 2. Measure the insulation resistance between each phase conductor and the Protective Earth conductor using a measuring voltage of 500 V DC. The insulation resistance of an ABB motor must exceed 100 Mohm (reference value at 25 °C or 77 °F). For the insulation resistance of other motors, please consult the manufacturer's instructions.



Note: Moisture inside the motor casing will reduce the insulation resistance. If moisture is suspected, dry the motor and repeat the measurement.

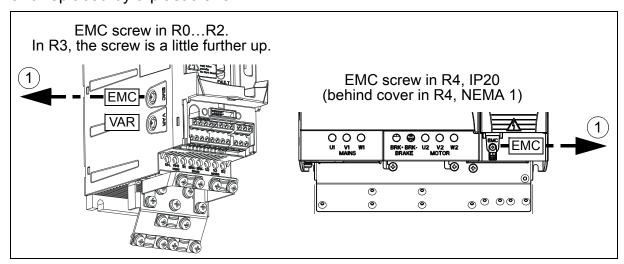
Checking the compatibility with IT (ungrounded) and corner-grounded TN systems

WARNING! Disconnect the internal EMC filter when installing the drive on an IT system (an ungrounded power system or a high-resistance-grounded [over 30 ohms] power system), otherwise the system will be connected to ground potential through the EMC filter capacitors. This may cause danger or damage the drive.

Disconnect the internal EMC filter when installing the drive on a corner-grounded TN system, otherwise the drive will be damaged

Note: When the internal EMC filter is disconnected, the drive is not EMC compatible without an external filter.

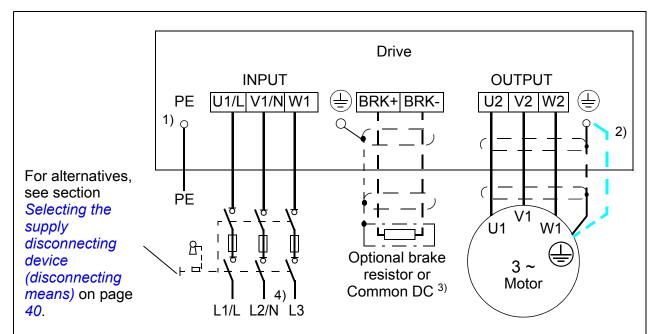
1. If you have an IT (ungrounded) or corner-grounded TN system, disconnect the internal EMC filter by removing the EMC screw. For 3-phase U-type drives (with type designation ACS355-03U-), the EMC screw is already removed at the factory and replaced by a plastic one.





Connecting the power cables

Connection diagram



- 1) Ground the other end of the PE conductor at the distribution board.
- 2) Use a separate grounding cable if the conductivity of the cable shield is insufficient (smaller than the conductivity of the phase conductor) and there is no symmetrically constructed grounding conductor in the cable. See section Selecting the power cables on page 41.
- 3) For more information on Common DC, see ACS355 Common DC application guide (3AUA0000070130 [EN]).
- 4) In one-phase installations, connect the neutral cable here.

Note:

Do not use an asymmetrically constructed motor cable.

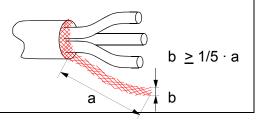
If there is a symmetrically constructed grounding conductor in the motor cable in addition to the conductive shield, connect the grounding conductor to the grounding terminal at the drive and motor ends.

Route the motor cable, input power cable and control cables separately. For more information, see section Routing the cables on page 44.

Grounding of the motor cable shield at the motor end

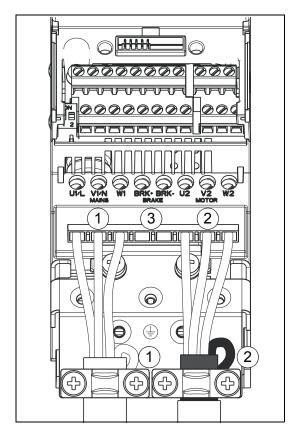
For minimum radio frequency interference:

- ground the cable by twisting the shield as follows: flattened width > 1/5 · length
- or ground the cable shield 360 degrees at the leadthrough of the motor terminal box.



Connection procedure

- 1. Strip the input power cable. Ground the bare shield of the cable (if any) 360 degrees under the grounding clamp. Fasten the grounding conductor (PE) of the input power cable under the grounding clamp. Connect the phase conductors to the U1, V1 and W1 terminals. Use a tightening torque of 0.8 N·m (7 lbf·in) for frame sizes R0...R2, 1.7 N·m (15 lbf·in) for R3 and 2.5 N·m (22 lbf·in) for R4.
- 3. Strip the input power cable. Ground the bare shield of the cable (if any) 360 degrees under the grounding clamp. Twist the shield to form as short a pigtail as possible. Fasten the twisted shield under the grounding clamp. Connect the phase conductors to the U2, V2 and W2 terminals. Use a tightening torque of 0.8 N·m (7 lbf·in) for frame sizes R0...R2, 1.7 N·m (15 lbf·in) for R3 and 2.5 N·m (22 lbf·in) for R4.
- 2. Connect the optional brake resistor to the BRK+ and BRK- terminals with a shielded cable using the same procedure as for the motor cable in the previous step.
- 3. Secure the cables outside the drive mechanically.

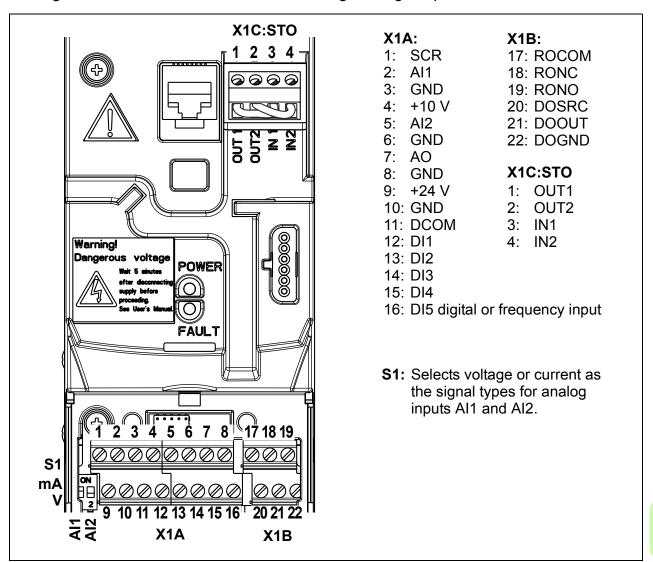




Connecting the control cables

I/O terminals

The figure below shows the I/O terminals. Tightening torque is 0.4 N·m / 3.5 lbf·in.



Voltage and current selection for analog inputs

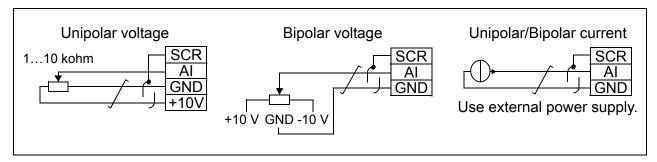
Switch S1 selects voltage (0 [2]...10 V / -10...10 V) or current (0 [4]...20 mA / -20...20 mA) as the signal types for analog inputs Al1 and Al2. The factory settings are unipolar voltage for Al1 (0 [2]...10 V) and unipolar current for Al2 (0 [4]...20 mA), which correspond to the default usage in the application macros. The switch is located to the left of I/O terminal 9 (see the I/O terminal figure above).



Top position (ON): I (0 [4]...20 mA, default for AI2; or -20...20 mA) Bottom position (OFF): U (0 [2]...10 V, default for Al1; or -10...10 V)

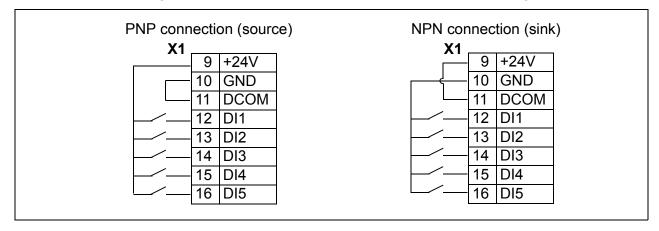
Voltage and current connection for analog inputs

Bipolar voltage (-10...10 V) and current (-20...20 mA) are also possible. If a bipolar connection is used instead of a unipolar one, see section *Programmable analog inputs* on page 135 for how to set parameters accordingly.



PNP and NPN configuration for digital inputs

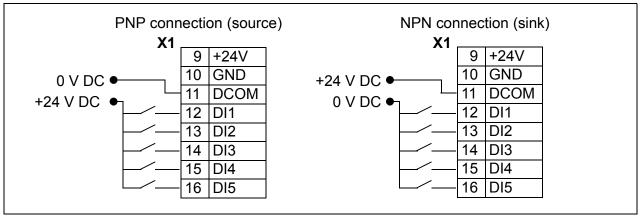
You can wire the digital input terminals in either a PNP or NPN configuration.



External power supply for digital inputs



For using an external +24 V supply for the digital inputs, see the figure below.



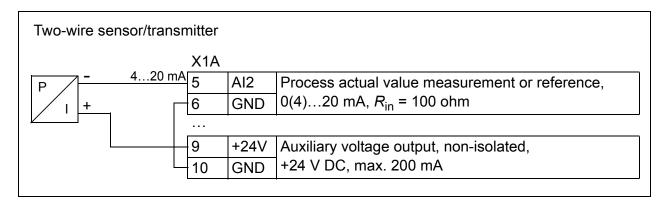
Frequency input

If DI5 is used as a frequency input, see section *Frequency input* on page 138 for how to set parameters accordingly.

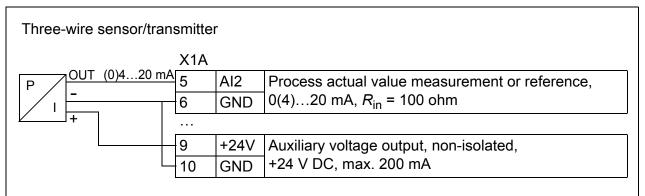
Connection examples of two-wire and three-wire sensors

Hand/Auto, PID control, and Torque control macros (see section *Application macros*, pages 118, 119 and 120, respectively) use analog input 2 (Al2). The macro wiring diagrams on these pages use an externally powered sensor (connections not shown). The figures below give examples of connections using a two-wire or three-wire sensor/transmitter supplied by the drive auxiliary voltage output.

Note: Maximum capability of the auxiliary 24 V (200 mA) output must not be exceeded.



Note: The sensor is supplied through its current output and the drive feeds the supply voltage (+24 V). Thus the output signal must be 4...20 mA, not 0...20 mA.



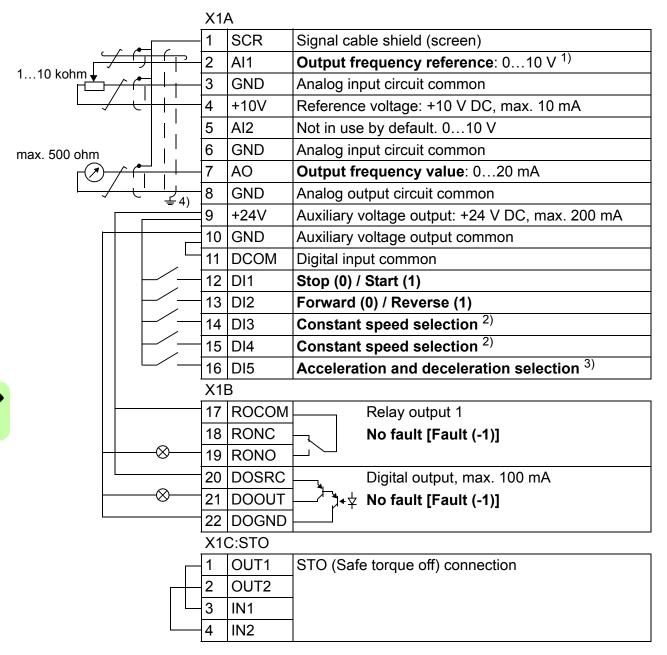


Default I/O connection diagram

The default connection of the control signals depends on the application macro in use, which is selected with parameter 9902 APPLIC MACRO.

The default macro is the ABB standard macro. It provides a general purpose I/O configuration with three constant speeds. Parameter values are the default values given in section Default values with different macros on page 182. For information on other macros, see chapter *Application macros* on page 111.

The default I/O connections for the ABB standard macro are given in the figure below.





- 1) Al1 is used as a speed reference if vector mode is selected.
- ²⁾ See parameter group *12 CONSTANT* SPEEDS:

DI3	DI4	Operation (parameter)	
0	0	Set speed through AI1	
1	0	Speed 1 (1202)	
0	1	Speed 2 (1203)	
1	1	Speed 3 (1204)	

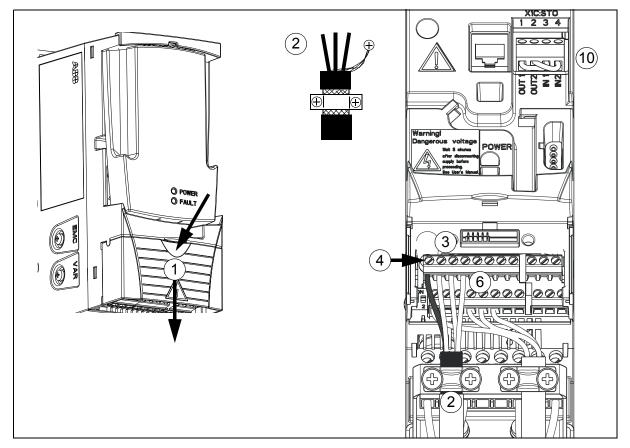
- $^{3)}$ 0 = ramp times according to parameters 2202 and 2203.
 - 1 = ramp times according to parameters 2205 and 2206.
- ⁴⁾ 360 degree grounding under a clamp.

Tightening torque: 0.4 N·m / 3.5 lbf·in.



Connection procedure

- 1. Remove the terminal cover by simultaneously pushing the recess and sliding the cover off the frame.
- 2. Analog signals: Strip the outer insulation of the analog signal cable 360 degrees and ground the bare shield under the clamp.
- 3. Connect the conductors to the appropriate terminals. Use a tightening torque of 0.4 N·m (3.5 lbf·in).
- 4. Twist the grounding conductors of each pair in the analog signal cable together and connect the bundle to the SCR terminal (terminal 1).
- 5. Digital signals: Strip the outer insulation of the digital signal cable 360 degrees and ground the bare shield under the clamp.
- 6. Connect the conductors of the cable to the appropriate terminals. Use a tightening torque of 0.4 N·m (3.5 lbf·in).
- 7. For double-shielded cables, twist also the grounding conductors of each pair in the cable together and connect the bundle to the SCR terminal (terminal 1).
- 8. Secure all cables outside the drive mechanically.
- 9. Unless you need to install the optional fieldbus module (see section Attach the optional fieldbus module on page 38), slide the terminal cover back in place.
- 10. Connect STO conductors to the appropriate terminals. Use a tightening torque of 0.4 N·m (3.5 lbf·in).







Installation checklist

What this chapter contains

This chapter contains a list for checking the mechanical and electrical installation of the drive.

Checking the installation

Check the mechanical and electrical installation of the drive before start-up. Go through the checklist below together with another person. Read chapter Safety on page 17 of this manual before you work on the drive.

	Check
ME	CHANICAL INSTALLATION
	The ambient operating conditions are within allowed limits. (See <i>Mechanical installation:</i> Checking the installation site on page 33 as well as <i>Technical data: Losses, cooling data and noise</i> on page 378 and <i>Ambient conditions</i> on page 385.)
	The drive is fixed properly on an even vertical non-flammable wall. (See <i>Mechanical installation</i> on page 33.)
	The cooling air will flow freely. (See <i>Mechanical installation</i> : <i>Free space around the drive</i> on page <i>34</i> .)
	The motor and the driven equipment are ready for start. (See <i>Planning the electrical installation</i> : <i>Checking the compatibility of the motor and drive</i> on page 40 as well as <i>Technical data: Motor connection data</i> on page 381.)
	ECTRICAL INSTALLATION (See <i>Planning the electrical installation</i> on page 39 and ctrical installation on page 49.)
	For ungrounded and corner-grounded systems: The internal EMC filter is disconnected (EMC screw removed).
	The capacitors are reformed if the drive has been stored over a year.

Check
The drive is grounded properly.
The input power voltage matches the drive nominal input voltage.
The input power connections at U1/L, V1/N and W1 are OK and tightened with the correct torque.
Appropriate input power fuses and disconnector are installed.
The motor connections at U2, V2 and W2 are OK and tightened with the correct torque.
The motor cable, input power cable and control cables are routed separately.
The external control (I/O) connections are OK.
Safe torque off (STO) connections, operation and reaction are OK.
The input power voltage cannot be applied to the output of the drive (with a bypass connection).
Terminal cover and, for NEMA 1, hood and connection box, are in place.

Start-up, control with I/O and **ID** run

What this chapter contains

The chapter tells how to:

- perform the start-up
- start, stop, change the direction of the motor rotation and adjust the speed of the motor through the I/O interface
- perform an Identification run for the drive.

Using the control panel to do these tasks is explained briefly in this chapter. For details on how to use the control panel, refer to chapter *Control panels* on page 75.

Starting up the drive



WARNING! The start-up may only be carried out by a qualified electrician.

The safety instructions given in chapter Safety on page 17 must be followed during the start-up procedure.

The drive will start up automatically at power-up if the external run command is on and the drive is in the remote control mode.



Check that the starting of the motor does not cause any danger. **De-couple the** driven machine if:

- there is a risk of damage in case of incorrect direction of rotation, or
- an ID run needs to be performed during the drive start-up. ID run is essential only in applications that require the ultimate in motor control accuracy.
- Check the installation. See the checklist in chapter *Installation checklist* on page *5*9.

How you start up the drive depends on the control panel you have, if any.

- If you have no control panel, follow the instructions given in section Starting up the drive without a control panel on page 62.
- If you have a basic control panel (ACS-CP-C), follow the instructions given in section Performing a manual start-up on page 63.
- If you have an assistant control panel (ACS-CP-A, ACS-CP-D), you can either run the Start-up assistant (see section *Performing a guided start-up* on page 68) or perform a manual start-up (see section *Performing a manual start-up* on page *63*).

The Start-up assistant, which is included in the assistant control panel only, guides you through all essential settings to be done. In the manual start-up, the drive gives no guidance; you go through the very basic settings by following the instructions given in section *Performing a manual start-up* on page 63.

Starting up the drive without a control panel

POWER-UP
Apply input power and wait for a moment.
Check that the red LED is not lit and the green LED is lit but not blinking.
The drive is now ready for use.



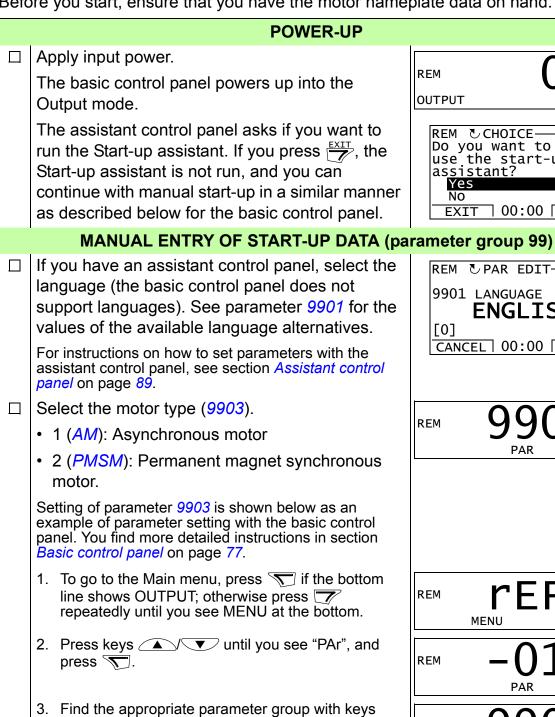
REM

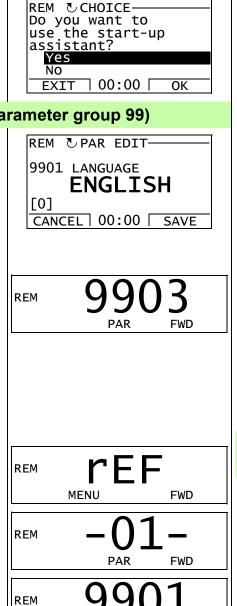
ΗZ

Performing a manual start-up

For the manual start-up, you can use the basic control panel or the assistant control panel. The instructions below are valid for both control panels, but the displays shown are the basic control panel displays, unless the instruction applies to the assistant control panel only.

Before you start, ensure that you have the motor nameplate data on hand.







FWD

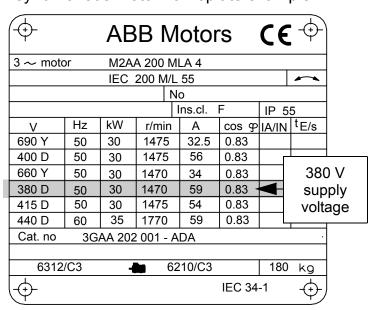
- 4. Find the appropriate parameter in the group with keys ▲/▼. 5. Press and hold for about two seconds until the
- parameter value is shown with **SET** under the value
- 6. Change the value with keys _____. The value changes faster while you keep the key pressed down.
- 7. Save the parameter value by pressing \square.

Select the application macro (parameter 9902) according to how the control cables are connected.

The default value 1 (ABB STANDARD) is suitable in most cases.

- Select the motor control mode (parameter 9904).
 - 1 (VECTOR: SPEED) is suitable in most cases. 2 (VECTOR: TORQ) is suitable for torque control applications.
 - 3 (SCALAR: FREQ) is recommended
 - for multimotor drives when the number of the motors connected to the drive is variable
 - when the nominal motor current is less than 20% of the nominal current of the drive
 - when the drive is used for test purposes with no motor connected.
 - 3 (SCALAR: FREQ) is not recommended for permanent magnet synchronous motors.
- Enter the motor data from the motor nameplate.

Asynchronous motor nameplate example:



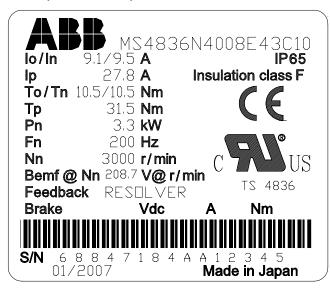
	REM	9903 FWD
)).	REM	PAR SET FWD
9	REM	PAR SEE FWD
	REM	9903 PAR FWD
	REM	9902 FWD

REM

Note: Set the motor data to exactly the same value as on the motor nameplate. For example, if the motor nominal speed is 1470 rpm on the nameplate, setting the value of parameter 9908 MOTOR NOM SPEED to 1500 rpm results in the wrong operation of the drive.



Permanent magnet synchronous motor nameplate example:



motor nominal voltage (parameter 9905).

For permanent magnet synchronous motors, enter the back emf voltage at nominal speed here. Otherwise use nominal voltage and perform ID run. If the voltage is given as voltage per rpm, eg 60 V per 1000 rpm, the voltage for 3000 rpm nominal speed is 3 · 60 V = 180 V.

- nominal motor current (parameter 9906) Allowed range: $0.2...2.0 \cdot I_{2N}$ A
- motor nominal frequency (parameter 9907)
- motor nominal speed (parameter 9908)
- motor nominal power (parameter 9909)

REM PAR FWD

REM PAR **FWD** REM FWD **PAR** REM PAR FWD REM

PAR

FWD



Select the motor identification method (parameter 9910).

The default value 0 (OFF/IDMAGN) using the identification magnetization is suitable for most applications. It is applied in this basic start-up procedure. Note however that this requires that parameter 9904 is set to 1 (VECTOR: SPEED) or 2 (VECTOR: TORQ).

If your selection is 0 (*OFF/IDMAGN*), move to the next step.

Value 1 (ON) should be selected if:

- the operation point is near zero speed, and/or
- operation at torque range above the motor nominal torque over a wide speed range and without any measured speed feedback is required.

If you decide to perform the ID run (value 1 [ON]), continue by following the separate instructions given on page 71 in section ID run procedure and then return to step DIRECTION OF THE MOTOR ROTATION on page 66.

IDENTIFICATION MAGNETIZATION WITH ID RUN SELECTION 0 (OFF/IDMAGN)

Press key (26) to switch to local control (LOC shown on the left).

Press 🔷 to start the drive. The motor model is now calculated by magnetizing the motor for 10 to 15 s at zero speed.

DIRECTION OF THE MOTOR ROTATION

- Check the direction of the motor rotation. П
 - If the drive is in remote control (REM shown on the left), switch to local control by pressing (26).
 - To go to the Main menu, press T if the bottom line shows OUTPUT; otherwise press repeatedly until you see MENU at the bottom.
 - Press keys until you see "rEF" and press _.
 - Increase the frequency reference from zero to a small value with key
 - Press to start the motor.
 - Check that the actual direction of the motor is the same as indicated on the display (FWD means forward and REV reverse).
 - Press 🕲 to stop the motor.

To change the direction of the motor rotation:









reverse direction



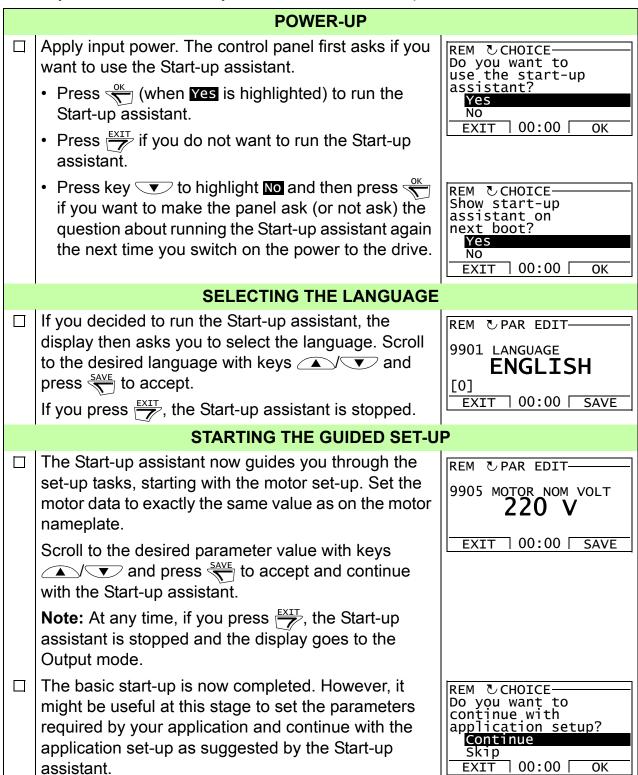
 Invert the phases by changing the value of parameter 9914 to the opposite, ie from 0 (NO) to 1 (YES), or vice versa. Verify your work by applying input power and repeating the check as described above. 	PAR FWD
SPEED LIMITS AND ACCELERATION/DEC	ELERATION TIMES
Set the minimum speed (parameter 2001).	LOC 2001 FWD
Set the maximum speed (parameter 2002).	LOC 2002 FWD
Set the acceleration time 1 (parameter 2202).	LOC 2202
Note: Set also acceleration time 2 (parameter 2205) if two acceleration times will be used in the application.	2202 PAR FWD
Set the deceleration time 1 (parameter 2203).	LOC 777
Note: Set also deceleration time 2 (parameter 2206) if two deceleration times will be used in the application.	2203 FWD
SAVING A USER MACRO AND FIN	AL CHECK
The start-up is now completed. However, it might be useful at this stage to set the parameters required by your application and save the settings as a user macro as instructed in section <i>User macros</i> on page <i>123</i> .	PAR FWD
Check that the drive state is OK.	
Basic control panel: Check that there are no faults or alarms shown on the display.	
If you want to check the LEDs on the front of the drive, switch first to remote control (otherwise a fault is generated) before removing the panel and verifying that the red LED is not lit and the green LED is lit but not blinking.	
Assistant control panel: Check that there are no faults or alarms shown on the display and that the panel LED is green and does not blink.	
The drive is now ready for	use.



Performing a guided start-up

To be able to perform the guided start-up, you need the assistant control panel. Guided start-up is applicable to AC induction motors.

Before you start, ensure that you have the motor nameplate data on hand.





Select the application macro according to which the control cables are connected.

Continue with the application set-up. After completing a set-up task, the Start-up assistant suggests the next one.

- Press (when Continue is highlighted) to continue with the suggested task.
- Press key to highlight skip and then press to move to the following task without doing the suggested task.
- Press to stop the Start-up assistant.

REM OPAR EDIT-9902 APPLIC MACRO ABB STANDARD [1]EXIT 00:00 SAVE

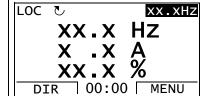
REM ○CHOICE Do you want to continue with EXT1 reference setup? Continue Skip 7 00:00 □ EXIT

DIRECTION OF THE MOTOR ROTATION

- Press (26) to switch to local control (LOC shown on the left).
 - If the drive is in remote control (REM shown on the status line), switch to local control by pressing (26).
 - If you are not in the Output mode, press repeatedly until you get there.
 - Increase the frequency reference from zero to a small value with key
 - Press 💿 to start the motor.
 - · Check that the actual direction of the motor is the same as indicated on the display (means forward and J reverse).
 - Press 🕲 to stop the motor.

To change the direction of the motor rotation:

- Invert the phases by changing the value of parameter 9914 to the opposite, ie from 0 (NO) to 1 (YES), or vice versa.
- · Verify your work by applying input power and repeating the check as described above.

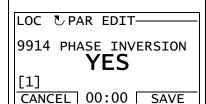






direction

direction



FINAL CHECK

After the whole set-up is completed, check that there are no faults or alarms shown on the display and the panel LED is green and does not blink.

The drive is now ready for use.



Controlling the drive through the I/O interface

The table below instructs how to operate the drive through the digital and analog inputs when:

- the motor start-up is performed, and
- the default (standard) parameter settings are valid.

Displays of the basic control panel are shown as an example.

PRELIMINARY SETTINGS

If you need to change the direction of rotation, check that parameter 1003 DIRECTION is set to 3 (REQUEST).

Ensure that the control connections are wired according to the connection diagram given for the ABB standard macro.

Ensure that the drive is in remote control. Press key (Real to switch between remote and local control.)

See section Default I/O connection diagram on page *56*.

In remote control, the panel display shows text REM.

STARTING AND CONTROLLING THE SPEED OF THE MOTOR

Start by switching digital input DI1 on.

Basic control panel: Text FWD starts flashing fast and stops after the setpoint is reached

Assistant control panel: The arrow starts rotating. It is dotted until the setpoint is reached.

Regulate the drive output frequency (motor speed) by adjusting the voltage of analog input Al1.

REM	0. 0 Hz
ОИТРИТ	FWD

REM OUTPUT

CHANGING THE DIRECTION OF THE MOTOR ROTATION

Reverse direction: Switch digital input DI2 on.

Forward direction: Switch digital input DI2 off.

REM	500 Hz
OUTPUT	REV
REM	500 Hz
OUTPUT	FWD

STOPPING THE MOTOR

Switch digital input DI1 off. The motor stops.

Basic control panel: Text FWD starts flashing slowly.

Assistant control panel: The arrow stops rotating.





Performing the ID run

The drive estimates motor characteristics automatically when the drive is started for the first time and after any motor parameter (group 99 START-UP DATA) is changed. This is valid when parameter 9910 ID RUN has value 0 (OFF/IDMAGN).

In most applications there is no need to perform a separate ID run. The ID run should be selected if:

- vector control mode is used (parameter 9904 = 1 [VECTOR: SPEED] or 2 [VECTOR: TORQ]), and
- operation point is near zero speed and/or
- operation at torque range above the motor nominal torque, over a wide speed range, and without any measured speed feedback (ie without a pulse encoder) is needed or
- permanent magnet synchronous motor is used and the back emf voltage is unknown.

Note: If motor parameters (group 99 START-UP DATA) are changed after the ID run, it must be repeated.

ID run procedure

The general parameter setting procedure is not repeated here. For basic control panel, see page 77 and for assistant control panel, see page 89 in chapter Control panels. The ID run cannot be performed without a control panel.

	PRE-CHECK		
<u>√</u> dire	WARNING! The motor will run at up to approximately 5080% of the nominal speed during the ID run. The motor will rotate in the forward ection. Ensure that it is safe to run the motor before performing the ID run!		
	De-couple the motor from the driven equipment.		
	If parameter values (group 01 OPERATING DATA to group 98 OPTIONS) are changed before the ID run, check that the new settings meet the following conditions:		
	2001 MINIMUM SPEED < 0 rpm		
	2002 MAXIMUM SPEED > 80% of the motor rated speed		
	2003 MAX CURRENT > I _{2N}		
	2017 MAX TORQUE 1 > 50% or 2018 MAX TORQUE 2 > 50%, depending on which limit is in use according to parameter 2014 MAX TORQUE SEL.		
	Check that the Run enable signal is on (parameter 1601).		
	Ensure that the panel is in local control (LOC shown at the top). Press key (26) to switch between local and remote control.		



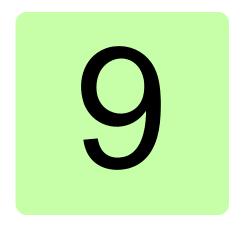
ID RUN WITH THE BASIC CONTROL PANEL Change parameter 9910 ID RUN to 1 (ON). Save LOC the new setting by pressing \square. LOC PAR SET FWD If you want to monitor actual values during the ID П LOC ΗZ run, go to the Output mode by pressing repeatedly until you get there. OUTPUT Press 🔷 to start the ID run. The panel keeps LOC A201 switching between the display that was shown when you started the run and the alarm display presented on the right. In general, it is recommended not to press any control panel keys during the ID run. However, you can stop the ID run at any time by pressing **®**. After the ID run is completed, the alarm display is LOC F001 not shown any more. If the ID run fails, the fault display presented on the right is shown. ID RUN WITH THE ASSISTANT CONTROL PANEL Change parameter 9910 ID RUN to 1 (ON). Save REM OPAR EDITthe new setting by pressing SAVE. 9910 ID RUN ON [1] CANCEL 00:00 SAVE If you want to monitor actual values during the ID LOC U 50.0Hz run, go to the Output mode by pressing EXIT HZ repeatedly until you get there. DIR 00:00 MENU Press to start the ID run. The panel keeps LOC &ALARMswitching between the display that was shown **ALARM 2019** when you started the run Run and the alarm ID RUN display presented on the right. 7 00:00 「 In general, it is recommended not to press any control panel keys during the ID run. However, you can stop the ID run at any time by pressing **®**.



After the ID run is completed, the alarm display is LOC & FAULT not shown any more. FAULT 11 If the ID run fails, the fault display presented on ID RUN FAIL the right is shown. 7 00:00 □







Control panels

What this chapter contains

The chapter describes the control panel keys, LED indicators and display fields. It also instructs in using the panel in control, monitoring and changing the settings.

About control panels

Use a control panel to control the ACS355, read status data, and adjust parameters. The drive works with either of two different control panel types:

- Basic control panel This panel (described in section Basic control panel on page 77) provides basic tools for manual entry of parameter values.
- Assistant control panel This panel (described in section Assistant control panel on page 89) includes pre-programmed assistants to automate the most common parameter setups. The panel provides language support. It is available with different language sets.

Applicability

The manual is applicable to panels with the panel revisions and the panel firmware versions given in the table below.

Panel type	Type code Panel revision		Panel firmware version	
Basic control panel	ACS-CP-C	M or later	1.13 or later	
Assistant control panel	ACS-CP-A	F or later	2.04 or later	
Assistant control panel (Asia)	ACS-CP-D	Q or later	2.04 or later	

To find out the panel revision, see the label on the back of the panel. An example label and explanation of the label contents are shown below.



1 Panel type code
2 Serial number of format MYYWWRXXXX, where
M: Manufacturer
YY: 09, 10, 11, ..., for 2009, 2010, 2011, ...
WW: 01, 02, 03, ... for week 1, week 2, week 3, ...
R: A, B, C, ... for panel revision
XXXX: Integer starting every week from 0001
3 RoHS mark (the label of your drive shows the valid markings)

To find out the panel firmware version of your assistant control panel, see page 93. For the basic control panel, see page 80.

See parameter 9901 LANGUAGE to find out the languages supported by the different assistant control panels.

Basic control panel

Features

The basic control panel features:

- numeric control panel with an LCD display
- copy function parameters can be copied to the control panel memory for later transfer to other drives or for backup of a particular system.

Overview

The following table summarizes the key functions and displays on the basic control panel.

No.	Use	
1	LCD display – Divided into five areas:	
	a. Upper left – Control location: LOC: drive control is local, that is, from the control panel REM: drive control is remote, such as the drive I/O or fieldbus.	1a Loc 1c 1.1 A 1b 1e 1e
	b. Upper right – Unit of the displayed value.	RESET MENU EXIT ENTER
	c. Center – Variable; in general, shows parameter and signal values, menus or lists. Shows also fault and alarm codes.	2 7/4 A 3 6 6 5 V 0 7
	 d. Lower left and center – Panel operation state: OUTPUT: Output mode PAR: Parameter mode MENU: Main menu. FAULT: Fault mode. 	8
	 e. Lower right – Indicators: FWD (forward) / REV (reverse): direction of the m Flashing slowly: stopped Flashing rapidly: running, not at setpoint Steady: running, at setpoint SETT: Displayed value can be modified (in the Par 	
2	RESET/EXIT – Exits to the next higher menu level w Resets faults in the Output and Fault modes.	ithout saving changed values.
3	MENU/ENTER – Enters deeper into menu level. In the displayed value as the new setting.	ne Parameter mode, saves the
4	Up –	
	Scrolls up through a menu or list.	
	 Increases a value if a parameter is selected. 	
	 Increases the reference value in the Reference months. 	ode.
	Holding the key down changes the value faster.	
5	Down –	
	Scrolls down through a menu or list. Decreases a value if a representation along the decrease and a second to the decrease and	
	 Decreases a value if a parameter is selected. Decreases the reference value in the Reference m 	ando
	 Holding the key down changes the value faster. 	loue.
6	LOC/REM – Changes between local and remote con	trol of the drive.
7	DIR – Changes the direction of the motor rotation.	
8	STOP – Stops the drive in local control.	
9	START – Starts the drive in local control.	

Operation

You operate the control panel with the help of menus and keys. You select an option, eg operation mode or parameter, by scrolling the __ and __ arrow keys until the option is visible in the display and then pressing the \text{\sqrt} key.

With the key, you return to the previous operation level without saving the made changes.

The basic control panel has five panel modes: Output mode, Reference mode, Parameter mode, Copy mode and Fault mode. The operation in the first four modes is described in this chapter. When a fault or alarm occurs, the panel goes automatically to the Fault mode showing the fault or alarm code. You can reset the fault or alarm in the Output or Fault mode (see chapter *Fault tracing* on page 347).

After the power is switched on, the panel is in the Output mode, where you can start, stop, change the direction, switch between local and remote control and monitor up to three actual values (one at a time). To do other tasks, go first to the Main menu and select the appropriate mode.



How to do common tasks

The table below lists common tasks, the mode in which you can perform them and the page number where the steps to do the task are described in detail.

Task	Mode	Page
How to find out the panel firmware version	At power up	80
How to switch between local and remote control	Any	80
How to start and stop the drive	Any	80
How to change the direction of the motor rotation	Any	81
How to browse the monitored signals	Output	82
How to set the speed, frequency or torque reference	Reference	83
How to change the value of a parameter	Parameter	84
How to select the monitored signals	Parameter	85
How to reset faults and alarms	Output, Fault	347
How to copy parameters from the drive to the control panel	Сору	88
How to restore parameters from the control panel to the drive	Сору	88

How to find out the panel firmware version

Step	Action	Display
1.	If the power is switched on, switch it off.	
2.	Keep key pressed down while you switch on the power and read the panel firmware version shown on the display.	XXX
	When you release the key, the panel goes to the Output mode.	

How to start, stop and switch between local and remote control

You can start, stop and switch between local and remote control in any mode. To be able to start or stop the drive, the drive must be in local control.

Step	Action	Display
1.	To switch between remote control (REM shown on the left) and local control (LOC shown on the left), press Note: Switching to local control can be disabled with parameter 1606 LOCAL LOCK.	оитрит 49.1 нz
	After pressing the key, the display briefly shows message "LoC" or "rE", as appropriate, before returning to the previous display.	LOC
	The very first time the drive is powered up, it is in remote control (REM) and controlled through the drive I/O terminals. To switch to local control (LOC) and control the drive using the control panel, press . The result depends on how long you press the key:	
	 If you release the key immediately (the display flashes "LoC"), the drive stops. Set the local control reference as instructed on page 83. 	
	 If you press the key for about two seconds (release when the display changes from "LoC" to "LoC r"), the drive continues as before. The drive copies the current remote values for the run/stop status and the reference, and uses them as the initial local control settings. 	
	To stop the drive in local control, press .	Text FWD or REV on the bottom line starts flashing slowly.
	To start the drive in local control, press .	Text FWD or REV on the bottom line starts flashing rapidly. It stops flashing when the drive reaches the setpoint.

How to change the direction of the motor rotation

You can change the direction of the motor rotation in any mode.

Step	Action	Display	
1.	If the drive is in remote control (REM shown on the left), switch to local control by pressing (E). The	LOC 49.1 Hz	
	display briefly shows message "LoC" before returning to the previous display.	OUTPUT FWD	
2.	To change the direction from forward (FWD shown at the bottom) to reverse (REV shown at the bottom), or vice versa, press ().	LOC 49.1 Hz	
	vice versa, press •.	OUTPUT REV	
	Note : Parameter 1003 DIRECTION must be set to 3 (REQUEST).		

Output mode

In the Output mode, you can:

- monitor actual values of up to three group 01 OPERATING DATA signals, one signal at a time
- start, stop, change the direction and switch between local and remote control.

You get to the Output mode by pressing wintil the display shows text OUTPUT at the bottom.

The display shows the value of one group *01*OPERATING DATA signal. The unit is shown on the right. Page *85* tells how to select up to three signals to be monitored in the Output mode. The table below shows how to view them one at a time.



How to browse the monitored signals

Step	Action	Display
1.	 If more than one signals have been selected to be monitored (see page 85), you can browse them in the Output mode. To browse the signals forward, press key repeatedly. To browse them backward, press key repeatedly. 	REM 49.1 HZ OUTPUT FWD
		REM O.5 A OUTPUT
		REM 10.7 % OUTPUT FWD

Reference mode

In the Reference mode, you can:

- set the speed, frequency or torque reference
- start, stop, change the direction and switch between local and remote control.

How to set the speed, frequency or torque reference

Step	Action	Display	
1.	Go to the Main menu by pressing if you are in the Output mode, otherwise by pressing repeatedly until you see MENU at the bottom.	REM PAT FWD	
2.	If the drive is in remote control (REM shown on the left), switch to local control by pressing . The display briefly shows "LoC" before switching to local control. Note: With group 11 REFERENCE SELECT, you can allow the reference modification in remote control (REM).	PAr MENU FWD	
3.	If the panel is not in the Reference mode ("rEF" not visible), press key or until you see "rEF" and then press . Now the display shows the current reference value with SET under the value.	LOC PEF SWD HZ	
4.	 To increase the reference value, press To decrease the reference value, press The value changes immediately when you press the key. It is stored in the drive permanent memory and restored automatically after power switch-off. 	LOC 500 HZ	

Parameter mode

In the Parameter mode, you can:

- view and change parameter values
- select and modify the signals shown in the Output mode
- start, stop, change the direction and switch between local and remote control.

How to select a parameter and change its value

Step	Action	Display	
1.	Go to the Main menu by pressing if you are in the Output mode, otherwise by pressing repeatedly until you see MENU at the bottom.	LOC PEF	
2.	If the panel is not in the Parameter mode ("PAr" not visible), press key or until you see "PAr" and then press . The display shows the number of one of the parameter groups.	PAr MENU FWD LOC -01- FWD	
3.	Use keys and to find the desired parameter group.	LOC -11-	
4.	Press T. The display shows one of the parameters in the selected group.	1101	
5.	Use keys and to find the desired parameter.	LOC 1103 FWD	
6.	Press and hold for about two seconds until the display shows the value of the parameter with set underneath indicating that changing of the value is now possible. Note: When set is visible, pressing keys and simultaneously changes the displayed value to the default value of the parameter.	PAR SET FWD	
7.	Use keys A and to select the parameter value. When you have changed the parameter value, starts flashing.	LOC PAR SEE FWD	
	 To save the displayed parameter value, press To cancel the new value and keep the original, press 	LOC 1103 FWD	

How to select the monitored signals

Step	Action	Display
1.	You can select which signals are monitored in the Output mode and how they are displayed with group 34 PANEL DISPLAY parameters. See page 84 for detailed instructions on changing parameter values. By default, the display shows three signals. Signal 1: 0102 SPEED for macros 3-wire, Alternate, Motor potentiometer, Hand/Auto and PID control; 0103 OUTPUT FREQ for macros ABB standard and Torque control Signal 2: 0104 CURRENT Signal 3: 0105 TORQUE. To change the default signals, select up to three signals from group 01 OPERATING DATA to be shown. Signal 1: Change the value of parameter 3401 SIGNAL1 PARAM to the index of the signal parameter in group 01 OPERATING DATA (= number of the parameter without the leading zero), eg 105 means parameter 0105 TORQUE. Value 100 means that no signal is displayed. Repeat for signals 2 (3408 SIGNAL2 PARAM) and 3 (3415 SIGNAL3 PARAM). For example, if 3401 = 0 and 3415 = 0, browsing is disabled and only the signal specified by 3408 appears in the display. If all three parameters are set to 0, ie no signals are selected for monitoring, the panel displays text "n.A".	LOC 104 PAR SEE FWD LOC 105 PAR SEE FWD
2.	Specify the decimal point location, or use the decimal point location and unit of the source signal (setting 9 [DIRECT]). Bar graphs are not available for basic control panel. For details, see parameter 3404. Signal 1: parameter 3404 OUTPUT1 DSP FORM Signal 2: parameter 3411 OUTPUT2 DSP FORM Signal 3: parameter 3418 OUTPUT3 DSP FORM.	PAR SET FWD
3.	Select the units to be displayed for the signals. This has no effect if parameter 3404/3411/3418 is set to 9 (DIRECT). For details, see parameter 3405. Signal 1: parameter 3405 OUTPUT1 UNIT Signal 2: parameter 3412 OUTPUT2 UNIT Signal 3: parameter 3419 OUTPUT3 UNIT.	PAR SEE FWD

Step	Action	Display	
4.	Select the scalings for the signals by specifying the minimum and maximum display values. This has no effect if parameter 3404/3411/3418 is set to 9 (DIRECT). For details, see parameters 3406 and 3407. Signal 1: parameters 3406 OUTPUT1 MIN and 3407 OUTPUT1 MAX Signal 2: parameters 3413 OUTPUT2 MIN and 3414 OUTPUT2 MAX Signal 3: parameters 3420 OUTPUT3 MIN and 3421 OUTPUT3 MAX.	LOC PAR SEE FWD HZ PAR SEE FWD	

Copy mode

The basic control panel can store a full set of drive parameters and up to three user sets of drive parameters to the control panel. Uploading and downloading can be performed in local control. The control panel memory is non-volatile.

In the Copy mode, you can do the following:

- Copy all parameters from the drive to the control panel (uL Upload). This includes all defined user sets of parameters and internal (not adjustable by the user) parameters such as those created by the ID run.
- Restore the full parameter set from the control panel to the drive (dL A Download all). This writes all parameters, including the internal non-useradjustable motor parameters, to the drive. It does not include the user sets of parameters.

Note: Only use this function to restore a drive, or to transfer parameters to systems that are identical to the original system.

Copy a partial parameter set from the control panel to a drive (dL P – Download partial). The partial set does not include user sets, internal motor parameters, parameters 9905...9909, 1605, 1607, 5201, nor any group 51 EXT COMM MODULE and 53 EFB PROTOCOL parameters.

The source and target drives and their motor sizes do not need to be the same.

Copy user set 1 parameters from the control panel to the drive (dL u1 – Download user set 1). A user set includes group 99 START-UP DATA parameters and the internal motor parameters.

The function is only shown on the menu when user set 1 has been first saved using parameter 9902 APPLIC MACRO (see section user macros on page 123) and then uploaded to panel.

- Copy user set 2 parameters from the control panel to the drive (dL u2 Download user set 2). As dL u1 – Download user set 1 above.
- Copy user set 3 parameters from the control panel to the drive (dL u3 Download user set 2). As dL u1 – Download user set 1 above.
- Start, stop, change the direction and switch between local and remote control.

How to upload and download parameters

For the upload and download functions available, see above. Note that the drive has to be in local control for uploading and downloading.

Step	Action	Display		
1.	Go to the Main menu by pressing if you are in the Output mode, otherwise by pressing repeatedly until you see MENU at the bottom. – If REM is shown on the left, press first to switch to local control.	LOC	PA MENU	FWD
2.	If the panel is not in the Copy mode ("CoPY" not visible), press key or until you see "CoPY". Press .	LOC	MENU	PY
			U L MENU	- FWD
3.	To upload all parameters (including user sets) from the drive to the control panel, step to "uL" with keys and v.	LOC	U L MENU	- FWD
	Press T. During the transfer, the display shows the transfer status as a percentage of completion.	LOC	uL	50 %
	To perform downloads, step to the appropriate operation (here "dL A", Download all, is used as an example) with keys and	LOC	dL MENU	A
	Press T. During the transfer, the display shows the transfer status as a percentage of completion.	LOC	dL	50 %

Basic control panel alarm codes

In addition to the faults and alarms generated by the drive (see chapter Fault tracing on page 347), the basic control panel indicates control panel alarms with a code of form A5xxx. See section Alarms generated by the basic control panel on page 352 for a list of the alarm codes and descriptions.

Assistant control panel

Features

The assistant control panel features:

- alphanumeric control panel with an LCD display
- language selection for the display
- Start-up assistant to ease drive commissioning
- copy function parameters can be copied to the control panel memory for later transfer to other drives or for backup of a particular system.
- · context-sensitive help
- real time clock.

Overview

The following table summarizes the key functions and displays on the assistant control panel.

No.	Use	
1	Status LED – Green for normal operation. If LED is flashing, or red, see section <i>LEDs</i> on page 370.	2a LOC V 49.1HZ 49.1 HZ 0.5 A 10.7 % DIR 100:00 MENU 3 7 6 V ? 8
2	 LCD display – Divided into three main areas: f. Status line – variable, depending on the mode of operation, see section <i>Status line</i> on page <i>91</i>. g. Center – variable; in general, shows signal and parameter values, menus or lists. Shows also faults and alarms. h. Bottom line – shows current functions of the two soft keys and, if enabled, the clock display. 	
3	Soft key 1 – Function depends on the context. The text in the lower left corner of the LCD display indicates the function.	9 0 10 STOP START
4	Soft key 2 – Function depends on the context. The teLCD display indicates the function.	ext in the lower right corner of the
5	 Up – Scrolls up through a menu or list displayed in the center of the LCD display. Increments a value if a parameter is selected. Increments the reference value if the upper right corner is highlighted. Holding the key down changes the value faster. 	
6	Down – • Scrolls down through a menu or list displayed in the center of the LCD display. • Decrements a value if a parameter is selected. • Decrements the reference value if the upper right corner is highlighted. Holding the key down changes the value faster.	
7	LOC/REM - Changes between local and remote con	trol of the drive.
8	Help – Displays context-sensitive information when the key is pressed. The information displayed describes the item currently highlighted in the center of the display.	
9	STOP – Stops the drive in local control.	

Status line

The top line of the LCD display shows the basic status information of the drive.



No.	Field	Alternatives	Significance
1	Control location	LOC	Drive control is local, that is, from the control panel.
		REM	Drive control is remote, such as the drive I/O or fieldbus.
2	State	₹	Forward shaft direction
		<u>J</u>	Reverse shaft direction
		Rotating arrow	Drive is running at setpoint.
		Dotted rotating arrow	Drive is running but not at setpoint.
		Stationary arrow	Drive is stopped.
		Dotted stationary arrow	Start command is present, but the motor is
			not running, eg because start enable is
			missing.
3	Panel operation		Name of the current mode
	mode		Name of the list or menu shown
			Name of the operation state, eg PAR EDIT.
4	Reference value or		Reference value in the Output mode
	number of the selected item		Number of the highlighted item, eg mode, parameter group or fault.

Operation

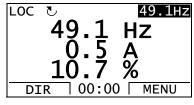
You operate the control panel with menus and keys. The keys include two contextsensitive soft keys, whose current function is indicated by the text shown in the display above each key.

You select an option, eg operation mode or parameter, by scrolling the ___ and varrow keys until the option is highlighted (in reverse video) and then pressing the relevant soft key. With the right soft key you usually enter a mode, accept an option or save the changes. The left soft key ris used to cancel the made changes and return to the previous operation level.

The assistant control panel has nine panel modes: Output mode, Parameter mode, Assistants mode, Changed parameters mode, Fault logger mode, Time and date mode, Parameter backup mode, I/O settings mode and Fault mode. The operation in the first eight modes is described in this chapter. When a fault or alarm occurs, the panel goes automatically to the Fault mode showing the fault or alarm. You can reset it in the Output or Fault mode (see chapter Fault tracing on page 347).

Initially, the panel is in the Output mode, where you can start, stop, change the direction, switch between local and remote control, modify the reference value and monitor up to three actual values.

To do other tasks, go first to the Main menu and select the appropriate mode on the menu. The status line (see section Status line on page 91) shows the name of the current menu, mode, item or state.





How to do common tasks

The table below lists common tasks, the mode in which you can perform them and the page number where the steps to do the task are described in detail.

Task	Mode	Page
How to get help	Any	93
How to find out the panel version	At power up	93
How to adjust the display contrast	Output	96
How to switch between local and remote control	Any	94
How to start and stop the drive	Any	95
How to change the direction of the motor rotation	Output	95
How to set the speed, frequency or torque reference	Output	96
How to change the value of a parameter	Parameters	97
How to select the monitored signals	Parameters	98
How to do guided tasks (specification of related parameter sets) with assistants	Assistants	100
How to view and edit changed parameters	Changed parameters	102
How to view faults	Fault logger	103
How to reset faults and alarms	Output, Fault	347
How to show/hide the clock, change date and time formats, set the clock and enable/disable automatic clock transitions according to the daylight saving changes	Time and date	104
How to copy parameters from the drive to the control panel	Parameter backup	107
How to restore parameters from the control panel to the drive	Parameter backup	107
How to view backup information	Parameter backup	108
How to edit and change parameter settings related to I/O terminals	I/O settings	109

How to get help

Step	Action	Display
1.	Press ? to read the context-sensitive help text for the item that is highlighted.	LOC PAR GROUPS—10 01 OPERATING DATA 03 FB ACTUAL SIGNALS 04 FAULT HISTORY 10 START/STOP/DIR 11 REFERENCE SELECT EXIT 00:00 SEL
	If help text exists for the item, it is shown on the display.	LOC THELP————————————————————————————————————
2.	If the whole text is not visible, scroll the lines with keys and .	LOC THELP—external sources (EXT1 and EXT2) for commands that enable start, stop and direction changes. EXIT 00:00
3.	After reading the text, return to the previous display by pressing .	LOC PAR GROUPS—10 01 OPERATING DATA 03 FB ACTUAL SIGNALS 04 FAULT HISTORY 10 START/STOP/DIR 11 REFERENCE SELECT EXIT 00:00 SEL

How to find out the panel version

Step	Action	Display
1.	If the power is switched on, switch it off.	
2.	Keep key ? pressed down while you switch on the power and read the information. The display shows the following panel information: Panel SW: panel firmware version ROM CRC: panel ROM check sum Flash Rev: flash content version Flash content comment. When you release the ? key, the panel goes to the Output mode.	PANEL VERSION INFO Panel SW: x.xx Rom CRC: xxxxxxxxx Flash Rev: x.xx xxxxxxxxxxxxxxxxxxxxxxxxxxxxxxxxx

How to start, stop and switch between local and remote control

You can start, stop and switch between local and remote control in any mode. To be able to start or stop the drive, the drive must be in local control.

Step	Action	Display
1.	To switch between remote control (REM shown on the status line) and local control (LOC shown on the status line), press	LOC MESSAGE——————————————————————————————————
	Note: Switching to local control can be disabled with parameter <i>1606 LOCAL LOCK</i> .	00:00
	The very first time the drive is powered up, it is in remote control (REM) and controlled through the drive I/O terminals. To switch to local control (LOC) and control the drive using the control panel, press . The result depends on how long you press the key: • If you release the key immediately (the display flashes "Switching to the local control mode"), the drive stops. Set the local control reference as instructed on page 96. • If you press the key for about two seconds, the drive continues as before. The drive copies the current remote values for the run/stop status and the reference, and uses them as the initial local control settings.	
	To stop the drive in local control, press	The arrow (౿ or ౷) on the status line stops rotating.
	To start the drive in local control, press	The arrow (or) on the status line starts rotating. It is dotted until the drive reaches the setpoint.

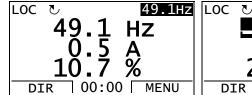
Output mode

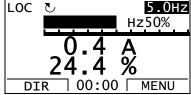
In the Output mode, you can:

- monitor actual values of up to three signals in group 01 OPERATING DATA
- change the direction of the motor rotation
- set the speed, frequency or torque reference
- adjust the display contrast
- start, stop, change the direction and switch between local and remote control.

You get to the Output mode by pressing repeatedly.

The top right corner of the display shows the reference value. The center can be configured to show up to three signal values or bar graphs. If just one or two signals are





selected for display, the number and name of each displayed signal are shown in addition to the value or bar graph. See page 98 for instructions on selecting and modifying the monitored signals.

How to change the direction of the motor rotation

Step	Action	Display
1.	If you are not in the Output mode, press repeatedly until you get there.	49.1 HZ 49.1 HZ 0.5 A 10.7 % DIR 00:00 MENU
2.	If the drive is in remote control (REM shown on the status line), switch to local control by pressing . The display briefly shows a message about changing the mode and then returns to the Output mode.	49.1 HZ 49.1 HZ 0.5 A 10.7 % DIR 00:00 MENU
3.	To change the direction from forward (shown on the status line) to reverse (shown on the status line), or vice versa, press . Note: Parameter 1003 DIRECTION must be set to 3 (REQUEST).	49.1 HZ 49.1 HZ 0.5 A 10.7 % DIR 00:00 MENU

How to set the speed, frequency or torque reference

Step	Action	Display
1.	If you are not in the Output mode, press repeatedly until you get there.	49.1HZ 49.1 HZ 0.5 A 10.7 % DIR 00:00 MENU
2.	If the drive is in remote control (REM shown on the status line), switch to local control by pressing . The display briefly shows a message about changing the mode and then returns to the Output mode. Note: With group 11 REFERENCE SELECT, you can allow the reference modification in remote control.	49.1 HZ 49.1 HZ 0.5 A 10.7 % DIR 00:00 MENU
3.	 To increase the highlighted reference value shown in the top right corner of the display, press The value changes immediately. It is stored in the drive permanent memory and restored automatically after power switch-off. To decrease the value, press 	50.0 HZ 0.5 A 10.7 % DIR 00:00 MENU

How to adjust the display contrast

Step	Action	Display
1.	If you are not in the Output mode, press repeatedly until you get there.	49.1 HZ 0.5 A 10.7 % DIR 00:00 MENU
2.	 To increase the contrast, press keys and simultaneously. To decrease the contrast, press keys and simultaneously. 	49.1 HZ 49.1 HZ 0.5 A 10.7 % DIR 00:00 MENU

Parameters mode

In the Parameters mode, you can:

- view and change parameter values
- start, stop, change the direction and switch between local and remote control.

How to select a parameter and change its value

Step	Action	Display
1.	Go to the Main menu by pressing if you are in the Output mode, otherwise by pressing repeatedly until you get to the Main menu.	PARAMETERS ASSISTANTS CHANGED PAR EXIT 00:00 ENTER
2.	Go to the Parameters mode by selecting PARAMETERS on the menu with keys and , and pressing enter.	LOC PAR GROUPS—01 01 OPERATING DATA 03 FB ACTUAL SIGNALS 04 FAULT HISTORY 10 START/STOP/DIR 11 REFERENCE SELECT EXIT 00:00 SEL
3.	Select the appropriate parameter group with keys and .	LOC PAR GROUPS—99 99 START-UP DATA 01 OPERATING DATA 03 FB ACTUAL SIGNALS 04 FAULT HISTORY 10 START/STOP/DIR EXIT 00:00 SEL
	Press SEL.	LOC PARAMETERS 9901 LANGUAGE ENGLISH 9902 APPLIC MACRO 9903 MOTOR TYPE 9904 MOTOR CTRL MODE EXIT 00:00 EDIT
4.	Select the appropriate parameter with keys and The current value of the parameter is shown below the selected parameter. Press	DOC PARAMETERS 9901 LANGUAGE 9902 APPLIC MACRO ABB STANDARD 9903 MOTOR TYPE 9904 MOTOR CTRL MODE EXIT 00:00 EDIT
		9902 APPLIC MACRO ABB STANDARD [1] CANCEL 00:00 SAVE
5.	Specify a new value for the parameter with keys and . Pressing the key once increments or decrements the value. Holding the key down changes the value faster. Pressing the keys simultaneously replaces the displayed value with the default value.	PAR EDIT— 9902 APPLIC MACRO 3-WIRE [2] CANCEL 00:00 SAVE

Step	Action	Display
6.	 To save the new value, press . To cancel the new value and keep the original, press . 	LOC PARAMETERS 9901 LANGUAGE 9902 APPLIC MACRO 3-WIRE 9903 MOTOR TYPE
		9904 MOTOR CTRL MODE EXIT 00:00 EDIT

How to select the monitored signals

Step	Action	Display
1.	You can select which signals are monitored in the Output mode and how they are displayed with group 34 PANEL DISPLAY parameters. See page 97 for detailed instructions on changing parameter values. By default, the display shows three signals. Signal 1: 0102 SPEED for macros 3-wire, Alternate, Motor potentiometer, Hand/Auto and PID control; 0103 OUTPUT FREQ for macros ABB standard and Torque control Signal 2: 0104 CURRENT Signal 3: 0105 TORQUE. To change the default signals, select up to three signals from group 01 OPERATING DATA to be shown. Signal 1: Change the value of parameter 3401 SIGNAL1 PARAM to the index of the signal parameter in group 01 OPERATING DATA (= number of the parameter without the leading zero), eg 105 means parameter 0105 TORQUE. Value 0 means that no signal is displayed. Repeat for signals 2 (3408 SIGNAL2 PARAM) and 3 (3415 SIGNAL3 PARAM).	SIGNAL1 PARAM OUTPUT FREQ 103 CANCEL 00:00 SAVE
2.	Select how you want the signals to be displayed: as a decimal number or a bar graph. For decimal numbers, you can specify the decimal point location, or use the decimal point location and unit of the source signal (setting 9 [DIRECT]). For details, see parameter 3404. Signal 1: parameter 3404 OUTPUT1 DSP FORM Signal 2: parameter 3411 OUTPUT2 DSP FORM Signal 3: parameter 3418 OUTPUT3 DSP FORM.	LOC PAR EDIT 3404 OUTPUT1 DSP FORM DIRECT [9] CANCEL 00:00 SAVE
3.	Select the units to be displayed for the signals. This has no effect if parameter 3404/3411/3418 is set to 9 (DIRECT). For details, see parameter 3405. Signal 1: parameter 3405 OUTPUT1 UNIT Signal 2: parameter 3412 OUTPUT2 UNIT Signal 3: parameter 3419 OUTPUT3 UNIT.	IOC PAR EDIT 3405 OUTPUT1 UNIT HZ [3] CANCEL 00:00 SAVE

Step	Action	Display
4.	Select the scalings for the signals by specifying the minimum and maximum display values. This has no effect if parameter 3404/3411/3418 is set to 9 (DIRECT). For details, see parameters 3406 and 3407.	SAUG OUTPUT1 MIN O.O HZ
	Signal 1: parameters 3406 OUTPUT1 MIN and 3407 OUTPUT1 MAX Signal 2: parameters 3413 OUTPUT2 MIN and 3414 OUTPUT2 MAX Signal 3: parameters 3420 OUTPUT3 MIN and 3421 OUTPUT3 MAX.	CANCEL 00:00 SAVE LOC PAR EDIT— 3407 OUTPUT1 MAX 500.0 HZ
		CANCEL 00:00 SAVE

Assistants mode

When the drive is first powered up, the Start-up assistant guides you through the setup of the basic parameters. The Start-up assistant is divided into assistants, each of which is responsible for the specification of a related parameter set, for example Motor set-up or PID control. The Start-up assistant activates the assistants one after the other. You may also use the assistants independently. For more information on the tasks of the assistants, see section *Start-up assistant* on page *125*.

In the Assistants mode, you can:

- use assistants to guide you through the specification of a set of basic parameters
- start, stop, change the direction and switch between local and remote control.

How to use an assistant

The table below shows the basic operation sequence which leads you through assistants. The Motor set-up assistant is used as an example.

Step	Action	Display
1.	Go to the Main menu by pressing sif you are in the Output mode, otherwise by pressing repeatedly until you get to the Main menu.	PARAMETERS ASSISTANTS CHANGED PAR EXIT 00:00 ENTER
2.	Go to the Assistants mode by selecting ASSISTANTS on the menu keys and , and pressing .	LOC CASSISTANTS—1 Start-up assistant Motor Set-up Application Speed control EXT1 Speed control EXT2 EXIT 00:00 SEL
3.	Select the assistant with keys and , and press. If you select any other assistant than the Start-up assistant, it guides you through the task of specification of its parameter set as shown in steps 4. and 5. below. After that you can select another assistant on the Assistants menu or exit the Assistants mode. The Motor set-up assistant is used here as an example.	9905 MOTOR NOM VOLT 200 V EXIT 00:00 SAVE
	If you select the Start-up assistant, it activates the first assistant, which guides you through the task of specification of its parameter set as shown in steps 4. and 5. below. The Start-up assistant then asks if you want to continue with the next assistant or skip it – select the appropriate answer with keys and , and press. If you choose to skip, the Start-up assistant asks the same question about the next assistant, and so on.	LOC CHOICE—Do you want to continue with application setup? Continue Skip EXIT 00:00 OK

Step	Action	Display
4.	To specify a new value, press keys	PAR EDIT———9905 MOTOR NOM VOLT 240 V
	To ask for information on the requested parameter, press key ?. Scroll the help text with keys and . Close the help by pressing . **To ask for information on the requested parameter, press key ?. Scroll the help text with keys and	EXIT 00:00 SAVE LOC
5.	 To accept the new value and continue to the setting of the next parameter, press To stop the assistant, press 	PAR EDIT————————————————————————————————————

Changed parameters mode

In the Changed parameters mode, you can:

- view a list of all parameters that have been changed from the macro default values
- change these parameters
- start, stop, change the direction and switch between local and remote control.

How to view and edit changed parameters

Step	Action	Display
1.	Go to the Main menu by pressing sif you are in the Output mode, otherwise by pressing repeatedly until you get to the Main menu.	PARAMETERS ASSISTANTS CHANGED PAR EXIT 00:00 ENTER
2.	Go to the Changed parameters mode by selecting CHANGED PAR on the menu with keys A and T, and pressing ENTER.	LOC CHANGED PAR————————————————————————————————————
3.	Select the changed parameter on the list with keys and . The value of the selected parameter is shown below it. Press to modify the value.	LOC PAR EDIT————————————————————————————————————
4.	Specify a new value for the parameter with keys and . Pressing the key once increments or decrements the value. Holding the key down changes the value faster. Pressing the keys simultaneously replaces the displayed value with the default value.	LOC PAR EDIT————————————————————————————————————
5.	 To accept the new value, press . If the new value is the default value, the parameter is removed from the list of changed parameters. To cancel the new value and keep the original, press . 	LOC CHANGED PAR————————————————————————————————————

Fault logger mode

In the Fault logger mode, you can:

- view the drive fault history of maximum ten faults (after a power off, only the three latest faults are kept in the memory)
- see the details of the three latest faults (after a power off, the details of only the most recent fault is kept in the memory)
- read the help text for the fault
- start, stop, change the direction and switch between local and remote control.

How to view faults

Step	Action	Display
1.	Go to the Main menu by pressing if you are in the Output mode, otherwise by pressing repeatedly until you get to the Main menu.	LOC MAIN MENU—1 PARAMETERS ASSISTANTS CHANGED PAR EXIT 00:00 ENTER
2.	Go to the Fault logger mode by selecting FAULT LOGGER on the menu with keys and , and pressing The display shows the fault log starting with the latest fault. The number on the row is the fault code according to which the causes and corrective actions are listed in chapter Fault tracing on page 347.	LOC FAULT LOGGER—1 10: PANEL LOSS 19.03.05 13:04:57 6: DC UNDERVOLT 7: AI1 LOSS EXIT 00:00 DETAIL
3.	To see the details of a fault, select it with keys and , and press .	LOC PANEL LOSS DI STATUS AT FLT 00000 bin FAULT TIME 1 13:04:57 FAULT TIME 2 EXIT 00:00 DIAG
4.	To show the help text, press Scroll the help text with keys and . After reading the help, press to return to the previous display.	LOC DIAGNOSTICS—Check: comm lines and connections, parameter 3002, parameters in groups 10 and 11. EXIT 00:00 OK

Time and date mode

In the Time and date mode, you can:

- show or hide the clock
- change date and time display formats
- · set the date and time
- enable or disable automatic clock transitions according to the daylight saving changes
- start, stop, change the direction and switch between local and remote control.

The assistant control panel contains a battery to ensure the function of the clock when the panel is not powered by the drive.

How to show or hide the clock, change display formats, set the date and time and enable or disable clock transitions due to daylight saving changes

Step	Action	Display
1.	Go to the Main menu by pressing sif you are in the Output mode, otherwise by pressing repeatedly until you get to the Main menu.	PARAMETERS ASSISTANTS CHANGED PAR EXIT 00:00 ENTER
2.	Go to the Time and date mode by selecting TIME & DATE on the menu with keys and , and pressing ENTER.	LOC TIME & DATE—1 CLOCK VISIBILITY TIME FORMAT DATE FORMAT SET TIME SET DATE EXIT 00:00 SEL
3.	To show (hide) the clock, select CLOCK VISIBLILITY on the menu, press, select Show clock (Hide clock) and press, or, if you want to return to the previous display without making changes, press.	LOC CLOCK VISIB—1 Show clock Hide clock EXIT 00:00 SEL
	To specify the date format, select DATE FORMAT on the menu, press and select a suitable format. Press to save or to cancel your changes.	LOC CDATE FORMAT—1 dd.mm.yy mm/dd/yy dd.mm.yyyy mm/dd/yyyy CANCEL 00:00 OK
	To specify the time format, select TIME FORMAT on the menu, press and select a suitable format. Press to save or to cancel your changes.	LOC TIME FORMAT—1 24-hour 12-hour CANCEL 00:00 SEL
I		3

Step	Action	Display
	• To set the time, select SET TIME on the menu and press. Specify the hours with keys and and and and and to save or to cancel your changes.	LOC SET TIME————————————————————————————————————
	 To set the date, select SET DATE on the menu and press SEL. Specify the first part of the date (day or month depending on the selected date format) with keys and , and press Repeat for the second part. After specifying the year, press . To cancel your changes, press . To cancel your changes, press . To enable or disable the automatic clock transitions according to the daylight saving changes, select DAYLIGHT SAVING on the menu and press . 	CANCEL 00:00 OK LOC SET DATE 19.03.05 CANCEL 00:00 OK LOC DAYLIGHT SAV—1 Off EU US
	 Pressing ? opens the help that shows the beginning and end dates of the period during which daylight saving time is used in each country or area whose daylight saving changes you can select to be followed. Scroll the help text with keys and . To disable automatic clock transitions according to the daylight saving changes, select Off and press . To enable automatic clock transitions, select the country or area whose daylight saving changes are followed and press . To return to the previous display without making changes, press . 	Australia1:NSW,Vict Australia2:Tasmania EXIT 00:00 SEL LOC

Parameter backup mode

The Parameter backup mode is used to export parameters from one drive to another or to make a backup of the drive parameters. Uploading to the panel stores all drive parameters, including up to three user sets, to the assistant control panel. The full set, partial parameter set (application) and user sets can then be downloaded from the control panel to another drive or the same drive. Uploading and downloading can be performed in local control.

The control panel memory is non-volatile and does not depend on the panel battery.

In the Parameter backup mode, you can:

- Copy all parameters from the drive to the control panel (UPLOAD TO PANEL).
 This includes all defined user sets of parameters and internal (not adjustable by the user) parameters such as those created by the ID run.
- View the information about the backup stored to the control panel with UPLOAD TO PANEL (BACKUP INFO). This includes eg the type and rating of the drive where the backup was made. It is useful to check this information when you are going to copy the parameters to another drive with DOWNLOAD FULL SET to ensure that the drives match.
- Restore the full parameter set from the control panel to the drive (DOWNLOAD FULL SET). This writes all parameters, including the internal non-user-adjustable motor parameters, to the drive. It does not include the user sets of parameters.
 - **Note:** Only use this function to restore a drive from a backup or to transfer parameters to systems that are identical to the original system.
- Copy a partial parameter set (part of the full set) from the control panel to a drive (DOWNLOAD APPLICATION). The partial set does not include user sets, internal motor parameters, parameters 9905...9909, 1605, 1607, 5201, nor any group 51 EXT COMM MODULE and 53 EFB PROTOCOL parameters.
 - The source and target drives and their motor sizes do not need to be the same.
- Copy user set 1 parameters from the control panel to the drive (DOWNLOAD USER SET1). A user set includes group 99 START-UP DATA parameters and the internal motor parameters.
 - The function is only shown on the menu when user set 1 has been first saved using parameter 9902 APPLIC MACRO (see section user macros on page 123) and then uploaded to the control panel with UPLOAD TO PANEL.
- Copy user set 2 parameters from the control panel to the drive (DOWNLOAD USER SET2). As DOWNLOAD USER SET1 above.
- Copy user set 3 parameters from the control panel to the drive (DOWNLOAD USER SET3). As DOWNLOAD USER SET1 above.
- Start, stop, change the direction and switch between local and remote control.

How to upload and download parameters

For the upload and download functions available, see above. Note that the drive has to be in local control for uploading and downloading.

Step	Action	Display
1.	Go to the Main menu by pressing if you are in the Output mode, otherwise by pressing repeatedly until you get to the Main menu. – If REM is shown on the status line, press first to switch to local control.	LOC MAIN MENU—1 PARAMETERS ASSISTANTS CHANGED PAR EXIT 00:00 ENTER
2.	Go to the Par backup mode by selecting PAR BACKUP on the menu with keys and , and pressing .	LOC PAR BACKUP—1 UPLOAD TO PANEL BACKUP INFO DOWNLOAD FULL SET DOWNLOAD APPLICATION DOWNLOAD USER SET1 EXIT 00:00 SEL
3.	To copy all parameters (including user sets and internal parameters) from the drive to the control panel, select UPLOAD TO PANEL on the Par backup menu with keys and , and press . During the transfer, the display shows the transfer status as a percentage of completion. Press if you want to stop the operation.	LOC PAR BACKUP————————————————————————————————————
	After the upload is completed, the display shows a message about the completion. Press to return to the Par backup menu.	LOC ©MESSAGE——————————————————————————————————
	To perform downloads, select the appropriate operation (here DOWNLOAD FULL SET is used as an example) on the Par backup menu with keys and , and press. The display shows the transfer status as a percentage of completion. Press if you want to stop the operation. After the download is completed, the display shows a	OK 00:00 LOC PAR BACKUP— Downloading parameters (full set) ABORT 00:00 LOC MESSAGE—
	message about the completion. Press to return to the Par backup menu.	Parameter download successfully completed. OK 00:00

How to view information about the backup

Step	Action	Display
1.	Go to the Main menu by pressing if you are in the Output mode, otherwise by pressing repeatedly until you get to the Main menu.	PARAMETERS ASSISTANTS CHANGED PAR EXIT 00:00 ENTER
2.	Go to the Par backup mode by selecting PAR BACKUP on the menu with keys and , and pressing enter.	LOC TPAR BACKUP——1 UPLOAD TO PANEL BACKUP INFO DOWNLOAD FULL SET DOWNLOAD APPLICATION DOWNLOAD USER SET1 EXIT 00:00 SEL
3.	Select BACKUP INFO on the Par backup menu with keys and , and press. The display shows the following information about the drive where the backup was made: DRIVE TYPE: type of the drive DRIVE RATING: rating of the drive in format XXXYZ, where XXX: Nominal current rating. If present, an "A" indicates a decimal point, eg 9A7 means 9.7 A. Y: 2 = 200 V 4 = 400 V Z: i = European loading package n = US loading package FIRMWARE: firmware version of the drive. You can scroll the information with keys and .	LOC & BACKUP INFODRIVE TYPE ACS355 3304 DRIVE RATING 9A74i 3301 FIRMWARE EXIT 00:00 LOC & BACKUP INFOACS355 3304 DRIVE RATING 9A74i 3301 FIRMWARE 241A hex EXIT 00:00
4.	Press to return to the Par backup menu.	LOC PAR BACKUP—1 UPLOAD TO PANEL BACKUP INFO DOWNLOAD FULL SET DOWNLOAD APPLICATION DOWNLOAD USER SET1 EXIT 00:00 SEL

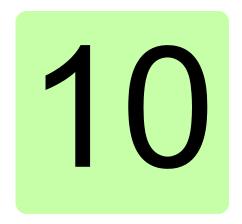
I/O settings mode

In the I/O settings mode, you can:

- check the parameter settings related to any I/O terminal
- edit the parameter setting. For example, if "1103: REF1" is listed under Ain1 (Analog input 1), that is, parameter 1103 REF1 SELECT has value Al1, you can change its value to eg A/2. You cannot, however, set the value of parameter 1106 REF2 SELECT to AI1.
- start, stop, change the direction and switch between local and remote control.

How to edit and change parameter settings related to I/O terminals

Step	Action	Display
1.	Go to the Main menu by pressing if you are in the Output mode, otherwise by pressing repeatedly until you get to the Main menu.	LOC &MAIN MENU 1 PARAMETERS ASSISTANTS CHANGED PAR EXIT 00:00 ENTER
2.	Go to the I/O settings mode by selecting I/O SETTINGS on the menu with keys and , and pressing .	LOC & I/O SETTINGS—1 DIGITAL INPUTS (DI) ANALOG INPUTS (AI) RELAY OUTPUTS (ROUT) ANALOG OUTPUTS (AOUT) PANEL EXIT 00:00 SEL
3.	Select the I/O group, eg DIGITAL INPUTS, with keys and , and press. After a brief pause, the display shows the current settings for the selection.	LOC & I/O SETTINGS— -DI1- 1001:START/STOP (E1) -DI2- 1001:DIR (E1) -DI3- EXIT 00:00
4.	Select the setting (line with a parameter number) with keys and , and press .	LOC PAR EDIT————————————————————————————————————
5.	Specify a new value for the setting with keys and . Pressing the key once increments or decrements the value. Holding the key down changes the value faster. Pressing the keys simultaneously replaces the displayed value with the default value.	LOC PAR EDIT————————————————————————————————————
6.	 To save the new value, press SAVE. To cancel the new value and keep the original, press CANCEL. 	LOC & I/O SETTINGS————————————————————————————————————



Application macros

What this chapter contains

The chapter describes the application macros. For each macro, there is a wiring diagram showing the default control connections (digital and analog I/O). The chapter also explains how to save a user macro and how to recall it.

Overview of macros

Application macros are pre-programmed parameter sets. While starting up the drive, the user typically selects one of the macros - the one that is best suited for the purpose - with parameter 9902 APPLIC MACRO, makes the essential changes and saves the result as a user macro.

The ACS355 has eight standard macros and three user macros. The table below contains a summary of the macros and describes suitable applications.

Macro	Suitable applications
ABB standard	Ordinary speed control applications where no, one, two or three constant speeds are used. Start/stop is controlled with one digital input (level start and stop). It is possible to switch between two acceleration and deceleration times.
3-wire	Ordinary speed control applications where no, one, two or three constant speeds are used. The drive is started and stopped with push buttons.
Alternate	Speed control applications where no, one, two or three constant speeds are used. Start, stop and direction are controlled by two digital inputs (combination of the input states determines the operation).
Motor potentiometer	Speed control applications where no or one constant speed is used. The speed is controlled by two digital inputs (increase / decrease / keep unchanged).

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Macro	Suitable applications
Hand/Auto	Speed control applications where switching between two control devices is needed. Some control signal terminals are reserved for one device, the rest for the other. One digital input selects between the terminals (devices) in use.
PID control	Process control applications, for example different closed loop control systems such as pressure control, level control and flow control. It is possible to switch between process and speed control: Some control signal terminals are reserved for process control, others for speed control. One digital input selects between process and speed control.
Torque control	Torque control applications. It is possible to switch between torque and speed control: Some control signal terminals are reserved for torque control, others for speed control. One digital input selects between torque and speed control.
AC500 Modbus	Applications that require a complex control logic and when several drives are connected together through a Modbus link. AC500-eCo PLC is used for controlling and monitoring the system.
User	The user can save the customized standard macro, ie the parameter settings including group 99 START-UP DATA, and the results of the motor Identification run into the permanent memory, and recall the data at a later time. For example, three user macros can be used when switching between three different motors is required.

Summary of the I/O connections of the application macros

The following table gives the summary of the default I/O connections of all application macros.

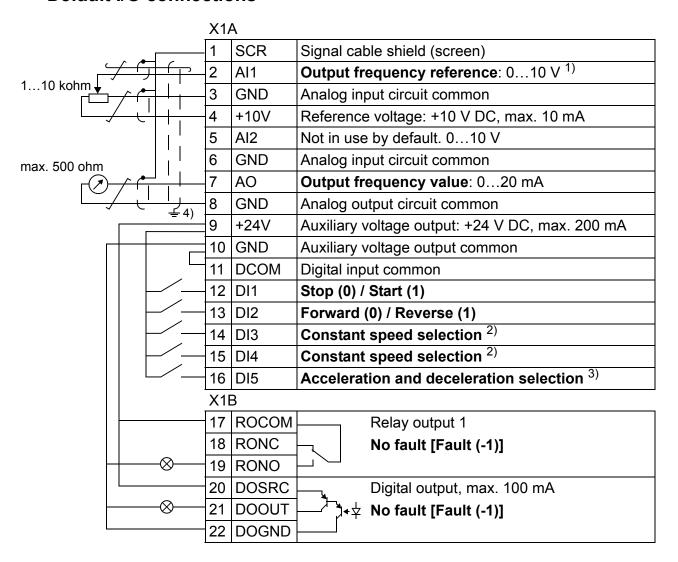
Input/	Масто						
output	ABB standard	3-wire	Alternate	Motor potentiom.	Hand/Auto	PID control	Torque control
AI1 (010 V)	Freq. ref.	Speed ref.	Speed ref.	-	Speed ref. (Hand)	Proc. ref. (PID) / Freq. ref. (Hand)	Speed ref. (Speed)
AI2 (020 mA)	-	-	-	-	Speed ref. (Auto)	Process value	Torque ref. (Torque)
AO	Output freq.	Speed	Speed	Speed	Speed	Speed	Speed
DI1	Stop/Start	Start (pulse)	Start (fwd)	Stop/Start	Stop/Start (Hand)	Stop/Start (PID)	Stop/Start (Speed)
DI2	Fwd/Rev	Stop (pulse)	Start (rev)	Fwd/Rev	Fwd/Rev (Hand)	PID/Hand	Fwd/Rev
DI3	Const. speed input 1	Fwd/Rev	Const. speed input 1	Speed ref. up	Hand/Auto	Const. speed 1	Speed/ Torque
DI4	Const. speed input 2	Const. speed input 1	Const. speed input 2	Speed ref. down	Fwd/Rev (Auto)	Run enable	Const. speed 1
DI5	Ramp pair selection	Const. speed input 2	Ramp pair selection	Const. speed 1	Stop/Start (Auto)	Stop/Start (Hand)	Ramp pair selection
RO	Fault (-1)	Fault (-1)	Fault (-1)	Fault (-1)	Fault (-1)	Fault (-1)	Fault (-1)
DO	Fault (-1)	Fault (-1)	Fault (-1)	Fault (-1)	Fault (-1)	Fault (-1)	Fault (-1)

ABB standard macro

This is the default macro. It provides a general purpose I/O configuration with three constant speeds. Parameter values are the default values given in section *Parameters* on page 192.

If you use other than the default connections presented below, see section I/O terminals on page 53.

Default I/O connections



- 1) Al1 is used as a speed reference if vector mode is selected.
- 2) See parameter group 12 CONSTANT SPEEDS:

DI3	DI4	Operation (parameter)
0	0	Set speed through AI1
1	0	Speed 1 (1202)
0	1	Speed 2 (1203)
1	1	Speed 3 (1204)

- 3) 0 = ramp times according to parameters 2202 and 2203.
 - 1 = ramp times according to parameters 2205 and 2206.
- 4) 360 degree grounding under a clamp.

Tightening torque: 0.4 N·m / 3.5 lbf·in.

Safe torque off connections (X1C:STO; not shown in the diagram) are jumpered by default.

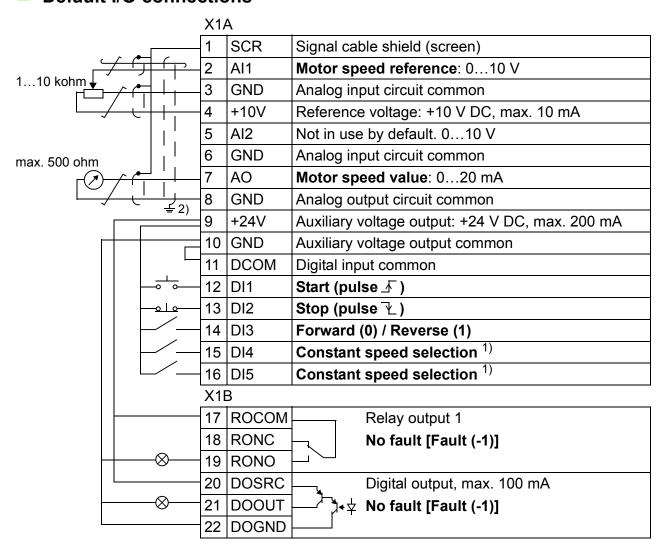
3-wire macro

This macro is used when the drive is controlled using momentary push-buttons. It provides three constant speeds. To enable the macro, set the value of parameter 9902 APPLIC MACRO to 2 (3-WIRE).

For the parameter default values, see section Default values with different macros on page 182. If you use other than the default connections presented below, see section I/O terminals on page 53.

Note: When the stop input (DI2) is deactivated (no input), the control panel start and stop buttons are disabled.

Default I/O connections



1) See parameter group 12 CONSTANT SPEEDS:

DI4	DI5	Operation (parameter)	
0	0	Set speed through AI1	
1	0	Speed 1 (1202)	
0	1	Speed 2 (1203)	
1	1	Speed 3 (1204)	

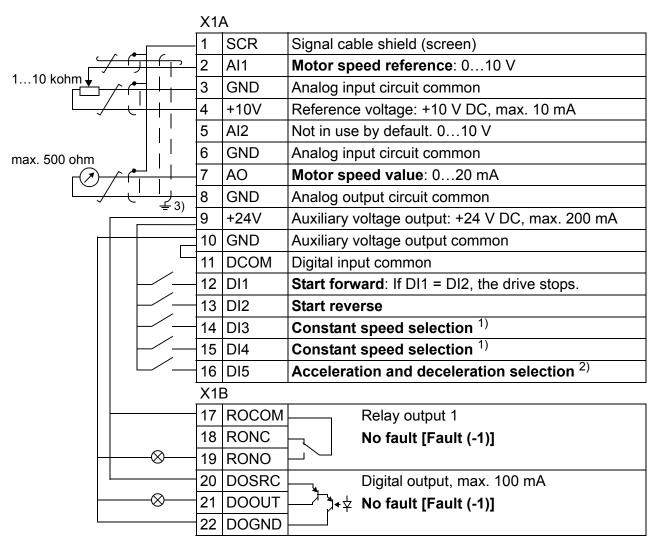
²⁾ 360 degree grounding under a clamp. Tightening torque: 0.4 N·m / 3.5 lbf·in. Safe torque off connections (X1C:STO; not shown in the diagram) are jumpered by default.

Alternate macro

This macro provides an I/O configuration adapted to a sequence of DI control signals used when alternating the rotation direction of the motor. To enable the macro, set the value of parameter 9902 APPLIC MACRO to 3 (ALTERNATE).

For the parameter default values, see section *Default values with different macros* on page 182. If you use other than the default connections presented below, see section *I/O terminals* on page 53.

Default I/O connections



1) See parameter group 12 CONSTANT SPEEDS:

DI3	DI4	Operation (parameter)
0	0	Set speed through AI1
1	0	Speed 1 (1202)
0	1	Speed 2 (1203)
1	1	Speed 3 (1204)

- ²⁾ 0 = ramp times according to parameters 2202 and 2203.
 - 1 = ramp times according to parameters 2205 and 2206.
- ³⁾ 360 degree grounding under a clamp.

Tightening torque: 0.4 N·m / 3.5 lbf·in.

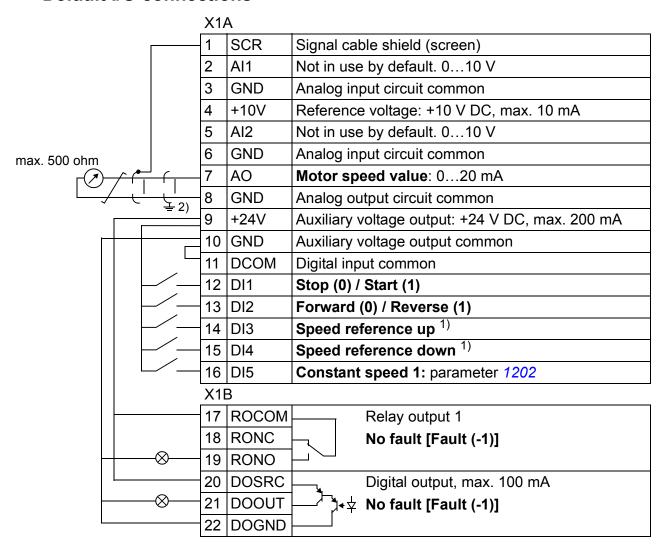
Safe torque off connections (X1C:STO; not shown in the diagram) are jumpered by default.

Motor potentiometer macro

This macro provides a cost-effective interface for PLCs that vary the speed of the motor using only digital signals. To enable the macro, set the value of parameter 9902 APPLIC MACRO to 4 (MOTOR POT).

For the parameter default values, see section *Default values with different macros* on page 182. If you use other than the default connections presented below, see section I/O terminals on page 53.

Default I/O connections



¹⁾ If DI3 and DI4 are both active or inactive, the speed reference is unchanged.

The existing speed reference is stored during stop and power down.

²⁾ 360 degree grounding under a clamp. Tightening torque: 0.4 N·m / 3.5 lbf·in. Safe torque off connections (X1C:STO; not shown in the diagram) are jumpered by default.

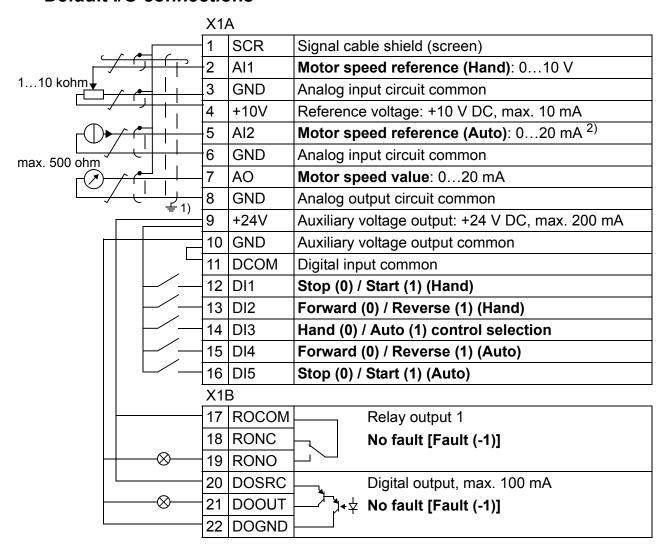
Hand/Auto macro

This macro can be used when switching between two external control devices is needed. To enable the macro, set the value of parameter 9902 APPLIC MACRO to 5 (HAND/AUTO).

For the parameter default values, see section *Default values with different macros* on page 182. If you use other than the default connections presented below, see section *I/O terminals* on page 53.

Note: Parameter 2108 START INHIBIT must remain in the default setting 0 (OFF).

Default I/O connections



^{1) 360} degree grounding under a clamp.

Tightening torque: 0.4 N·m / 3.5 lbf·in.

Safe torque off connections (X1C:STO; not shown in the diagram) are jumpered by default.

²⁾ The signal source is powered externally. See the manufacturer's instructions. To use sensors supplied by the drive aux. voltage output, see page 55.

PID control macro

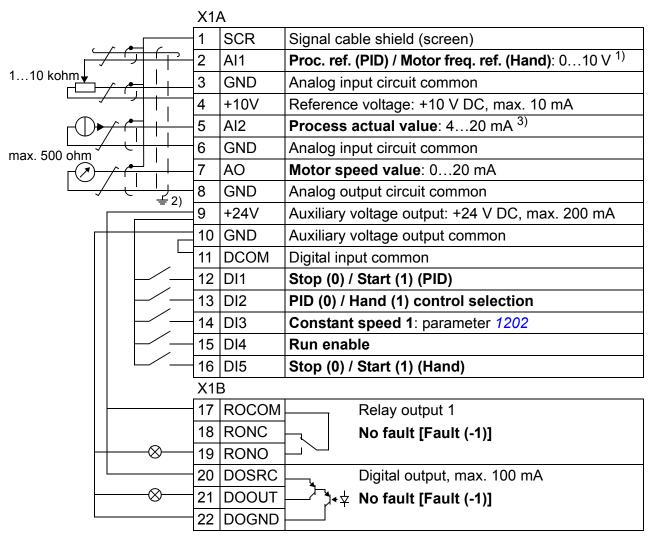
This macro provides parameter settings for closed-loop control systems such as pressure control, flow control, etc. Control can also be switched to speed control using a digital input. To enable the macro, set the value of parameter 9902 APPLIC MACRO to 6 (PID CONTROL).

For the parameter default values, see section *Default values with different macros* on page 182. If you use other than the default connections presented below, see section I/O terminals on page 53.

Note: The default I/O connections described below are applicable to firmware version 5.050 or later. For the default values in earlier firmware versions, see Revision A of this user's manual.

Note: Parameter 2108 START INHIBIT must remain in the default setting 0 (OFF).

Default I/O connections



^{&#}x27;' Hand: 0...10 V -> speed reference. PID: 0...10 V -> 0...100% PID setpoint.

sensors supplied by the drive aux. voltage output, see page 55.

Tightening torque: 0.4 N·m / 3.5 lbf·in.

Safe torque off connections (X1C:STO; not shown in the diagram) are jumpered by default

²⁾ 360 degree grounding under a clamp.

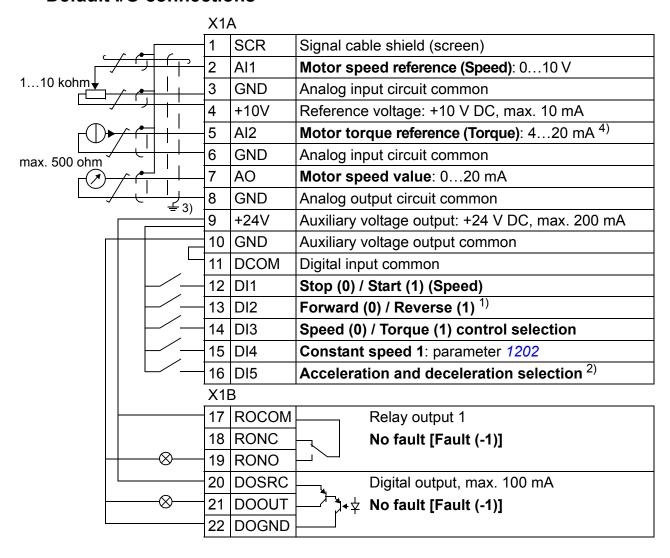
³⁾ The signal source is powered externally. See the manufacturer's instructions. To use

Torque control macro

This macro provides parameter settings for applications that require torque control of the motor. Control can also be switched to speed control using a digital input. To enable the macro, set the value of parameter 9902 APPLIC MACRO to 8 (TORQUE CTRL).

For the parameter default values, see section *Default values with different macros* on page 182. If you use other than the default connections presented below, see section *I/O terminals* on page 53.

Default I/O connections



Speed control: Changes rotation direction.
 Torque control: Changes torque direction.

Tightening torque: 0.4 N·m / 3.5 lbf·in.

Safe torque off connections (X1C:STO; not shown in the diagram) are jumpered by default.

²⁾ 0 = ramp times according to parameters 2202 and 2203.

^{1 =} ramp times according to parameters 2205 and 2206.

^{3) 360} degree grounding under a clamp.

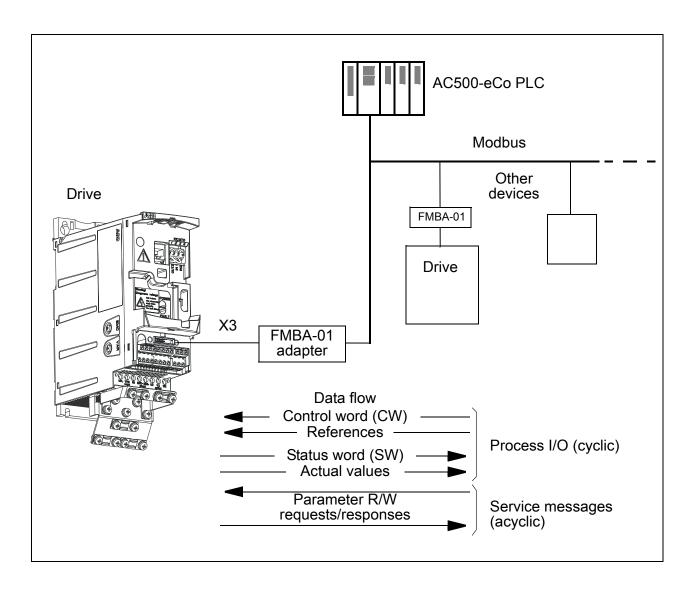
⁴⁾ The signal source is powered externally. See the manufacturer's instructions. To use sensors supplied by the drive aux. voltage output, see page *55*.

AC500 Modbus macro

The AC500 Modbus application macro configures the ACS355 drive communication and control parameters to be applicable with the pre-engineered Starter kit for AC500-eCo PLC and ACS355 drive over STD Modbus connection (FMBA-01 adapter).

The macro is available in ACS355 drives with firmware version 5.03C or later.

To activate the macro, set parameter 9902 APPLIC MACRO to AC500 MODBUS (10).



The AC500 Modbus application macro default values for the drive parameters correspond to the ABB standard macro (parameter 9902, value 1 (ABB STANDARD), see section ABB standard macro on page 114), with the following differences:

No.	Name	Default value
1001	EXT1 COMMANDS	10 (COMM)
1102	EXT1/EXT2 SEL	8 (COMM)
1103	REF1 SELECT	8 (COMM)
1604	FAULT RESET SEL	8 (COMM)
2201	ACC/DEC 1/2 SEL	0 (NOT SEL)
3018	COMM FAULT FUNC	1 (FAULT)
5302	EFB STATION ID	2
5303	EFB BAUD RATE	192 (19.2 kb/s)
5304	EFB PARITY	1 (8 NONE 1)
5305	EFB CTRL PROFILE	2 (ABB DRV FULL)
5310	EFB PAR 10	101
5311	EFB PAR 11	303
5312	EFB PAR 12	305
9802	COMM PROT SEL	1 (STD MODBUS)

Note: The default slave address of the drive is 2 (parameter 5303 EFB STATION ID), but if several drives are used, the address must be unique for each drive.

For more information regarding the Starter kit configuration, please refer to AC500-eCo and ACS355 quick installation guide (2CDC125145M0201 [English]), and ACS355 and AC500-eCo application guide (2CDC125152M0201 [English]).

User macros

In addition to the standard application macros, it is possible to create three user macros. The user macro allows the user to save the parameter settings, including group 99 START-UP DATA, and the results of the motor identification into the permanent memory and recall the data at a later time. The panel reference is also saved if the macro is saved and loaded in local control. The remote control setting is saved into the user macro, but the local control setting is not.

The steps below show how to create and recall User macro 1. The procedure for the other two macros is identical, only the parameter 9902 APPLIC MACRO values are different.

To create User macro 1:

- Adjust the parameters. Perform the motor identification if it is needed in the application but it is not done yet.
- Save the parameter settings and the results of the motor identification to the permanent memory by changing parameter 9902 APPLIC MACRO to -1 (USER S1 SAVE).
- Press (assistant control panel) or (basic control panel) to save.

To recall User macro 1:

- Change parameter 9902 APPLIC MACRO to 0 (USER S1 LOAD).
- Press (assistant control panel) or (basic control panel) to load.

The user macro can also be switched through digital inputs (see parameter 1605 USER PAR SET CHG).

Note: User macro load restores the parameter settings, including group 99 START-UP DATA and the results of the motor identification. Check that the settings correspond to the motor used.

Hint: The user can, for example, switch the drive between three motors without having to adjust the motor parameters and to repeat the motor identification every time the motor is changed. The user needs only to adjust the settings and perform the motor identification once for each motor and then to save the data as three user macros. When the motor is changed, only the corresponding user macro needs to be loaded, and the drive is ready to operate.

Program features

What this chapter contains

The chapter describes program features. For each feature, there is a list of related user settings, actual signals, and fault and alarm messages.

Start-up assistant

Introduction

The Start-up assistant (requires the assistant control panel) guides the user through the start-up procedure, helping to enter the requested data (parameter values) to the drive. The Start-up assistant also checks that the entered values are valid, ie within the allowed range.

The Start-up assistant calls other assistants, each of which guides the user through the task of specifying a related parameter set. At the first start, the drive suggests entering the first task, Language select, automatically. The user may activate the tasks either one after the other as the Start-up assistant suggests, or independently. The user may also adjust the drive parameters in the conventional way without using the assistant at all.

See section Assistants mode on page 100 for how to start the Start-up assistant or other assistants.

Default order of the tasks

Depending on the selection made in the Application task (parameter 9902 APPLIC MACRO), the Start-up assistant decides which consequent tasks it suggests. The default tasks are shown in the table below.

Application selection	Default tasks
ABB STANDARD	Language select, Motor set-up, Application, Option modules, Speed control EXT1, Speed control EXT2, Start/Stop control, Timed functions, Protections, Output signals
3-WIRE	Language select, Motor set-up, Application, Option modules, Speed control EXT1, Speed control EXT2, Start/Stop control, Timed functions, Protections, Output signals
ALTERNATE	Language select, Motor set-up, Application, Option modules, Speed control EXT1, Speed control EXT2, Start/Stop control, Timed functions, Protections, Output signals
MOTOR POT	Language select, Motor set-up, Application, Option modules, Speed control EXT1, Speed control EXT2, Start/Stop control, Timed functions, Protections, Output signals
HAND/AUTO	Language select, Motor set-up, Application, Option modules, Speed control EXT1, Speed control EXT2, Start/Stop control, Timed functions, Protections, Output signals
PID CONTROL	Language select, Motor set-up, Application, Option modules, PID control, Speed control EXT2, Start/Stop control, Timed functions, Protections, Output signals
TORQUE CTRL	Language select, Motor set-up, Application, Option modules, Speed control EXT2, Start/Stop control, Timed functions, Protections, Output signals
AC500 MODBUS	Language select, Motor set-up, Application, Option modules, Speed control EXT1, Speed control EXT2, Start/Stop control, Timed functions, Protections, Output signals

List of the tasks and the relevant drive parameters

Depending on the selection made in the Application task (parameter 9902 APPLIC MACRO), the Start-up assistant decides which consequent tasks it suggests.

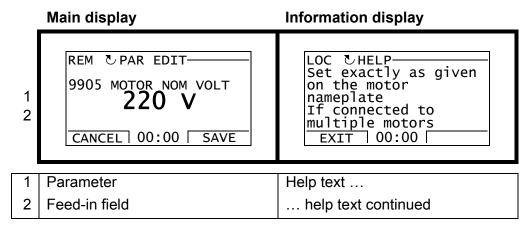
Name	Description	Set parameters
Language select	Selecting the language	9901
Motor set-up	Setting the motor data	99049909
	Performing the motor identification. (If the speed limits are not in the allowed range: Setting the limits.)	9910
Application	Selecting the application macro	9902, parameters associated to the macro
Option modules	Activating the option modules	Group 35 MOTOR TEMP MEAS, group 52 PANEL COMM 9802
Speed control EXT1	Selecting the source for the speed reference	1103
	(If AI1 is used: Setting analog input AI1 limits, scale, inversion)	(13011303, 3001)
	Setting the reference limits	1104, 1105
	Setting the speed (frequency) limits	2001, 2002 (2007, 2008)
	Setting the acceleration and deceleration times	2202, 2203
Speed control EXT2	Selecting the source for the speed reference	1106
	(If AI1 is used: Setting analog input AI1 limits, scale, inversion)	(13011303, 3001)
	Setting the reference limits	1107, 1108
Torque control	Selecting the source for the torque reference	1106
	(If AI1 is used: Setting analog input AI1 limits, scale, inversion)	(13011303, 3001)
	Setting the reference limits	1107, 1108
	Setting the torque ramp up and ramp down times	2401, 2402
PID control	Selecting the source for the process reference	1106
	(If AI1 is used: Setting analog input AI1 limits, scale, inversion)	(13011303, 3001)
	Setting the reference limits	1107, 1108
	Setting the speed (frequency) limits	2001, 2002 (2007, 2008)
	Setting the source and limits for the process actual value	4016, 4018, 4019

Name	Description	Set parameters
Start/Stop control	Selecting the source for start and stop signals of the two external control locations, EXT1 and EXT2	1001, 1002
	Selecting between EXT1 and EXT2	1102
	Defining the direction control	1003
	Defining the start and stop modes	21012103
	Selecting the use of Run enable signal	1601
Protections	Setting the current and torque limits	2003, 2017
Output signals	Selecting the signals indicated through relay output RO1 and, if MREL-01 output relay module is in use, RO2RO4.	Group 14 RELAY OUTPUTS
	Selecting the signals indicated through analog output AO	Group 15 ANALOG OUTPUTS
	Setting the minimum, maximum, scaling and inversion	
Timed functions	Setting the timed functions	Group 36 TIMED FUNCTIONS
	Selecting the timed start/stop control for external control locations EXT1 and EXT2	1001, 1002
	Selecting timed EXT1/EXT2 control	1102
	Activation of timed constant speed 1	1201
	Selecting timed function status indicated through relay output RO1 or, if MREL-01 output relay module is in use, RO2RO4.	14011403, 1410
	Selecting timed PID1 parameter set 1/2 control	4027

Contents of the assistant displays

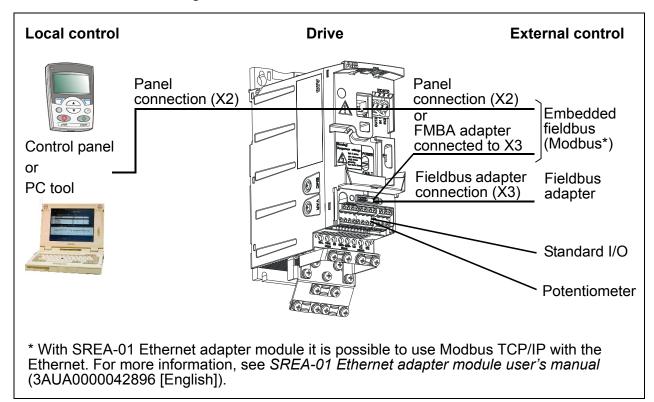
There are two types of displays in the Start-up assistant: Main displays and information displays. The main displays prompt the user to feed in information. The assistant steps through the main displays. The information displays contain help texts

for the main displays. The figure below shows a typical example of both and explanations of the contents.



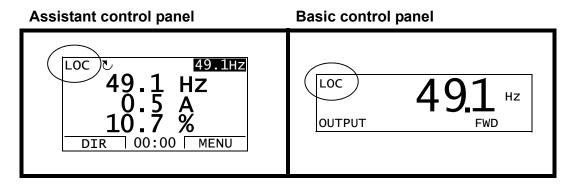
Local control vs. external control

The drive can receive start, stop and direction commands and reference values from the control panel or through digital and analog inputs. Embedded fieldbus or an optional fieldbus adapter enables control over an open fieldbus link. A PC equipped with the DriveWindow Light 2 PC tool can also control the drive.



Local control

The control commands are given from the control panel keypad when the drive is in local control. LOC indicates local control on the panel display.

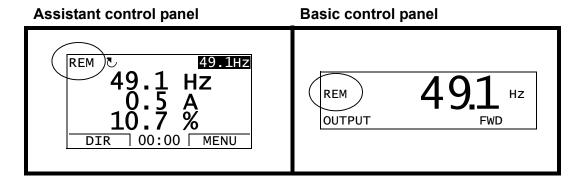


The control panel always overrides the external control signal sources when used in local control.

External control

When the drive is in external (remote) control, the commands are given through the standard I/O terminals (digital and analog inputs) and/or the fieldbus interface. In addition, it is also possible to set the control panel as the source for the external control.

External control is indicated with REM on the panel display.



The user can connect the control signals to two external control locations, *EXT1* or EXT2. Depending on the user selection, either one is active at a time. This function operates on a 2 ms time level.

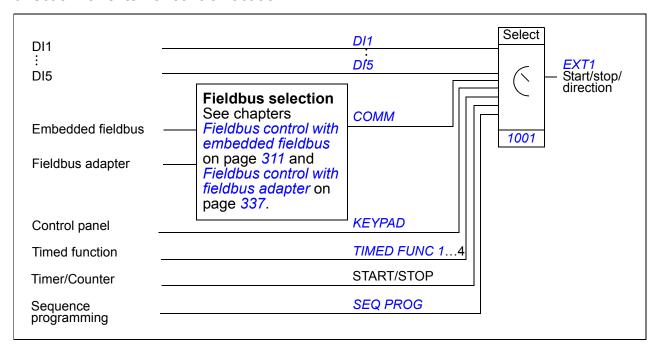
Settings

Panel key	Additional information	
LOC/REM	Selection between local and external (remote) control	
Parameter		
1102	Selection between EXT1 and EXT2	
1001/1002	Start, stop, direction source for EXT1/EXT2	
1103/1106	Reference source for EXT1/EXT2	

Actual signal	Additional information
0111/0112	EXT1/EXT2 reference

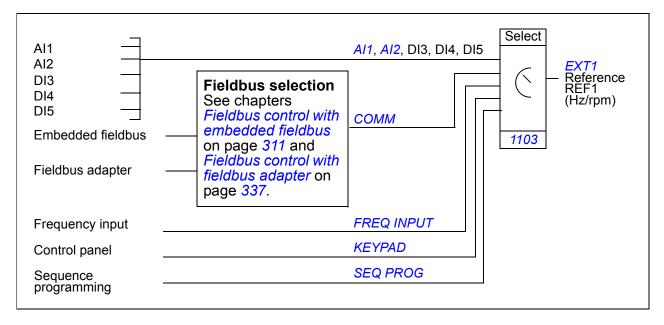
Block diagram: Start, stop, direction source for EXT1

The figure below shows the parameters that select the interface for start, stop, and direction for external control location *EXT1*.



Block diagram: Reference source for EXT1

The figure below shows the parameters that select the interface for the speed reference of external control location *EXT1*.



Reference types and processing

The drive can accept a variety of references in addition to the conventional analog input and control panel signals.

- The drive reference can be given with two digital inputs: One digital input increases the speed, the other decreases it.
- The drive can form a reference out of two analog input signals by using mathematical functions: addition, subtraction, multiplication and division.
- The drive can form a reference out of an analog input signal and a signal received through a serial communication interface by using mathematical functions: addition and multiplication.
- The drive reference can be given with frequency input.
- In external control location EXT1/2, the drive can form a reference out of an analog input signal and a signal received through Sequence programming by using a mathematical function: addition.

It is possible to scale the external reference so that the signal minimum and maximum values correspond to a speed other than the minimum and maximum speed limits.

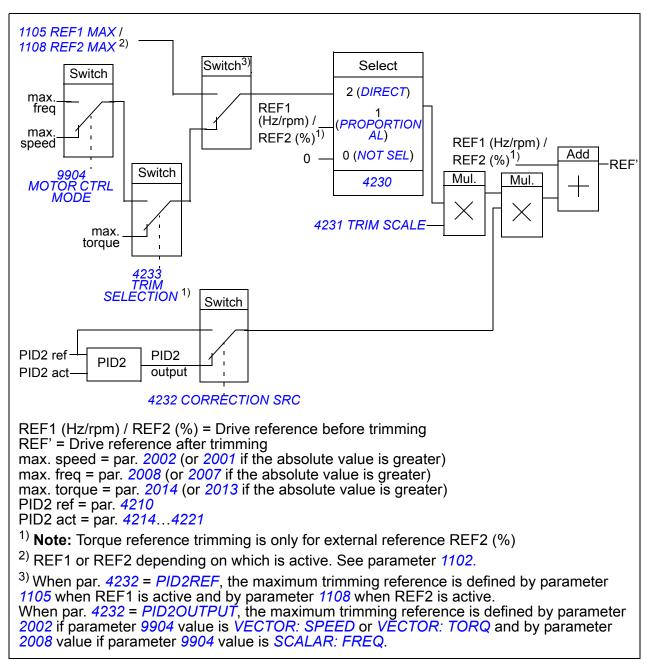
Settings

Parameter	Additional information
Group 11 REFERENCE SELECT	External reference source, type and scaling
Group 20 LIMITS	Operating limits
Group 22 ACCEL/DECEL	Speed reference acceleration/deceleration ramps
Group 24 TORQUE CONTROL	Torque reference ramp times
Group 32 SUPERVISION	Reference supervision

Actual signal	Additional information
0111/0112	REF1/REF2 reference
Group 03 FB ACTUAL SIGNALS	References in different stages of the reference processing chain

Reference trimming

In reference trimming, the external reference is corrected depending on the measured value of a secondary application variable. The block diagram below illustrates the function.



Settings

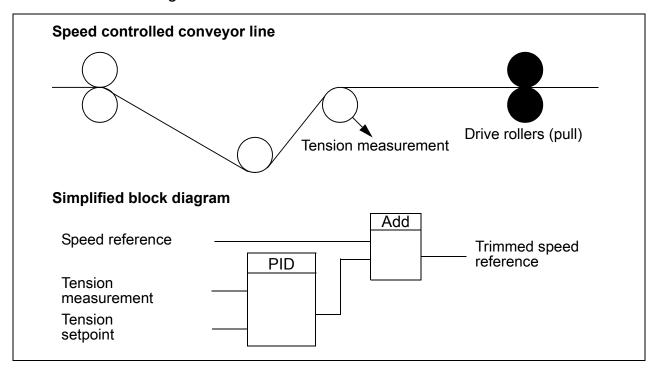
Parameter	Additional information
1102	REF1/2 selection
42304232	Trimming function settings
42014229	PID control settings
Group 20 LIMITS	Drive operation limits

Example

The drive runs a conveyor line. It is speed controlled but the line tension also needs to be taken into account: If the measured tension exceeds the tension setpoint, the speed will be slightly decreased, and vice versa.

To accomplish the desired speed correction, the user

- activates the trimming function and connects the tension setpoint and the measured tension to it.
- tunes the trimming to a suitable level.



Programmable analog inputs

The drive has two programmable analog voltage/current inputs. The inputs can be inverted, filtered and the maximum and minimum values can be adjusted. The update cycle for the analog input is 8 ms (12 ms cycle once per second). The cycle time is shorter when information is transferred to the application program (8 ms -> 2 ms).

Settings

Parameter	Additional information
Group 11 REFERENCE SELECT	Al as reference source
Group 13 ANALOG INPUTS	Analog input processing
3001, 3021, 3022, 3107	Al loss supervision
Group 35 MOTOR TEMP MEAS	Al in motor temperature measurement
Groups 40 PROCESS PID SET 1 42 EXT / TRIM PID	Al as PID process control reference or actual value source

Parameter	Additional information
8420, 8425, 8426	Al as Sequence programming reference or trigger
8430, 8435, 8436	signal
8490, 8495, 8496	

Diagnostics

Actual signal	Additional information
0120, 0121	Analog input values
1401	AI1/AI2 signal loss through RO 1
1402/1403/1410	AI1/AI2 signal loss through RO 24. With option MREL-01 only.
Alarm	
Al1 LOSS / Al2 LOSS	AI1/AI2 signal below limit 3021 AI1 FAULT LIMIT / 3022 AI2 FAULT LIMIT
Fault	
Al1 LOSS / Al2 LOSS	AI1/AI2 signal below limit 3021 AI1 FAULT LIMIT / 3022 AI2 FAULT LIMIT
PAR AI SCALE	Incorrect AI signal scaling (1302 < 1301 or 1305 < 1304)

Programmable analog output

One programmable current output (0...20 mA) is available. Analog output signal can be inverted, filtered and the maximum and minimum values can be adjusted. The analog output signals can be proportional to motor speed, output frequency, output current, motor torque, motor power, etc. The update cycle for the analog output is 2 ms.

Analog output can be controlled with Sequence programming. It is also possible to write a value to an analog output through a serial communication link.

Settings

Parameter	Additional information
Group 15 ANALOG OUTPUTS	AO value selection and processing
Group 35 MOTOR TEMP MEAS	AO in motor temperature measurement
8423/8433//8493	AO control with Sequence programming

Actual signal	Additional information
0124	AO value

Actual signal	Additional information
0170	AO control values defined by Sequence programming
Fault	
PAR AO SCALE	Incorrect AO signal scaling (1503 < 1502)

Programmable digital inputs

The drive has five programmable digital inputs. The update time for the digital inputs is 2 ms.

One digital input (DI5) can be programmed as a frequency input. See section Frequency input on page 138.

Settings

Parameter	Additional information
Group 10 START/STOP/DIR	DI as start, stop, direction
Group 11 REFERENCE SELECT	DI in reference selection, or reference source
Group 12 CONSTANT SPEEDS	DI in constant speed selection
Group 16 SYSTEM CONTROLS	DI as external Run enable, fault reset or user macro change signal
Group 19 TIMER & COUNTER	DI as timer or counter control signal source
2013, 2014	DI as torque limit source
2109	DI as external emergency stop command source
2201	DI as acceleration and deceleration ramp selection signal
2209	DI as zero ramp force signal
3003	DI as external fault source
Group 35 MOTOR TEMP MEAS	DI in motor temperature measurement
3601	DI as timed function enable signal source
3622	DI as booster activation signal source
4010/4110/4210	DI as PID controller reference signal source
4022/4122	DI as sleep function activation signal in PID1
4027	DI as PID1 parameter set 1/2 selection signal source
4228	DI as external PID2 function activation signal source
Group 84 SEQUENCE PROG	DI as Sequence programming control signal source

Actual signal	Additional information
0160	DI status
0414	DI status at the time the latest fault occurred

Programmable relay output

The drive has one programmable relay output. It is possible to add three additional relay outputs with the optional MREL-01 output relay module. For more information, see MREL-01 output relay module user's manual (3AUA0000035974 [English]).

With a parameter setting it is possible to choose what information to indicate through the relay output: Ready, running, fault, alarm, etc. The update time for the relay output is 2 ms.

A value can be written to a relay output through a serial communication link.

Settings

Parameter	Additional information
Group 14 RELAY OUTPUTS	RO value selections and operation times
8423	RO control with Sequence programming

Diagnostics

Actual signal	Additional information
0134	RO Control word through fieldbus control
0162	RO 1 status
0173	RO 24 status. With option MREL-01 only.

Frequency input

Digital input DI5 can be programmed as a frequency input. Frequency input (0...16000 Hz) can be used as the external reference signal source. The update time for the frequency input is 50 ms. Update time is shorter when information is transferred to the application program (50 ms -> 2 ms).

Settings

Parameter	Additional information
Group 18 FREQ IN & TRAN OUT	Frequency input minimum and maximum values and filtering
1103/1106	External reference REF1/2 through frequency input
4010, 4110, 4210	Frequency input as PID reference source

Actual signal	Additional information
0161	Frequency input value

Transistor output

The drive has one programmable transistor output. The output can be used either as a digital output or frequency output (0...16000 Hz). The update time for the transistor/frequency output is 2 ms.

Settings

Parameter	Additional information
Group 18 FREQ IN & TRAN OUT	Transistor output settings
8423	Transistor output control with Sequence programming

Diagnostics

Actual signal	Additional information
0163	Transistor output status
0164	Transistor output frequency

Actual signals

Several actual signals are available:

- Drive output frequency, current, voltage and power
- Motor speed and torque
- Intermediate circuit DC voltage
- Active control location (LOCAL, EXT1 or EXT2)
- Reference values
- Drive temperature
- Operating time counter (h), kWh counter
- Digital I/O and analog I/O status
- PID controller actual values.

Three signals can be shown simultaneously on the assistant control panel display (one signal on the basic control panel display). It is also possible to read the values through the serial communication link or through the analog outputs.

Settings

Parameter	Additional information
1501	Selection of an actual signal to AO
1808	Selection of an actual signal to frequency output
Group 32 SUPERVISION	Actual signal supervision
Group 34 PANEL DISPLAY	Selection of an actual signals to be displayed on the control panel

Diagnostics

Actual signal	Additional information
Groups 01 OPERATING DATA 04 FAULT HISTORY	Lists of actual signals

Motor identification

The performance of vector control is based on an accurate motor model determined during the motor start-up.

A motor Identification magnetization is automatically performed the first time the start command is given. During this first start-up, the motor is magnetized at zero speed for several seconds to allow the motor model to be created. This identification method is suitable for most applications.

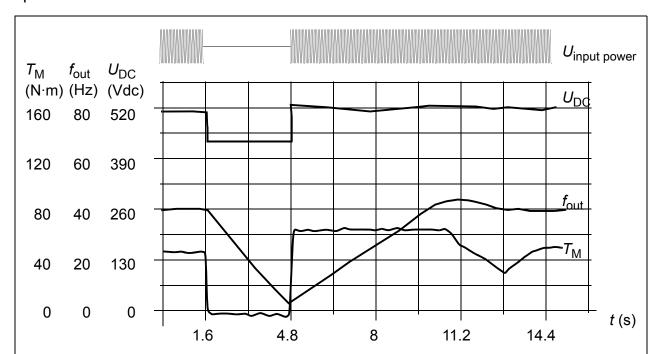
In demanding applications a separate Identification run (ID run) can be performed.

Settings

Parameter 9910 ID RUN

Power loss ride-through

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



 $U_{\rm DC}$ = Intermediate circuit voltage of the drive, $f_{\rm out}$ = Output frequency of the drive, $T_{\rm M}$ = Motor torque

Loss of supply voltage at nominal load ($f_{\rm out}$ = 40 Hz). The intermediate circuit DC voltage drops to the minimum limit. The controller keeps the voltage steady as long as the input power is switched off. The drive runs the motor in generator mode. The motor speed falls but the drive is operational as long as the motor has enough kinetic energy.

Settings

Parameter 2006 UNDERVOLT CTRL

DC magnetizing

When DC magnetizing is activated, the drive automatically magnetizes the motor before starting. This feature guarantees the highest possible break-away torque, up to 180% of the motor nominal torque. By adjusting the premagnetizing time, it is possible to synchronize the motor start and eg a mechanical brake release. The Automatic start feature and DC magnetizing cannot be activated at the same time.

Settings

Parameters 2101 START FUNCTION and 2103 DC MAGN TIME

Maintenance trigger

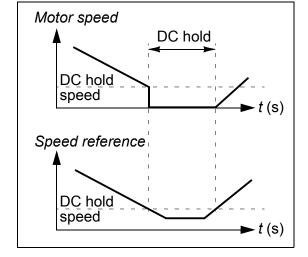
A maintenance trigger can be activated to show a notice on the panel display when eg drive power consumption has exceeded the defined trigger point.

Settings

Parameter group 29 MAINTENANCE TRIG

DC hold

With the motor DC hold feature, it is possible to lock the rotor at zero speed. When both the reference and the motor speed fall below the preset DC hold speed, the drive stops the motor and starts to inject DC into the motor. When the reference speed again exceeds the DC hold speed, the normal drive operation resumes.

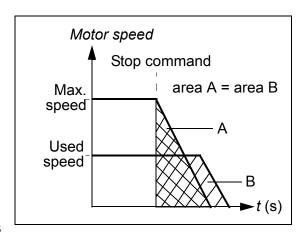


Settings

Parameters 2101...2106

Speed compensated stop

Speed compensation stop is available, for example, for applications where a conveyer needs to travel a certain distance after receiving the stop command. At maximum speed, the motor is stopped normally along the defined deceleration ramp. Below maximum speed, stop is delayed by running the drive at current speed before the motor is ramped to a stop. As shown in the figure, the distance travelled after the stop command is the same in both cases, that is, area A equals area B.



Speed compensation can be restricted to forward or reverse rotating direction.

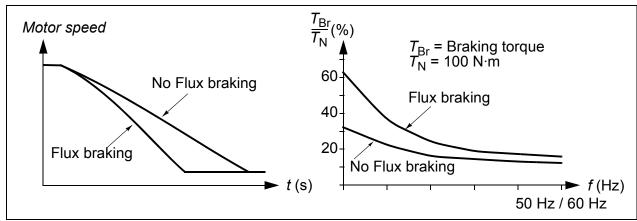
Note: The speed compensated stop feature is active only when the used speed is more than 10% of the maximum speed.

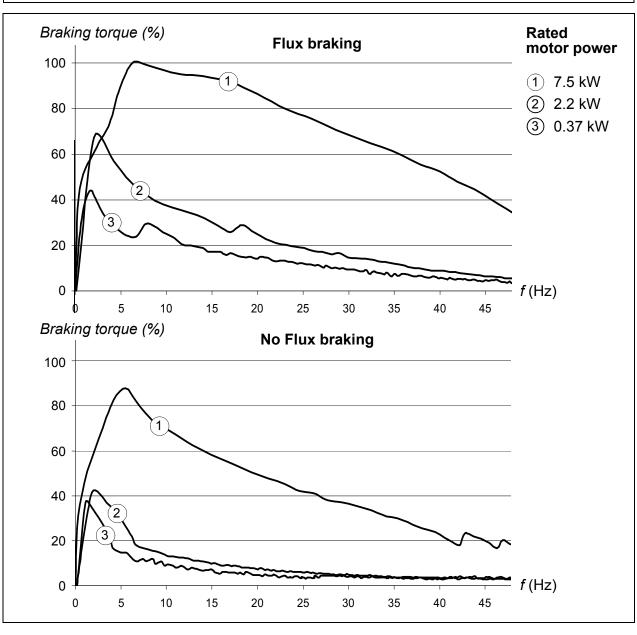
Settings

Parameter 2102 STOP FUNCTION

Flux braking

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





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

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

Settings

Parameter 2602 FLUX BRAKING

Flux optimization

Flux optimization reduces the total energy consumption and motor noise level when the drive operates below the nominal load. The total efficiency (motor and the drive) can be improved by 1% to 10%, depending on the load torque and speed.

Settings

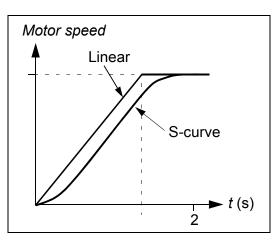
Parameter 2601 FLUX OPT ENABLE

Acceleration and deceleration ramps

Two user-selectable acceleration and deceleration ramps are available. It is possible to adjust the acceleration/deceleration times and the ramp shape. Switching between the two ramps can be controlled through a digital input or fieldbus.

The available ramp shape alternatives are Linear and S-curve.

Linear shape is suitable for drives requiring steady or slow acceleration/deceleration.



S-curve shape is ideal for conveyors carrying fragile loads, or other applications where a smooth transition is required when changing the speed.

Settings

Parameter group 22 ACCEL/DECEL

Sequence programming offers eight additional ramp times. See section *Sequence programming* on page *172*.

Critical speeds

Critical speeds function is available for applications where it is necessary to avoid certain motor speeds or speed bands because of eg mechanical resonance problems. The user can define three critical speeds or speed bands.

Settings

Parameter group 25 CRITICAL SPEEDS

Constant speeds

It is possible to define seven positive constant speeds. Constant speeds are selected with digital inputs. Constant speed activation overrides the external speed reference.

Constant speed selections are ignored if

- torque control is active, or
- PID reference is being followed, or
- drive is in local control mode.

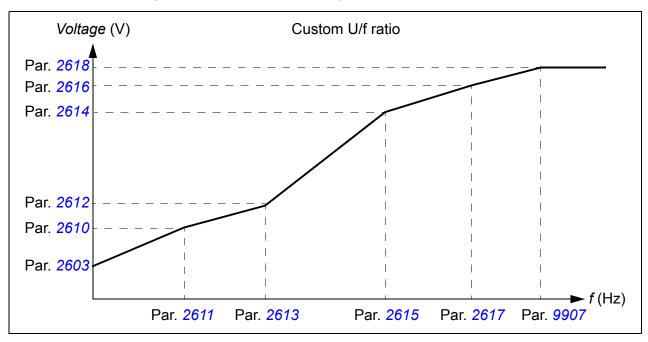
This function operates on a 2 ms time level.

Settings

Parameter	Additional information
Group 12 CONSTANT SPEEDS	Constant speed settings
1207	Constant speed 6. Used also for jogging function. See section <i>Jogging</i> on page <i>166</i> .
1208	Constant speed 7. Used also for fault functions (see group 30 FAULT FUNCTIONS) and for jogging function (see section Jogging on page 166).

Custom U/f ratio

The user can define a U/f curve (output voltage as a function of frequency). This custom ratio is used only in special applications where linear and squared U/f ratio are not sufficient (eg when motor break-away torque needs to be boosted).



Note: The U/f curve can be used in scalar control only, ie when 9904 MOTOR CTRL MODE setting is SCALAR: FREQ.

Note: The voltage and the frequency points of the U/f curve must fulfill the following requirements:



WARNING! High voltage at low frequencies may result in poor performance or motor damage (overheating).

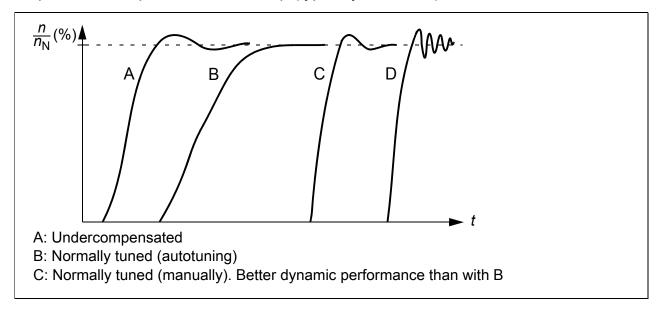
Settings

Parameter	Additional information	
2605	Custom U/f ratio activation	
26102618	Custom U/f ratio settings	

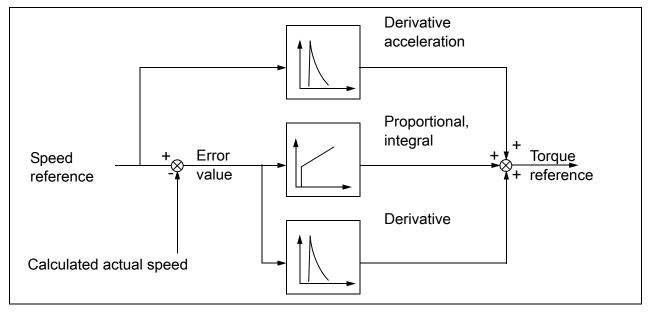
Fault	Additional information
PAR USER U/F	Incorrect U/f ratio

Speed controller tuning

It is possible to manually adjust the controller gain, integration time and derivation time, or let the drive perform a separate speed controller Autotune run (parameter 2305 AUTOTUNE RUN). In Autotune run, the speed controller is tuned based on the load and inertia of the motor and the machine. The figure below shows speed responses at a speed reference step (typically, 1 to 20%).



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



Note: The speed controller can be used in vector control, ie when 9904 MOTOR CTRL MODE setting is VECTOR: SPEED or VECTOR: TORQ.

Settings

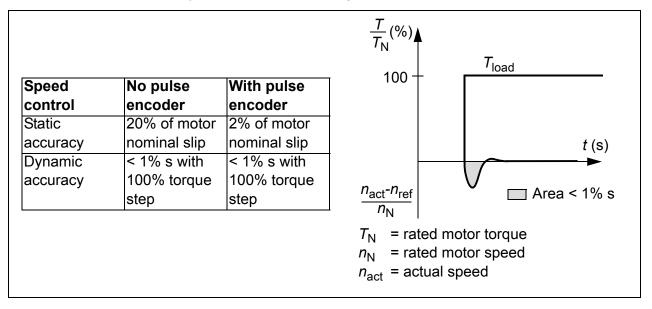
Parameter groups 23 SPEED CONTROL and 20 LIMITS

Diagnostics

Actual signal 0102 SPEED

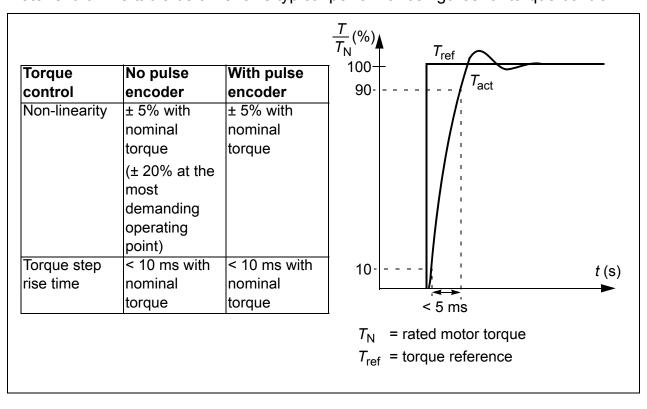
Speed control performance figures

The table below shows typical performance figures for speed control.



Torque control performance figures

The drive can perform precise torque control without any speed feedback from the motor shaft. The table below shows typical performance figures for torque control.



Scalar control

It is possible to select scalar control as the motor control method instead of vector control. In the scalar control mode, the drive is controlled with a frequency reference.

It is recommended to activate the scalar control mode in the following special applications:

- In multimotor drives: 1) if the load is not equally shared between the motors, 2) if the motors are of different sizes, or 3) if the motors are going to be changed after the motor identification.
- If the nominal motor current is less than 20% of the nominal output current of the drive.
- When the drive is used for test purposes with no motor connected.

The scalar control mode is not recommended for permanent magnet synchronous motors.

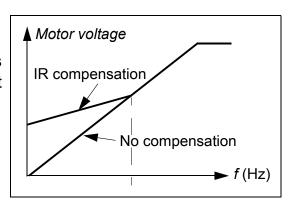
In the scalar control mode, some standard features are not available.

Settings

Parameter 9904 MOTOR CTRL MODE

IR compensation for a scalar controlled drive

IR compensation is active only when the motor control mode is scalar (see section Scalar control on page 149). When IR compensation is activated, the drive gives an extra voltage boost to the motor at low speeds. IR compensation is useful in applications that require high breakaway torque. In vector control, no IR compensation is possible/needed.



Settings

Parameter 2603 IR COMP VOLT

Programmable protection functions

AI<Min

Al<Min function defines the drive operation if an analog input signal falls below the set minimum limit.

Settings

Parameters 3001 AI<MIN FUNCTION, 3021 AI1 FAULT LIMIT and 3022 AI2 FAULT **LIMIT**

Panel loss

Panel loss function defines the operation of the drive if the control panel selected as the control location for the drive stops communicating.

Settings

Parameter 3002 PANEL COMM ERR

External fault

External faults (1 and 2) can be supervised by defining one digital input as a source for an external fault indication signal.

Settings

Parameters 3003 EXTERNAL FAULT 1 and 3004 EXTERNAL FAULT 2

Stall protection

The drive protects the motor in a stall situation. It is possible to adjust the supervision limits (frequency, time) and choose how the drive reacts to the motor stall condition (alarm indication / fault indication & drive stop / no reaction).

Settings

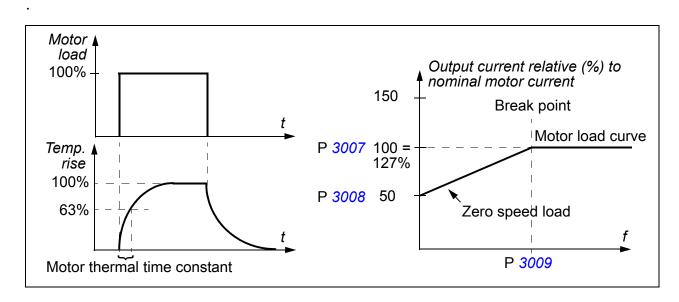
Parameters 3010 STALL FUNCTION, 3011 STALL FREQUENCY and 3012 STALL TIME

Motor thermal protection

The motor can be protected against overheating by activating the Motor thermal protection function.

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

- The motor is in the ambient temperature of 30 °C (86°F) when power is applied to the drive.
- Motor temperature is calculated using either the user-adjustable or automatically calculated motor thermal time constant and motor load curve (see the figures below). The load curve should be adjusted if the ambient temperature exceeds 30 °C (86°F).



Settings

Parameters 3005 MOT THERM PROT, 3006 MOT THERM TIME, 3007 MOT LOAD CURVE, 3008 ZERO SPEED LOAD and 3009 BREAK POINT FREQ

Note: It is also possible to use the motor temperature measurement function. See section Motor temperature measurement through the standard I/O on page 160.

Underload protection

Loss of motor load may indicate a process malfunction. The drive provides an underload function to protect the machinery and process in such a serious fault condition. Supervision limits - underload curve and underload time - can be specified as well as the action taken by the drive upon the underload condition (alarm indication / fault indication & drive stop / no reaction).

Settings

Parameters 3013 UNDERLOAD FUNC, 3014 UNDERLOAD TIME and 3015 UNDERLOAD CURVE

Earth fault protection

The Earth fault protection detects earth faults in the motor or motor cable. The protection can be selected to be active during start and run or during start only.

An earth fault in the input power line does not activate the protection.

Settings

Parameter 3017 EARTH FAULT

Incorrect wiring

Defines the operation when incorrect input power cable connection is detected.

Settings

Parameter 3023 WIRING FAULT

Input phase loss

Input phase loss protection circuits supervise the input power cable connection status by detecting intermediate circuit ripple. If a phase is lost, the ripple increases.

Settings

Parameter 3016 SUPPLY PHASE

Pre-programmed faults

Overcurrent

The overcurrent trip limit for the drive is 325% of the drive nominal current.

DC overvoltage

The DC overvoltage trip limit is 420 V (for 200 V drives) and 840 V (for 400 V drives).

DC undervoltage

The DC undervoltage trip limit is adaptive. See parameter 2006 UNDERVOLT CTRL.

Drive temperature

The drive supervises the IGBT temperature. There are two supervision limits: Alarm limit and fault trip limit.

Short-circuit

If a short-circuit occurs, the drive will not start and a fault indication is given.

Internal fault

If the drive detects an internal fault, the drive is stopped and a fault indication is given.

Operation limits

The drive has adjustable limits for speed, current (maximum), torque (maximum) and DC voltage.

Settings

Parameter group 20 LIMITS

Power limit

Power limitation is used to protect the input bridge and the DC intermediate circuit. If the maximum allowed power is exceeded, the drive torque is automatically limited. Maximum overload and continuous power limits depend on the drive hardware. For specific values, see chapter *Technical data* on page *371*.

Automatic resets

The drive can automatically reset itself after overcurrent, overvoltage, undervoltage, external and "analog input below a minimum" faults. The Automatic resets must be activated by the user.

Settings

Parameter	Additional information
Group 31 AUTOMATIC RESET	Automatic reset settings

Diagnostics

Alarm	Additional information
AUTORESET	Automatic reset alarm

Supervisions

The drive monitors whether certain user selectable variables are within the userdefined limits. The user may set limits for speed, current etc. The supervision status can be indicated through relay or digital output.

The supervision functions operate on a 2 ms time level.

Settings

Parameter group 32 SUPERVISION

Actual signal	Additional information
1401	Supervision status through RO 1
1402/1403/1410	Supervision status through RO 24. With option MREL-01 only.
1805	Supervision status through DO
8425, 8426 / 8435, 8436 //8495, 8496	Sequence programming state change according to supervision functions

Parameter lock

The user can prevent parameter adjustment by activating the parameter lock.

Settings

Parameters 1602 PARAMETER LOCK and 1603 PASS CODE

PID control

There are two built-in PID controllers in the drive:

- · Process PID (PID1) and
- External/Trim PID (PID2).

The PID controller can be used when the motor speed needs to be controlled based on process variables such as pressure, flow or temperature.

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

The control operates on a 2 ms time level.

Process controller PID1

PID1 has two separate sets of parameters (40 PROCESS PID SET 1, 41 PROCESS PID SET 2). Selection between parameter sets 1 and 2 is defined by a parameter.

In most cases when there is only one transducer signal wired to the drive, only parameter set 1 is needed. Two different parameter sets (1 and 2) are used eg when the load of the motor changes considerably in time.

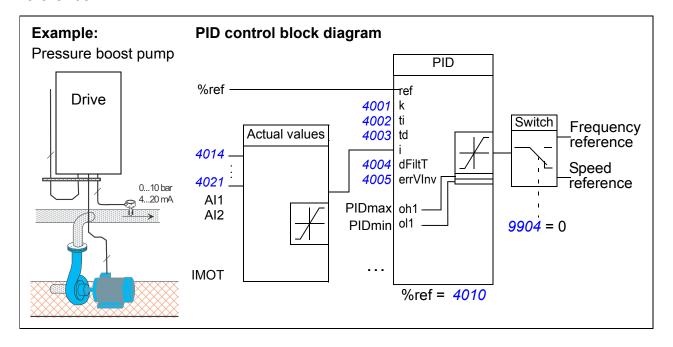
External/Trim controller PID2

PID2 (42 EXT / TRIM PID) can be used in two different ways:

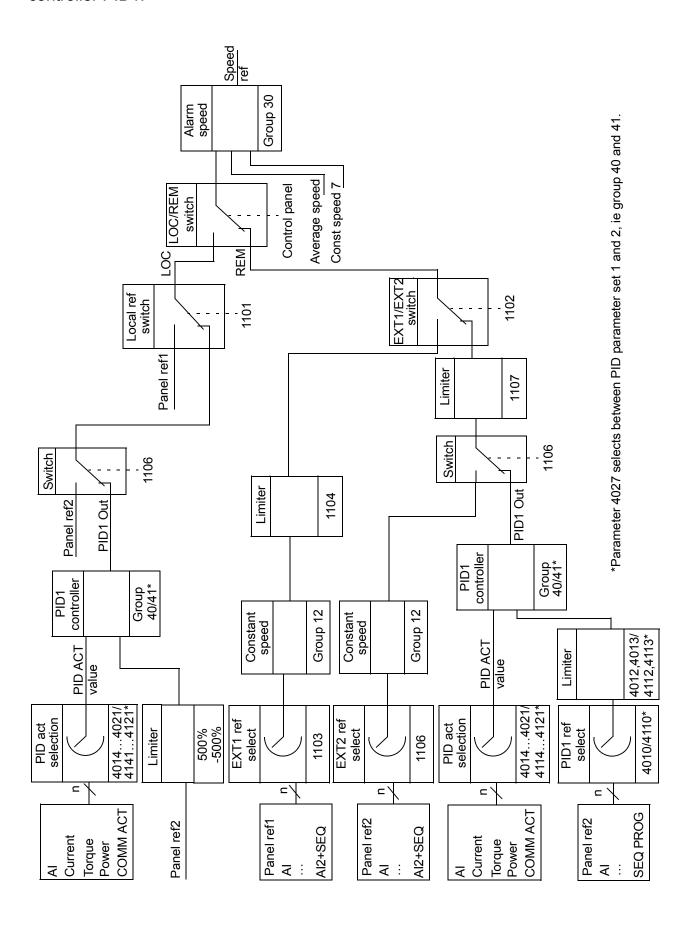
- External controller: Instead of using additional PID controller hardware, the user can connect PID2 output through drive analog output or fieldbus controller to control a field instrument like a damper or a valve.
- Trim controller: PID2 can be used to trim or fine tune the reference of the drive.
 See section Reference trimming on page 134.

Block diagrams

The figure below shows an application example: The controller adjusts the speed of a pressure boost pump according to the measured pressure and the set pressure reference.



The following figure presents the speed/scalar control block diagram for process controller PID1.



Settings

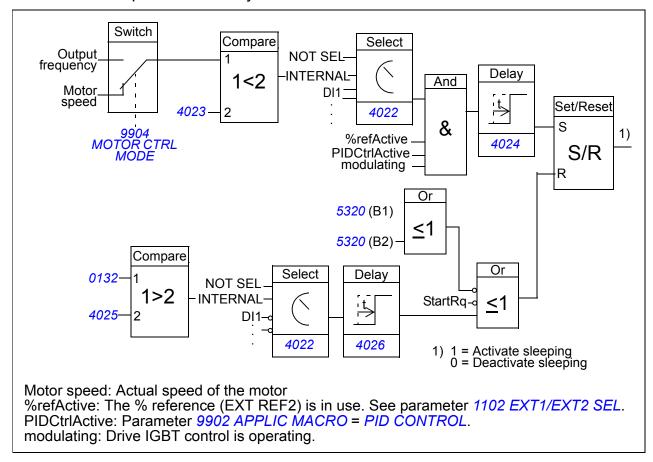
Parameter	Additional information
1101	Local control mode reference type selection
1102	EXT1/EXT2 selection
1106	PID1 activation
1107	REF2 minimum limit
1501	PID2 output (external controller) connection to AO
9902	PID control macro selection
Groups 40 PROCESS PID SET 141 PROCESS PID SET 2	PID1 settings
Group 42 EXT / TRIM PID	PID2 settings

Actual signal	Additional information
0126/0127	PID 1/2 output value
0128/0129	PID 1/2 setpoint value
0130/0131	PID 1/2 feedback value
0132/0133	PID 1/2 deviation
0170	AO value defined by Sequence programming

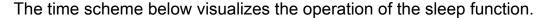
Sleep function for the process PID (PID1) control

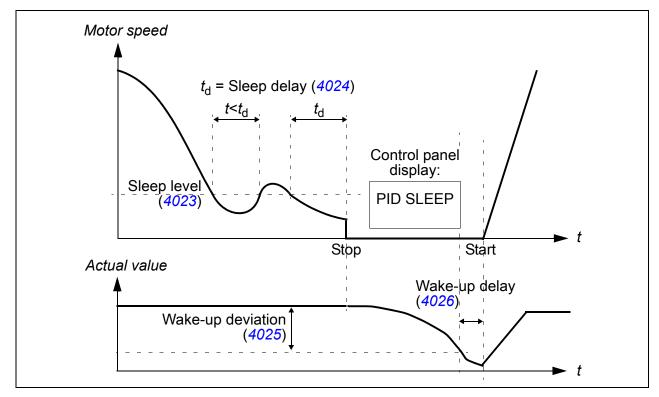
The sleep function operates on a 2 ms time level.

The block diagram below illustrates the sleep function enable/disable logic. The sleep function can be put into use only when the PID control is active.



Example





Sleep function for a PID controlled pressure boost pump (when parameter 4022 SLEEP SELECTION is set to INTERNAL): The water consumption falls at night. As a consequence, the PID process controller decreases the motor speed. However, due to natural losses in the pipes and the low efficiency of the centrifugal pump at low speeds, the motor does not stop but keeps rotating. The sleep function detects the slow rotation, and stops the unnecessary pumping after the sleep delay has passed. The drive shifts into sleep mode, still monitoring the pressure. The pumping restarts when the pressure falls under the allowed minimum level and the wake-up delay has passed.

Settings

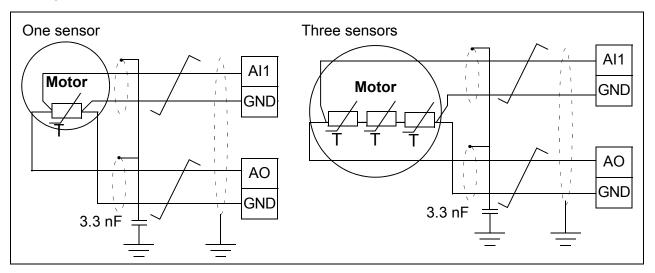
Parameter	Additional information
9902	PID control activation
40224026, 41224126	Sleep function settings

Parameter	Additional information
1401	PID sleep function status through RO 1
1402/1403/1410	PID sleep function status through RO 24. With option MREL-01 only.
Alarm	Additional information
PID SLEEP	Sleep mode

Motor temperature measurement through the standard I/O

This section describes the temperature measurement of one motor when the drive I/O terminals are used as the connection interface.

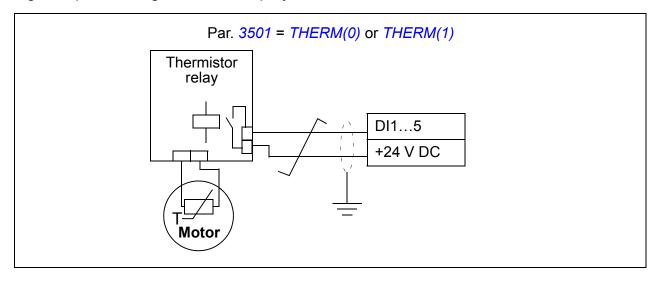
Motor temperature can be measured using Pt100 or PTC sensors connected to analog input and output.



WARNING! According to IEC 664, the connection of the motor temperature sensor requires double or reinforced insulation between motor live parts and the sensor. Reinforced insulation entails a clearance and creepage distance of 8 mm (0.3 in) (400/500 V AC equipment).

If the assembly does not fulfill the requirement, the I/O board terminals must be protected against contact and they may not be connected to other equipment, or the temperature sensor must be isolated from the I/O terminals.

It is also possible to monitor motor temperature by connecting a PTC sensor and a thermistor relay between the +24 V DC voltage supply offered by the drive and a digital input. The figure below displays the connection.



WARNING! According to IEC 664, the connection of the motor thermistor to the digital input requires double or reinforced insulation between motor live parts and the thermistor. Reinforced insulation entails a clearance and creeping distance of 8 mm (0.3 in) (400/500 V AC equipment).

If the thermistor assembly does not fulfill the requirement, the other I/O terminals of the drive must be protected against contact, or a thermistor relay must be used to isolate the thermistor from the digital input.

Settings

Parameter	Additional information
Group 13 ANALOG INPUTS	Analog input settings
Group 15 ANALOG OUTPUTS	Analog output settings
Group 35 MOTOR TEMP MEAS	Motor temperature measurement settings
Other	

At the motor end the cable shield should be grounded through, eg a 3.3 nF capacitor. If this is not possible, the shield is to be left unconnected.

Actual signal	Additional information
0145	Motor temperature
Alarm/Fault	Additional information
MOTOR TEMP/MOT OVERTEMP	Excessive motor temp

Control of a mechanical brake

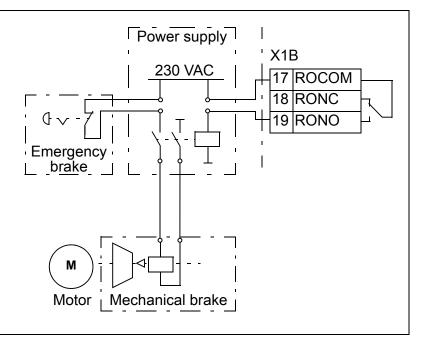
The mechanical brake is used for holding the motor and driven machinery at zero speed when the drive is stopped, or not powered.

Example

The figure below shows a brake control application example.

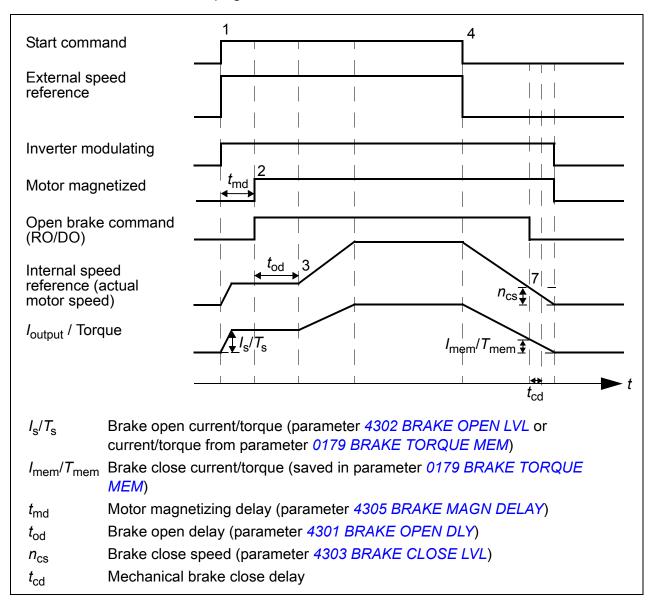
WARNING! Make sure that the machinery into which the drive with brake control function is integrated fulfills the personnel safety regulations. Note that the frequency converter (a Complete Drive Module or a Basic Drive Module, as defined in IEC 61800-2), is not considered a safety device mentioned in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

Brake control logic is integrated in the drive application program. The user has to take care of the power supply and wiring.
Brake on/off control is through relay output RO.

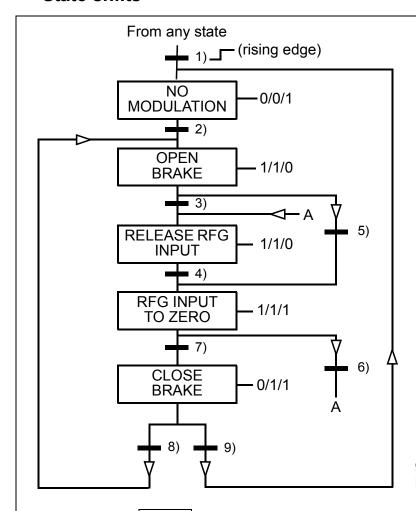


Operation time scheme

The time scheme below illustrates the operation of the brake control function. See also section State shifts on page 164.



State shifts



RFG = Ramp function generator in the speed control loop (reference handling).

State (Symbol NN — X/Y/Z)

- NN: State name
- X/Y/Z: State outputs/operations
 - X = 1 Open the brake. The relay output set to brake on/off control energizes.
 - Y = 1 Forced start. The function keeps the internal Start on until the brake is closed in spite of the status of the external Start signal.
- Z = 1 Ramp in zero. Forces the used speed reference (internal) to zero along a ramp. State change conditions (Symbol ——)
- 1) Brake control active 0 -> 1 OR Inverter is modulating = 0
- 2) Motor magnetised = 1 AND Drive running = 1
- 3) Brake is open AND Brake open delay passed AND Start = 1
- 4) Start = 0
- 5) Start = 0
- 6) Start = 1
- 7) Actual motor speed < Brake close speed AND Start = 0
- 8) Start = 1
- 9) Brake is closed AND Brake close delay passed = 1 AND Start = 0

Settings

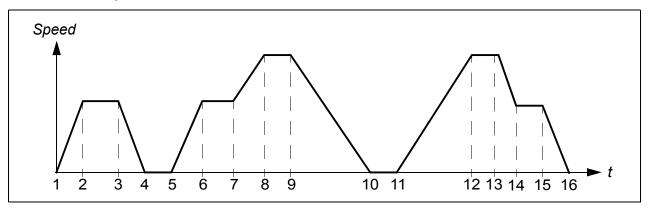
Parameter	Additional information
1401/1805	Mechanical brake activation through RO 1 / DO
1402/1403/1410	Mechanical brake activation through RO 24. With option MREL-01 only.
2112	Zero speed delay
Group 43 MECH BRK CONTROL	Brake function settings

Jogging

The jogging function is typically used to control a cyclical movement of a machine section. One push button controls the drive through the whole cycle: When it is on, the drive starts, accelerates to a preset speed at a preset rate. When it is off, the drive decelerates to zero speed at a preset rate.

The figure and table below describe the operation of the drive. They also represent how the drive shifts to normal operation (= jogging inactive) when the drive start command is switched on. Jog cmd = State of the jogging input, Start cmd = State of the drive start command.

The function operates on a 2 ms time level



Phase	Jog cmd	Start cmd	Description
1-2	1	0	Drive accelerates to the jogging speed along the acceleration ramp of the jogging function.
2-3	1	0	Drive runs at the jogging speed.
3-4	0	0	Drive decelerates to zero speed along the deceleration ramp of the jogging function.
4-5	0	0	Drive is stopped.
5-6	1	0	Drive accelerates to the jogging speed along the acceleration ramp of the jogging function.
6-7	1	0	Drive runs at the jogging speed.
7-8	Х	1	Normal operation overrides the jogging. Drive accelerates to the speed reference along the active acceleration ramp.
8-9	Х	1	Normal operation overrides the jogging. Drive follows the speed reference.
9-10	0	0	Drive decelerates to zero speed along the active deceleration ramp.
10-11	0	0	Drive is stopped.
11-12	Х	1	Normal operation overrides the jogging. Drive accelerates to the speed reference along the active acceleration ramp.
12-13	Х	1	Normal operation overrides the jogging. Drive follows the speed reference.
13-14	1	0	Drive decelerates to the jogging speed along the deceleration ramp of the jogging function.
14-15	1	0	Drive runs at the jogging speed.
15-16	0	0	Drive decelerates to zero speed along the deceleration ramp of the jogging function.

x =state can be either 1 or 0

Note: The jogging is not operational when the drive start command is on.

Note: The jogging speed overrides the constant speeds.

Note: The jogging uses ramp stop even if parameter 2102 STOP FUNCTION selection is COAST.

Note: The ramp shape time is set to zero during the jogging (ie linear ramp).

Jogging function uses constant speed 7 as jogging speed and acceleration/deceleration ramp pair 2.

It is also possible to activate jogging function 1 or 2 through fieldbus. Jogging function 1 uses constant speed 7 and jogging function 2 uses constant speed 6. Both functions use acceleration/deceleration ramp pair 2.

Settings

Parameter	Additional information
1010	Jogging activation
1208	Jogging speed
1208/1207	Jogging speed for jogging function 1/2 activated through fieldbus
2112	Zero speed delay
2205, 2206	Acceleration and deceleration times
2207	Acceleration and deceleration ramp shape time: Set to zero during the jogging (ie linear ramp).

Actual signal	Additional information
0302	Jogging 1/2 activation through fieldbus
1401	Jogging function status through RO 1
1402/1403/1410	Jogging function status through RO 24. With option MREL-01 only.
1805	Jogging function status through DO

Real-time clock and timed functions

Real-time clock

The real-time clock has the following features:

- · four daily times
- four weekly times
- timed boost function, eg a constant speed which is on for a certain preprogrammed time.
- · timer enable with digital inputs
- timed constant speed selection
- timed relay activation.

For more information, see Group 36 TIMED FUNCTIONS on page 268.

Note: To be able to use the timed functions, the internal clock has to be set first. For information on the Time and date mode, see section *Time and date mode* on page 104.

Note: The timed functions work only when the assistant control panel is connected to the drive.

Note: Removing the control panel for upload/download purposes does not affect the clock.

Note: Daylight saving changeover is automatic if activated.

Timed functions

A variety of drive functions can be time controlled, eg start/stop and EXT1/EXT2 control. The drive offers

- four start and stop times (START TIME 1...START TIME 4, STOP TIME 1...STOP TIME 4)
- four start and stop days (START DAY 1...START DAY 4, STOP DAY 1...STOP DAY 4)
- four timed functions for collecting the selected time periods 1...4 together (TIMED FUNC 1 SRC...TIMED FUNC 4 SRC)
- booster time (an additional booster time connected to timed functions).

Configuring the timed functions

You can use the Timed functions assistant for easy configuring. For more information on the assistants, see section *Assistants mode* on page *100*.

Use the control panel to configure the timer in four stages:

1. Enable the timer.

Configure how the timer is activated. The timer can be enabled from one of the digital inputs or inverted digital inputs.

2. Set the time period.

Define the start and stop times and start and stop day when the timer operates. These constitute a time period.

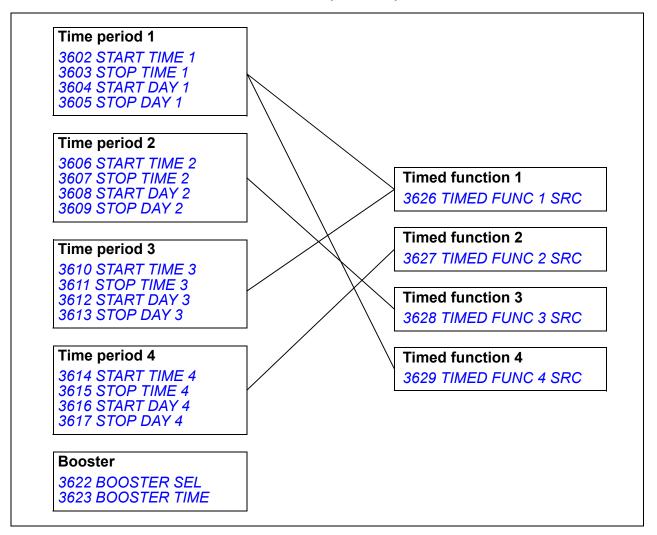
Create the timer.

Assign the selected time period to certain timer(s). Different time periods can be collected in a timer and connected to parameters. The timer can act as the source of start/stop and change direction commands, constant speed selection and relay activation signals. Time periods can be in multiple timed functions, but a parameter can only be connected to a single timer. It is possible to create up to four timers.

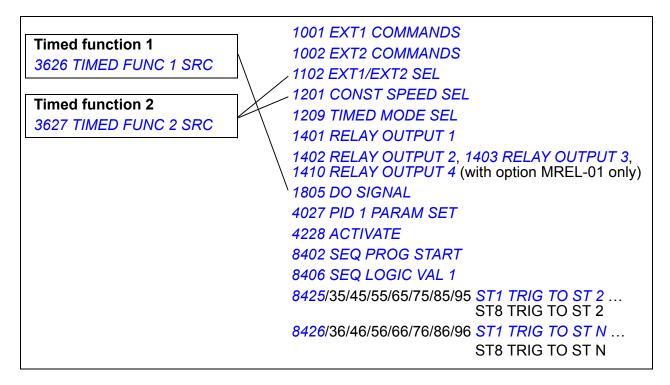
4. Connect selected parameters to the timer.

A parameter can only be connected to one timer.

A timed function can be connected to multiple time periods.



A parameter which is triggered by a timed function can be connected to only one timed function at a time.



Example

Air conditioning is active on weekdays from 8:00 to 15:30 (8 a.m to 3:30 p.m) and on Sundays from 12:00 to 15:00 (12 to 3 p.m). By pressing the extension time switch, the air-conditioning is on for an extra hour.

Parameter	Setting
3601 TIMERS ENABLE	DI1
3602 START TIME 1	08:00:00
3603 STOP TIME 1	15:30:00
3604 START DAY 1	MONDAY
3605 STOP DAY 1	FRIDAY
3606 START TIME 2	12:00:00
3607 STOP TIME 2	15:00:00
3608 START DAY 2	SUNDAY
3609 STOP DAY 2	SUNDAY
3622 BOOSTER SEL	DI5 (cannot be the same as parameter 3601 value)
3623 BOOSTER TIME	01:00:00
3626 TIMED FUNC 1 SRC	T1+T2+B

Settings

Parameter	Additional information
36 TIMED FUNCTIONS	Timed functions settings
1001, 1002	Timed start/stop control
1102	Timed EXT1/EXT2 selection
1201	Timed constant speed 1 activation
1209	Timed speed selection
1401	Timed function status indicated through relay output RO 1
1402/1403/1410	Timed function status indicated through relay output RO 24. With option MREL-01 only.
1805	Timed function status indicated through digital output DO
4027	Timed PID1 parameter set 1/2 selection
4228	Timed external PID2 activation
8402	Timed Sequence programming activation
8425/8435//8495 8426/8436//8496	Sequence programming state change trigger with timed function

Timer

Drive start and stop can be controlled with timer functions.

Settings

Parameter	Additional information
1001, 1002	Start/stop signal sources
Group 19 TIMER & COUNTER	Timer for start and stop

Diagnostics

Actual signal	Additional information
0165	Start/stop control time count

Counter

Drive start and stop can be controlled with counter functions. The counter function can also be used as state change trigger signal in Sequence programming. See section Sequence programming on page 172.

Settings

Parameter	Additional information
1001, 1002	Start/Stop signal sources
Group 19 TIMER & COUNTER	Timer for start and stop

Parameter	Additional information
8425, 8426 / 8435, 8436 //8495, 8496	Counter signal as state change trigger in Sequence programming

Diagnostics

Actual signal	Additional information
0166	Start/stop control pulse count

Sequence programming

The drive can be programmed to perform a sequence where the drive shifts typically through 1...8 states. User defines the operation rules for the whole sequence and for each state. The rules of a particular state are effective when the Sequence program is active and the program has entered the state. The rules to be defined for each state are:

- Run, stop and direction commands for the drive (forward/reverse/stop)
- Acceleration and deceleration ramp time for the drive
- Source for the drive reference value
- State duration
- RO/DO/AO status
- Signal source for triggering the shift to the next state
- Signal source for triggering the shift to any state (1...8).

Every state can also activate drive outputs to give an indication to external devices.

Sequence programming allows state transitions either to the next state or to a selected state. State change can be activated with eg timed functions, digital inputs and supervision functions.

Sequence programming can be applied in simple mixer applications as well as in more complicated traverse applications.

The programming can be done with control panel or with a PC tool. The drive is supported by version 2.91 or later of the DriveWindow Light 2 PC tool which includes a graphical Sequence programming tool.

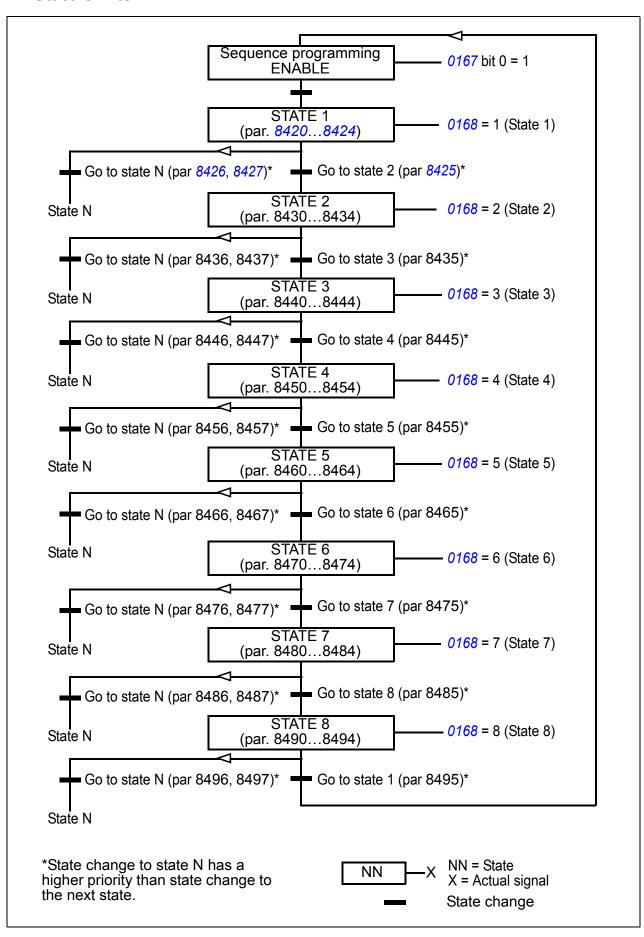
Note: By default all Sequence programming parameters can be changed even when the Sequence programming is active. It is recommended that after the Sequence programming parameters are set, parameters are locked with parameter *1602 PARAMETER LOCK*.

Settings

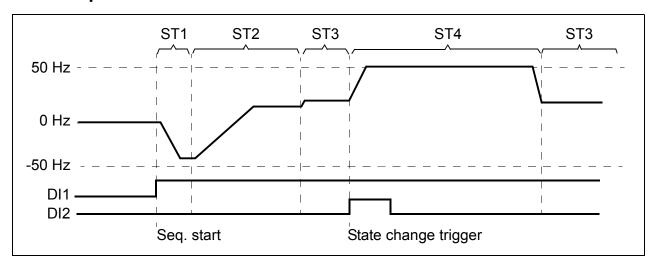
Parameter	Additional information
1001/1002	Start, stop and direction commands for EXT1/EXT2
1102	EXT1/EXT2 selection
1106	REF2 source
1201	Constant speed deactivation. Constant speed always overrides the Sequence programming reference.
1401	Sequence programming output through RO 1
1402/1403/1410	Sequence programming output through relay output RO 24. With option MREL-01 only.
1501	Sequence programming output through AO
1601	Run enable activation/deactivation
1805	Sequence programming output through DO
Group 19 TIMER & COUNTER	State change according to counter limit
Group 32 SUPERVISION	Timed state change
22012207	Acceleration/deceleration and ramp time settings
Group 32 SUPERVISION	Supervision settings
4010/4110/4210	Sequence programming output as PID reference signal
Group 84 SEQUENCE PROG	Sequence programming settings

Actual signal	Additional information
0167	Sequence programming status
0168	Sequence programming active state
0169	Current state time counter
0170	Analog output PID reference control values
0171	Executed sequence counter

State shifts



Example 1



Sequence programming is activated by digital input DI1.

ST1: Drive is started in reverse direction with -50 Hz reference and 10 s ramp time. State 1 is active for 40 s.

ST2: Drive is accelerated to 20 Hz with 60 s ramp time. State 2 is active for 120 s.

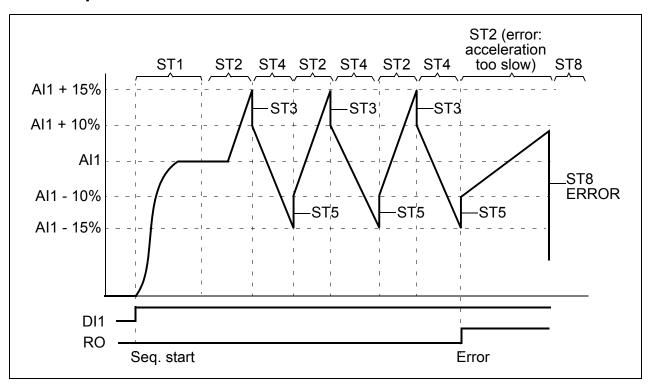
ST3: Drive is accelerated to 25 Hz with 5 s ramp time. State 3 is active until the Sequence programming is disabled or until booster start is activated by DI2.

ST4: Drive is accelerated to 50 Hz with 5 s ramp time. State 4 is active for 200 s and after that the state shifts back to state 3.

Parameter	Setting	Additional information
1002 EXT2 COMMANDS	SEQ PROG	Start, stop, direction commands for EXT2
1102 EXT1/EXT2 SEL	EXT2	EXT2 activation
1106 REF2 SELECT	SEQ PROG	Sequence programming output as REF2
1601 RUN ENABLE	NOT SEL	Deactivation of Run enable
2102 STOP FUNCTION	RAMP	Ramp stop
2201 ACC/DEC 1/2 SEL	SEQ PROG	Ramp as defined by parameter 8422//8452.
8401 SEQ PROG ENABLE	ALWAYS	Sequence programming enabled
8402 SEQ PROG START	DI1	Sequence programming activation through digital input (DI1)
8404 SEQ PROG RESET	DI1(INV)	Sequence programming reset (ie reset to state 1, when DI1 signal is lost (1 -> 0)

ST1			ST2		ST3	ST4		Additional
Par.	Setting	Par.	Setting	Par.	Setting	Par.	Setting	information
8420 ST1 REF SEL	100%	8430	40%	8440	50%	8450	100%	State reference
8421 ST1 COMMANDS	START REV	8431	START FRW	8441	START FRW	8451	START FRW	Run, direction and stop command
8422 ST1 RAMP	10 s	8432	60 s	8442	5 s	8452	5 s	Ramp time
8424 ST1 CHANGE DLY	40 s	8434	120 s	8444		8454	200 s	State change delay
8425 ST1 TRIG TO ST 2	CHANG E DLY	8435	CHANG E DLY	8445	DI2	8455		
8426 ST1 TRIG TO ST N	NOT SEL	8436	NOT SEL	8446	NOT SEL	8456	CHANG E DLY	State change trigger
8427 ST1 STATE N	-	8437	-	8447	-	8457	STATE 3	

Example 2



Drive is programmed for traverse control with 30 sequences.

Sequence programming is activated by digital input DI1

ST1: Drive is started in forward direction with Al1 (Al1 + 50% - 50%) reference and ramp pair 2. State shifts to the next state when reference is reached. All relay and analog outputs are cleared.

- ST2: Drive is accelerated with Al1 + 15% (Al1 + 65% 50%) reference and 1.5 s ramp time. State shifts to the next state when reference is reached. If reference is not reached within 2 s, state shifts to state 8 (error state).
- ST3: Drive is decelerated with Al1 + 10% (Al1 + 60% 50%) reference and 0 s ramp time¹⁾. State shifts to the next state when reference is reached. If reference is not reached within 0.2 s, state shifts to state 8 (error state).
- ST4: Drive is decelerated with AI1 15% (AI1 + 35% -50%) reference and 1.5 s ramp time. State shifts to the next state when reference is reached. If reference is not reached within 2 s, state shifts to state 8 (error state).²⁾
- ST5: Drive is accelerated with Al1 -10% (Al1 + 40% -50%) reference and 0 s ramp time¹⁾. State shifts to the next state when reference is reached. Sequence counter value is increased by 1. If sequence counter elapses, state shifts to state 7 (sequence completed).
- ST6: Drive reference and ramp times are the same as in state 2. Drive state shifts immediately to state 2 (delay time is 0 s).
- ST7 (sequence completed): Drive is stopped with ramp pair 1. Digital output DO is activated. If Sequence programming is deactivated by the falling edge of digital input DI1, state machine is reset to state 1. New start command can be activated by digital input DI1 or by digital inputs DI4 and DI5 (both inputs DI4 and DI5 must be simultaneously active).
- ST8 (error state): Drive is stopped with ramp pair 1. Relay output RO is activated. If Sequence programming is deactivated by the falling edge of digital input DI1, state machine is reset to state 1. New start command can be activated by digital input DI1 or by digital inputs DI4 and DI5 (both inputs DI4 and DI5 must be simultaneously active).
- 1) 0 second ramp time = drive is accelerated/decelerated as rapidly as possible.
- 2) State reference must be between 0...100%, ie scaled Al1 value must be between 15...85%. If Al1 = 0, reference = 0% + 35% - 50% = -15% < 0%.

Parameter	Setting	Additional information
1002 EXT2 COMMANDS	SEQ PROG	Start, stop, direction commands for EXT2
1102 EXT1/EXT2 SEL	EXT2	EXT2 activation
1106 REF2 SELECT	AI1+SEQ PROG	Sequence programming output as REF2
1201 CONST SPEED SEL	NOT SEL	Deactivation of constant speeds
1401 RELAY OUTPUT 1	SEQ PROG	Relay output RO 1 control as defined by parameter 8423//8493
1601 RUN ENABLE	NOT SEL	Deactivation of Run enable
1805 DO SIGNAL	SEQ PROG	Digital output DO control as defined by parameter 8423//8493
2102 STOP FUNCTION	RAMP	Ramp stop
2201 ACC/DEC 1/2 SEL	SEQ PROG	Ramp as defined by parameter 8422//8452.
2202 ACCELER TIME 1	1 s	Acceleration/deceleration ramp pair 1
2203 DECELER TIME 1	0 s	
2205 ACCELER TIME 2	20 s	Acceleration/deceleration ramp pair 2
2206 DECELER TIME 2	20 s	
2207 RAMP SHAPE 2	5 s	Shape of the acceleration/deceleration ramp 2
3201 SUPERV 1 PARAM	171	Sequence counter (signal 0171 SEQ CYCLE CNTR) supervision
3202 SUPERV 1 LIM LO	30	Supervision low limit
3203 SUPERV 1 LIM HI	30	Supervision high limit
8401 SEQ PROG ENABLE	EXT2	Sequence programming enabled
8402 SEQ PROG START	DI1	Sequence programming activation through digital input (DI1)
8404 SEQ PROG RESET	DI1(INV)	Sequence programming reset (ie reset to state 1, when DI1 signal is lost (1 -> 0)
8406 SEQ LOGIC VAL 1	DI4	Logic value 1
8407 SEQ LOGIC OPER 1	AND	Operation between logic value 1 and 2
8408 SEQ LOGIC VAL 2	DI5	Logic value 2
8415 CYCLE CNT LOC	ST5 TO NEXT	Sequence counter activation, ie sequence count increases every time the state changes from state 5 to state 6.
8416 CYCLE CNT RST	STATE 1	Sequence counter reset during state transition to state 1

ST1			ST2		ST3	ST4		Additional
Par.	Setting	Par.	Setting	Par.	Setting	Par.	Setting	information
8420 ST1 REF SEL	50%	8430	65%	8440	60%	8450	35%	State reference
8421 ST1 COMMANDS	START FRW	8431	START FRW	8441	START FRW	8451	START FRW	Run, direction and stop commands
8422 ST1 RAMP	-0.2 (ramp pair 2)	8432	1.5 s	8442	0 s	8452	1.5 s	Acceleration/ deceleration ramp time
8423 ST1 OUT CONTROL	R=0,D=0 ,AO=0	8433	AO=0	8443	AO=0	8453	AO=0	Relay, digital and analog output control
8424 ST1 CHANGE DLY	0 s	8434	2 s	8444	0.2 s	8454	2 s	State change delay
8425 ST1 TRIG TO ST 2	ENTER SETPNT	8435	ENTER SETPNT	8445	ENTER SETPNT	8455	ENTER SETPNT	
8426 ST1 TRIG TO ST N	NOT SEL	8436	CHANG E DLY	8446	CHANG E DLY	8456	CHANG E DLY	State change trigger
8427 ST1 STATE N	STATE 1	8437	STATE 8	8447	STATE 8	8457	STATE 8	

ST5			ST6		ST7	ST8		Additional
Par.	Setting	Par.	Setting	Par.	Setting	Par.	Setting	information
8460 ST5 REF SEL	40%	8470	65%	8480	0%	8490	0%	State reference
8461 ST5 COMMANDS	START FRW	8471	START FRW	8481	DRIVE STOP	8491	DRIVE STOP	Run, direction and stop commands
8462 ST5 RAMP	0 s	8472	1.5 s	8482	-0.1 (ramp pair 1)	8492	-0.1 (ramp pair 1)	Acceleration/ deceleration ramp time
8463 ST5 OUT CONTROL	AO=0	8473	AO=0	8483	DO=1	8493	RO=1	Relay, digital and analog output control

ST5			ST6		ST7	ST8		Additional
Par.	Setting	Par.	Setting	Par.	Setting	Par.	Setting	information
8464 ST5 CHANGE DLY	0.2 s	8474	0 s	8484	0 s	8494	0 s	State change delay
8465 ST5 TRIG TO ST6	ENTER SETPNT	8475	NOT SEL	8485	NOT SEL	8495	LOGIC VAL	
8466 ST5 TRIG TO ST N	SUPRV1 OVER	8476	CHANG E DLY	8486	LOGIC VAL	8496	NOT SEL	State change trigger
8467 ST5 STATE N	STATE 7	8477	STATE 2	8487	STATE 1	8497	STATE 1	

Safe torque off (STO) function

See Appendix: Safe torque off (STO) on page 411.



Actual signals and parameters

What this chapter contains

The chapter describes the actual signals and parameters and gives the fieldbus equivalent values for each signal/parameter. It also contains a table of the default values for the different macros.

Terms and abbreviations

Term	Definition
Actual signal	Signal measured or calculated by the drive. Can be monitored by the user. No user setting possible. Groups 0104 contain actual signals.
Def	Parameter default value
Parameter	A user-adjustable operation instruction of the drive. Groups 1099 contain parameters.
	Note: Parameter selections are shown on the basic control panel as integer values. Eg parameter <i>1001 EXT1 COMMANDS</i> selection <i>COMM</i> is shown as value 10 (which is equal to the fieldbus equivalent FbEq).
FbEq	Fieldbus equivalent: The scaling between the value and the integer used in serial communication.
E	Refers to types 01E- and 03E- with European parametrization
U	Refers to types 01U- and 03U- with US parametrization

Fieldbus addresses

For FCAN-01 CANopen adapter, FDNA-01 DeviceNet adapter, FECA-01 EtherCAT adapter, FENA-01 Ethernet adapter, FMBA-01 Modbus adapter, FLON-01 LonWorks® adapter, and FPBA-01 PROFIBUS DP adapter, see the user's manual of the adapter.

Fieldbus equivalent

Example: If 2017 MAX TORQUE 1 (see page 225) is set from an external control system, an integer value of 1000 corresponds to 100.0%. All the read and sent values are limited to 16 bits (-32768...32767).

Storing the parameters

All parameter settings are stored automatically to the permanent memory of the drive. However, if an external +24 V DC power supply is used for the drive control unit, it is highly recommended to force a save using parameter 1607 PARAM SAVE before powering down the control unit after any parameter changes.

Default values with different macros

When the application macro is changed (parameter 9902 APPLIC MACRO), the software updates the parameter values to their default values. The table below shows the parameter default values for different macros. For other parameters, the default values are the same for all macros (shown in the parameter list starting on page 192).

If you have made changes to the parameter values and want to restore the default values, you must first select another macro (parameter 9902 APPLIC MACRO), save the change, select the original marco again and save. This restores the default parameter values of the original macro.

The default values for the AC500 Modbus application macro correspond to the ABB Standard macro with some differences, see section AC500 Modbus macro on page 121.

Index	Name/	ABB	3-WIRE	ALTERNA	MOTOR	HAND/	PID	TORQUE
	Selection	STANDARD		TE	POT	AUTO	CONTROL	CONTROL
9902	APPLIC	1 =	2=	3 =	4 =	5 =	6 =	7 =
	MACRO	ABB	3-WIRE	ALTERNAT	MOTOR	HAND/AUT	PID	TORQUE
		STANDARD		E	POT	0	CONTROL	CTRL
1001	EXT1	2 = D11, 2	4 =	9 = DI1F, 2R	2 = DI1, 2	2 = DI1, 2	20 = <i>DI5</i>	2 = DI1, 2
	COMMANDS		DI1P,2P,3					
1002	EXT2	0 = NOT	0 = NOT	0 = NOT	0 = NOT	21 = D15,4	1 = <i>DI1</i>	2 = DI1, 2
	COMMANDS	SEL	SEL	SEL	SEL			
1003	DIRECTION	3 =	3 =	3 =	3 =	3 =	1 =	3 =
		REQUEST	REQUEST	REQUEST	REQUEST	REQUEST	FORWARD	REQUEST
1102	EXT1/EXT2	0 = EXT1	0 = EXT1	0 = EXT1	0 = EXT1	3 = <i>DI3</i>	-2 =	3 = <i>DI3</i>
	SEL						DI2(INV)	
1103	REF1 SELECT	1 = <i>AI1</i>	1 = <i>AI1</i>	1 = <i>AI1</i>	12 =	1 = <i>AI1</i>	1 = <i>AI1</i>	1 = <i>AI1</i>
					DI3U,4D(N			
					C)			
1106	REF2 SELECT	2 = A/2	2 = A/2	2 = <i>AI2</i>	2 = AI2	2 = AI2	19 =	2 = <i>AI2</i>
							PID10UT	
1201	CONST	9 = D13,4	10 = DI4,5	9 = <i>DI3,4</i>	5 = <i>DI5</i>	0 = NOT	3 = D/3	4 = <i>DI4</i>
	SPEED SEL					SEL		
	MINIMUM AI2	1.0%	1.0%	1.0%	1.0%	20.0%	20.0%	20.0%
1501		103	102	102	102	102	102	102
	CONTENT SEL							
1601	RUN ENABLE	-	0 = NOT	0 = NOT	0 = NOT	0 = NOT	4 = <i>DI4</i>	0 = NOT
		SEL	SEL	SEL	SEL	SEL		SEL
2201	ACC/DEC 1/2	5 = <i>DI5</i>	0 = <i>NOT</i>	5 = <i>DI5</i>	0 = NOT	0 = NOT	0 = NOT	5 = <i>DI5</i>
	SEL		SEL		SEL	SEL	SEL	
	SUPERV 1	103	102	102	102	102	102	102
	PARAM							
	SIGNAL1	103	102	102	102	102	102	102
	PARAM							
		3 =	1 =	1 =	1 =	1 =	3 =	2=
	MODE	SCALAR:	VECTOR:	VECTOR:	VECTOR:	VECTOR:	SCALAR:	VECTOR:
		FREQ	SPEED	SPEED	SPEED	SPEED	FREQ	TORQ

Note: It is possible to control several functions with one input (DI or AI), and there is a chance of mismatch between these functions. In some cases it is desired to control several functions with one input.

For example in the ABB standard macro, DI3 and DI4 are set to control constant speeds. On the other hand, it is possible to select value 6 (*DI3U,4D*) for parameter 1103 REF1 SELECT. That would mean a mismatched duplicate functionality for DI3 and DI4: either constant speed or acceleration and deceleration. The function that is not required must be disabled. In this case the constant speed selection must be disabled by setting parameter 1201 CONST SPEED SEL to NOT SEL or to values not related to DI3 and DI4.

Remember to also check the default values of the selected macro when configuring the drive inputs.

Differences between the default values in E and U type drives

The type designation label shows the type of the drive, see section *Type designation* key on page 31.

The following table lists the differences between the parameter default values in the E and U type drives.

No.	Name	E type EMC filter screw connected	U type EMC filter screw disconnected
9905	MOTOR NOM VOLT	230/400V	230/460V
9907	MOTOR NOM FREQ	50	60
9909	MOTOR NOM POWER	[kW]	[hp]
1105	REF1 MAX	50	60
1202	CONST SPEED 1	5	6
1203	CONST SPEED 2	10	12
1204	CONST SPEED 3	15	18
1205	CONST SPEED 4	20	24
1206	CONST SPEED 5	25	30
1207	CONST SPEED 6	40	48
1208	CONST SPEED 7	50	60
2002	MAXIMUM SPEED	1500	1800
2008	MAXIMUM FREQ	50	60

Actual signals

Actua	al signals		
No.	Name/Value	Description	FbEq
01 OF DATA	PERATING	Basic signals for monitoring the drive (read-only)	
0101	SPEED & DIR	Calculated motor speed in rpm. A negative value indicates reverse direction.	1 = 1 rpm
0102	SPEED	Calculated motor speed in rpm	1 = 1 rpm
0103	OUTPUT FREQ	Calculated drive output frequency in Hz. (Shown by default on the panel Output mode display.)	1 = 0.1 Hz
0104	CURRENT	Measured motor current in A. (Shown by default on the panel Output mode display.)	1 = 0.1 A
0105	TORQUE	Calculated motor torque as a percentage of the motor nominal torque	1 = 0.1%
0106	POWER	Measured motor power in kW	1 = 0.1 kW
0107	DC BUS VOLTAGE	Measured intermediate circuit voltage in V DC	1 = 1 V
0109	OUTPUT VOLTAGE	Calculated motor voltage in V AC	1 = 1 V
0110	DRIVE TEMP	Measured IGBT temperature in °C	1 = 0.1 °C
0111	EXTERNAL REF 1	External reference REF1 in rpm or Hz. Unit depends on parameter 9904 MOTOR CTRL MODE setting.	1 = 0.1 Hz / 1 rpm
0112	EXTERNAL REF 2	External reference REF2 as a percentage. Depending on the use, 100% equals the maximum motor speed, nominal motor torque, or maximum process reference.	1 = 0.1%
0113	CTRL LOCATION	Active control location. (0) LOCAL; (1) EXT1; (2) EXT2. See section <i>Local control vs. external control</i> on page <i>130</i> .	1 = 1
0114	RUN TIME (R)	Elapsed drive running time counter (hours). Runs when the drive is modulating. The counter can be reset by pressing the UP and DOWN keys simultaneously when the control panel is in the Parameter mode.	1 = 1 h
0115	KWH COUNTER (R)	kWh counter. The counter value is accumulated till it reaches 65535 after which the counter rolls over and starts again from 0. The counter can be reset by pressing UP and DOWN keys simultaneously when the control panel is in the Parameter mode.	1 = 1 kWh
0120	Al 1	Relative value of analog input Al1 as a percentage	1 = 0.1%
0121	Al 2	Relative value of analog input Al2 as a percentage	1 = 0.1%
0124	AO 1	Value of analog output AO in mA	1 = 0.1 mA
0126	PID 1 OUTPUT	Output value of the process PID1 controller as a percentage	1 = 0.1%
0127	PID 2 OUTPUT	Output value of the PID2 controller as a percentage	1 = 0.1%

Actua	al signals		
No.	Name/Value	Description	FbEq
0128	PID 1 SETPNT	Setpoint signal (reference) for the process PID1 controller. Unit depends on parameter 4006 UNITS, 4007 UNIT SCALE and 4027 PID 1 PARAM SET settings.	-
0129	PID 2 SETPNT	Setpoint signal (reference) for the PID2 controller. Unit depends on parameter 4106 UNITS and 4107 UNIT SCALE settings.	-
0130	PID 1 FBK	Feedback signal for the process PID1 controller. Unit depends on parameter 4006 UNITS, 4007 UNIT SCALE and 4027 PID 1 PARAM SET settings.	-
0131	PID 2 FBK	Feedback signal for the PID2 controller. Unit depends on parameter 4106 UNITS and 4107 UNIT SCALE settings.	-
0132	PID 1 DEVIATION	Deviation of the process PID1 controller, ie the difference between the reference value and the actual value. Unit depends on parameter 4006 UNITS, 4007 UNIT SCALE and 4027 PID 1 PARAM SET settings.	-
0133	PID 2 DEVIATION	Deviation of the PID2 controller, ie the difference between the reference value and the actual value. Unit depends on parameter 4106 UNITS and 4107 UNIT SCALE settings.	-
0134	COMM RO WORD	Relay output Control word through fieldbus (decimal). See parameter 1401 RELAY OUTPUT 1.	1 = 1
0135	COMM VALUE 1	Data received from fieldbus	1 = 1
0136	COMM VALUE 2	Data received from fieldbus	1 = 1
0137	PROCESS VAR 1	Process variable 1 defined by parameter group 34 PANEL DISPLAY	-
0138	PROCESS VAR 2	Process variable 2 defined by parameter group 34 PANEL DISPLAY	-
0139	PROCESS VAR 3	Process variable 3 defined by parameter group 34 PANEL DISPLAY	-
0140	RUN TIME	Elapsed drive running time counter (thousands of hours). Runs when the drive is modulating. Counter cannot be reset.	1 = 0.01 kh
0141	MWH COUNTER	MWH counter. The counter value is accumulated till it reaches 65535 after which the counter rolls over and starts again from 0. Cannot be reset.	1 = 1 MWh
0142	REVOLUTION CNTR	Motor revolution counter (millions of revolutions). The counter can be reset by pressing UP and DOWN keys simultaneously when the control panel is in the Parameter mode.	1 = 1 Mrev
0143	DRIVE ON TIME HI	Drive control board power-on time in days. Counter cannot be reset.	1 = 1 days

Actua	al signals		
No.	Name/Value	Description	FbEq
0144	DRIVE ON TIME LO	Drive control board power-on time in 2 second ticks (30 ticks = 60 seconds). Counter cannot be reset.	1 = 2 s
0145	MOTOR TEMP	Measured motor temperature. Unit depends on the sensor type selected by group 35 MOTOR TEMP MEAS parameters.	1 = 1
0146	MECH ANGLE	Calculated mechanical angle	1 = 1
0147	MECH REVS	Mechanical revolutions, ie the motor shaft revolutions calculated by the encoder	1 = 1
0148	Z PLS DETECTED	Encoder zero pulse detector. 0 = not detected, 1 = detected.	1 = 1
0150	CB TEMP	Temperature of the drive control board in degrees Celsius (0.0150.0 °C).	1 = 0.1 °C
0158	PID COMM VALUE 1	Data received from fieldbus for PID control (PID1 and PID2)	1 = 1
0159	PID COMM VALUE 2	Data received from fieldbus for PID control (PID1 and PID2)	1 = 1
0160	DI 1-5 STATUS	Status of digital inputs. Example: 10000 = DI1 is on, DI2DI5 are off.	
0161	PULSE INPUT FREQ	Value of frequency input in Hz	1 = 1 Hz
0162	RO STATUS	Status of relay output 1. 1 = RO is energized, 0 = RO is de- energized.	1 = 1
0163	TO STATUS	Status of transistor output, when transistor output is used as a digital output.	1 = 1
0164	TO FREQUENCY	Transistor output frequency, when transistor output is used as a frequency output.	1 = 1 Hz
0165	TIMER VALUE	Timer value of timed start/stop. See parameter group 19 TIMER & COUNTER.	1 = 0.01 s
0166	COUNTER VALUE	Pulse counter value of counter start/stop. See parameter group 19 TIMER & COUNTER.	1 = 1
0167	SEQ PROG STS	Status word of the Sequence programming:	1 = 1
		Bit 0 = ENABLED (1 = enabled)	
		Bit 1 = STARTED	
		Bit 2 = PAUSED	
		Bit 3 = LOGIC VALUE (logic operation defined by parameters <i>8406…8410</i>).	
0168	SEQ PROG STATE	Active state of the Sequence programming. 18 = state 18.	1 = 1
0169	SEQ PROG TIMER	Current state time counter of the Sequence programming	1 = 2 s

Actua	al signals		
No.	Name/Value	Description	FbEq
		Bit 3 = SHORT CIRC	
		Bit 4 = Reserved	
		Bit 5 = DC UNDERVOLT	
		Bit 6 = AI1 LOSS	
		Bit 7 = <i>Al2 LOSS</i>	
		Bit 8 = MOT OVERTEMP	
		Bit 9 = PANEL LOSS	
		Bit 10 = ID RUN FAIL	
		Bit 11 = MOTOR STALL	
		Bit 12 = CB OVERTEMP	
		Bit 13 = EXT FAULT 1	
		Bit 14 = EXT FAULT 2	
		Bit 15 = EARTH FAULT	
0306	FAULT WORD 2	A 16-bit data word. For the possible causes and remedies and fieldbus equivalents, see chapter <i>Fault tracing</i> on page 347.	
		Bit 0 = UNDERLOAD	
		Bit 1 = THERM FAIL	
		Bit 23 = Reserved	
		Bit 4 = CURR MEAS	
		Bit 5 = SUPPLY PHASE	
		Bit 6 = ENCODER ERR	
		Bit 7 = OVERSPEED	
		Bit 89 = Reserved	
		Bit 10 = CONFIG FILE	
		Bit 11 = SERIAL 1 ERR	
		Bit 12 = <i>EFB CON FILE</i> . Configuration file reading error.	
		Bit 13 = FORCE TRIP	
		Bit 14 = MOTOR PHASE	
		Bit 15 = OUTP WIRING	
0307	FAULT WORD 3	A 16-bit data word. For the possible causes and remedies and fieldbus equivalents, see chapter <i>Fault tracing</i> on page 347.	
		Bit 02 Reserved	
		Bit 3 = INCOMPATIBLE SW	
		Bit 4 = SAFE TORQUE OFF	
		Bit 5 = STO1 LOST	
		Bit 6 = STO2 LOST	
I			1

Actual signals				
	Name/Value	Description	FbEq	
		Bit 710 Reserved		
		Bit 11 = CB ID ERROR	=	
		Bit 12 = DSP STACK ERROR	-	
		Bit 13 = DSP T1 OVERLOADDSP T3 OVERLOAD	=	
		Bit 14 = SERF CORRUPT / SERF MACRO	=	
		Bit 15 = PAR PCU 1 / PAR PCU 2 / PAR HZRPM / PAR AI		
		SCALE PAR AO SCALE PAR FBUSMISS PAR USER U/F PAR SETUP 1		
0308	ALARM WORD 1	A 16-bit data word. For the possible causes and remedies and fieldbus equivalents, see chapter <i>Fault tracing</i> on page 347.		
		An alarm can be reset by resetting the whole alarm word: Write zero to the word.		
		Bit 0 = OVERCURRENT		
		Bit 1 = OVERVOLTAGE	1	
		Bit 2 = UNDERVOLTAGE		
		Bit 3 = DIR LOCK		
		Bit 4 = IO COMM		
		Bit 5 = AI1 LOSS		
		Bit 6 = <i>Al2 LOSS</i>		
		Bit 7 = PANEL LOSS		
		Bit 8 = DEVICE OVERTEMP		
		Bit 9 = MOTOR TEMP		
		Bit 10 = UNDERLOAD		
		Bit 11 = MOTOR STALL		
		Bit 12 = AUTORESET		
		Bit 1315 = Reserved	1	
0309	ALARM WORD 2	A 16-bit data word. For the possible causes and remedies and fieldbus equivalents, see chapter <i>Fault tracing</i> on page 347.		
		An alarm can be reset by resetting the whole alarm word: Write zero to the word.		
		Bit 0 = Reserved		
		Bit 1 = PID SLEEP	1	
		Bit 2 = ID RUN	1	
		Bit 3 = Reserved	1	
		Bit 4 = START ENABLE 1 MISSING	1	
		Bit 5 = START ENABLE 2 MISSING	1	
		Bit 6 = EMERGENCY STOP	1	

Actua	al signals		
No.	Name/Value	Description	FbEq
		Bit 7 = ENCODER ERROR	
		Bit 8 = FIRST START	
		Bit 9 = INPUT PHASE LOSS	
		Bit 1011 = Reserved	-
		Bit 12 = MOTOR BACK EMF	-
		Bit 13 = SAFE TORQUE OFF	-
		Bit 1415 = Reserved	-
04 FA	ULT HISTORY	Fault history (read-only)	
0401	LAST FAULT	Code of the latest fault. See chapter <i>Fault tracing</i> on page 347 for the codes. 0 = Fault history is clear (on panel display = NO RECORD).	1 = 1
0402	FAULT TIME 1	Day on which the latest fault occurred.	1 = 1
		Format: Date if the real time clock is operating. / The number of days elapsed after the power-on if the real time clock is not used, or was not set.	days
0403	FAULT TIME 2	Time at which the latest fault occurred.	1 = 2 s
		Format on the assistant control panel: Real time (hh:mm:ss) if the real time clock is operating. / Time elapsed after the power-on (hh:mm:ss minus the whole days stated by signal 0402 FAULT TIME 1) if real time clock is not used, or was not set.	
		Format on the basic control panel: Time elapsed after power-on in 2 second ticks (minus the whole days stated by signal <i>0402 FAULT TIME 1</i>). 30 ticks = 60 seconds. Eg value 514 equals 17 minutes and 8 seconds (= 514/30).	
0404	SPEED AT FLT	Motor speed in rpm at the time the latest fault occurred	1 = 1 rpm
0405	FREQ AT FLT	Frequency in Hz at the time the latest fault occurred	1 = 0.1 Hz
0406	VOLTAGE AT FLT	Intermediate circuit voltage in V DC at the time the latest fault occurred	1 = 0.1 V
0407	CURRENT AT FLT	Motor current in A at the time the latest fault occurred	1 = 0.1 A
0408	TORQUE AT FLT	Motor torque as a percentage of the motor nominal torque at the time the latest fault occurred	1 = 0.1%
0409	STATUS AT FLT	Drive status in hexadecimal format at the time the latest fault occurred	
0412	PREVIOUS FAULT 1	Fault code of the 2nd latest fault. See chapter Fault tracing on page 347 for the codes.	1 = 1
0413	PREVIOUS FAULT 2	Fault code of the 3rd latest fault. See chapter Fault tracing on page 347 for the codes.	1 = 1
0414	DI 1-5 AT FLT	Status of digital inputs DI15 at the time the latest fault occurred (binary). Example: 10000 = DI1 is on, DI2DI5 are off.	

Parameters

All parameters		
No. Name/Value	Description	Def/FbEq
10 START/STOP/DIR	The sources for external start, stop and direction control	
1001 EXT1 COMMANDS	Defines the connections and the source for the start, stop and direction commands for external control location 1 (EXT1). Note: Start signal must be reset if the drive has been	DI1,2
	stopped through STO (Safe torque off) input (see parameter 3025 STO OPERATION) or emergency stop selection (see parameter 2109 EMERG STOP SEL).	
NOT SEL	No start, stop and direction command source	0
DI1	Start and stop through digital input DI1. 0 = stop, 1 = start. Direction is fixed according to parameter 1003 DIRECTION (setting REQUEST = FORWARD).	1
DI1,2	Start and stop through digital input DI1. 0 = stop, 1 = start. Direction through digital input DI2. 0 = forward, 1 = reverse. To control direction, parameter 1003 DIRECTION setting must be REQUEST.	2
DI1P,2P	Pulse start through digital input DI1. 0 -> 1: Start. (In order to start the drive, digital input DI2 must be activated prior to the pulse fed to DI1.) Pulse stop through digital input DI2. 1 -> 0: Stop. Direction of rotation is fixed according to parameter 1003 DIRECTION (setting REQUEST = FORWARD).	3
	Note: When the stop input (DI2) is deactivated (no input), the control panel start and stop keys are disabled.	
DI1P,2P,3	Pulse start through digital input DI1. 0 -> 1: Start. (In order to start the drive, digital input DI2 must be activated prior to the pulse fed to DI1.) Pulse stop through digital input DI2. 1 -> 0: Stop. Direction through digital input DI3. 0 = forward, 1 = reverse. To control direction, parameter 1003 DIRECTION setting must be REQUEST.	4
	Note: When the stop input (DI2) is deactivated (no input), the control panel start and stop keys are disabled.	
DI1P,2P,3P	Pulse start forward through digital input DI1. 0 -> 1: Start forward. Pulse start reverse through digital input DI2. 0 -> 1: Start reverse. (In order to start the drive, digital input DI3 must be activated prior to the pulse fed to DI1/DI2). Pulse stop through digital input DI3. 1 -> 0: Stop. To control the direction, parameter 1003 DIRECTION setting must be REQUEST.	5
	Note: When the stop input (DI3) is deactivated (no input), the control panel start and stop keys are disabled.	

All p	arameters					
No.	Name/Value	Description		Def/FbEq		
	KEYPAD	Start, stop and owner EXT1 is a 1003 DIRECTION	8			
	DI1F,2R	Start, stop and c	direction commands through digital inputs	9		
			Operation			
			Stop Stort forward			
			Start forward Start reverse			
			Stop			
		.	Clop			
		Parameter 1003	B DIRECTION setting must be REQUEST.			
	COMM	commands, ie C 01. The Contr through the field (Modbus) to the	rieldbus interface as the source for the start and stop ommands, ie Control word 0301 FB CMD WORD 1 bits1. The Control word is sent by the fieldbus controller nrough the fieldbus adapter or embedded fieldbus Modbus) to the drive. For the Control word bits, see section OCU communication profile on page 331.			
	TIMED FUNC 1	timed function 1	Timed start/stop control. Timed function 1 active = start, timed function 1 inactive = stop. See parameter group 36 TIMED FUNCTIONS.			
	TIMED FUNC 2	See selection T	See selection TIMED FUNC 1.			
	TIMED FUNC 3	See selection T	IMED FUNC 1.	13		
	TIMED FUNC 4	See selection T	IMED FUNC 1.	14		
	DI5	Direction is fixed	nrough digital input DI5. 0 = stop, 1 = start. d according to parameter 1003 DIRECTION ST = FORWARD).	20		
	DI5,4	Direction throug	hrough digital input DI5. 0 = stop, 1 = start. h digital input DI4. 0 = forward, 1 = reverse. ion, parameter 1003 DIRECTION must be	21		
	TIMER STOP	Stop when timer DELAY has pass the signal is sele	22			
	TIMER START	Start when timer delay defined by parameter 1901 TIMER DELAY has passed. Stop when timer is reset by parameter 1903 TIMER RESET.				
	COUNTER STOP	COUNTER LIMI	ter limit defined by parameter 1905 IT has been exceeded. Start with counter tree for the signal is selected by parameter COMMAND.	24		

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
11 RE SELE	EFERENCE ECT	Panel reference type, external control location selection and external reference sources and limits	
1101	KEYPAD REF SEL	Selects the type of the reference in local control mode.	REF1(Hz/rpm)
	REF1(Hz/rpm)	Frequency reference in rpm. Frequency reference (Hz) if parameter 9904 MOTOR CTRL MODE setting is SCALAR: FREQ.	1
	REF2(%)	%-reference	2
1102	EXT1/EXT2 SEL	Defines the source from which the drive reads the signal that selects between the two external control locations, EXT1 or EXT2.	EXT1
	EXT1	EXT1 active. The control signal sources are defined by parameters 1001 EXT1 COMMANDS and 1103 REF1 SELECT.	0
	DI1	Digital input DI1. 0 = EXT1, 1 = EXT2.	1
	DI2	See selection DI1.	2
	DI3	See selection DI1.	3
	DI4	See selection DI1.	4
	DI5	See selection DI1.	5
	EXT2	EXT2 active. The control signal sources are defined by parameters 1002 EXT2 COMMANDS and 1106 REF2 SELECT.	7
	COMM	Fieldbus interface as the source for EXT1/EXT2 selection, ie Control word 0301 FB CMD WORD 1 bit 5 (with ABB drives profile 5319 EFB PAR 19 bit 11). The Control word is sent by the fieldbus controller through the fieldbus adapter or embedded fieldbus (Modbus) to the drive. For the Control word bits, see sections DCU communication profile on page 331 and ABB drives communication profile on page 326.	8
	TIMED FUNC 1	Timed EXT1/EXT2 control selection. Timed function 1 active = EXT2, timed function 1 inactive = EXT1. See parameter group 36 TIMED FUNCTIONS.	9
	TIMED FUNC 2	See selection TIMED FUNC 1.	10
	TIMED FUNC 3	See selection TIMED FUNC 1.	11
	TIMED FUNC 4	See selection TIMED FUNC 1.	12
	DI1(INV)	Inverted digital input DI1. 1 = EXT1, 0 = EXT2.	-1
	DI2(INV)	See selection DI1(INV).	-2
	DI3(INV)	See selection DI1(INV).	-3
	DI4(INV)	See selection DI1(INV).	-4
	DI5(INV)	See selection DI1(INV).	-5

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
1103	REF1 SELECT	Selects the signal source for external reference REF1. See section <i>Block diagram: Reference source for EXT1</i> on page 132.	Al1
	KEYPAD	Control panel	0
	Al1	Analog input AI1	1
	Al2	Analog input Al2	2
	Al1/JOYST	Analog input Al1 as joystick. The minimum input signal runs the motor at the maximum reference in the reverse direction, the maximum input at the maximum reference in the forward direction. Minimum and maximum references are defined by parameters 1104 REF1 MIN and 1105 REF1 MAX. Note: Parameter 1003 DIRECTION must be set to REQUEST. Speed ref par. 1301 = 20%, par 1302 = 100% (REF1) 1105 1104 11	3
		Set the following parameters to activate a fault when analog input signal is lost: Set parameter 1301 MINIMUM AI1 to 20% (2 V or 4 mA). Set parameter 3021 AI1 FAULT LIMIT to 5% or higher. Set parameter 3001 AI	
	AI2/JOYST	See selection AI1/JOYST.	4
	DI3U,4D(R)	Digital input DI3: Reference increase. Digital input DI4: Reference decrease. Stop command resets the reference to zero. Parameter 2205 ACCELER TIME 2 defines the rate of the reference change.	5
	DI3U,4D	Digital input DI3: Reference increase. Digital input DI4: Reference decrease. The program stores the active speed reference (not reset by a stop command). When the drive is restarted, the motor ramps up at the selected acceleration rate to the stored reference. Parameter 2205 ACCELER TIME 2 defines the rate of the reference change.	6
	COMM	Fieldbus reference REF1	8

All parameters						
No.	Name/Value	Description	Def/FbEq			
	COMM+AI1	Summation of fieldbus reference REF1 and analog input Al. See section <i>Reference selection and correction</i> on page <i>318</i> .	9			
	COMM*AI1	Multiplication of fieldbus reference REF1 and analog input Al1. See section <i>Reference selection and correction</i> on page 318.	10			
	DI3U,4D(RNC)	Digital input DI3: Reference increase. Digital input DI4: Reference decrease. Stop command resets the reference to zero.	11			
		The reference is not saved if the control source is changed (from EXT1 to EXT2, from EXT2 to EXT1 or from LOC to REM). Parameter 2205 ACCELER TIME 2 defines the rate of the reference change.				
	DI3U,4D(NC)	Digital input DI3: Reference increase. Digital input DI4: Reference decrease.	12			
		The program stores the active speed reference (not reset by a stop command). The reference is not saved if the control source is changed (from EXT1 to EXT2, from EXT2 to EXT1 or from LOC to REM). When the drive is restarted, the motor ramps up at the selected acceleration rate to the stored reference. Parameter 2205 ACCELER TIME 2 defines the rate of the reference change.				
	Al1+Al2	Reference is calculated with the following equation: REF = AI1(%) + AI2(%) - 50%	14			
	Al1*Al2	Reference is calculated with the following equation: REF = AI1(%) · (AI2(%) / 50%)	15			
	Al1-Al2	Reference is calculated with the following equation: REF = AI1(%) + 50% - AI2(%)	16			
	Al1/Al2	Reference is calculated with the following equation: REF = AI1(%) · (50% / AI2 (%))	17			
	KEYPAD(RNC)	Defines the control panel as the reference source. Stop command resets the reference to zero (the R stands for reset). The reference is not saved if the control source is changed (from EXT1 to EXT2, from EXT2 to EXT1).	20			
	KEYPAD(NC)	Defines the control panel as the reference source. Stop command does not reset the reference to zero. The reference is stored. The reference is not saved if the control source is changed (from EXT1 to EXT2, from EXT2 to EXT1).	21			
	DI4U,5D	See selection <i>DI3U,4D</i> .	30			
	DI4U,5D(NC)	See selection <i>DI3U,4D(NC)</i> .	31			
	FREQ INPUT	Frequency input	32			

All parameters								
No.	Name/Value	Description	Def/FbEq					
	SEQ PROG	Sequence programming output. See parameter 8420 ST1 REF SEL.	33					
	AI1+SEQ PROG	Addition of analog input Al1 and Sequence programming output	34					
	AI2+SEQ PROG	Addition of analog input Al2 and Sequence programming output	35					
1104	REF1 MIN	Defines the minimum value for external reference REF1. Corresponds to the minimum setting of the used source signal.	0.0 Hz / 1 rpm					
	0.0500.0 Hz/ 030000 rpm	Minimum value in rpm. Hz if parameter 9904 MOTOR CTRL MODE setting is SCALAR: FREQ.	1 = 0.1 Hz / 1 rpm					
		Example: Analog input Al1 is selected as the reference source (value of parameter 1103 is Al1). The reference minimum and maximum correspond to the 1301 MINIMUM Al1 and 1302 MAXIMUM Al1 settings as follows: REF1 MAX						
		REF1 MIN (1104) 1302 1301 Al1 signal (%) -REF1 MIN (1104) 1301 1302 -REF1 MAX (1105)						
1105	REF1 MAX	Defines the maximum value for external reference REF1. Corresponds to the maximum setting of the used source signal.	E: 50.0 Hz U: 60.0 Hz					
	0.0500.0 Hz/ 030000 rpm	Maximum value in rpm. Hz if parameter 9904 MOTOR CTRL MODE setting is SCALAR: FREQ. See the example for parameter 1104 REF1 MIN.	1 = 0.1 Hz / 1 rpm					
1106	REF2 SELECT	Selects the signal source for external reference REF2.	AI2					
	KEYPAD	See parameter 1103 REF1 SELECT.	0					
	Al1	See parameter 1103 REF1 SELECT.	1					
	Al2	See parameter 1103 REF1 SELECT.	2					
	AI1/JOYST	See parameter 1103 REF1 SELECT.	3					
	AI2/JOYST	See parameter 1103 REF1 SELECT.	4					
	DI3U,4D(R)	See parameter 1103 REF1 SELECT.	5					
	DI3U,4D	See parameter 1103 REF1 SELECT.	6					
	COMM	See parameter 1103 REF1 SELECT.	8					

All pa	All parameters						
No.	Name/Value	Description	Def/FbEq				
	COMM+AI1	See parameter 1103 REF1 SELECT.	9				
	COMM*AI1	See parameter 1103 REF1 SELECT.	10				
	DI3U,4D(RNC)	See parameter 1103 REF1 SELECT.	11				
	DI3U,4D(NC)	See parameter 1103 REF1 SELECT.	12				
	Al1+Al2	See parameter 1103 REF1 SELECT.	14				
	Al1*Al2	See parameter 1103 REF1 SELECT.	15				
	Al1-Al2	See parameter 1103 REF1 SELECT.	16				
	Al1/Al2	See parameter 1103 REF1 SELECT.	17				
	PID1OUT	PID controller 1 output. See parameter groups 40 PROCESS PID SET 1 and 41 PROCESS PID SET 2.	19				
	KEYPAD(RNC)	See parameter 1103 REF1 SELECT.	20				
	KEYPAD(NC)	See parameter 1103 REF1 SELECT.	21				
	DI4U,5D	See parameter 1103 REF1 SELECT.	30				
	DI4U,5D(NC)	See parameter 1103 REF1 SELECT.	31				
	FREQ INPUT	See parameter 1103 REF1 SELECT.	32				
	SEQ PROG	See parameter 1103 REF1 SELECT.	33				
	AI1+SEQ PROG	See parameter 1103 REF1 SELECT.	34				
	AI2+SEQ PROG	See parameter 1103 REF1 SELECT.	35				
1107	REF2 MIN	Defines the minimum value for external reference REF2. Corresponds to the minimum setting of the used source signal.	0.0%				
	0.0100.0%	Value as a percentage of the maximum frequency / maximum speed / nominal torque. See the example for parameter 1104 REF1 MIN for correspondence to the source signal limits.	1 = 0.1%				
1108	REF2 MAX	Defines the maximum value for external reference REF2. Corresponds to the maximum setting of the used source signal.	100.0%				
	0.0100.0%	Value as a percentage of the maximum frequency / maximum speed / nominal torque. See the example for parameter 1104 REF1 MIN for correspondence to the source signal limits.	1 = 0.1%				
12 CO SPEE	ONSTANT EDS	Constant speed selection and values. See section <i>Constant speeds</i> on page <i>145</i> .					
1201	CONST SPEED SEL	Activates the constant speeds or selects the activation signal.	DI3,4				
	NOT SEL	No constant speed in use	0				
	DI1	Speed defined by parameter 1202 CONST SPEED 1 is activated through digital input DI1. 1 = active, 0 = inactive.	1				

All pa	arameters				
No.	Name/Value	Description	Def/FbEq		
	TIMED FUN1&2	External speed reference or speed defined by parameter 1202 CONST SPEED 1 1205 CONST SPEED 4 is used, depending on the selection of parameter 1209 TIMED MODE SEL and the state of timed functions 1 and 2. See parameter group 36 TIMED FUNCTIONS.	19		
	DI1(INV)	Speed defined by parameter 1202 CONST SPEED 1 is activated through inverted digital input DI1. 0 = active, 1 = inactive.	-1		
	DI2(INV)	Speed defined by parameter 1202 CONST SPEED 1 is activated through inverted digital input DI2. 0 = active, 1 = inactive.	-2		
	DI3(INV)	Speed defined by parameter 1202 CONST SPEED 1 is activated through inverted digital input DI3. 0 = active, 1 = inactive.	-3		
	DI4(INV)	Speed defined by parameter 1202 CONST SPEED 1 is activated through inverted digital input DI4. 0 = active, 1 = inactive.	-4		
	DI5(INV)	Speed defined by parameter 1202 CONST SPEED 1 is activated through inverted digital input DI5. 0 = active, 1 = inactive.			
	DI1,2(INV)	Constant speed selection through inverted digital inputs DI1 and DI2. 1 = DI active, 0 = DI inactive. DI1 DI2 Operation	-7		
		1 0 Speed defined by par. 1202 CONST SPEED 1 0 0 Speed defined by par. 1203 CONST SPEED 2 0 0 Speed defined by par. 1204 CONST SPEED 3			
	DI2,3(INV)	See selection <i>DI1,2(INV)</i> .	-8		
	DI3,4(INV)	See selection <i>DI1,2(INV)</i> .	-9		
	DI4,5(INV)	See selection DI1,2(INV).	-10		
	DI1,2,3(INV)	Constant speed selection through inverted digital inputs DI1, DI2 and DI3. 1 = DI active, 0 = DI inactive. DI DI2 DI3 Operation	-12		
<u> </u>	יסום, די,טוווע <i>)</i>	OGG SCIGOLION DIT,2,3(INV).	-10		

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
1202	CONST SPEED 1	Defines constant speed (or drive output frequency) 1.	E: 5.0 Hz U: 6.0 Hz
	0.0600.0 Hz/ 030000 rpm	Speed in rpm. Output frequency in Hz if parameter 9904 MOTOR CTRL MODE setting is SCALAR: FREQ.	1 = 0.1 Hz / 1 rpm
1203	CONST SPEED 2	Defines constant speed (or drive output frequency) 2.	E: 10.0 Hz U: 12.0 Hz
	0.0600.0 Hz/ 030000 rpm	Speed in rpm. Output frequency in Hz if parameter 9904 MOTOR CTRL MODE setting is SCALAR: FREQ.	1 = 0.1 Hz / 1 rpm
1204	CONST SPEED 3	Defines constant speed (or drive output frequency) 3.	E: 15.0 Hz U: 18.0 Hz
	0.0500.0 Hz/ 030000 rpm	Speed in rpm. Output frequency in Hz if parameter 9904 MOTOR CTRL MODE setting is SCALAR: FREQ.	1 = 0.1 Hz / 1 rpm
1205	CONST SPEED 4	Defines constant speed (or drive output frequency) 4.	E: 20.0 Hz U: 24.0 Hz
	0.0500.0 Hz/ 030000 rpm	Speed in rpm. Output frequency in Hz if parameter 9904 MOTOR CTRL MODE setting is SCALAR: FREQ.	1 = 0.1 Hz / 1 rpm
1206	CONST SPEED 5	Defines constant speed (or drive output frequency) 5.	E: 25.0 Hz U: 30.0 Hz
	0.0500.0 Hz/ 030000 rpm	Speed in rpm. Output frequency in Hz if parameter 9904 MOTOR CTRL MODE setting is SCALAR: FREQ.	1 = 0.1 Hz / 1 rpm
1207	CONST SPEED 6	Defines constant speed (or drive output frequency) 6.	E: 40.0 Hz U: 48.0 Hz
	0.0500.0 Hz/ 030000 rpm	Speed in rpm. Output frequency in Hz if parameter 9904 MOTOR CTRL MODE setting is SCALAR: FREQ. Constant speed 6 is used also as jogging speed. See section Control of a mechanical brake on page 162.	1 = 0.1 Hz / 1 rpm
1208	CONST SPEED 7	Defines constant speed (or drive output frequency) 7. Constant speed 7 is used also as jogging speed (see section <i>Control of a mechanical brake</i> on page 162) or with fault functions (3001 AI <min 3002="" and="" comm="" err).<="" function="" panel="" td=""><td>E: 50.0 Hz U: 60.0 Hz</td></min>	E: 50.0 Hz U: 60.0 Hz
	0.0500.0 Hz/ 030000 rpm	Speed in rpm. Output frequency in Hz if parameter 9904 MOTOR CTRL MODE setting is SCALAR: FREQ. Constant speed 7 is used also as jogging speed. See section Control of a mechanical brake on page 162.	1 = 0.1 Hz / 1 rpm

All parameters								
No.	Name/Value	Description	n		Def/FbEq			
1209	TIMED MODE SEL	be used to constant sp	change bet eeds when on is <i>TIME</i>	activated speed. Timed function can ween the external reference and parameter 1201 CONST SPEED D FUNC 1 TIMED FUNC 4 or	CS1/2/3/4			
	EXT/CS1/2/3	FUNC 1 external spe	TIMED FU eed referen	CONST SPEED SEL = TIMED NC 4, this timed function selects an ce or constant speed. 1 = timed ed function inactive.	1			
		Timed fund	Timed function 14 Operation					
		(0 External reference					
				Speed defined by par. 1202 CONST SPEED 1				
		When parameter 1201 CONST SPEED SEL = TIMED FUN1&2, timed functions 1 and 2 select an external speed reference or constant speed. 1 = timed function active, 0 = timed function inactive.						
		Timed	Timed	Operation				
		function 1	function 2					
		0	0	External reference				
	1 0 Speed defined by par. 1202 CONST							
		0	1	Speed defined by par. 1203 CONST SPEED 2				
		1	1	Speed defined by par. 1204 CONST SPEED 3				

All pa	arameters				
No.	Name/Value	Description	n		Def/FbEq
	CS1/2/3/4	When parameters of the paramet	2		
		Timed function 1	Timed	Operation Speed defined by parameter 1202	
		1	0	CONST SPEED 1 Speed defined by parameter 1203 CONST SPEED 2	
		0	1	Speed defined by parameter 1204 CONST SPEED 3	
		1	1	Speed defined by parameter 1205 CONST SPEED 4	
13 A	NALOG INPUTS	Analog inpu	ıt signal pro	ocessing	
1301	MINIMUM AI1	mA/(V) sign reference, t setting. 020 mA = 420 mA = -1010 mA Example: I reference F parameter Note: MINI value.	he value co control of the value co control of the value co control of the value control	% ected as the source for external value corresponds to the value of MIN. alue must not exceed MAXIMUM AI1	1.0%
	-100.0100.0%	Example: I	f the minimovalue for 0	of the full signal range. um value for analog input is 4 mA, the20 mA range is: o = 20%	1 = 0.1%

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
1302	MAXIMUM AI1	Defines the maximum %-value that corresponds to maximum mA/(V) signal for analog input Al1. When used as a reference, the value corresponds to the reference maximum setting. 020 mA ≜ 0100% 420 mA ≜ 20100% -1010 mA ≜ -5050% Example: If Al1 is selected as the source for external reference REF1, this value corresponds to the value of parameter 1105 REF1 MAX.	100.0%
	-100.0100.0%	Value as a percentage of the full signal range.	1 = 0.1%
		Example: If the maximum value for analog input is 10 mA, the percentage value for 020 mA range is: (10 mA / 20 mA) · 100% = 50%	
1303	FILTER AI1	Defines the filter time constant for analog input Al1, ie the time within which 63% of a step change is reached.	0.1 s
		Unfiltered signal 63 Filtered signal Time constant	
	0.010.0 s	Filter time constant	1 = 0.1 s
1304	MINIMUM AI2	Defines the minimum %-value that corresponds to minimum mA/(V) signal for analog input Al2. See parameter 1301 MINIMUM Al1.	20%
	-100.0100.0%	See parameter 1301 MINIMUM AI1.	1 = 0.1%
1305	MAXIMUM AI2	Defines the maximum %-value that corresponds to maximum mA/(V) signal for analog input Al2. See parameter 1302 MAXIMUM Al1.	100.0%
	-100.0100.0%	See parameter 1302 MAXIMUM AI1.	1 = 0.1%
1306	FILTER AI2	Defines the filter time constant for analog input Al2. See parameter 1303 FILTER Al1.	0.1 s
	0.010.0 s	Filter time constant	1 = 0.1 s

All pa	arameters								
No.	Name/Value	Descrip	otion						Def/FbEq
	REF LOSS	Referen	ice or acti	ve contro	l location	ı is lost.			20
	OVERCURRE NT	Alarm/F	ault by ov	ercurren	t protection	on functio	n		21
	OVERVOLTAG E	Alarm/F	m/Fault by overvoltage protection function					22	
	DRIVE TEMP	Alarm/F	ault by dr	ive overte	emperatu	re protec	tion fun	ction	23
	UNDERVOLTA GE	Alarm/F	ault by ur	ndervoltaç	ge protec	tion funct	ion		24
	Al1 LOSS	Analog	input AI1	signal is	lost.				25
	Al2 LOSS	Analog	input Al2	signal is	lost.				26
	MOTOR TEMP		ault by manager		•	•	ction fu	nction.	27
	STALL		ault by sta	•	ion functi	ion. See p	aramet	ter 3010	28
	UNDERLOAD		ault by ur ter 3013 t				. See		29
	PID SLEEP		ep function 41 PROC	•	•	group 40 I	PROCE	SS PID	30
	FLUX READY	Motor is	magnetiz	zed and a	able to su	pply nom	inal tor	que.	33
	USER MACRO 2	User ma	acro 2 is a	active.					34
	COMM	Fieldbus	s control s	signal 013	34 COMN	1 RO WO	<i>RD</i> . 0 =	= de-	35
			e output,						
		0134	Binary	RO4	RO3	RO2	DO	RO1	
		value 0	00000	0	0	(MREL)	0	0	
		1	00001	0	0	0	0	1	
		2	00010	0	0	0	1	0	
		3	00011	0	0	0	1	1	
		4	00100	0	0	1	0	0	
		530							
		31	11111	1	1	1	1	1	
	COMM(-1)	Fioldbur	s control s	signal 01'	24 COM	1 PO WO	PD 0 -	- do	36
	COMMIC-1)		e output,	•			ND . 0 -	- ue-	30
		0134	Binary	RO4	RO3	RO2	DO	RO1	
		value		(MREL)			- •		
		0	00000	1	1	1	1	1	
		1	00001	1	1	1	1	0	
		2	00010	1	1	1	0	1	
		3	00011	1	1	1	0	0	
		4	00100	1	1	0	1	1	
		530							
		31	11111	0	0	0	0	0	
<u> </u>		<u> </u>							<u> </u>

All parameters							
No.	Name/Value	Description	Def/FbEq				
1405	RO 1 OFF DELAY	Defines the release delay for relay output RO 1.	0.0 s				
	0.03600.0 s	Delay time. See the figure for parameter 1404 RO 1 ON DELAY.	1 = 0.1 s				
1406	RO 2 ON DELAY	See parameter 1404 RO 1 ON DELAY.	0.0 s				
1407	RO 2 OFF DELAY	See parameter 1405 RO 1 OFF DELAY.	0.0 s				
1408	RO 3 ON DELAY	See parameter 1404 RO 1 ON DELAY.	0.0 s				
1409	RO 3 OFF DELAY	See parameter 1405 RO 1 OFF DELAY.	0.0 s				
1410	RELAY OUTPUT 4	See parameter 1401 RELAY OUTPUT 1. Available only if the MREL-01 output relay extension module is connected to the drive. See parameter 0181 EXT MODULE STATUS.	NOT SEL				
1413	RO 4 ON DELAY	See parameter 1404 RO 1 ON DELAY.	0.0 s				
1414	RO 4 OFF DELAY	See parameter 1405 RO 1 OFF DELAY.	0.0 s				
	15 ANALOG OUTPUTS Selection of the actual signals to be indicated through analog output and output signal processing.						
1501	AO1 CONTENT SEL	Connects a drive signal to analog output AO.	103				
	XX	Parameter index in group <i>01 OPERATING DATA</i> . Eg 102 = <i>0102 SPEED</i> .					
1502	AO1 CONTENT MIN	Defines the minimum value for the signal selected with parameter 1501 AO1 CONTENT SEL. AO minimum and maximum correspond to the 1504 MINIMUM AO1 and 1505 MAXIMUM AO1 settings as follows: AO (mA) 1505 AO (mA) 1505	-				
	xx	1504 1503 AO 1503 AO content Setting range depends on the parameter 1501 AO1	-				
1500		CONTENT SEL setting.					
1503	CONTENT MAX	Defines the maximum value for the signal selected with parameter 1501 AO1 CONTENT SEL. See the figure for parameter 1502 AO1 CONTENT MIN.	-				

All parameters						
No.	Name/Value	Description	Def/FbEq			
	xx	Setting range depends on the parameter 1501 AO1 CONTENT SEL setting.	-			
1504	MINIMUM AO1	Defines the minimum value for the analog output signal AO. See the figure for parameter 1502 AO1 CONTENT MIN.	0.0 mA			
	0.020.0 mA	Minimum value	1 = 0.1 mA			
1505	MAXIMUM AO1	Defines the maximum value for the analog output signal AO. See the figure for parameter 1502 AO1 CONTENT MIN.	20.0 mA			
	0.020.0 mA	Maximum value	1 = 0.1 mA			
1506	FILTER AO1	Defines the filter time constant for analog output AO, ie the time within which 63% of a step change is reached. See the figure for parameter 1303 FILTER AI1.	0.1 s			
	0.010.0 s	Filter time constant	1 = 0.1 s			
	/STEM TROLS	Parameter view, Run enable, parameter lock etc.				
1601	RUN ENABLE	Selects a source for the external Run enable signal.	NOT SEL			
	NOT SEL	Allows the drive to start without an external Run enable signal.	0			
	DI1	External signal required through digital input DI1. 1 = Run enable. If Run enable signal is switched off, the drive will not start or coasts to stop if it is running.	1			
	DI2	See selection DI1.	2			
	DI3	See selection DI1.	3			
	DI4	See selection DI1.	4			
	DI5	See selection DI1.	5			
	COMM	Fieldbus interface as the source for inverted Run enable signal (Run disable), ie Control word 0301 FB CMD WORD 1 bit 6 (with ABB drives profile 5319 EFB PAR 19 bit 3). The Control word is sent by the fieldbus controller through the fieldbus adapter or embedded fieldbus (Modbus) to the drive. For the Control word bits, see sections DCU communication profile on page 331 and ABB drives communication profile on page 326.	7			
	DI1(INV)	External signal required through inverted digital input DI1. 0 = Run enable. If Run enable signal is switched on, the drive will not start or coasts to stop if it is running.	-1			
	DI2(INV)	See selection DI1(INV).	-2			
	DI3(INV)	See selection DI1(INV).	-3			
	DI4(INV)	See selection DI1(INV).	-4			
	DI5(INV)	See selection DI1(INV).	-5			

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
1602	PARAMETER LOCK	Selects the state of the parameter lock. The lock prevents parameter changing from the control panel.	OPEN
	LOCKED	Parameter values cannot be changed from the control panel. The lock can be opened by entering the valid code to parameter 1603 PASS CODE. The lock does not prevent parameter changes made by macros or fieldbus.	0
	OPEN	The lock is open. Parameter values can be changed.	1
	NOT SAVED	Parameter changes from the control panel are not stored into the permanent memory. To store changed parameter values, set parameter 1607 PARAM SAVE value to SAVE	2
1603	PASS CODE	Selects the pass code for the parameter lock (see parameter 1602 PARAMETER LOCK).	0
	065535	Pass code. Setting 358 opens the lock. The value reverts back to 0 automatically.	1 = 1
1604	FAULT RESET SEL	Selects the source for the fault reset signal. The signal resets the drive after a fault trip if the cause of the fault no longer exists.	KEYPAD
	KEYPAD	Fault reset only from the control panel	0
	DI1	Reset through digital input DI1 (reset on the rising edge of DI1) or from the control panel	1
	DI2	See selection DI1.	2
	DI3	See selection DI1.	3
	DI4	See selection DI1.	4
	DI5	See selection DI1.	5
	START/STOP	Reset along with the stop signal received through a digital input, or from the control panel. Note: Do not use this option when start, stop and direction commands are received through fieldbus communication.	7
	COMM	Fieldbus interface as the source for the fault reset signal, ie Control word 0301 FB CMD WORD 1 bit 4 (with ABB drives profile 5319 EFB PAR 19 bit 7). The Control word is sent by the fieldbus controller through the fieldbus adapter or embedded fieldbus (Modbus) to the drive. For the Control word bits, see sections DCU communication profile on page 331 and ABB drives communication profile on page 326.	8
	DI1(INV)	Reset through inverted digital input DI1 (reset on the falling edge of DI1) or from the control panel	-1
	DI2(INV)	See selection <i>DI1(INV)</i> .	-2
	DI3(INV)	See selection DI1(INV).	-3
	DI4(INV)	See selection DI1(INV).	-4

All parameter	'S		
No. Name/V	'alue	Description	Def/FbEq
DI5(INV	·)	See selection DI1(INV).	-5
1605 USER F SET CH		Enables the change of the User parameter set through a digital input. See parameter 9902 APPLIC MACRO. The change is only allowed when the drive is stopped. During the change, the drive will not start.	NOT SEL
		Note: Always save the User parameter set with parameter 9902 after changing any parameter setting, or reperforming the motor identification. The last settings saved by the user are loaded into use whenever the power is switched off and on again or the parameter 9902 setting is changed. Any unsaved changes will be lost.	
		Note: The value of this parameter is not included in the User parameter sets. A setting once made remains despite User parameter set change.	
		Note: Selection of User parameter set 2 can be supervised through relay outputs RO 14 and digital output DO. See parameters 1401 RELAY OUTPUT 1 1403 RELAY OUTPUT 3, 1410 RELAY OUTPUT 4 and 1805 DO SIGNAL.	
NOT SE	EL	User parameter set change is not possible through a digital input. Parameter sets can be changed only from the control panel.	0
DI1		User parameter set control through digital input DI1. Falling edge of digital input DI1: User parameter set 1 is loaded into use. Rising edge of digital input DI1: User parameter set 2 is loaded into use.	1
DI2		See selection DI1.	2
DI3		See selection DI1.	3
DI4		See selection DI1.	4
DI5		See selection <i>DI1</i> .	5
DI1,2		User parameter set selection through digital inputs DI1 and DI2. 1 = DI active, 0 = DI inactive.	7
		DI1 DI2 User parameter set 0 0 User parameter set 1 1 0 User parameter set 2 0 1 User parameter set 3	
DI2,3		See selection DI1,2.	8
DI3,4		See selection DI1,2.	9
DI4,5		See selection DI1,2.	10
DI1(INV)	User parameter set control through inverted digital input DI1. Falling edge of inverted digital input DI1: User parameter set 2 is loaded into use. Rising edge of inverted digital input DI1: User parameter set 1 is loaded into use.	-1

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
	DI2(INV)	See selection <i>DI1(INV)</i> .	-2
	DI3(INV)	See selection <i>DI1(INV)</i> .	-3
	DI4(INV)	See selection <i>DI1(INV)</i> .	-4
	DI1,2(INV)	User parameter set selection through inverted digital inputs DI1 and DI2. 1 = DI inactive, 0 =DI active. DI1 DI2 User parameter set	-7
		1 User parameter set 1 0 1 User parameter set 2 1 0 User parameter set 3	
	DI2,3(INV)	See selection DI1,2.	-8
	DI3,4(INV)	See selection DI1,2.	-9
	DI4,5(INV)	See selection DI1,2.	-10
1606	LOCAL LOCK	Disables entering local control mode or selects the source for the local control mode lock signal. When local lock is active, entering the local control mode is disabled (LOC/REM key of the panel).	NOT SEL
	NOT SEL	Local control is allowed.	0
	DI1	Local control mode lock signal through digital input DI1. Rising edge of digital input DI1: Local control disabled. Falling edge of digital input DI1: Local control allowed.	1
	DI2	See selection DI1.	2
	DI3	See selection DI1.	3
	DI4	See selection DI1.	4
	DI5	See selection DI1.	5
	ON	Local control is disabled.	7
	COMM	Fieldbus interface as the source for the local lock, ie Control word 0301 FB CMD WORD 1 bit 14. The Control word is sent by the fieldbus controller through the fieldbus adapter or embedded fieldbus (Modbus) to the drive. For the Control word bits, see section DCU communication profile on page 331. Note: This setting applies only for the DCU profile.	8
	DI1(INV)	Local lock through inverted digital input DI1. Rising edge of inverted digital input DI1: Local control allowed. Falling edge of inverted digital input DI1: Local control disabled.	-1
	DI2(INV)	See selection DI1(INV).	-2
	DI3(INV)	See selection DI1(INV).	-3
	DI4(INV)	See selection DI1(INV).	-4
	DI5(INV)	See selection DI1(INV).	-5

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
1607	PARAM SAVE	Saves the valid parameter values to the permanent memory. Note: A new parameter value of a standard macro is saved automatically when changed from the panel but not when altered through a fieldbus connection.	DONE
	DONE	Saving completed	0
	SAVE	Saving in progress	1
1608	START ENABLE 1	Note: Functionality of the Start enable 1 signal. Note: Functionality of the Start enable signal is different from the Run enable signal. Example: External damper control application using Start enable and Run enable. Motor can start only after the damper is fully open. Drive started Start/Stop command (group 10) Start enable signals (1608 and 1609) Relay de- energized Damper closed Damper closed Damper closed Damper status Damper status Damper status Damper closed Acceleration time (2202) Motor speed	NOT SEL
	NOT SEL	Start enable signal is on.	0
	DI1	External signal required through digital input DI1. 1 = Start enable. If Start enable signal is switched off, the drive will not start or it coasts to stop if it is running and alarm START ENABLE 1 MISSING (2021) is activated	1
	DI2	See selection DI1.	2
	DI3	See selection DI1.	3
	DI4	See selection DI1.	4
	DI5	See selection DI1.	5

All pa	All parameters			
No.	Name/Value	Description	Def/FbEq	
	COMM	Fieldbus interface as the source for the inverted Start enable (Start disable) signal, ie Control word 0302 FB CMD WORD 2 bit 18 (bit 19 for Start enable 2). The Control word is sent by the fieldbus controller through the fieldbus adapter or embedded fieldbus (Modbus) to the drive. For the Control word bits, see section DCU communication profile on page 331. Note: This setting applies only for the DCU profile.	7	
	DI1(INV)	External signal required through inverted digital input DI1. 0 = Start enable. If Start enable signal is switched off, the drive will not start or it coasts to stop if it is running and alarm START ENABLE 1 MISSING (2021) is activated.	-1	
	DI2(INV)	See selection DI1(INV).	-2	
	DI3(INV)	See selection DI1(INV).	-3	
	DI4(INV)	See selection <i>DI1(INV)</i> .	-4	
	DI5(INV)	See selection <i>DI1(INV)</i> .	-5	
1609	START ENABLE 2	Selects the source for the Start enable 2 signal. See parameter 1608 START ENABLE 1.	NOT SEL	
		See parameter 1608 START ENABLE 1.		
1610	DISPLAY ALARMS	Activates/deactivates alarms OVERCURRENT (2001), OVERVOLTAGE (2002), PID SLEEP (2018) and DEVICE OVERTEMP (2009). For more information, see chapter Fault tracing on page 347.	NO	
	NO	Alarms are inactive.	0	
	YES	Alarms are active.	1	
1611	PARAMETER VIEW	Selects the parameter view, ie which parameters are shown. Note: This parameter is visible only when it is activated by the optional FlashDrop device. FlashDrop is designed for fast copying of parameters to unpowered drives. It allows for easy customization of the parameter list, eg selected parameters can be hidden. For more information, see MFDT-01 FlashDrop user's manual (3AFE68591074 [English]). FlashDrop parameter values are activated by setting parameter 9902 APPLIC MACRO to 31 (LOAD FD SET).	DEFAULT	
	DEFAULT	Complete long and short parameter lists	0	
	FLASHDROP	FlashDrop parameter list. Does not include short parameter list. Parameters which are hidden by the FlashDrop device are not visible.	1	

All parameters			
No.	Name/Value	Description	Def/FbEq
	0.03600.0 s	Delay time	1 = 0.1 s
1808	FO CONTENT SEL	Selects a drive signal to be connected to frequency output FO.	104
	xx	Parameter index in group 01 OPERATING DATA. Eg 102 = 0102 SPEED.	
1809	FO CONTENT MIN	Defines the minimum frequency output FO signal value. Signal is selected with parameter 1808 FO CONTENT SEL. FO minimum and maximum correspond to 1811 MINIMUM FO and 1812 MAXIMUM FO settings as follows: 1811 1811 1811 1809 1810 FO content 1809 1810 FO content	-
	xx	Setting range depends on parameter 1808 FO CONTENT SEL setting.	-
1810	FO CONTENT MAX	Defines the maximum frequency output FO signal value. Signal is selected with parameter 1808 FO CONTENT SEL. See parameter 1809 FO CONTENT MIN.	-
	xx	Setting range depends on parameter 1808 FO CONTENT SEL setting.	-
1811	MINIMUM FO	Defines the minimum value for frequency output FO.	10 Hz
	1016000 Hz	Minimum frequency. See parameter 1809 FO CONTENT MIN.	1 = 1 Hz
1812	MAXIMUM FO	Defines the maximum value for frequency output FO.	1000 Hz
	1016000 Hz	Maximum frequency. See parameter 1809 FO CONTENT MIN.	1 = 1 Hz
1813	FILTER FO	Defines the filter time constant for frequency output FO, ie the time within which 63% of a step change is reached.	0.1 s
	0.010.0 s	Filter time constant	1 = 0.1 s
	MER & NTER	Timer and counter for start and stop control	
1901	TIMER DELAY	Defines the time delay for the timer.	10.00 s
	0.01120.00 s	Delay time	1 = 0.01 s
1902	TIMER START	Selects the source for the timer start signal.	NOT SEL

All pa	All parameters			
No.	Name/Value	Description	Def/FbEq	
	DI1(INV)	Counter enable signal through inverted digital input DI1. 0 = active, 1 = inactive.	-1	
	DI2(INV)	See selection DI1(INV).	-2	
	DI3(INV)	See selection DI1(INV).	-3	
	DI4(INV)	See selection DI1(INV).	-4	
	DI5(INV)	See selection DI1(INV).	-5	
	DISABLED	No counter enable	0	
	DI1	Counter enable signal through digital input DI1. 1 = active, 0 = inactive.	1	
	DI2	See selection DI1.	2	
	DI3	See selection DI1.	3	
	DI4	See selection DI1.	4	
	DI5	See selection DI1.	5	
	ENABLED	Counter enabled	6	
1905	COUNTER LIMIT	Defines the counter limit.	1000	
	065535	Limit value	1 = 1	
1906	COUNTER INPUT	Selects the input signal source for the counter.	PLS IN(DI 5)	
	PLS IN(DI 5)	Digital input DI5 pulses. When a pulse is detected, the counter value increases by 1.	1	
	ENC W/O DIR	Encoder pulse edges. When a rising or a falling edge is detected, the counter value increases by 1.	2	
	ENC WITH DIR	Encoder pulse edges. The direction of rotation is taken into account. When a rising or a falling edge is detected and the direction of rotation is forward, the counter value increases by 1. When the direction of rotation is reverse, the counter value decreases by 1.	3	
	FILTERED DI5	Filtered digital input DI5 pulses. When a pulse is detected, the counter value increases by 1. Note: Due to filtering, the maximum input signal frequency is 50 Hz.	4	
1907	COUNTER RESET	Selects the source for the counter reset signal.	NOT SEL	
	DI1(INV)	Counter reset through inverted digital input DI1. 0 = active, 1 = inactive.	-1	
	DI2(INV)	See selection DI1(INV).	-2	
	DI3(INV)	See selection DI1(INV).	-3	
	DI4(INV)	See selection DI1(INV).	-4	
	DI5(INV)	See selection DI1(INV).	-5	

All pa	All parameters			
No.	Name/Value	Description	Def/FbEq	
1911	CNTR S/S COMMAND	Selects the source for the drive start/stop command when parameter 1001 EXT1 COMMANDS value is set to COUNTER START / COUNTER STOP.	NOT SEL	
	DI1(INV)	Start/stop command through inverted digital input DI1. When parameter 1001 EXT1 COMMANDS value is COUNTER STOP: 0 = start. Stop when counter limit defined by parameter 1905 COUNTER LIMIT has been exceeded. When parameter 1001 value is COUNTER START: 0 = stop. Start when counter limit defined by parameter 1905 has been exceeded.	-1	
	DI2(INV)	See selection <i>DI1(INV)</i> .	-2	
	DI3(INV)	See selection DI1(INV).	-3	
	DI4(INV)	See selection DI1(INV).	-4	
	DI5(INV)	See selection DI1(INV).	-5	
	NOT SEL	Not start/stop command source	0	
	DI1	Start/stop command through digital input DI1. When parameter 1001 EXT1 COMMANDS value is COUNTER STOP: 1 = start. Stop when counter limit defined by parameter 1905 COUNTER LIMIT has been exceeded. When parameter 1001 value is COUNTER START: 1 = stop. Start when counter limit defined by parameter 1905 has been exceeded.	1	
	DI2	See selection DI1.	2	
	DI3	See selection DI1.	3	
	DI4	See selection DI1.	4	
	DI5	See selection DI1.	5	
	ACTIVATE	External start/stop command, eg through fieldbus	6	

All parameters			
No.	Name/Value	Description	Def/FbEq
20 LI	MITS	Drive operation limits. Speed values are used in vector control and frequency values are used in scalar control. The control mode is selected by parameter 9904 MOTOR CTRL MODE.	
2001	MINIMUM SPEED	Defines the allowed minimum speed. A positive (or zero) minimum speed value defines two ranges, one positive and one negative. A negative minimum speed value defines one speed range. Speed 2001 value is < 0 Allowed speed range 2001 Allowed speed range 1	0 rpm
	-30000 30000 rpm	Minimum speed	1 = 1 rpm
2002	MAXIMUM SPEED	Defines the allowed maximum speed. See parameter 2001 MINIMUM SPEED.	E: 1500 rpm / U: 1800 rpm
	030000 rpm	Maximum speed	1 = 1 rpm
2003	MAX CURRENT	Defines the allowed maximum motor current.	1.8 · <i>I</i> _{2N} A
	0.01.8 · <i>I</i> _{2N} A	Current	1 = 0.1 A
2005	OVERVOLT CTRL	Activates or deactivates the overvoltage control of the intermediate DC link. Fast braking of a high inertia load causes the voltage to rise to the overvoltage control limit. To prevent the DC voltage from exceeding the limit, the overvoltage controller automatically decreases the braking torque. Note: If a brake chopper and resistor are connected to the drive, the controller must be off (selection DISABLE) to allow chopper operation.	ENABLE
	DISABLE	Overvoltage control deactivated	0
	ENABLE	Overvoltage control activated	1

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
2006	UNDERVOLT CTRL	Activates or deactivates the undervoltage control of the intermediate DC link. If the DC voltage drops due to input power cut off, the undervoltage controller will automatically decrease the motor speed in order to keep the voltage above the lower limit. By decreasing the motor speed, the inertia of the load will cause regeneration back into the drive, keeping the DC link charged and preventing an undervoltage trip until the motor coasts to stop. This will act as a power-loss ridethrough functionality in systems with a high inertia, such as a centrifuge or a fan. See section <i>Motor identification</i> on page 140.	ENABLE(TIME)
	DISABLE	Undervoltage control deactivated	0
	ENABLE(TIME)	Undervoltage control activated. The undervoltage control is active for 500 ms.	1
	ENABLE	Undervoltage control activated. No operation time limit.	2
2007	MINIMUM FREQ	Defines the minimum limit for the drive output frequency. A positive (or zero) minimum frequency value defines two ranges, one positive and one negative. A negative minimum frequency value defines one speed range. Note: MINIMUM FREQ ≤ MAXIMUM FREQ. 2008 2008 value is < 0 2008 Allowed frequency range 1 1 1 1 1 1 1 1 1	0.0 Hz
	-500.0500.0 Hz	Minimum frequency	1 = 0.1 Hz
2008	MAXIMUM FREQ	Defines the maximum limit for the drive output frequency.	E: 50.0 Hz U: 60.0 Hz
	0.0600.0 Hz	Maximum frequency	1 = 0.1 Hz
2013	MIN TORQUE SEL	Selects the minimum torque limit for the drive.	MIN TORQUE 1
	MIN TORQUE 1	Value defined by parameter 2015 MIN TORQUE 1	0
	DI1	Digital input DI1. 0 = parameter 2015 MIN TORQUE 1 value. 1 = parameter 2016 MIN TORQUE 2 value.	1

All pa	All parameters			
No.	Name/Value	Description	Def/FbEq	
	COMM	Fieldbus interface as the source for the torque limit 1/2 selection, ie Control word 0301 FB CMD WORD 1 bit 15. The Control word is sent by the fieldbus controller through the fieldbus adapter or embedded fieldbus (Modbus) to the drive. For the Control word bits, see section DCU communication profile on page 331. Maximum torque limit 1 is defined by parameter 2017 MAX TORQUE 1 and maximum torque limit 2 is defined by parameter 2018 MAX TORQUE 2.	7	
		Note: This setting applies only for the DCU profile.		
	EXT2	Value of signal 0112 EXTERNAL REF 2	11	
	DI1(INV)	Inverted digital input DI1. 1 = parameter 2017 MAX TORQUE 1 value. 0 = parameter 2018 MAX TORQUE 2 value.	-1	
	DI2(INV)	See selection DI1(INV).	-2	
	DI3(INV)	See selection DI1(INV).	-3	
	DI4(INV)	See selection DI1(INV).	-4	
	DI5(INV)	See selection DI1(INV).	-5	
2015	MIN TORQUE 1	Defines minimum torque limit 1 for the drive. See parameter 2013 MIN TORQUE SEL.	-300%	
	-600.00.0%	Value as a percentage of the motor nominal torque	1 = 0.1%	
2016	MIN TORQUE 2	Defines minimum torque limit 2 for the drive. See parameter 2013 MIN TORQUE SEL.	-300%	
	-600.00.0%	Value as a percentage of the motor nominal torque	1 = 0.1%	
2017	MAX TORQUE 1	Defines maximum torque limit 1 for the drive. See parameter 2014 MAX TORQUE SEL.	300%	
	0.0600.0%	Value as a percentage of the motor nominal torque	1 = 0.1%	
2018	MAX TORQUE 2	Defines maximum torque limit 2 for the drive. See parameter 2014 MAX TORQUE SEL.	300%	
	0.0600.0%	Value as a percentage of the motor nominal torque	1 = 0.1%	

All p	All parameters			
No.	Name/Value	Description	Def/FbEq	
	DC MAGN	The drive pre-magnetizes the motor with DC current before the start. The pre-magnetizing time is defined by parameter <i>2103 DC MAGN TIME</i> .	2	
		If parameter 9904 MOTOR CTRL MODE value is VECTOR: SPEED or VECTOR: TORQ, DC magnetizing guarantees the highest possible break-away torque when the premagnetizing is set long enough. Note: Starting the drive connected to a rotating motor is not		
		possible when <i>DC MAGN</i> is selected. When a permanent magnet synchronous motor is used, alarm <i>MOTOR BACK EMF</i> (2029) is generated.		
		WARNING! The drive will start after the set premagnetizing time has passed even if the motor magnetization is not completed. In applications where a full break-away torque is essential, always ensure that the constant magnetizing time is long enough to allow generation of full magnetization and torque.		
	TORQ BOOST	Torque boost should be selected if a high break-away torque is required. Used only when parameter 9904 MOTOR CTRL MODE setting is SCALAR: FREQ.	4	
		The drive pre-magnetizes the motor with DC current before the start. The pre-magnetizing time is defined by parameter <i>2103 DC MAGN TIME</i> .		
		Torque boost is applied at start. Torque boost is stopped when output frequency exceeds 20 Hz or when it is equal to the reference value. See parameter 2110 TORQ BOOST CURR.		
		Note: Starting the drive connected to a rotating motor is not possible when <i>TORQ BOOST</i> is selected.		
		WARNING! The drive will start after the set premagnetizing time has passed although the motor magnetization is not completed. In applications where a full break-away torque is essential, always ensure that the constant magnetizing time is long enough to allow generation of full magnetization and torque.		
	SCAN START	Frequency scanning flying start (starting the drive connected to a rotating motor). Based on frequency scanning (interval 2008 MAXIMUM FREQ2007 MINIMUM FREQ) to identify the frequency. If frequency identification fails, DC magnetization is used (see selection DC MAGN). Not for multimotor drives.	6	

All parameters			
No.	Name/Value	Description	Def/FbEq
	DC HOLD	DC hold function active. DC hold is not possible if parameter 9904 MOTOR CTRL MODE setting is SCALAR: FREQ.	1
		When both the reference and the motor speed drop below the value of parameter 2105 DC HOLD SPEED, the drive will stop generating sinusoidal current and start to inject DC into the motor. The current is set by parameter 2106 DC CURR REF. When the reference speed exceeds parameter 2105 value, normal drive operation continues.	
		Motor speed	
		Note: DC hold has no effect if the start signal is switched off. Note: Injecting DC current into the motor causes the motor to heat up. In applications where long DC hold times are required, externally ventilated motors should be used. If the DC hold period is long, the DC hold cannot prevent the motor shaft from rotating if a constant load is applied to the	
	DC BRAKING	motor. DC current braking function active.	2
	DO DIVARINO	If parameter 2102 STOP FUNCTION is set to COAST, DC braking is applied after the start command is removed. If parameter 2102 STOP FUNCTION is set to RAMP, DC braking is applied after the ramp.	_
2105	DC HOLD SPEED	Defines the DC hold speed. See parameter 2104 DC HOLD CTL.	5 rpm
	0360 rpm	Speed	1 = 1 rpm
2106	DC CURR REF	Defines the DC hold current. See parameter 2104 DC HOLD CTL.	30%
	0100%	Value as a percentage of the nominal motor current (parameter 9906 MOTOR NOM CURR)	1 = 1%
2107	DC BRAKE TIME	Defines the DC brake time.	0.0 s
	0.0250.0 s	Time	1 = 0.1 s

All pa	All parameters			
No.	Name/Value	Description	Def/FbEq	
	START INHIBIT	 Sets the Start inhibit function on or off. If the drive is not actively started and running, the Start inhibit function ignores a pending start command in any of the following situations and a new start command is required: a fault is reset. Run enable signal activates while the start command is active. See parameter 1601 RUN ENABLE. control mode changes from local to remote. external control mode switches from EXT1 to EXT2 or from EXT2 to EXT1. the drive that is set to external pulse start (parameter 1001 EXT1 COMMANDS is set to DI1P,2P; DI1P,2P,3 or DI1P,2P,3P) is powered up and the corresponding digital inputs (DI1 and DI2 or DI3) are at high level during power-up. 	OFF	
	OFF	Disabled	0	
	ON	Enabled	1	
2109	EMERG STOP SEL	Selects the source for the external emergency stop command. The drive cannot be restarted before the emergency stop command is reset. Note: The installation must include emergency stop devices and any other safety equipment that may be needed. Pressing the stop key on the drive's control panel does NOT: • generate an emergency stop of the motor • separate the drive from dangerous potential.	NOT SEL	
	NOT SEL	Emergency stop function is not selected	0	
	DI1	Digital input DI1. 1 = stop along the emergency stop ramp. See parameter 2208 EMERG DEC TIME. 0 = emergency stop command reset.	1	
	DI2	See selection DI1.	2	
	DI3	See selection DI1.	3	
	DI4	See selection DI1.	4	
	DI5	See selection DI1.	5	
	DI1(INV)	Inverted digital input DI. 0 = stop along the emergency stop ramp. See parameter 2208 EMERG DEC TIME. 1 = emergency stop command reset	-1	
	DI2(INV)	See selection <i>DI1(INV)</i> .	-2	
	DI3(INV)	See selection DI1(INV).	-3	
	DI4(INV)	See selection DI1(INV).	-4	
	DI5(INV)	See selection <i>DI1(INV)</i> .	-5	

All parameters			
No.	Name/Value	Description	Def/FbEq
2110	TORQ BOOST CURR	Defines the maximum supplied current during torque boost. See parameter <i>2101 START FUNCTION</i> .	100%
	15300%	Value as a percentage	1 = 1%
2111	STOP SIGNAL DLY	Defines the stop signal delay time when parameter 2102 STOP FUNCTION is set to SPEED COMP.	0 ms
	010000 ms	Delay time	1 = 1 ms
2112	ZERO SPEED DELAY	Defines the delay for the Zero speed delay function. The function is useful in applications where a smooth and quick restarting is essential. During the delay the drive knows accurately the rotor position. No Zero speed delay With Zero speed delay	0.0 = NOT SEL
		Speed controller switched off: Motor coasts to stop. No Zero speed delay The drive receives a stop command and decelerates along a ramp. When the motor actual speed falls below an internal limit (called Zero speed), the speed controller is switched off. The inverter modulation is stopped and the motor coasts to standstill. With Zero speed delay The drive receives a stop command and decelerates along a ramp. When the actual motor speed falls below an internal limit (called Zero speed), the zero speed falls below an internal limit (called Zero speed), the zero speed delay function activates. During the delay the functions keeps the speed controller live: The inverter modulates, motor is magnetized and the drive is ready for a quick restart.	
	0.0 = NOT SEL 0.060.0 s	Delay time. If parameter value is set to zero, Zero speed delay function is disabled.	1 = 0.1 s
22 A	CCEL/DECEL	Acceleration and deceleration times	
2201	ACC/DEC 1/2 SEL	Defines the source from which the drive reads the signal that selects between the two ramp pairs, acceleration/deceleration pair 1 and 2. Ramp pair 1 is defined by parameters 22022204. Ramp pair 2 is defined by parameters 22052207.	DI5
	NOT SEL	Ramp pair 1 is used.	0
	DI1	Digital input DI1. 1 = ramp pair 2, 0 = ramp pair 1.	1

All parameters			
No.	Name/Value	Description	Def/FbEq
	DI2	See selection <i>DI1</i> .	2
	DI3	See selection DI1.	3
	DI4	See selection DI1.	4
	DI5	See selection DI1.	5
	COMM	Fieldbus interface as the source for ramp pair 1/2 selection, ie Control word 0301 FB CMD WORD 1 bit 10. The Control word is sent by the fieldbus controller through the fieldbus adapter or embedded fieldbus (Modbus) to the drive. For the Control word bits, see section DCU communication profile on page 331. Note: This setting applies only for the DCU profile.	7
	SEQ PROG	Sequence programming ramp defined by parameter 8422 ST1 RAMP (or 8423//8492)	10
	DI1(INV)	Inverted digital input DI1. 0 = ramp pair 2, 1 = ramp pair 1.	-1
	DI2(INV)	See selection <i>DI1(INV)</i> .	-2
	DI3(INV)	See selection <i>DI1(INV)</i> .	-3
	DI4(INV)	See selection DI1(INV).	-4
	DI5(INV)	See selection DI1(INV).	-5
2202	ACCELER TIME 1	Defines the acceleration time 1, ie the time required for the speed to change from zero to the speed defined by parameter 2008 MAXIMUM FREQ (in scalar control) / 2002 MAXIMUM SPEED (in vector control). The control mode is selected by parameter 9904 MOTOR CTRL MODE. • If the speed reference increases faster than the set acceleration rate, the motor speed will follow the acceleration rate. • If the speed reference increases slower than the set acceleration rate, the motor speed will follow the reference signal. • If the acceleration time is set too short, the drive will automatically prolong the acceleration in order not to exceed the drive operating limits. Actual acceleration time depends on parameter 2204 RAMP SHAPE 1 setting.	5.0 s
	0.01800.0 s	Time	1 = 0.1 s

All parameters			
No.	Name/Value	Description	Def/FbEq
2203	DECELER TIME 1	Defines the deceleration time 1, ie the time required for the speed to change from the value defined by parameter 2008 MAXIMUM FREQ (in scalar control) / 2002 MAXIMUM SPEED (in vector control) to zero. The control mode is selected by parameter 9904 MOTOR CTRL MODE. • If the speed reference decreases slower than the set deceleration rate, the motor speed will follow the	5.0 s
		 reference signal. If the reference changes faster than the set deceleration rate, the motor speed will follow the deceleration rate. 	
		If the deceleration time is set too short, the drive will automatically prolong the deceleration in order not to exceed drive operating limits.	
		If a short deceleration time is needed for a high inertia application, the drive should be equipped with a brake resistor.	
		Actual deceleration time depends on parameter 2204 RAMP SHAPE 1 setting.	
	0.01800.0 s	Time	1 = 0.1 s
2204	RAMP SHAPE 1	Selects the shape of the acceleration/deceleration ramp 1. The function is deactivated during emergency stop and jogging.	0.0 = LINEAR
	0.0 = LINEAR 0.11000.0 s	0.0: Linear ramp. Suitable for steady acceleration or deceleration and for slow ramps. 0.11000.0 s: S-curve ramp. S-curve ramps are ideal for conveyors carrying fragile loads, or other applications where a smooth transition is required when changing from one speed to another. The S-curve consists of symmetrical curves at both ends of the ramp and a linear part in between. A rule of thumb: A suitable relation between the ramp shape time and the acceleration ramp time is 1/5. Speed Linear ramp: Par. 2204 = 0 s Max Par. 2202 Par. 2204	1 = 0.1 s

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
2205	ACCELER TIME 2	Defines the acceleration time 2, ie the time required for the speed to change from zero to the speed defined by parameter 2008 MAXIMUM FREQ (in scalar control) / 2002 MAXIMUM SPEED (in vector control). The control mode is selected by parameter 9904 MOTOR CTRL MODE. See parameter 2202 ACCELER TIME 1. Acceleration time 2 is used also as jogging acceleration time. See parameter 1010 JOGGING SEL.	60.0 s
	0.01800.0 s	Time	1 = 0.1 s
2206	DECELER TIME 2	Defines the deceleration time 2, ie the time required for the speed to change from the value defined by parameter 2008 MAXIMUM FREQ (in scalar control) / 2002 MAXIMUM SPEED (in vector control) to zero. The control mode is selected by parameter 9904 MOTOR CTRL MODE. See parameter 2203 DECELER TIME 1. Deceleration time 2 is used also as jogging deceleration time. See parameter 1010 JOGGING SEL.	60.0 s
	0.01800.0 s	Time	1 = 0.1 s
2207	RAMP SHAPE 2	Selects the shape of the acceleration/deceleration ramp 2. The function is deactivated during emergency stop. During jogging, parameter value is set to zero (ie linear ramp). See 1010 JOGGING SEL.	0.0 = LINEAR
	0.0 = LINEAR 0.11000.0 s	See parameter 2204 RAMP SHAPE 1.	1 = 0.1 s
2208	EMERG DEC TIME	Defines the time within which the drive is stopped if an emergency stop is activated. See parameter 2109 EMERG STOP SEL.	1.0 s
	0.01800.0 s	Time	1 = 0.1 s
2209	RAMP INPUT 0	Defines the control for forcing the speed to 0 with the currently used deceleration ramp (see parameters 2203 DECELER TIME 1 and 2206 DECELER TIME 2).	NOT SEL
	NOT SEL	Not selected	0
	DI1	 Digital input DI1. Defines digital input DI1 as the control for forcing the speed to zero. Activating the digital input forces the speed to zero, after which the speed will stay at zero. De-activating the digital input: speed control resumes normal operation. 	1
	DI2	See selection DI1.	2
	DI3	See selection DI1.	3
	DI4	See selection DI1.	4
	DI5	See selection DI1.	5

All parameters	All parameters			
No. Name/Value	Description	Def/FbEq		
COMM	Defines bit 13 of Command word 1 as the control for forcing the speed to zero. The Command word 1 is supplied through fieldbus communication (parameter <i>0301</i>).	7		
DI1(INV)	 Inverted digital input DI1. Defines inverted digital input DI1 as the control for forcing the speed to zero. De-activating the digital input forces the speed to zero. Activating the digital input: speed control resumes normal operation. 	-1		
DI2(INV)	See selection DI1(INV).	-2		
DI3(INV)	See selection DI1(INV).	-3		
DI4(INV)	See selection DI1(INV).	-4		
DI5(INV)	See selection DI1(INV).	-5		
23 SPEED CONTROL	Speed controller variables. See section Speed controller tuning on page 147. Note: These parameters do not affect drive operation in scalar control, ie when parameter 9904 MOTOR CTRL MODE setting is SCALAR: FREQ.			
2301 PROP GAIN	Defines a relative gain for the speed controller. High gain may cause speed oscillation. The figure below shows the speed controller output after an error step when the error remains constant. $ \begin{array}{c} \text{Gain} = K_p = 1 \\ T_1 = \text{Integration time} = 0 \\ T_D = \text{Derivation time} = 0 \end{array} $ Controller output $= K_p \cdot e$ $ \begin{array}{c} \text{Controller output} \\ \text{Value} \end{array} $ Controller output $= K_p \cdot e$ $ \begin{array}{c} \text{Controller output} \\ \text{Value} \end{array} $ Note: For automatic setting of the gain, use autotune run (parameter 2305 AUTOTUNE RUN).	5.00		
0.00200.00	Gain	1 = 0.01		

All parameters			
No.	Name/Value	Description	Def/FbEq
	INTEGRATION TIME	Defines an integration time for the speed controller. The integration time defines the rate at which the controller output changes when the error value is constant. The shorter the integration time, the faster the continuous error value is corrected. Too short an integration time makes the control unstable. The figure below shows the speed controller output after an error step when the error remains constant. $ \begin{array}{c} Gain = K_p = 1 \\ T_l = Integration time > 0 \\ T_D = Derivation time = 0 \end{array} $ Note: For automatic setting of the integration time, use autotune run (parameter 2305 AUTOTUNE RUN).	0.50 s
	0.00600.00 s	Time	1 = 0.01 s

All parameters			
No. Name/	Value	Description	Def/FbEq
2303 DERIV TIME		Defines the derivation time for the speed controller. Derivative action boosts the controller output if the error value changes. The longer the derivation time, the more the speed controller output is boosted during the change. If the derivation time is set to zero, the controller works as a PI controller, otherwise as a PID controller. The derivation makes the control more responsive for disturbances. The figure below shows the speed controller output after an error step when the error remains constant. $K_p \cdot T_D \cdot \frac{\Delta e}{T_s}$ $K_p \cdot e$	0 ms
010	000 ms	Time	1 = 1 ms

All parame	eters		
-	e/Value	Description	Def/FbEq
2304 ACC		Defines the derivation time for acceleration/(deceleration) compensation. In order to compensate inertia during acceleration, a derivative of the reference is added to the output of the speed controller. The principle of a derivative action is described for parameter 2303 DERIVATION TIME. Note: As a general rule, set this parameter to the value between 50 and 100% of the sum of the mechanical time constants of the motor and the driven machine. (The speed controller Autotune run does this automatically, see parameter 2305 AUTOTUNE RUN.) The figure below shows the speed responses when a high inertia load is accelerated along a ramp. No acceleration compensation Acceleration compensation Acceleration compensation	0.00 s
0.00	600.00 s	Time	1 = 0.01 s
2305 AUT		 Start automatic tuning of the speed controller. Instructions: Run the motor at a constant speed of 20 to 40% of the rated speed. Change the autotuning parameter 2305 to ON. Note: The motor load must be connected to the motor. 	OFF
OFF		No autotuning	0
ON		Activates the speed controller autotuning. The drive • accelerates the motor • calculates values for proportional gain, integration time and acceleration compensation (parameter 2301 PROP GAIN, 2302 INTEGRATION TIME and 2304 ACC COMPENSATION values). Setting is automatically reverted to OFF.	1
24 TORQU CONTROL		Torque control variables	
2401 TOR UP		Defines the torque reference ramp up time, ie the minimum time for the reference to increase from zero to the nominal motor torque.	0.00 s
0.00	120.00 s	Time	1 = 0.01 s

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
2402	TORQ RAMP DOWN	Defines the torque reference ramp down time, ie the minimum time for the reference to decrease from the nominal motor torque to zero.	0.00 s
	0.00120.00 s	Time	1 = 0.01 s
25 CI SPEE	RITICAL EDS	Speed bands within which the drive is not allowed to operate.	
2501	CRIT SPEED SEL	Activates/deactivates the critical speeds function. The critical speed function avoids specific speed ranges. Example: A fan has vibrations in the range of 18 to 23 Hz and 46 to 52 Hz. To make the drive to jump over the vibration speed ranges: • Activate the critical speeds function. • Set the critical speed ranges as in the figure below. $f_{\text{output}} \text{ (Hz)}$	OFF
	OFF	Inactive	0
	ON	Active	1
2502	CRIT SPEED 1 LO 0.0500.0 Hz/ 030000 rpm	Defines the minimum limit for critical speed/frequency range 1. Limit in rpm. Limit in Hz if parameter 9904 MOTOR CTRL MODE setting is SCALAR: FREQ. The value cannot be	0.0 Hz / 1 rpm 1 = 0.1 Hz / 1 rpm
2503	CRIT SPEED 1 HI	above the maximum (parameter 2503 CRIT SPEED 1 HI). Defines the maximum limit for critical speed/frequency range 1.	0.0 Hz / 1 rpm
	0.0500.0 Hz/ 030000 rpm	Limit in rpm. Limit in Hz if parameter 9904 MOTOR CTRL MODE setting is SCALAR: FREQ. The value cannot be below the minimum (parameter 2502 CRIT SPEED 1 LO).	1 = 0.1 Hz / 1 rpm
2504	CRIT SPEED 2 LO	See parameter 2502 CRIT SPEED 1 LO.	0.0 Hz / 1 rpm
	0.0500.0 Hz/ 030000 rpm	See parameter 2502.	1 = 0.1 Hz / 1 rpm
2505	CRIT SPEED 2 HI	See parameter 2503 CRIT SPEED 1 HI.	0.0 Hz / 1 rpm

All pa	All parameters			
No.	Name/Value	Description	Def/FbEq	
	0.0500.0 Hz/ 030000 rpm	See parameter 2503.	1 = 0.1 Hz / 1 rpm	
2506	CRIT SPEED 3 LO	See parameter 2502 CRIT SPEED 1 LO.	0.0 Hz / 1 rpm	
	0.0500.0 Hz/ 030000 rpm	See parameter 2502.	1 = 0.1 Hz / 1 rpm	
2507	CRIT SPEED 3 HI	See parameter 2503 CRIT SPEED 1 HI.	0.0 Hz / 1 rpm	
	0.0500.0 Hz/ 030000 rpm	See parameter 2503.	1 = 0.1 Hz / 1 rpm	
	OTOR TROL	Motor control variables		
2601	FLUX OPT ENABLE	Activates/deactivates the flux optimization function. Flux optimization reduces the total energy consumption and motor noise level when the drive operates below the nominal load. The total efficiency (motor and the drive) can be improved by 1% to 10%, depending on the load torque and speed. The disadvantage of this function is that the dynamic performance of the drive is weakened.	OFF	
	OFF	Inactive	0	
	ON	Active	1	
2602	FLUX BRAKING	Activates/deactivates the Flux braking function. See section Flux braking on page 143.	OFF	
	OFF	Inactive	0	
	MODERATE	Flux level is limited during the braking. Deceleration time is longer compared to full braking.	1	
	FULL	Maximum braking power. Almost all available current is used to convert the mechanical braking energy to thermal energy in the motor.	2	

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
	IR COMP VOLT	Defines the output voltage boost at zero speed (IR compensation). The function is useful in applications with a high break-away torque when vector control cannot be applied. To prevent overheating, set IR compensation voltage as low as possible. Note: The function can be used only when parameter 9904 MOTOR CTRL MODE setting is SCALAR: FREQ. The figure below illustrates the IR compensation. Typical IR compensation values: P_N (kW)	Type dependent
	0.0100.0 V	Voltage boost	1 = 0.1 V
2604	IR COMP FREQ	Defines the frequency at which the IR compensation is 0 V. See the figure for parameter 2603 IR COMP VOLT Note: If parameter 2605 U/F RATIO is set to USER DEFINED, this parameter is not active. The IR compensation frequency is set by parameter 2610 USER DEFINED U1.	
	0100%	Value as a percentage of the motor frequency	1 = 1%
2605	U/F RATIO	Selects the voltage to frequency (U/f) ratio below the field weakening point. For scalar control only.	LINEAR
	LINEAR	Linear ratio for constant torque applications.	1
	SQUARED	Squared ratio for centrifugal pump and fan applications. With squared U/f ratio the noise level is lower for most operating frequencies. Not recommended for permanent magnet synchronous motors.	2
	USER DEFINED	Custom ratio defined by parameters 26102618. See section Custom U/f ratio on page 146.	3

* Temperature depends on the drive output frequency.

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
	ON (LOAD)	The drive is started with 4 kHz switching frequency to gain maximum output during the start. After start-up, the switching frequency is controlled towards the selected value (parameter 2607 SWITCH FREQ CTRL) if the output current or the temperature allows. This selection provides adaptive switching frequency control. Adaptation decreases the output performance in some cases. $f_{\text{SW}} \text{ limit} \blacktriangle$	2
		Drive current I _{2N} Drive temperature	
		80100 °C * 100120 °C * 50% ** 100% **	
		* Temperature depends on the drive output frequency. ** Short term overloading is allowed with each switching frequency depending on actual loading.	
2608	SLIP COMP RATIO	Defines the slip gain for the motor slip compensation control. 100% means full slip compensation, 0% means no slip compensation. Other values can be used if a static speed error is detected despite the full slip compensation. Can be used only in scalar control (ie when parameter 9904 MOTOR CTRL MODE setting is SCALAR: FREQ). Example: 35 Hz constant speed reference is given to the drive. Despite the full slip compensation (SLIP COMP RATIO = 100%), a manual tachometer measurement from the motor axis gives a speed value of 34 Hz. The static speed error is 35 Hz - 34 Hz = 1 Hz. To compensate the error, the slip gain should be increased.	0%
	0200%	Slip gain	1 = 1%
2609	NOISE SMOOTHING	Enables the noise smoothing function. Noise smoothing distributes the acoustic motor noise over a range of frequencies instead of a single tonal frequency resulting in lower peak noise intensity. A random component with an average of 0 Hz is added to the switching frequency set by parameter 2606 SWITCHING FREQ. Note: Parameter has no effect if parameter 2606	DISABLE
		SWITCHING FREQ is set to 16 kHz.	
	DISABLE	Disabled	0

All pa	rameters		
No.	Name/Value	Description	Def/FbEq
	ENABLE	Enabled	1
2610	USER DEFINED U1	Defines the first voltage point of the custom U/f curve at the frequency defined by parameter 2611 USER DEFINED F1. See section Custom U/f ratio on page 146.	19% of <i>U</i> _N
	0120% of <i>U</i> _N V	Voltage	1 = 1 V
2611	USER DEFINED F1	Defines the first frequency point of the custom U/f curve.	10.0 Hz
	0.0500.0 Hz	Frequency	1 = 0.1 Hz
2612	USER DEFINED U2	Defines the second voltage point of the custom U/f curve at the frequency defined by parameter 2613 USER DEFINED F2. See section Custom U/f ratio on page 146.	38% of <i>U</i> _N
	0120% of <i>U</i> _N V	Voltage	1 = 1 V
2613	USER DEFINED F2	Defines the second frequency point of the custom U/f curve.	20.0 Hz
	0.0500.0 Hz	Frequency	1 = 0.1 Hz
2614	USER DEFINED U3	Defines the third voltage point of the custom U/f curve at the frequency defined by parameter 2615 USER DEFINED F3. See section Custom U/f ratio on page 146.	47.5% of <i>U</i> _N
	0120% of <i>U</i> _N V	Voltage	1 = 1 V
2615	USER DEFINED F3	Defines the third frequency point of the custom U/f curve.	25.0 Hz
	0.0500.0 Hz	Frequency	1 = 0.1 Hz
2616	USER DEFINED U4	Defines the fourth voltage point of the custom U/f curve at the frequency defined by parameter 2617 USER DEFINED F4. See section Custom U/f ratio on page 146.	76% of <i>U</i> _N
	0120% of <i>U</i> _N V	Voltage	1 = 1 V
2617	USER DEFINED F4	Defines the fourth frequency point of the custom U/f curve.	40.0 Hz
	0.0500.0 Hz	Frequency	1 = 0.1 Hz
2618	FW VOLTAGE	Defines the voltage of the U/f curve when frequency is equal to or exceeds the motor nominal frequency (9907 MOTOR NOM FREQ). See section Custom U/f ratio on page 146.	95% of <i>U</i> _N
	0120% of <i>U</i> _N V	Voltage	1 = 1 V
2619	DC STABILIZER	Enables or disables the DC voltage stabilizer. The DC stabilizer is used to prevent possible voltage oscillations in the drive DC bus caused by motor load or weak supply network. In case of voltage variation, the drive tunes the frequency reference to stabilize the DC bus voltage and therefore the load torque oscillation.	DISABLE
	DISABLE	Disabled	0
	ENABLE	Enabled	1

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
2621	SMOOTH START	Selects the forced current vector rotation mode at low speeds. When the smooth start mode is selected, the rate of acceleration is limited by the acceleration and deceleration ramp times (parameters 2202 and 2203). If the process driven by the permanent magnet synchronous motor has high inertia, slow ramp times are recommended. Can be used for permanent magnet synchronous motors only (see chapter Appendix: Permanent magnet synchronous motors (PMSMs)).	NO
	NO	Disabled	0
	ALWAYS	Enabled always when the frequency is below the smooth start frequency (parameter 2623 SMOOTH START FRQ).	1
	START ONLY	Enabled below the smooth start frequency (parameter 2623 SMOOTH START FRQ) only when starting the motor.	2
2622	SMOOTH START CUR	Current used in the current vector rotation at low speeds. Increase the smooth start current if the application requires high pull-up torque. Decrease the smooth start current if motor shaft swinging needs to be minimized. Note that accurate torque control is not possible in the current vector rotation mode. Can be used for permanent magnet synchronous motors	50%
		only (see chapter Appendix: Permanent magnet synchronous motors (PMSMs)).	
	10100%	Value as a percentage of the nominal motor current	1 = 1%
2623	SMOOTH START FRQ	Output frequency up to which the current vector rotation is used. Can be used for permanent magnet synchronous motors only (see chapter <i>Appendix: Permanent magnet synchronous motors (PMSMs)</i>).	10%
	2100%	Value as a percentage of the motor nominal frequency	1 = 1%
2624	SMOOTH START TIME	The maximum time the smooth start feature is active. When value is set to 0 (default), the smooth start time limitation is not activated.	0 s
	0.2100.0 s	Maximum time in seconds	1 = 1 s
29 MA	AINTENANCE	Maintenance triggers	
2901	COOLING FAN TRIG	Defines the trigger point for the drive cooling fan run time counter. Value is compared to parameter 2902 COOLING FAN ACT value.	0.0 kh
	0.06553.5 kh	Time. If parameter value is set to zero, the trigger is disabled.	1 = 0.1 kh

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
30 FA	AULT CTIONS	Programmable protection functions	
3001	AI <min FUNCTION</min 	Defines the drive response if the analog input (AI) signal drops below the fault limits and AI is used	NOT SEL
		as the active reference source (group 11 REFERENCE SELECT)	
		 as the process or external PID controllers' feedback or setpoint source (group 40 PROCESS PID SET 1, 41 PROCESS PID SET 2 or 42 EXT / TRIM PID) and the corresponding PID controller is active. 	
		3021 AI1 FAULT LIMIT and 3022 AI2 FAULT LIMIT set the fault limits.	
	NOT SEL	Protection is inactive.	0
	FAULT	The drive trips on fault AI1 LOSS (0007) / AI2 LOSS (0008) and the motor coasts to stop. Fault limit is defined by parameter 3021 AI1 FAULT LIMIT / 3022 AI2 FAULT LIMIT.	1
	CONST SP 7	The drive generates alarm A/1 LOSS (2006) / A/2 LOSS (2007) and sets the speed to the value defined by parameter 1208 CONST SPEED 7. Alarm limit is defined by parameter 3021 A/1 FAULT LIMIT / 3022 A/2 FAULT LIMIT.	2
		WARNING! Make sure that it is safe to continue operation in case the analog input signal is lost.	
	LAST SPEED	The drive generates alarm Al1 LOSS (2006) / Al2 LOSS (2007) and freezes the speed to the level the drive was operating at. The speed is determined by the average speed over the previous 10 seconds. Alarm limit is defined by parameter 3021 Al1 FAULT LIMIT / 3022 Al2 FAULT LIMIT.	3
		WARNING! Make sure that it is safe to continue operation in case the analog input signal is lost.	
3002	PANEL COMM ERR	Selects how the drive reacts to a control panel communication break.	FAULT
		Note: When either of the two external control locations are active, and start, stop and/or direction are through the control panel – 1001 EXT1 COMMANDS / 1002 EXT2 COMMANDS = 8 (KEYPAD) – the drive follows the speed reference according to the configuration of the external control locations, instead of the value of the last speed or parameter 1208 CONST SPEED 7.	
	FAULT	Drive trips on fault <i>PANEL LOSS</i> (0010) and the motor coasts to stop.	1

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
	CONST SP 7	The drive generates alarm <i>PANEL LOSS</i> (2008) and sets the speed to the speed defined by parameter 1208 CONST SPEED 7. WARNING! Make sure that it is safe to continue operation in case of a panel communication break.	2
	LAST SPEED	The drive generates alarm <i>PANEL LOSS</i> (2008) and freezes the speed to the level the drive was operating at. The speed is determined by the average speed over the previous 10 seconds. WARNING! Make sure that it is safe to continue operation in case of a panel communication break.	3
3003	EXTERNAL FAULT 1	Selects an interface for an external fault 1 signal.	NOT SEL
	NOT SEL	Not selected	0
	DI1	External fault indication through digital input DI1. 1 = Fault trip on EXT FAULT 1 (0014). Motor coasts to stop. 0 = No external fault.	1
	DI2	See selection DI1.	2
	DI3	See selection <i>DI1</i> .	3
	DI4	See selection <i>DI1</i> .	4
	DI5	See selection DI1.	5
	DI1(INV)	External fault indication through inverted digital input DI1. 0 = Fault trip on EXT FAULT 1 (0014). Motor coasts to stop. 1 = No external fault.	-1
	DI2(INV)	See selection <i>DI1(INV)</i> .	-2
	DI3(INV)	See selection <i>DI1(INV)</i> .	-3
	DI4(INV)	See selection DI1(INV).	-4
	DI5(INV)	See selection <i>DI1(INV)</i> .	-5
3004	EXTERNAL FAULT 2	Selects an interface for an external fault 2 signal.	NOT SEL
		See parameter 3003 EXTERNAL FAULT 1.	
3005	MOT THERM PROT	Selects how the drive reacts when the motor overtemperature is detected.	FAULT
	NOT SEL	Protection is inactive.	0
	FAULT	The drive trips on fault <i>MOT OVERTEMP</i> (0009) when the temperature exceeds 110 °C, and the motor coasts to stop.	1
	ALARM	The drive generates alarm <i>MOTOR TEMP</i> (2010) when the motor temperature exceeds 90 °C.	2

All pa	All parameters			
No.	Name/Value	Description	Def/FbEq	
3006	MOT THERM TIME	Defines the thermal time constant for the motor thermal model, ie the time within which the motor temperature has reached 63% of the nominal temperature with steady load. For thermal protection according to UL requirements for NEMA class motors, use the rule of thumb: Motor thermal time = 35 · t6. t6 (in seconds) is specified by the motor manufacturer as the time the motor can safely operate at six times its rated current. Thermal time for a Class 10 trip curve is 350 s, for a Class 20 trip curve 700 s, and for a Class 30 trip curve 1050 s. Motor load Par. 3006	500 s	
	2569999 s	Time constant	1 = 1 s	

All parameters			
No. Name/Value	Description	Def/FbEq	
3007 MOT LOAD CURVE	Defines the load curve together with parameters 3008 ZERO SPEED LOAD and 3009 BREAK POINT FREQ. With the default value 100%, motor overload protection is functioning when the constant current exceeds 127% of the parameter 9906 MOTOR NOM CURR value. The default overloadability is at the same level as what motor manufacturers typically allow below 30 °C (86 °F) ambient temperature and below 1000 m (3300 ft) altitude. When the ambient temperature exceeds 30 °C (86 °F) or the installation altitude is over 1000 m (3300 ft), decrease the parameter 3007 value according to the motor	100%	
	manufacturer's recommendation. Example: If the constant protection level needs to be 115% of the nominal motor current, set parameter 3007 value to 91% (= 115/127·100%). Output current relative (%) to 9906 MOTOR NOM CURR		
	Par. 3007 100 = 127% Par. 3008 50 Par. 3009		
50150%	Allowed continuous motor load relative to the nominal motor current	1 = 1%	
3008 ZERO SPEED LOAD	Defines the load curve together with parameters 3007 MOT LOAD CURVE and 3009 BREAK POINT FREQ.	70%	
25150%	Allowed continuous motor load at zero speed as a percentage of the nominal motor current	1 = 1%	

All parameters			
No.	Name/Value	Description	Def/FbEq
3009	BREAK POINT FREQ	Defines the load curve together with parameters 3007 MOT LOAD CURVE and 3008 ZERO SPEED LOAD. Example: Thermal protection trip times when parameters 30063008 have default values.	35 Hz
		I_{O} = Output current I_{N} = Nominal motor current f_{O} = Output frequency f_{BRK} = Break point frequency A = Trip time 3.5 3.0 4 3.0 4 3.0 50 8 90 s 2.0 180 s 1.5 1.0 0 0.2 0.4 0.6 0.8 1.0 1.2	
	1250 Hz	Drive output frequency at 100% load	1 = 1 Hz

All parameters			
No.	Name/Value	Description	Def/FbEq
3010	STALL FUNCTION	Selects how the drive reacts to a motor stall condition. The protection wakes up if the drive has operated in a stall region (see the figure below) longer than the time set by parameter 3012 STALL TIME.	NOT SEL
		In vector control the user defined limit = 2017 MAX TORQUE 1 / 2018 MAX TORQUE 2 (applies for positive and negative torques).	
		In scalar control the user defined limit = 2003 MAX CURRENT.	
		The control mode is selected by parameter 9904 MOTOR CTRL MODE.	
		Torque (%) / Stall region	
		0.95 · User defined limit	
		Par. 3011	
	NOT SEL	Protection is inactive.	0
	FAULT	The drive trips on fault MOTOR STALL (0012) and the motor coasts to stop.	1
	ALARM	The drive generates alarm MOTOR STALL (2012).	2
3011	STALL FREQUENCY	Defines the frequency limit for the stall function. See parameter 3010 STALL FUNCTION.	20.0 Hz
	0.550.0 Hz	Frequency	1 = 0.1 Hz
3012	STALL TIME	Defines the time for the stall function. See parameter 3010 STALL FUNCTION.	20 s
	10400 s	Time	1 = 1 s
3013	UNDERLOAD FUNC	Selects how the drive reacts to underload. The protection wakes up if:	NOT SEL
		the motor torque falls below the curve selected by parameter 3015 UNDERLOAD CURVE,	
		output frequency is higher than 10% of the nominal motor frequency and	
		the above conditions have been valid longer than the time set by parameter 3014 UNDERLOAD TIME.	
	NOT SEL	Protection is inactive.	0

All parameters				
No.	Name/Value	Desc	ription	Def/FbEq
	FAULT	The drive trips on fault <i>UNDERLOAD</i> (0017) and the motor coasts to stop. Note: Set parameter value to <i>FAULT</i> only after the drive ID run is performed! If <i>FAULT</i> is selected, the drive may generate an <i>UNDERLOAD</i> fault during ID run.		1
	ALARM	_	drive generates alarm <i>UNDERLOAD</i> (2011).	2
3014	UNDERLOAD TIME	Defin	es the time limit for the underload function. See neter 3013 UNDERLOAD FUNC.	20 s
	10400 s	Time	limit	1 = 1 s
3015	UNDERLOAD CURVE		(%) Underload curve types 3 70%	
		20 -	f_{N} $2.4 \cdot f_{N}$	
	15	Numb	per of the load curve type in the figure	1 = 1
3016	SUPPLY PHASE		ets how the drive reacts to supply phase loss, ie when oltage ripple is excessive.	FAULT
	FAULT The drive trips on fault SUPPLY PHASE (0022) and the motor coasts to stop when the DC voltage ripple exceeds 14% of the nominal DC voltage. LIMIT/ALARM Drive output current is limited and alarm INPUT PHASE LOSS (2026) is generated when the DC voltage ripple exceeds 14% of the nominal DC voltage. There is a 10 s delay between the activation of the alarm and the output current limitation. The current is limited until the ripple drops under the minimum limit, 0.3 · Ihd.			0
				1
	ALARM		drive generates alarm INPUT PHASE LOSS (2026) the DC ripple exceeds 14% of the nominal DC ge.	2

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
3017	EARTH FAULT	Selects how the drive reacts when an earth (ground) fault is detected in the motor or the motor cable.	ENABLE
	DISABLE	Note: Disabling earth (ground) fault may void the warranty. No action	0
	ENABLE		1
		The drive trips on fault <i>EARTH FAULT</i> (0016) when the earth fault is detected during run.	
	START ONLY	The drive trips on fault <i>EARTH FAULT</i> (0016) when the earth fault is detected before run.	2
3018	COMM FAULT FUNC	Selects how the drive reacts in a fieldbus communication break. The time delay is defined by parameter 3019 COMM FAULT TIME.	NOT SEL
	NOT SEL	Protection is inactive.	0
	FAULT	Protection is active. The drive trips on fault SERIAL 1 ERR (0028) and coasts to stop.	1
	CONST SP 7	Protection is active. The drive generates alarm <i>IO COMM</i> (2005) and sets the speed to the value defined by parameter 1208 CONST SPEED 7.	2
		WARNING! Make sure that it is safe to continue operation in case of a communication break.	
	LAST SPEED	Protection is active. The drive generates alarm <i>IO COMM</i> (2005) and freezes the speed to the level the drive was operating at. The speed is determined by the average speed over the previous 10 seconds.	3
		WARNING! Make sure that it is safe to continue operation in case of a communication break.	
3019	COMM FAULT TIME	Defines the time delay for the fieldbus communication break supervision. See parameter 3018 COMM FAULT FUNC.	3.0 s
	0.0600.0 s	Delay time	1 = 0.1 s
3021	AI1 FAULT LIMIT	Defines a fault level for analog input Al1. If parameter 3001 AI AI MIN FUNCTION is set to FAULT, the drive trips on fault Al1 LOSS (0007) when the analog input signal falls below the set level.	0.0%
		Do not set this limit below the level defined by parameter 1301 MINIMUM AI1.	
	0.0100.0%	Value as a percentage of the full signal range	1 = 0.1%
3022	AI2 FAULT LIMIT	Defines a fault level for analog input Al2. If parameter 3001 Al <min (0008)="" al2="" analog="" below="" drive="" falls="" fault="" fault,="" function="" input="" is="" level.<="" loss="" on="" set="" signal="" td="" the="" to="" trips="" when=""><td>0.0%</td></min>	0.0%
		Do not set this limit below the level defined by parameter 1304 MINIMUM AI2.	
	0.0100.0%	Value as a percentage of the full signal range	1 = 0.1%

All pa	All parameters			
No.	Name/Value	Description	Def/FbEq	
3023	WIRING FAULT	Selects how the drive reacts when incorrect input power and motor cable connection is detected (ie the input power cable is connected to the motor connection of the drive). Note: Disabling wiring fault (ground fault) may void the warranty.	ENABLE	
	DISABLE	No action	0	
	ENABLE	The drive trips on fault OUTP WIRING (0035).	1	
3025	STO OPERATION	Selects how the drive reacts when the drive detects that the STO (Safe torque off) function is active.	ONLY ALARM	
	ONLY FAULT	The drive trips on fault SAFE TORQUE OFF (0044).	1	
	ALARM&FAUL T	The drive generates alarm SAFE TORQUE OFF (2035) when stopped and trips on fault SAFE TORQUE OFF (0044) when running.	2	
	NO & FAULT	The drive gives no indication to the user when stopped and trips on fault SAFE TORQUE OFF (0044) when running.	3	
	ONLY ALARM	The drive generates alarm SAFE TORQUE OFF (2035).	4	
		Note: The start signal must be reset (toggled to 0) if STO (Safe torque off) has been used while the drive has been running.		
3026	POWER FAIL START	Selects how the drive reacts when the control board is externally powered by the MPOW-01 auxiliary power extension module (see <i>Appendix: Extension modules</i> on page <i>405</i>) and start is requested by the user.	ALARM	
	ALARM	The drive generates alarm UNDERVOLTAGE (2003).	1	
	FAULT	The drive trips on fault DC UNDERVOLT (0006).	2	
	NO	The drive gives no indication to the user.	3	
3027	OPTION COM LOSS	Selects how the drive reacts when the MREL-01 output relay module is removed from the drive, and parameters 1402 RELAY OUTPUT 2, 1403 RELAY OUTPUT 3 or 1410 RELAY OUTPUT 4 have non-zero values.	1	
	DISABLE	No action.	0	
	ENABLE	The drive trips on fault 1006 PAR EXT RO.	1	

All pa	arameters			
No.	Name/Value	Description	Def/FbEq	
31 AU RESE	JTOMATIC ET	Automatic fault reset. Automatic resets are possible only for certain fault types and when the automatic reset function is activated for that fault type.		
3101	NR OF TRIALS	PIALS Defines the number of automatic fault resets the drive performs within the time defined by parameter 3102 TRIAL TIME. If the number of automatic resets exceeds the set number (within the trial time), the drive prevents additional automatic resets and remains stopped. The drive must be reset from the control panel or from a source selected by parameter 1604 FAULT RESET SEL. Example: Three faults have occurred during the trial time defined by parameter 3102. Last fault is reset only if the number defined by parameter 3101 is 3 or more. Trial time X = Automatic reset		
	05	Number of the automatic resets	1 = 1	
3102	TRIAL TIME	Defines the time for the automatic fault reset function. See parameter 3101 NR OF TRIALS.	30.0 s	
	1.0600.0 s	Time	1 = 0.1 s	
3103	DELAY TIME	Defines the time that the drive will wait after a fault before attempting an automatic reset. See parameter 3101 NR OF TRIALS. If delay time is set to zero, the drive resets immediately.	0.0 s	
	0.0120.0 s	Time	1 = 0.1 s	
3104	AR OVERCURRE NT	Activates/deactivates the automatic reset for the overcurrent fault. Automatically resets fault OVERCURRENT (0001) after the delay set by parameter 3103 DELAY TIME.	DISABLE	
	DISABLE	Inactive	0	
	ENABLE	Active	1	
3105	AR OVERVOLTAG E	Activates/deactivates the automatic reset for the intermediate link overvoltage fault. Automatically resets fault DC OVERVOLT (0002) after the delay set by parameter 3103 DELAY TIME.	DISABLE	
	DISABLE	Inactive	0	
	ENABLE	Active	1	
3106	AR UNDERVOLTA GE	Activates/deactivates the automatic reset for the intermediate link undervoltage fault. Automatically resets fault <i>DC UNDERVOLT</i> (0006) after the delay set by parameter 3103 DELAY TIME.	DISABLE	

All pa	All parameters				
No.	Name/Value	Description	Def/FbEq		
	DISABLE	Inactive	0		
	ENABLE	Active	1		
3107	AR AI <min< td=""><td>Activates/deactivates the automatic reset for AI<min (0007)="" (0008).="" (analog="" 3103="" after="" ai1="" ai2="" allowed="" and="" automatically="" by="" delay="" fault="" faults="" input="" level)="" loss="" minimum="" parameter="" resets="" set="" signal="" td="" the="" time.<="" under=""><td>DISABLE</td></min></td></min<>	Activates/deactivates the automatic reset for AI <min (0007)="" (0008).="" (analog="" 3103="" after="" ai1="" ai2="" allowed="" and="" automatically="" by="" delay="" fault="" faults="" input="" level)="" loss="" minimum="" parameter="" resets="" set="" signal="" td="" the="" time.<="" under=""><td>DISABLE</td></min>	DISABLE		
	DISABLE	Inactive	0		
	ENABLE	Active	1		
		WARNING! The drive may restart even after a long stop if the analog input signal is restored. Ensure that the use of this feature will not cause danger.			
3108	AR EXTERNAL FLT	Activates/deactivates the automatic reset for faults <i>EXT FAULT 1</i> (0014) and <i>EXT FAULT 2</i> (0015). Automatically resets the fault after the delay set by parameter 3103 <i>DELAY TIME</i> .	DISABLE		
	DISABLE	Inactive	0		
	ENABLE	Active	1		

All parameters			
No.	Name/Value	Description	Def/FbEq
		Example 2: If 3202 SUPERV 1 LIM LO > 3203 SUPERV 1 LIM HI	
		The lower limit 3203 SUPERV 1 LIM HI remains active until the supervised signal exceeds the higher limit 3202 SUPERV 1 LIM LO, making it the active limit. The new limit remains active until the supervised signal drops below the lower limit 3203 SUPERV 1 LIM HI, making it the active limit.	
		Case A = 1401 RELAY OUTPUT 1 value is set to SUPRV1 OVER. Relay is energized whenever the supervised signal exceeds the active limit.	
		Case B = 1401 RELAY OUTPUT 1 value is set to SUPRV1 UNDER. Relay is de-energized whenever the supervised signal drops below the active limit.	
		Value of supervised parameter Active limit	
		LO par. 3202 HI par. 3203	
		Case A Energized (1) Case B Energized (1) Case B Energized (1)	
	0, xx	Parameter index in group <i>01 OPERATING DATA</i> . Eg 102 = <i>0102 SPEED</i> . 0 = not selected.	1 = 1
3202	SUPERV 1 LIM LO	Defines the low limit for the first supervised signal selected by parameter 3201 SUPERV 1 PARAM. Supervision wakes up if the value is below the limit.	-
	XX	Setting range depends on parameter 3201 setting.	-
3203	SUPERV 1 LIM HI	Defines the high limit for the first supervised signal selected by parameter 3201 SUPERV 1 PARAM. Supervision wakes up if the value is above the limit.	-
	xx	Setting range depends on parameter 3201 setting.	-
3204	SUPERV 2 PARAM	Selects the second supervised signal. Supervision limits are defined by parameters 3205 SUPERV 2 LIM LO and 3206 SUPERV 2 LIM HI. See parameter 3201 SUPERV 1 PARAM.	104
	XX	Parameter index in group <i>01 OPERATING DATA</i> . Eg 102 = <i>0102 SPEED</i> .	1 = 1

All pa	All parameters			
No.	Name/Value	Description	Def/FbEq	
3205	SUPERV 2 LIM LO	Defines the low limit for the second supervised signal selected by parameter 3204 SUPERV 2 PARAM. Supervision wakes up if the value is below the limit.	-	
	XX	Setting range depends on parameter 3204 setting.	-	
3206	SUPERV 2 LIM HI	Defines the high limit for the second supervised signal selected by parameter 3204 SUPERV 2 PARAM. Supervision wakes up if the value is above the limit.	-	
	XX	Setting range depends on parameter 3204 setting.	-	
3207	SUPERV 3 PARAM	Selects the third supervised signal. Supervision limits are defined by parameters 3208 SUPERV 3 LIM LO and 3209 SUPERV 3 LIM HI. See parameter 3201 SUPERV 1 PARAM.	105	
	xx	Parameter index in group 01 OPERATING DATA. Eg 102 = 0102 SPEED.	1 = 1	
3208	SUPERV 3 LIM LO	Defines the low limit for the third supervised signal selected by parameter 3207 SUPERV 3 PARAM. Supervision wakes up if the value is below the limit.	-	
	xx	Setting range depends on parameter 3207 setting.	-	
3209	SUPERV 3 LIM HI	Defines the high limit for the third supervised signal selected by parameter 3207 SUPERV 3 PARAM. Supervision wakes up if the value is above the limit.	-	
	XX	Setting range depends on parameter 3207 setting.	-	
33 IN	FORMATION	Firmware package version, test date etc.		
3301	FIRMWARE	Displays the version of the firmware package.		
	0000FFFF hex	Eg 241A hex		
3302	LOADING PACKAGE	Displays the version of the loading package.	type dependent	
	220122FF hex	2201 hex = ACS355-0nE- 2202 hex = ACS355-0nU-		
3303	TEST DATE	Displays the test date.	00.00	
		Date value in format YY.WW (year, week)		
3304	DRIVE RATING	Displays the drive current and voltage ratings.	0000 hex	
	0000FFFF hex	Value in format XXXY hex: XXX = Nominal current of the drive in amperes. An "A" indicates decimal point. For example if XXX is 9A8, nominal current is 9.8 A. Y = Nominal voltage of the drive: 1 = 1-phase 200240 V 2 = 3-phase 200240 V 4 = 3-phase 380480 V		

All parameters			
No. 1	Name/Value	Description	Def/FbEq
	PARAMETER TABLE	Displays the version of the parameter table used in the drive.	
	0000FFFF nex	Eg 400E hex	
34 PAN	NEL DISPLAY	Selection of actual signals to be displayed on the panel	
	SIGNAL1 PARAM	Selects the first signal to be displayed on the control panel in the Output mode. Assistant control 3404 3405 panel O137 15.0 HZ O138 3.7 A O139 17.3 % DIR 00:00 MENU	103
5	0 = NOT SELECTED 101180	Parameter index in group 01 OPERATING DATA. Eg 102 = 0102 SPEED. If value is set to 0, no signal is selected.	1 = 1
3402 \$	SIGNAL1 MIN	Defines the minimum value for the signal selected by parameter 3401 SIGNAL1 PARAM. Display value 3407 3406 Source value Note: Parameter is not effective if parameter 3404 OUTPUT1 DSP FORM setting is DIRECT.	
	xx	Setting range depends on parameter 3401 setting.	
3403 \$	SIGNAL1 MAX	Defines the maximum value for the signal selected by parameter 3401 SIGNAL1 PARAM. See the figure for parameter 3402 SIGNAL1 MIN. Note: Parameter is not effective if parameter 3404 OUTPUT1 DSP FORM setting is DIRECT.	-
>	xx	Setting range depends on parameter 3401 setting.	-

All pa	All parameters				
No.	Name/Value	Description			Def/FbEq
3404	OUTPUT1 DSP FORM	Defines the format for parameter 3401 SIG		nal (selected by	DIRECT
	+/-0	Signed/Unsigned value. Unit is selected by parameter 3405 OUTPUT1 UNIT. Example: PI (3.14159)			0
	+/-0.0				1
	+/-0.00				2
	+/-0.000	3404 value	Display	Range	3
	+0	+/-0	<u>+</u> 3 <u>+</u> 3.1	-32768+32767	4
	+0.0	+/-0.00	<u>+</u> 3.14		5
	+0.00	+/-0.000	<u>+</u> 3.142	-	6
	+0.000	+0 +0.0 +0.00 +0.000	3 3.1 3.14 3.142	065535	7
	BAR METER	Bar graph			8
	DIRECT	Direct value. Decimal point location and units of measure are the same as for the source signal. Note: Parameters 3402, 3403 and 34053407 are not effective.			9
3405	OUTPUT1 UNIT	Selects the unit for the displayed signal selected by parameter 3401 SIGNAL1 PARAM. Note: Parameter is not effective if parameter 3404 OUTPUT1 DSP FORM setting is DIRECT. Note: Unit selection does not convert values.			Hz
	NO UNIT	No unit selected			0
	Α	ampere			1
	V	volt			2
	Hz	hertz			3
	%	percentage			4
	s	second			5
	h	hour			6
	rpm	revolutions per minu	te		7
	kh	kilohour			8
	°C	celsius			9
	lb ft	pounds per foot			10
	mA	milliampere			11
	mV	millivolt			12
	kW	kilowatt			13
	W	watt			14
	kWh	kilowatt hour			15

All p	All parameters				
No.	Name/Value	Description	Def/FbEq		
	°F	fahrenheit	16		
	hp	horsepower	17		
	MWh	megawatt hour	18		
	m/s	meters per second	19		
	m3/h	cubic meters per hour	20		
	dm3/s	cubic decimeters per second	21		
	bar	bar	22		
	kPa	kilopascal	23		
	GPM	gallons per minute	24		
	PSI	pounds per square inch	25		
	CFM	cubic feet per minute	26		
	ft	foot	27		
	MGD	millions of gallons per day	28		
	inHg	inches of mercury	29		
	FPM	feet per minute	30		
	kb/s	kilobytes per second	31		
	kHz	kilohertz	32		
	ohm	ohm	33		
	ppm	pulses per minute	34		
	pps	pulses per second	35		
	l/s	liters per second	36		
	l/min	liters per minute	37		
	l/h	liters per hour	38		
	m3/s	cubic meters per second	39		
	m3/m	cubic meters per minute	40		
	kg/s	kilograms per second	41		
	kg/m	kilograms per minute	42		
	kg/h	kilograms per hour	43		
	mbar	millibar	44		
	Pa	pascal	45		
	GPS	gallons per second	46		
	gal/s	gallons per second	47		
	gal/m	gallons per minute	48		
	gal/h	gallons per hour	49		
	ft3/s	cubic feet per second	50		
	ft3/m	cubic feet per minute	51		
	ft3/h	cubic feet per hour	52		

All pa	All parameters				
No.	Name/Value	Description	Def/FbEq		
	xx	Setting range depends on parameter 3401 setting.	-		
3408	SIGNAL2 PARAM				
	0 = NOT SELECTED 101180	Parameter index in group <i>01 OPERATING DATA</i> . Eg 102 = <i>0102 SPEED</i> . If value is set to 0, no signal is selected.	1 = 1		
3409	SIGNAL2 MIN	Defines the minimum value for the signal selected by parameter 3408 SIGNAL2 PARAM. See parameter 3402 SIGNAL1 MIN.	-		
	xx	Setting range depends on parameter 3408 setting.	-		
3410	SIGNAL2 MAX	Defines the maximum value for the signal selected by parameter 3408 SIGNAL2 PARAM. See parameter 3402 SIGNAL1 MIN.	-		
	xx	Setting range depends on parameter 3408 setting.	-		
3411	OUTPUT2 DSP FORM	Defines the format for the displayed signal selected by parameter 3408 SIGNAL2 PARAM.	DIRECT		
		See parameter 3404 OUTPUT1 DSP FORM.	-		
3412	OUTPUT2 UNIT	Selects the unit for the displayed signal selected by parameter 3408 SIGNAL2 PARAM.	-		
		See parameter 3405 OUTPUT1 UNIT.	-		
3413	OUTPUT2 MIN	Sets the minimum display value for the signal selected by parameter 3408 SIGNAL2 PARAM. See parameter 3402 SIGNAL1 MIN.	-		
	XX	Setting range depends on parameter 3408 setting.	-		
3414	OUTPUT2 MAX	Sets the maximum display value for the signal selected by parameter 3408 SIGNAL2 PARAM. See parameter 3402 SIGNAL1 MIN.	-		
	XX	Setting range depends on parameter 3408 setting.	-		
3415	SIGNAL3 PARAM	Selects the third signal to be displayed on the control panel in the Output mode. See parameter 3401 SIGNAL1 PARAM.	105		
	0 = NOT SELECTED 101180	Parameter index in group 01 OPERATING DATA. Eg 102 = 0102 SPEED. If value is set to 0, no signal is selected.	1 = 1		
3416	SIGNAL3 MIN	Defines the minimum value for the signal selected by parameter 3415. See parameter 3402 SIGNAL1 MIN.	-		
	xx	Setting range depends on parameter 3415 SIGNAL3 PARAM setting.	-		
3417	SIGNAL3 MAX	Defines the maximum value for the signal selected by parameter 3415 SIGNAL3 PARAM. See parameter 3402 SIGNAL1 MIN.	-		

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
	xx	Setting range depends on parameter 3415 SIGNAL3 PARAM setting.	-
3418	OUTPUT3 DSP FORM	Defines the format for the displayed signal selected by parameter 3415 SIGNAL3 PARAM.	DIRECT
		See parameter 3404 OUTPUT1 DSP FORM.	-
3419	OUTPUT3 UNIT	Selects the unit for the displayed signal selected by parameter 3415 SIGNAL3 PARAM.	-
		See parameter 3405 OUTPUT1 UNIT.	-
3420	OUTPUT3 MIN	Sets the minimum display value for the signal selected by parameter 3415 SIGNAL3 PARAM. See parameter 3402 SIGNAL1 MIN.	-
	xx	Setting range depends on parameter 3415 SIGNAL3 PARAM setting.	-
3421	OUTPUT3 MAX	Sets the maximum display value for the signal selected by parameter 3415 SIGNAL3 PARAM. See parameter 3402 SIGNAL1 MIN.	-
	xx	Setting range depends on parameter 3415 setting.	-
35 MCAS	OTOR TEMP S	Motor temperature measurement. See section <i>Motor</i> temperature measurement through the standard I/O on page 160.	
3501	SENSOR TYPE	Activates the motor temperature measurement function and selects the sensor type. See also parameter group <i>15 ANALOG OUTPUTS</i> .	NONE
	NONE	The function is inactive.	0
	1 x PT100	The function is active. The temperature is measured with one Pt100 sensor. Analog output AO feeds constant current through the sensor. The sensor resistance increases as the motor temperature rises, as does the voltage over the sensor. The temperature measurement function reads the voltage through analog input AI1/2 and converts it to degrees centigrade.	1
	2 x PT100	The function is active. Temperature is measured using two Pt100 sensors. See selection 1 x PT100.	2
	3 x PT100	The function is active. Temperature is measured using three Pt100 sensors. See selection 1 x PT100.	3

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
	PTC	The function is active. The temperature is supervised using one PTC sensor. Analog output AO feeds constant current through the sensor. The resistance of the sensor increases sharply as the motor temperature rises over the PTC reference temperature (Tref), as does the voltage over the resistor. The temperature measurement function reads the voltage through analog input AI1/2 and converts it into ohms. The figure below shows typical PTC sensor resistance values as a function of the motor operating temperature.	4
		Temperature Resistance	
		Normal 01.5 kohm	
		Excessive ≥ 4 kohm	
		ohm 4000 1330 	
	THERM(0)	The function is active. Motor temperature is monitored using a PTC sensor (see selection <i>PTC</i>) connected to drive through a normally closed thermistor relay connected to a digital input. 0 = motor overtemperature.	5
	THERM(1)	The function is active. Motor temperature is monitored using a PTC sensor (see selection <i>PTC</i>) connected to drive through a normally open thermistor relay connected to a digital input. 1 = motor overtemperature.	6
3502	INPUT SELECTION	Selects the source for the motor temperature measurement signal.	AI1
	Al1	Analog input AI1. Used when Pt100 or PTC sensor is selected for the temperature measurement.	1
	Al2	Analog input Al2. Used when Pt100 or PTC sensor is selected for the temperature measurement	2
	DI1	Digital input DI1. Used when parameter 3501 SENSOR TYPE value is set to THERM(0)/THERM(1).	3
	DI2	Digital input DI2. Used when parameter 3501 SENSOR TYPE value is set to THERM(0)/THERM(1).	4

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
	DI5(INV)	See selection DI1(INV).	-5
3602	START TIME 1	Defines the daily start time 1. The time can be changed in 2-second steps.	00:00:00
	00:00:00	hours:minutes:seconds.	
	23:59:58	Example: If parameter value is set to 07:00:00, timed function 1 is activated at 7:00 (7 a.m).	
3603	STOP TIME 1	Defines the daily stop time 1. The time can be changed in 2-second steps.	00:00:00
	00:00:00	hours:minutes:seconds.	
	23:59:58	Example: If parameter value is set to 18:00:00, timed function 1 is deactivated at 18:00 (6 p.m).	
3604	START DAY 1	Defines the start day 1.	MONDAY
	MONDAY		1
	TUESDAY	Example: If parameter value is set to <i>MONDAY</i> , timed	2
	WEDNESDAY	function 1 is active from Monday midnight (00:00:00).	3
	THURSDAY		4
	FRIDAY		5
	SATURDAY		6
	SUNDAY		7
3605	STOP DAY 1	Defines the stop day 1.	MONDAY
		See parameter 3604 START DAY 1.	
		Example: If parameter is set to <i>FRIDAY</i> , timed function 1 is deactivated on Friday midnight (23:59:58).	
3606	START TIME 2	See parameter 3602 START TIME 1.	
		See parameter 3602 START TIME 1.	
3607	STOP TIME 2	See parameter 3603 STOP TIME 1.	
		See parameter 3603 STOP TIME 1.	
3608	START DAY 2	See parameter 3604 START DAY 1.	
		See parameter 3604 START DAY 1.	
3609	STOP DAY 2	See parameter 3605 STOP DAY 1.	
		See parameter 3605 STOP DAY 1.	
3610	START TIME 3	See parameter 3602 START TIME 1.	
		See parameter 3602 START TIME 1.	
3611	STOP TIME 3	See parameter 3603 STOP TIME 1.	
		See parameter 3603 STOP TIME 1.	
3612	START DAY 3	See parameter 3604 START DAY 1.	
		See parameter 3604 START DAY 1.	
3613	STOP DAY 3	See parameter 3605 STOP DAY 1.	

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
		See parameter 3605 STOP DAY 1.	·
3614	START TIME 4	See parameter 3602 START TIME 1.	
		See parameter 3602 START TIME 1.	
3615	STOP TIME 4	See parameter 3603 STOP TIME 1.	
		See parameter 3603 STOP TIME 1.	
3616	START DAY 4	See parameter 3604 START DAY 1.	
		See parameter 3604 START DAY 1.	
3617	STOP DAY 4	See parameter 3605 STOP DAY 1.	
		See parameter 3605 STOP DAY 1.	
3622	BOOSTER SEL	Selects the source for the booster activation signal.	NOT SEL
	NOT SEL	No booster activation signal	0
	DI1	Digital input DI1. 1 = active, 0 = inactive.	1
	DI2	See selection DI1.	2
	DI3	See selection DI1.	3
	DI4	See selection DI1.	4
	DI5	See selection DI1.	5
	DI1(INV)	Inverted digital input DI1. 0 = active, 1 = inactive.	-1
	DI2(INV)	See selection DI1(INV).	-2
	DI3(INV)	See selection DI1(INV).	-3
	DI4(INV)	See selection DI1(INV).	-4
	DI5(INV)	See selection DI1(INV).	-5
3623	BOOSTER TIME	Defines the time inside which the booster is deactivated after the booster activation signal is switched off.	00:00:00
	00:00:00	hours:minutes:seconds	
	23:59:58	Example: If parameter 3622 BOOSTER SEL is set to DI1 and 3623 BOOSTER TIME is set to 01:30:00, the booster is active for 1 hour and 30 minutes after digital input DI is deactivated.	
		Booster activeBooster time	
3626	TIMED FUNC 1 SRC	Selects the time periods for <i>TIMED FUNC 1 SRC</i> . Timed function can consist of 04 time periods and a booster.	NOT SEL
	NOT SEL	No time periods selected	0

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
	T1	Time period 1	1
	T2	Time period 2	2
	T1+T2	Time periods 1 and 2	3
	T3	Time period 3	4
	T1+T3	Time periods 1 and 3	5
	T2+T3	Time periods 2 and 3	6
	T1+T2+T3	Time periods 1, 2 and 3	7
	T4	Time period 4	8
	T1+T4	Time periods 1 and 4	9
	T2+T4	Time periods 2 and 4	10
	T1+T2+T4	Time periods 1, 2 and 4	11
	T3+T4	Time periods 4 and 3	12
	T1+T3+T4	Time periods 1, 3 and 4	13
	T2+T3+T4	Time periods 2, 3 and 4	14
	T1+T2+T3+T4	Time periods 1, 2, 3 and 4	15
	BOOSTER	Booster	16
	T1+B	Booster and time period 1	17
	T2+B	Booster and time period 2	18
	T1+T2+B	Booster and time periods 1 and 2	19
	T3+B	Booster and time period 3	20
	T1+T3+B	Booster and time periods 1 and 3	21
	T2+T3+B	Booster and time periods 2 and 3	22
	T1+T2+T3+B	Booster and time periods 1, 2 and 3	23
	T4+B	Booster and time period 4	24
	T1+T4+B	Booster and time periods 1 and 4	25
	T2+T4+B	Booster and time periods 2 and 4	26
	T1+T2+T4+B	Booster and time periods 1, 2 and 4	27
	T3+T4+B	Booster and time periods 3 and 4	28
	T1+T3+T4+B	Booster and time periods 1, 3 and 4	29
	T2+T3+T4+B	Booster and time periods 2, 3 and 4	30
	T1+2+3+4+B	Booster and time periods 1, 2, 3 and 4	31
3627	TIMED FUNC 2 SRC	See parameter 3626 TIMED FUNC 1 SRC.	
		See parameter 3626 TIMED FUNC 1 SRC.	
3628	TIMED FUNC 3 SRC	See parameter 3626 TIMED FUNC 1 SRC.	
		See parameter 3626 TIMED FUNC 1 SRC.	

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
	DERIVATION TIME	Defines the derivation time for the process PID controller. Derivative action boosts the controller output if the error value changes. The longer the derivation time, the more the speed controller output is boosted during the change. If the derivation time is set to zero, the controller works as a PI controller, otherwise as a PID controller. The derivation makes the control more responsive for disturbances. The derivative is filtered with a 1-pole filter. Filter time constant is defined by parameter 4004 PID DERIV FILTER. Error Process error value 100% D-part of controller output Gain 4001 D-part of controller output	0.0 s
	0.010.0 s	Derivation time. If parameter value is set to zero, the derivative part of the PID controller is disabled.	1 = 0.1 s
4004	PID DERIV FILTER	Defines the filter time constant for the derivative part of the process PID controller. Increasing the filter time smooths the derivative and reduces noise.	1.0 s
	0.010.0 s	Filter time constant. If parameter value is set to zero, the derivative filter is disabled.	1 = 0.1 s
4005	ERROR VALUE INV	Selects the relationship between the feedback signal and drive speed.	NO
	NO	Normal: A decrease in feedback signal increases drive speed. Error = Reference - Feedback	0
	YES	Inverted: A decrease in feedback signal decreases drive speed. Error = Feedback - Reference	1
4006	UNITS	Selects the unit for PID controller actual values.	%
	068	See parameter 3405 OUTPUT1 UNIT selections in the given range.	
4007	UNIT SCALE	Defines the decimal point location for PID controller actual values.	1

All pa	arameters				
No.	Name/Value	Description			Def/FbEq
	04	Example: PI (3.1415	93)		1 = 1
		4007 value	Entry	Display	
		0	00003	3	
		1	00031	3.1	
		2	00314	3.14	
		3	03142	3.142	
		4	31416	3.1416	
4008	0% VALUE	Defines together with scaling applied to the <i>Units</i> (4006)	•		0.0
		Scale (4007)		+1000%	
		A		100070	
		· ·	0% 100	Internal scale (%)	
		-1000%			
	XX	Unit and range deper parameters 4006 UN			
4009	100% VALUE	Defines together with scaling applied to the	•		100.0
	XX	Unit and range deper parameters 4006 UN		•	
4010	SET POINT SEL	Selects the source fo signal.	r the process PID	controller reference	INTERNA L
	KEYPAD	Control panel			0
	Al1	Analog input Al1			1
	Al2	Analog input Al2			2
	COMM	Fieldbus reference R	EF2		8
	COMM+AI1	Summation of fieldbu Al1. See section <i>Refe</i> page <i>318</i> .		• •	9
	COMM*AI1	Multiplication of fields Al1. See section <i>Refe</i> page <i>318</i> .		• .	10

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
	DI3U,4D(RNC)	Digital input DI3: Reference increase. Digital input DI4: Reference decrease. Stop command resets the reference to zero. The reference is not saved if the control source is changed from EXT1 to EXT2, from EXT2 to EXT1 or from LOC to REM.	11
	DI3U,4D(NC)	Digital input DI3: Reference increase. Digital input DI4: Reference decrease. The program stores the active reference (not reset by a stop command). The reference is not saved if the control source is changed from EXT1 to EXT2, from EXT2 to EXT1 or from LOC to REM.	12
	Al1+Al2	Reference is calculated with the following equation: REF = AI1(%) + AI2(%) - 50%	14
	Al1*Al2	Reference is calculated with the following equation: REF = AI1(%) · (AI2(%) / 50%)	15
	Al1-Al2	Reference is calculated with the following equation: REF = AI1(%) + 50% - AI2(%)	16
	Al1/Al2	Reference is calculated with the following equation: REF = AI1(%) · (50% / AI2 (%))	17
	INTERNAL	A constant value defined by parameter 4011 INTERNAL SETPNT.	19
	DI4U,5D(NC)	See selection <i>DI3U,4D(NC)</i> .	31
	FREQ INPUT	Frequency input	32
	SEQ PROG OUT	Sequence programming output. See parameter group 84 SEQUENCE PROG.	33
4011	INTERNAL SETPNT	Selects a constant value as process PID controller reference, when parameter 4010 SET POINT SEL value is set to INTERNAL.	40
	XX	Unit and range depend on the unit and scale defined by parameters 4006 UNITS and 4007 UNIT SCALE.	

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
	-32.768 32.767	Multiplier. If parameter value is set to zero, no multiplier is used.	1 = 0.001
4016	ACT1 INPUT	Defines the source for actual value 1 (ACT1). See also parameter 4018 ACT1 MINIMUM.	AI2
	Al1	Uses analog input 1 for ACT1	1
	Al2	Uses analog input 2 for ACT1	2
	CURRENT	Uses current for ACT1	3
	TORQUE	Uses torque for ACT1	4
	POWER	Uses power for ACT1	5
	COMM ACT 1	Uses value of signal 0158 PID COMM VALUE 1 for ACT1	6
	COMM ACT 2	Uses value of signal 0159 PID COMM VALUE 2 for ACT1	7
	FREQ INPUT	Frequency input	8
4017	ACT2 INPUT	Defines the source for actual value ACT2. See also parameter 4020 ACT2 MINIMUM.	AI2
		See parameter 4016 ACT1 INPUT.	
	MINIMUM	Scales the source signal used as the actual value ACT1 (defined by parameter 4016 ACT1 INPUT). For parameter 4016 values 6 (COMM ACT 1) and 7 (COMM ACT 2) scaling is not done.	
		Par Source Source min. Source max. 4016 1 Analog input 1 1301 MINIMUM AI1 1302 MAXIMUM AI1 2 Analog input 2 1304 MINIMUM AI2 1305 MAXIMUM AI2 3 Current 0 2 · nominal current 4 Torque -2 · nominal torque 2 · nominal torque 5 Power -2 · nominal power 2 · nominal power A = Normal; B = Inversion (ACT1 minimum > ACT1 maximum) ACT1 (%) ACT1 (%) 4019 4018 Source min. Source max. Source min. Source max.	
	1000 10000/	Source signal Source signal	1 - 10/
	-10001000%	Value as a percentage	1 = 1%

		I	
No.	Name/Value	Description	Def/FbEc
4019	ACT1 MAXIMUM	Defines the maximum value for variable ACT1 if an analog input is selected as a source for ACT1. See parameter 4016 ACT1 INPUT. The minimum (4018 ACT1 MINIMUM) and maximum settings of ACT1 define how the voltage/current signal received from the measuring device is converted to a percentage value used by the process PID controller. See parameter 4018 ACT1 MINIMUM.	100%
	-10001000%	Value as a percentage	1 = 1%
4020	ACT2 MINIMUM	See parameter 4018 ACT1 MINIMUM.	0%
	-10001000%	See parameter 4018.	1 = 1%
4021	ACT2 MAXIMUM	See parameter 4019 ACT1 MAXIMUM.	100%
	-10001000%	See parameter 4019.	1 = 1%
4022	SLEEP SELECTION	Activates the sleep function and selects the source for the activation input. See section <i>Sleep function for the process PID (PID1) control</i> on page 158.	NOT SEL
	NOT SEL	No sleep function selected	0
	DI1	The function is activated/deactivated through digital input DI1.1 = activation, 0 = deactivation. The internal sleep criteria set by parameters 4023 PID SLEEP LEVEL and 4025 WAKE-UP DEV are not effective. The sleep start and stop delay parameters 4024 PID SLEEP DELAY and 4026 WAKE-UP DELAY are effective.	1
	DI2	See selection DI1.	2
	DI3	See selection DI1.	3
	DI4	See selection <i>DI1</i> .	4
	DI5	See selection DI1.	5
	INTERNAL	Activated and deactivated automatically as defined by parameters 4023 PID SLEEP LEVEL and 4025 WAKE-UP DEV.	7
	DI1(INV)	The function is activated/deactivated through inverted digital input DI1. 1 = deactivation, 0 = activation.	-1
		The internal sleep criteria set by parameters 4023 PID SLEEP LEVEL and 4025 WAKE-UP DEV are not effective. The sleep start and stop delay parameters 4024 PID SLEEP DELAY and 4026 WAKE-UP DELAY are effective.	
	DI2(INV)	See selection DI1(INV).	-2
	DI3(INV)	See selection DI1(INV).	-3
	DI4(INV)	See selection <i>DI1(INV)</i> .	-4
	DI5(INV)	See selection <i>DI1(INV)</i> .	-5

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
4023	PID SLEEP LEVEL	Defines the start limit for the sleep function. If the motor speed is below a set level (4023) longer than the sleep delay (4024), the drive shifts to the sleeping mode: The motor is stopped and the control panel shows alarm message PID SLEEP (2018). Parameter 4022 SLEEP SELECTION must be set to INTERNAL. PID process feedback Wake-up delay (4026) Wake-up level deviation (4025) PID output level t _{sd} = Sleep delay (4024) PID SLEEP Sleeplevel Sleeplevel Sleeplevel Sleeplevel Stop Start	0.0 Hz / 0 rpm
	0.0500.0 Hz / 030000 rpm	Sleep start level	1 = 0.1 Hz 1 rpm
4024	PID SLEEP DELAY	Defines the delay for the sleep start function. See parameter 4023 PID SLEEP LEVEL. When the motor speed falls below the sleep level, the counter starts. When the motor speed exceeds the sleep level, the counter is reset.	60.0 s
	0.03600.0 s	Sleep start delay	1 = 0.1 s

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
	DI1(INV)	Inverted digital input DI1. 0 = PID SET 2, 1 = PID SET 1.	-1
	DI2(INV)	See selection DI1(INV).	-2
	DI3(INV)	See selection DI1(INV).	-3
	DI4(INV)	See selection DI1(INV).	-4
	DI5(INV)	See selection DI1(INV).	-5
41 PF SET 2	ROCESS PID 2	Process PID (PID1) control parameter set 2. See section PID control on page 154.	
4101	GAIN	See parameter 4001 GAIN.	
4102	INTEGRATION TIME	See parameter 4002 INTEGRATION TIME.	
4103	DERIVATION TIME	See parameter 4003 DERIVATION TIME.	
4104	PID DERIV FILTER	See parameter 4004 PID DERIV FILTER.	
4105	ERROR VALUE INV	See parameter 4005 ERROR VALUE INV.	
4106	UNITS	See parameter 4006 UNITS.	
4107	UNIT SCALE	See parameter 4007 UNIT SCALE.	
4108	0% VALUE	See parameter 4008 0% VALUE.	
4109	100% VALUE	See parameter 4009 100% VALUE.	
4110	SET POINT SEL	See parameter 4010 SET POINT SEL.	
4111	INTERNAL SETPNT	See parameter 4011 INTERNAL SETPNT.	
4112	SETPOINT MIN	See parameter 4012 SETPOINT MIN.	
4113	SETPOINT MAX	See parameter 4013 SETPOINT MAX.	
4114	FBK SEL	See parameter 4014 FBK SEL.	
4115	FBK MULTIPLIER	See parameter 4015 FBK MULTIPLIER.	
4116	ACT1 INPUT	See parameter 4016 ACT1 INPUT.	
4117	ACT2 INPUT	See parameter 4017 ACT2 INPUT.	
4118	ACT1 MINIMUM	See parameter 4018 ACT1 MINIMUM.	
4119	ACT1 MAXIMUM	See parameter 4019 ACT1 MAXIMUM.	
4120	ACT2 MINIMUM	See parameter 4020 ACT2 MINIMUM.	
4121	ACT2 MAXIMUM	See parameter 4021 ACT2 MAXIMUM.	

All pa	All parameters			
No.	Name/Value	Description	Def/FbEq	
4122	SLEEP SELECTION	See parameter 4022 SLEEP SELECTION.		
4123	PID SLEEP LEVEL	See parameter 4023 PID SLEEP LEVEL.		
4124	PID SLEEP DELAY	See parameter 4024 PID SLEEP DELAY.		
4125	WAKE-UP DEV	See parameter 4025 WAKE-UP DEV.		
4126	WAKE-UP DELAY	See parameter 4026 WAKE-UP DELAY.		
42 EX	(T / TRIM PID	External/Trim PID (PID2) control. See section <i>PID control</i> on page <i>154</i> .		
4201	GAIN	See parameter 4001 GAIN.		
4202	INTEGRATION TIME	See parameter 4002 INTEGRATION TIME.		
4203	DERIVATION TIME	See parameter 4003 DERIVATION TIME.		
4204	PID DERIV FILTER	See parameter 4004 PID DERIV FILTER.		
4205	ERROR VALUE INV	See parameter 4005 ERROR VALUE INV.		
4206	UNITS	See parameter 4006 UNITS.		
4207	UNIT SCALE	See parameter 4007 UNIT SCALE.		
4208	0% VALUE	See parameter 4008 0% VALUE.		
4209	100% VALUE	See parameter 4009 100% VALUE.		
4210	SET POINT SEL	See parameter 4010 SET POINT SEL.		
4211	INTERNAL SETPNT	See parameter 4011 INTERNAL SETPNT.		
4212	SETPOINT MIN	See parameter 4012 SETPOINT MIN.		
4213	SETPOINT MAX	See parameter 4013 SETPOINT MAX.		
4214	FBK SEL	See parameter 4014 FBK SEL.		
4215	FBK MULTIPLIER	See parameter 4015 FBK MULTIPLIER.		
4216	ACT1 INPUT	See parameter 4016 ACT1 INPUT.		
4217	ACT2 INPUT	See parameter 4017 ACT2 INPUT.		
4218	ACT1 MINIMUM	See parameter 4018 ACT1 MINIMUM.		
4219	ACT1 MAXIMUM	See parameter 4019 ACT1 MAXIMUM.		
4220	ACT2 MINIMUM	See parameter 4020 ACT2 MINIMUM.		

All pa	All parameters				
No.	Name/Value	Description	Def/FbEq		
4221	ACT2 MAXIMUM	See parameter 4021 ACT2 MAXIMUM.			
4228	ACTIVATE	Selects the source for the external PID function activation signal. Parameter 4230 TRIM MODE must be set to NOT SEL.	NOT SEL		
	NOT SEL	No external PID control activation selected	0		
	DI1	Digital input DI1. 1 = active, 0 = inactive.	1		
	DI2	See selection <i>DI1</i> .	2		
	DI3	See selection <i>DI1</i> .	3		
	DI4	See selection <i>DI1</i> .	4		
	DI5	See selection <i>DI1</i> .	5		
	DRIVE RUN	Activation at drive start. Start (drive running) = active.	7		
	ON	Activation at drive power-up. Power-up (drive powered) = active.	8		
	TIMED FUNC 1	Activation by a timed function. Timed function 1 active = PID control active. See parameter group 36 TIMED FUNCTIONS.	9		
	TIMED FUNC 2	See selection TIMED FUNC 1.	10		
	TIMED FUNC 3	See selection TIMED FUNC 1.	11		
	TIMED FUNC 4	See selection TIMED FUNC 1.	12		
	DI1(INV)	Inverted digital input DI1. 0 = active, 1 = inactive.	-1		
	DI2(INV)	See selection DI1(INV).	-2		
	DI3(INV)	See selection DI1(INV).	-3		
	DI4(INV)	See selection DI1(INV).	-4		
	DI5(INV)	See selection DI1(INV).	-5		
4229	OFFSET	Defines the offset for the external PID controller output. When PID controller is activated, controller output starts from the offset value. When PID controller is deactivated, controller output is reset to the offset value. Parameter 4230 TRIM MODE must be set to NOT SEL.	0.0%		
	0.0100.0%	Value as a percentage	1 = 0.1%		
4230	TRIM MODE	Activates the trim function and selects between the direct and proportional trimming. With trimming it is possible to combine a corrective factor to the drive reference. See section <i>Reference trimming</i> on page <i>134</i> .	NOT SEL		
	NOT SEL	No trim function selected	0		
	PROPORTION AL	Active. The trimming factor is proportional to the rpm/Hz reference before trimming (REF1).	1		
	DIRECT	Active. The trimming factor is relative to a fixed maximum limit used in the reference control loop (maximum speed, frequency or torque).	2		

All parameters				
No.	Name/Value	Description	Def/FbEq	
4304	FORCED OPEN LVL	Defines the speed at brake release. Parameter setting overrides parameter 4302 BRAKE OPEN LVL setting. After start, the drive speed is frozen to the set value, until the motor is magnetized. The purpose of this parameter is to generate enough start torque to prevent the motor rotating into the wrong direction because of the motor load.	0.0 = NOT SEL	
	0.0 = NOT SEL 0.0100.0%	Value as a percentage of the maximum frequency (in scalar control) or the maximum speed (in vector control). If parameter value is set to zero, the function is disabled. The control mode is selected by parameter 9904 MOTOR CTRL MODE.	1 = 0.1%	
4305	BRAKE MAGN DELAY	Defines motor magnetizing time. After start drive current/torque/speed is frozen to the value defined by parameter 4302 BRAKE OPEN LVL or 4304 FORCED OPEN LVL for the set time.	0 = NOT SEL	
	0 = NOT SEL 010000 ms	magnetizing time. If parameter value is set to zero, the function is disabled.	1 = 1 ms	
4306	RUNTIME FREQ LVL	Defines the brake close speed. When frequency falls below the set level during run, the brake is closed. The brake is reopened when the requirements set by parameters 43014305 are met.	0.0 = NOT SEL	
	0.0 = NOT SEL 0.0100.0%	Value as a percentage of the maximum frequency (in scalar control) or the maximum speed (in vector control). If parameter value is set to zero, the function is disabled. The control mode is selected by parameter 9904 MOTOR CTRL MODE.	1 = 0.1%	
4307	BRK OPEN LVL SEL	Selects the torque (in vector control) or current (in scalar control) applied at brake release.	PAR 4302	
	PAR 4302	Value of parameter 4302 BRAKE OPEN LVL used.	1	
	MEMORY	Torque value (in vector control) or current value (in scalar control) saved in parameter 0179 BRAKE TORQUE MEM used. Useful in applications where initial torque is needed to prevent unintended movement when the mechanical brake is released.	2	
50 EN	NCODER	Encoder connection.		
		For more information, see MTAC-01 pulse encoder interface module user's manual (3AFE68591091 [English]).		
5001	PULSE NR	States the number of encoder pulses per one revolution.	1024 ppr	
	3216384 ppr	Pulse number in pulses per round (ppr)	1 = 1 ppr	
5002	ENCODER ENABLE	Enables the encoder.	DISABLE	

All pa	All parameters				
No.	Name/Value	Description	Def/FbEq		
5128	FILE CPI FW REV	Displays the parameter table revision of the fieldbus adapter module mapping file stored in the memory of the drive. Format is xyz where:			
		x = major revision number			
		y = minor revision number			
		• x = correction letter.			
	0000FFFF hex	Parameter table revision	1 = 1		
5129	FILE CONFIG ID	Displays the drive type code of the fieldbus adapter module mapping file stored in the memory of the drive.			
	065535	Drive type code of fieldbus adapter module mapping file	1 = 1		
5130	FILE CONFIG REV	Displays the fieldbus adapter module mapping file revision stored in the memory of the drive in decimal format. Example: 1 = revision 1.			
	065535	Mapping file revision	1 = 1		
5131	FBA STATUS	Displays the status of the fieldbus adapter module			
		communication.			
	IDLE	Adapter is not configured.	0		
	EXECUT INIT	Adapter is initializing.	1		
	TIME OUT	A time-out has occurred in the communication between the adapter and the drive.	2		
	CONFIG ERROR	Adapter configuration error: The major or minor revision code of the common program revision in the fieldbus adapter module is not the revision required by the module (see parameter 5132 FBA CPI FW REV) or mapping file upload has failed more than three times.	3		
	OFF-LINE	Adapter is off-line.	4		
	ON-LINE	Adapter is on-line.	5		
	RESET	Adapter is performing a hardware reset.	6		
5132	FBA CPI FW REV	Displays the common program revision of the adapter module in format axyz, where:			
		a = major revision number			
		xy = minor revision numbers			
		• z = correction letter.			
		Example: 190A = revision 1.90A			
		Common program revision of the adapter module	1 = 1		

All parameters				
No.	Name/Value	Description	Def/FbEq	
	FBA APPL FW REV	Displays the application program revision of the adapter module in format axyz, where:		
		a = major revision number		
		xy = minor revision numbers		
		z = correction letter.		
		Example: 190A = revision 1.90A		
		Application program revision of the adapter module	1 = 1	
52 PA	ANEL COMM	Communication settings for the control panel port on the drive		
5201	STATION ID	Defines the address of the drive. Two units with the same address are not allowed on-line.	1	
	1247	Address	1 = 1	
5202	BAUD RATE	Defines the transfer rate of the link.	9.6 kb/s	
	1.2 kb/s	1.2 kbit/s	1 =	
	2.4 kb/s	2.4 kbit/s	0.1 kbit/s	
	4.8 kb/s	4.8 kbit/s		
	9.6 kb/s	9.6 kbit/s		
	19.2 kb/s	19.2 kbit/s		
	38.4 kb/s	38.4 kbit/s		
	57.6 kb/s	57.6 kbit/s		
	115.2 kb/s	115.2 kbit/s		
5203	PARITY	Defines the use of parity and stop bit(s). The same setting must be used in all on-line stations.	8 NONE 1	
	8 NONE 1	8 data bits, no parity bit, one stop bit	0	
	8 NONE 2	8 data bits, no parity bit, two stop bits	1	
	8 EVEN 1	8 data bits, even parity indication bit, one stop bit	2	
	8 ODD 1	8 data bits, odd parity indication bit, one stop bit	3	
5204	OK MESSAGES	Number of valid messages received by the drive. During normal operation, this number increases constantly.	0	
	065535	Number of messages	1 = 1	
5205	PARITY ERRORS	Number of characters with a parity error received from the Modbus link. If the number is high, check that the parity settings of the devices connected on the bus are the same. Note: High electromagnetic noise levels generate errors.	0	
	065535	Number of characters	1 = 1	
5206	FRAME ERRORS	Number of characters with a framing error received by the Modbus link. If the number is high, check that the communication speed settings of the devices connected on the bus are the same.	0	
		Note: High electromagnetic noise levels generate errors.		

All pa	All parameters			
No.	Name/Value	Description	Def/FbEq	
	065535	Number of characters	1 = 1	
5207	BUFFER OVERRUNS	Number of characters which overflow the buffer, ie number of characters which exceed the maximum message length, 128 bytes.	0	
	065535	Number of characters	1 = 1	
5208	CRC ERRORS	Number of messages with an CRC (cyclic redundancy check) error received by the drive. If the number is high, check CRC calculation for possible errors.	0	
	065535	Note: High electromagnetic noise levels generate errors.	1 = 1	
F2 F1		Number of messages	1 – 1	
53 Er	B PROTOCOL	Embedded fieldbus link settings. See chapter Fieldbus control with embedded fieldbus on page 311.		
5302	EFB STATION ID	Defines the address of the device. Two units with the same address are not allowed on-line.	1	
	0247	Address	1 = 1	
5303	EFB BAUD RATE	Defines the transfer rate of the link.	9.6 kb/s	
	1.2 kb/s	1.2 kbit/s	1 =	
	2.4 kb/s	2.4 kbit/s	0.1 kbit/s	
	4.8 kb/s	4.8 kbit/s		
	9.6 kb/s	9.6 kbit/s		
	19.2 kb/s	19.2 kbit/s		
	38.4 kb/s	38.4 kbit/s		
	57.6 kb/s	57.6 kbit/s		
	115.2 kb/s	115.2 kbit/s		
5304	EFB PARITY	Defines the use of parity and stop bit(s) and the data length. The same setting must be used in all on-line stations.	8 NONE 1	
	8 NONE 1	No parity bit, one stop bit, 8 data bits	0	
	8 NONE 2	No parity bit, two stop bits, 8 data bits	1	
	8 EVEN 1	Even parity indication bit, one stop bit, 8 data bits	2	
	8 ODD 1	Odd parity indication bit, one stop bit, 8 data bits	3	
5305	EFB CTRL PROFILE	Selects the communication profile. See section Communication profiles on page 326.	ABB DRV LIM	
	ABB DRV LIM	ABB drives limited profile	0	
	DCU PROFILE	DCU profile	1	
	ABB DRV FULL	ABB drives profile	2	
5306	EFB OK MESSAGES	Number of valid messages received by the drive. During normal operation, this number increases constantly.	0	
	065535	Number of messages	1 = 1	

	All parameters			
No.	Name/Value	Description	Def/FbEq	
5307	EFB CRC ERRORS	Number of messages with an CRC (cyclic redundancy check) error received by the drive. If the number is high, check CRC calculation for possible errors.	0	
		Note: High electromagnetic noise levels generate errors.		
	065535	Number of messages	1 = 1	
5310	EFB PAR 10	Selects an actual value to be mapped to Modbus register 40005.	0	
	065535	Parameter index	1 = 1	
5311	EFB PAR 11	Selects an actual value to be mapped to Modbus register 40006.	0	
	065535	Parameter index	1 = 1	
5312	EFB PAR 12	Selects an actual value to be mapped to Modbus register 40007.	0	
	065535	Parameter index	1 = 1	
5313	EFB PAR 13	Selects an actual value to be mapped to Modbus register 40008.	0	
	065535	Parameter index	1 = 1	
5314	EFB PAR 14	Selects an actual value to be mapped to Modbus register 40009.	0	
	065535	Parameter index	1 = 1	
5315	EFB PAR 15	Selects an actual value to be mapped to Modbus register 40010.	0	
	065535	Parameter index	1 = 1	
5316	EFB PAR 16	Selects an actual value to be mapped to Modbus register 40011.	0	
	065535	Parameter index	1 = 1	
5317	EFB PAR 17	Selects an actual value to be mapped to Modbus register 40012.	0	
	065535	Parameter index	1 = 1	
5318	EFB PAR 18	For Modbus: Sets an additional delay before the drive begins transmitting response to the master request.	0	
	065535	Delay in milliseconds	1 = 1	
5319	EFB PAR 19	ABB drives profile (ABB DRV LIM or ABB DRV FULL) Control word. Read only copy of the fieldbus Control word.	0000 hex	
	0000FFFF hex	Control word		
5320	EFB PAR 20	ABB drives profile (ABB DRV LIM or ABB DRV FULL) Status word. Read only copy of the fieldbus Status word.	0000 hex	
	0000FFFF hex	Status word		

All pa	rameters			
No.	Name/Value	Description		Def/FbEq
54 FB	A DATA IN	fieldbus adapter. See cha adapter on page 337.	fieldbus controller through a pter <i>Fieldbus control with fieldbus</i> the parameter group number is 3.	
5401	FBA DATA IN 1	Selects data to be transfe controller.	rred from the drive to the fieldbus	
	0	Not in use		
	16	Control and status data w	ords	
		5401 setting	Data word	
		1	Control word	
		2	REF1	
		3	REF2	
		4	Status word	
		5	Actual value 1	
		6	Actual value 2	
	1019999	Parameter index		
5402	FBA DATA IN 2	See 5401 FBA DATA IN 1		
5410	FBA DATA IN 10	See 5401 FBA DATA IN 1		
55 FB	A DATA OUT	fieldbus adapter. See cha adapter on page 337.	ntroller to the drive through a pter <i>Fieldbus control with fieldbus</i> the parameter group number is 2.	
	FBA DATA OUT 1	Selects data to be transfe the drive.	rred from the fieldbus controller to	
	0	Not in use		
	16	Control and status data w	ords	
		5501 setting	Data word	
		1	Control word	
		2	REF1	
		3	REF2	
		4	Status word	
		5	Actual value 1	
		6	Actual value 2	
	1019999	Drive parameter		
	FBA DATA OUT 2	See 5501 FBA DATA OU	T 1.	
	FBA DATA OUT 10	See 5501 FBA DATA OU	Т 1.	

All parameters			
No.	Name/Value	Description	Def/FbEq
84 SI PRO	EQUENCE G	Sequence programming. See section Sequence programming on page 172.	
8401	SEQ PROG ENABLE	Enables Sequence programming. If Sequence programming enable signal is lost, the Sequence programming is stopped, Sequence programming state (0168 SEQ PROG STATE) is set to 1 and all timers and outputs (RO/TO/AO) are set to zero.	DISABLE D
	DISABLED	Disabled	0
	EXT2	Enabled in external control location 2 (EXT2)	1
	EXT1	Enabled in external control location 1 (EXT1)	2
	EXT1&EXT2	Enabled in external control locations 1 and 2 (EXT1 and EXT2)	3
	ALWAYS	Enabled in external control locations 1 and 2 (EXT1 and EXT2) and in local control (LOCAL)	4
8402	SEQ PROG START	Selects the source for the Sequence programming activation signal. When Sequence programming is activated, the programming starts from the previously used state. If Sequence programming activation signal is lost, the Sequence programming is stopped and all timers and outputs (RO/TO/AO) are set to zero. Sequence programming state (0168 SEQ PROG STATE) remains unchanged. If start from the first Sequence programming state is required, the Sequence programming must be reset by parameter 8404 SEQ PROG RESET. If start from the first Sequence programming state is always required, reset and start signal sources (8404 and 8402 SEQ PROG START) must be through the same digital input. Note: The drive will not start if no Run enable signal is received (1601 RUN ENABLE).	NOT SEL
	DI1(INV)	Sequence programming activation through inverted digital input DI1. 0 = active, 1 = inactive.	-1
	DI2(INV)	See selection DI1(INV).	-2
	DI3(INV)	See selection DI1(INV).	-3
	DI4(INV)	See selection DI1(INV).	-4
	DI5(INV)	See selection <i>DI1(INV)</i> .	-5
	NOT SEL	No Sequence programming activation signal	0
	DI1	Sequence programming activation through digital input DI1. 1 = active, 0 = inactive.	1
	DI2	See selection DI1.	2
	DI3	See selection DI1.	3

All pa	All parameters			
No.	Name/Value	Description	Def/FbEq	
	DI4	See selection <i>DI1</i> .	4	
	DI5	See selection <i>DI1</i> .	5	
	DRIVE START	Sequence programming activation at drive start	6	
	TIMED FUNC 1	Sequence programming is activated by timed function 1. See parameter group 36 TIMED FUNCTIONS.	7	
	TIMED FUNC 2	See selection TIMED FUNC 1.	8	
	TIMED FUNC 3	See selection TIMED FUNC 1.	9	
	TIMED FUNC 4	See selection TIMED FUNC 1.	10	
	RUNNING	Sequence programming is always active.	11	
8403	SEQ PROG PAUSE	Selects the source for the Sequence programming pause signal. When Sequence programming pause is activated, all timers and outputs (RO/TO/AO) are frozen. Sequence programming state transition is possible only by parameter 8405 SEQ ST FORCE.	NOT SEL	
	DI1(INV)	Pause signal through inverted digital input DI1. 0 = active, 1 = inactive.	-1	
	DI2(INV)	See selection <i>DI1(INV)</i> .	-2	
	DI3(INV)	See selection <i>DI1(INV)</i> .	-3	
	DI4(INV)	See selection <i>DI1(INV)</i> .	-4	
	DI5(INV)	See selection <i>DI1(INV)</i> .	-5	
	NOT SEL	No pause signal	0	
	DI1	Pause signal through digital input DI1. 1 = active, 0 = inactive.	1	
	DI2	See selection DI1.	2	
	DI3	See selection DI1.	3	
	DI4	See selection <i>DI1</i> .	4	
	DI5	See selection <i>DI1</i> .	5	
	PAUSED	Sequence programming pause enabled	6	
8404	SEQ PROG RESET	Selects the source for the Sequence programming reset signal. Sequence programming state (0168 SEQ PROG STATE) is set to the first state and all timers and outputs (RO/TO/AO) are set to zero. Reset is possible only when Sequence programming is stopped.	NOT SEL	
	DI1(INV)	Reset through inverted digital input DI1. 0 = active, 1 = inactive.	-1	
	DI2(INV)	See selection DI1(INV).	-2	
	DI3(INV)	See selection DI1(INV).	-3	
	DI4(INV)	See selection DI1(INV).	-4	
	DI5(INV)	See selection DI1(INV).	-5	

All pa	All parameters			
No.	Name/Value	Description	Def/FbEq	
	NOT SEL	No reset signal	0	
	DI1	Reset through digital input DI1. 1 = active, 0 = inactive.	1	
	DI2	See selection DI1.	2	
	DI3	See selection DI1.	3	
	DI4	See selection DI1.	4	
	DI5	See selection DI1.	5	
	RESET	Reset. After reset parameter value is automatically set to NOT SEL.	6	
8405	SEQ ST	Forces the Sequence programming to a selected state.	STATE 1	
	FORCE	Note: State is changed only when Sequence programming is paused by parameter <i>8403 SEQ PROG PAUSE</i> and this parameter is set to the selected state.		
	STATE 1	State is forced to state 1.	1	
	STATE 2	State is forced to state 2.	2	
	STATE 3	State is forced to state 3.	3	
	STATE 4	State is forced to state 4.	4	
	STATE 5	State is forced to state 5.	5	
	STATE 6	State is forced to state 6.	6	
	STATE 7	State is forced to state 7.	7	
	STATE 8	State is forced to state 8.	8	
8406	SEQ LOGIC VAL 1	Defines the source for the logic value 1. Logic value 1 is compared to logic value 2 as defined by parameter 8407 SEQ LOGIC OPER 1. Logic operation values are used in state transitions. See	NOT SEL	
		parameter 8425 ST1 TRIG TO ST 2 / 8426 ST1 TRIG TO ST N selection LOGIC VAL.		
	DI1(INV)	Logic value 1 through inverted digital input DI1	-1	
	DI2(INV)	See selection DI1(INV).	-2	
	DI3(INV)	See selection DI1(INV).	-3	
	DI4(INV)	See selection DI1(INV).	-4	
	DI5(INV)	See selection DI1(INV).	-5	
	NOT SEL	No logic value	0	
	DI1	Logic value 1 through digital input DI1	1	
	DI2	See selection DI1.	2	
	DI3	See selection DI1.	3	
	DI4	See selection DI1.	4	
	DI5	See selection DI1.	5	
	SUPRV1 OVER	Logic value according to supervision parameters 32013203. See parameter group 32 SUPERVISION.	6	

All pa	All parameters			
No.	Name/Value	Description	Def/FbEq	
	SUPRV2 OVER	Logic value according to supervision parameters 32043206. See parameter group 32 SUPERVISION.	7	
	SUPRV3 OVER	Logic value according to supervision parameters 32073209. See parameter group 32 SUPERVISION.	8	
	SUPRV1 UNDER	See selection SUPRV1 OVER.	9	
	SUPRV2 UNDER	See selection SUPRV2 OVER.	10	
	SUPRV3 UNDER	See selection SUPRV3 OVER.	11	
	TIMED FUNC 1	Logic value 1 is activated by timed function 1. See parameter group 36 <i>TIMED FUNCTIONS</i> . 1 = timed function active.	12	
	TIMED FUNC 2	See selection TIMED FUNC 1.	13	
	TIMED FUNC 3	See selection TIMED FUNC 1.	14	
	TIMED FUNC 4	See selection TIMED FUNC 1.	15	
8407	SEQ LOGIC OPER 1	Selects the operation between logic value 1 and 2. Logic operation values are used in state transitions. See parameter 8425 ST1 TRIG TO ST 2 / 8426 ST1 TRIG TO ST N selection LOGIC VAL.	NOT SEL	
	NOT SEL	Logic value 1 (no logic comparison)	0	
	AND	Logic function: AND	1	
	OR	Logic function: OR	2	
	XOR	Logic function: XOR	3	
8408	SEQ LOGIC VAL 2	See parameter 8406 SEQ LOGIC VAL 1.	NOT SEL	
		See parameter 8406.		
8409	SEQ LOGIC OPER 2	Selects the operation between logic value 3 and the result of the first logic operation defined by parameter 8407 SEQ LOGIC OPER 1.	NOT SEL	
	NOT SEL	Logic value 2 (no logic comparison)	0	
	AND	Logic function: AND	1	
	OR	Logic function: OR	2	
	XOR	Logic function: XOR	3	
8410	SEQ LOGIC VAL 3	See parameter 8406 SEQ LOGIC VAL 1.	NOT SEL	
		See parameter 8406.		
8411	SEQ VAL 1 HIGH	Defines the high limit for the state change when parameter 8425 ST1 TRIG TO ST 2 is set to eg Al 1 HIGH 1.	0.0%	
	0.0100.0%	Value as a percentage	1 = 0.1%	

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
8412	SEQ VAL 1 LOW	Defines the low limit for the state change when parameter 8425 ST1 TRIG TO ST 2 is set to eg Al 1 LOW 1.	0.0%
	0.0100.0%	Value as a percentage	1 = 0.1%
8413	SEQ VAL 2 HIGH	Defines the high limit for the state change when parameter 8425 ST1 TRIG TO ST 2 is set to eg Al 2 HIGH 1.	0.0%
	0.0100.0%	Value as a percentage	1 = 0.1%
8414	SEQ VAL 2 LOW	Defines the low limit for the state change when parameter 8425 ST1 TRIG TO ST 2 is set to eg Al 2 LOW 1.	0.0%
	0.0100.0%	Value as a percentage	1 = 0.1%
8415	CYCLE CNT LOC	Activates the cycle counter for Sequence programming. Example: When parameter is set to <i>ST6 TO NEXT</i> , the cycle count (<i>0171 SEQ CYCLE CNTR</i>) increases every time the state changes from state 6 to state 7.	NOT SEL
	NOT SEL	Disabled	0
	ST1 TO NEXT	From state 1 to state 2	1
	ST2 TO NEXT	From state 2 to state 3	2
	ST3 TO NEXT	From state 3 to state 4	3
	ST4 TO NEXT	From state 4 to state 5	4
	ST5 TO NEXT	From state 5 to state 6	5
	ST6 TO NEXT	From state 6 to state 7	6
	ST7 TO NEXT	From state 7 to state 8	7
	ST8 TO NEXT	From state 8 to state 1	8
	ST1 TO N	From state 1 to state n. State n is defined by parameter 8427 ST1 STATE N.	9
	ST2 TO N	From state 2 to state n. State n is defined by parameter 8427 ST1 STATE N.	10
	ST3 TO N	From state 3 to state n. State n is defined by parameter 8427 ST1 STATE N.	11
	ST4 TO N	From state 4 to state n. State n is defined by parameter 8427 ST1 STATE N.	12
	ST5 TO N	From state 5 to state n. State n is defined by parameter 8427 ST1 STATE N.	13
	ST6 TO N	From state 6 to state n. State n is defined by parameter 8427 ST1 STATE N.	14
	ST7 TO N	From state 7 to state n. State n is defined by parameter 8427 ST1 STATE N.	15
	ST8 TO N	From state 8 to state n. State n is defined by parameter 8427 ST1 STATE N.	16
8416	CYCLE CNT RST	Selects the source for the cycle counter reset signal (0171 SEQ CYCLE CNTR).	NOT SEL

All parameters	All parameters			
No. Name/Value	Description	Def/FbEq		
DI1(INV)	Reset through inverted digital input DI1. 0 = active, 1 = inactive.	-1		
DI2(INV)	See selection DI1(INV).	-2		
DI3(INV)	See selection DI1(INV).	-3		
DI4(INV)	See selection DI1(INV).	-4		
DI5(INV)	See selection DI1(INV).	-5		
NOT SEL	No reset signal	0		
DI1	Reset through digital input DI1. 1 = active, 0 = inactive.	1		
DI2	See selection DI1.	2		
DI3	See selection DI1.	3		
DI4	See selection DI1.	4		
DI5	See selection DI1.	5		
STATE 1	Reset during state transition to state 1. Counter is reset, when the state has been reached.	6		
STATE 2	Reset during state transition to state 2. Counter is reset, when the state has been reached.	7		
STATE 3	Reset during state transition to state 3. Counter is reset, when the state has been reached.	8		
STATE 4	Reset during state transition to state 4. Counter is reset, when the state has been reached.	9		
STATE 5	Reset during state transition to state 5. Counter is reset, when the state has been reached.	10		
STATE 6	Reset during state transition to state 6. Counter is reset, when the state has been reached.	11		
STATE 7	Reset during state transition to state 7. Counter is reset, when the state has been reached.	12		
STATE 8	Reset during state transition to state 8. Counter is reset, when the state has been reached.	13		
SEQ PROG RST	Reset signal source defined by parameter 8404 SEQ PROG RESET	14		
8420 ST1 REF SEL	reference. Parameter is used when parameter 1103 REF1 SELECT or 1106 REF2 SELECT is set to SEQ PROG / AI1+SEQ PROG / AI2+SEQ PROG.	0.0%		
	Note: Constant speeds in group 12 CONSTANT SPEEDS overwrite the selected Sequence programming reference.			
COMM	0136 COMM VALUE 2. For scaling, see Fieldbus reference scaling on page 320.	-1.3		
AI1/AI2	Reference is calculated with the following equation: REF = AI1(%) · (50% / AI2 (%))	-1.2		

All parameters			
No.	Name/Value	Description	Def/FbEq
8422	ST1 RAMP	Selects the acceleration/deceleration ramp time for Sequence programming state 1, ie defines the rate of the reference change.	0.0 s
	-0.2/-0.1/	Time	1 = 0.1 s
	0.01800.0 s	When value is set to -0.2, ramp pair 2 is used. Ramp pair 2 is defined by parameters 22052207.	
		When value is set to -0.1, ramp pair 1 is used. Ramp pair 1 is defined by parameters 22022204.	
		With ramp pair 1/2, parameter 2201 ACC/DEC 1/2 SEL must be set to SEQ PROG. See also parameters 22022207.	
8423	ST1 OUT CONTROL	Selects the relay, transistor and analog output control for Sequence programming state 1.	AO=0
		The relay/transistor output control must be activated by setting parameter 1401 RELAY OUTPUT 1 / 1805 DO SIGNAL to SEQ PROG. Analog output control must be activated by parameter group 15 ANALOG OUTPUTS.	
		Analog output control values can be monitored with signal 0170 SEQ PROG AO VAL.	
	R=0,D=1,AO=0	Relay output is de-energized (opened), transistor output is energized and analog output is cleared.	-0.7
	R=1,D=0,AO=0	Relay output is energized (closed), transistor output is de- energized and analog output is cleared.	-0.6
	R=0,D=0,AO=0	Relay and transistor outputs are de-energized (opened) and analog output value is set to zero.	-0.5
	RO=0,DO=0	Relay and transistor outputs are de-energized (opened) and analog output control is frozen to the previously set value.	-0.4
	RO=1,DO=1	Relay and transistor outputs are energized (closed) and analog output control is frozen to the previously set value.	-0.3
	DO=1	Transistor output is energized (closed) and relay output is de-energized. Analog output control is frozen to the previously set value.	-0.2
	RO=1	Transistor output is de-energized (opened) and relay output is energized. Analog output control is frozen to the previously set value.	-0.1
	AO=0	Analog output value is set to zero. Relay and transistor outputs are frozen to the previously set value.	0.0
	0.1100.0%	Value written to signal 0170 SEQ PROG AO VAL. Value can be connected to control analog output AO by setting parameter 1501 AO1 CONTENT SEL value to 170 (ie signal 0170 SEQ PROG AO VAL). AO value is frozen to this value until it is zeroed.	

value.

All parameters	All parameters			
No. Name/Value	Description	Def/FbEq		
Al 1 HIGH 2	State change when Al1 value > par. 8413 SEQ VAL 2 HIGH value.			
AI 2 LOW 2	State change when Al2 value < par. 8414 SEQ VAL 2 LOW value.	16		
AI 2 HIGH 2	State change when Al2 value > par. 8413 SEQ VAL 2 HIGH value.	17		
Al1 OR 2 LO2	State change when Al1 or Al2 value < par. 8414 SEQ VAL 2 LOW value.	18		
AI1LO2AI2HI2	State change when Al1 value < par. 8414 SEQ VAL 2 LOW value and Al2 value > par. 8413 SEQ VAL 2 HIGH value.	19		
Al1LO2 ORDI5	State change when Al1 value < par. 8414 SEQ VAL 2 LOW value or when DI5 is active.	20		
Al2Hl2 ORDI5	State change when Al2 value > par. 8413 SEQ VAL 2 HIGH value or when DI5 is active.	21		
TIMED FUNC 1	Trigger with timed function 1. See parameter group 36 TIMED FUNCTIONS.	22		
TIMED FUNC 2	See selection TIMED FUNC 1.	23		
TIMED FUNC 3	See selection TIMED FUNC 1.	24		
TIMED FUNC 4	See selection TIMED FUNC 1.	25		
CHANGE DLY	State change after delay time defined by parameter 8424 ST1 CHANGE DLY has elapsed.	26		
DI1 OR DELAY	State change after DI1 activation or after delay time defined by parameter 8424 ST1 CHANGE DLY has elapsed.	27		
DI2 OR DELAY	See selection DI1 OR DELAY.	28		
DI3 OR DELAY	See selection DI1 OR DELAY.	29		
DI4 OR DELAY	See selection DI1 OR DELAY.	30		
DI5 OR DELAY	See selection DI1 OR DELAY.	31		
AI1HI1 ORDLY	State change when Al1 value > par. 8411 SEQ VAL 1 HIGH value or after delay time defined by parameter 8424 ST1 CHANGE DLY has elapsed.	32		
Al2LO1 ORDLY	State change when Al1 value < par. 8412 SEQ VAL 1 LOW value or after delay time defined by parameter 8424 ST1 CHANGE DLY has elapsed.	33		
Al1Hl2 ORDLY	State change when Al1 value > par. 8413 SEQ VAL 2 HIGH value or after delay time defined by parameter 8424 ST1 CHANGE DLY has elapsed.	34		
Al2LO2 ORDLY	State change when Al2 value < par. 8414 SEQ VAL 2 LOW value or after delay time defined by parameter 8424 ST1 CHANGE DLY has elapsed.	35		
SUPRV1 OVER	Logic value according to supervision parameters 32013203. See parameter group 32 SUPERVISION.	36		

All parameters			
No.	Name/Value	Description	Def/FbEq
	SUPRV2 OVER	Logic value according to supervision parameters 32043206. See parameter group 32 SUPERVISION.	37
	SUPRV3 OVER	Logic value according to supervision parameters 32073209. See parameter group 32 SUPERVISION.	38
	SUPRV1 UNDER	See selection SUPRV1 OVER.	39
	SUPRV2 UNDER	See selection SUPRV2 OVER.	40
	SUPRV3 UNDER	See selection SUPRV3 OVER.	41
	SPV10VRORD LY	State change according to supervision parameters 32013203 or when delay time defined by parameter 8424 ST1 CHANGE DLY has elapsed. See parameter group 32 SUPERVISION.	42
	SPV2OVRORD LY	State change according to supervision parameters 32043206 or when delay time defined by parameter 8424 ST1 CHANGE DLY has elapsed. See parameter group 32 SUPERVISION.	43
	SPV3OVRORD LY	State change according to supervision parameters 32073209 or when delay time defined by parameter 8424 ST1 CHANGE DLY has elapsed. See parameter group 32 SUPERVISION.	44
	SPV1UNDORD LY	See selection SPV10VRORDLY.	45
	SPV2UNDORD LY	See selection SPV2OVRORDLY.	46
	SPV3UNDORD LY	See selection SPV3OVRORDLY.	47
	CNTR OVER	State change when counter value exceeds the limit defined by par. 1905 COUNTER LIMIT. See parameters 19041911.	48
	CNTR UNDER	State change when counter value is below the limit defined by par. 1905 COUNTER LIMIT. See parameters 19041911.	49
	LOGIC VAL	State change according to logic operation defined by parameters 84068410	50
	ENTER SETPNT	State change when drive output frequency/speed enters the reference area (ie the difference is less than or equal to 4% of the maximum reference).	51
	AT SETPOINT	State change when drive output frequency/speed equals the reference value (= is within tolerance limits, ie the error is less than or equal to 1% of the maximum reference).	52
	Al1 L1 & Dl5	State change when Al1 value < par. 8412 SEQ VAL 1 LOW and when DI5 is active.	53

All pa	arameters		
No.	Name/Value	Description	Def/FbEq
	Al2 L2 & DI5	State change when Al2 value < par. 8414 SEQ VAL 2 LOW value and when DI5 is active.	54
1		State change when Al1 value > par. 8411 SEQ VAL 1 HIGH value and when DI5 is active.	55
	Al2 H2 & Dl5	State change when Al2 value > par. 8413 SEQ VAL 2 HIGH value and when DI5 is active.	56
	Al1 L1 & Dl4 State change when Al1 value < par. 8412 SEQ VAL 1 LOW value and when Dl4 is active.		57
	Al2 L2 & Dl4	State change when Al2 value < par. 8414 SEQ VAL 2 LOW value and when Dl4 is active.	58
	AI1 H1 & DI4	State change when Al1 value > par. 8411 SEQ VAL 1 HIGH value and when Dl4 is active.	59
	Al2 H2 & Dl4	State change when Al2 value > par. 8413 SEQ VAL 2 HIGH value and when Dl4 is active.	60
	DLY AND DI1	State change when delay time defined by parameter 8424 ST1 CHANGE DLY has elapsed and DI1 is active.	61
	DLY AND DI2	State change when delay time defined by parameter 8424 ST1 CHANGE DLY has elapsed and Dl2 is active.	62
DLY AND DI3		State change when delay time defined by parameter 8424 ST1 CHANGE DLY has elapsed and Dl3 is active.	63
	DLY AND DI4	State change when delay time defined by parameter 8424 ST1 CHANGE DLY has elapsed and DI4 is active.	64
	DLY AND DI5	State change when delay time defined by parameter 8424 ST1 CHANGE DLY has elapsed and DI5 is active.	65
	DLY & Al2 H2	State change when delay time defined by parameter 8424 ST1 CHANGE DLY has elapsed and Al2 value > par. 8413 SEQ VAL 2 HIGH value.	66
	DLY & Al2 L2	State change when delay time defined by parameter 8424 ST1 CHANGE DLY has elapsed and Al2 value < par. 8414 SEQ VAL 2 LOW value.	67
	DLY & Al1 H1 State change when delay time defined by parameter 8424 ST1 CHANGE DLY has elapsed and Al1 value > par. 8411 SEQ VAL 1 HIGH value.		68
	DLY & Al1 L1	State change when delay time defined by parameter 8424 ST1 CHANGE DLY has elapsed and Al1 value < par. 8412 SEQ VAL 1 LOW value.	69
	COMM VAL1 #0	0135 COMM VALUE 1 bit 0. 1 = state change.	70
	COMM VAL1 #1	0135 COMM VALUE 1 bit 1. 1 = state change.	71
	COMM VAL1 #2	0135 COMM VALUE 1 bit 2. 1 = state change.	72

All pa	arameters			
No.	Name/Value	ame/Value Description		
	COMM VAL1 #3	0135 COMM VALUE 1 bit 3. 1 = state change.	73	
	COMM VAL1 #4	0135 COMM VALUE 1 bit 4. 1 = state change.	74	
	COMM VAL1 #5	0135 COMM VALUE 1 bit 5. 1 = state change.		
	COMM VAL1 0135 COMM VALUE 1 bit 6. 1 = state change.		76	
	COMM VAL1 #7	0135 COMM VALUE 1 bit 7. 1 = state change.	77	
	AI2H2DI4SV1O	State change according to supervision parameters 32013203 when Al2 value > par. 8413 SEQ VAL 2 HIGH value and DI4 is active.	78	
	AI2H2DI5SV1O	State change according to supervision parameters 32013203 when Al2 value > par. 8413 SEQ VAL 2 HIGH value and DI5 is active.	79	
	STO State change when STO (Safe torque off) has been triggered.		80	
	STO(-1)	State change when STO (Safe torque off) becomes inactive and the drive operates normally.		
8426	ST1 TRIG TO ST N	Selects the source for the trigger signal which changes the state from state 1 to state N. State N is defined with parameter 8427 ST1 STATE N.	NOT SEL	
		Note: State change to state N (8426 ST1 TRIG TO ST N) has a higher priority than state change to the next state (8425 ST1 TRIG TO ST 2).		
		See parameter 8425 ST1 TRIG TO ST 2.		
8427	ST1 STATE N	Defines the state N. See parameter 8426 ST1 TRIG TO ST N.	STATE 1	
	STATE 1	State 1	1	
	STATE 2	State 2	2	
	STATE 3	State 3	3	
	STATE 4	State 4	4	
	STATE 5	State 5	5	
	STATE 6	State 6	6	
	STATE 7	State 7	7	
	STATE 8	State 8	8	
8430	ST2 REF SEL			
		See parameters 8420…8427.		
8497	ST8 STATE N			

All parameters		
No. Name/Value	Description	Def/FbEq
98 OPTIONS	External serial communication activation	
9802 COMM PROT SEL	Activates the external serial communication and selects the interface.	NOT SEL
NOT SEL	No communication	0
STD MODBUS	STD MODBUS Embedded fieldbus. Interface: EIA-485 provided by optional FMBA-01 Modbus adapter connected to drive terminal X3 See chapter <i>Fieldbus control with embedded fieldbus</i> on page 311.	
EXT FBA	The drive communicates through a fieldbus adapter module connected to drive terminal X3. See also parameter group 51 EXT COMM MODULE.	4
	See chapter <i>Fieldbus control with fieldbus adapter</i> on page 337.	
MODBUS RS232		
99 START-UP DATA	Language selection. Definition of motor set-up data.	
9901 LANGUAGE	Selects the display language used on the assistant control panel. Note: With the ACS-CP-D assistant control panel, the following languages are available: English (0), Chinese (1), Korean (2) and Japanese (3).	ENGLISH
ENGLISH	British English	0
ENGLISH (AM) American English	1
DEUTSCH	German	2
ITALIANO	Italian	3
ESPAÑOL	Spanish	4
PORTUGUES	Portuguese	5
NEDERLANDS	Dutch	6
FRANÇAIS	French	7
DANSK	Danish	8
SUOMI	Finnish	9
SVENSKA	Swedish	10
RUSSKI	Russian	11
POLSKI Polish		12
TÜRKÇE Turkish		13
CZECH	Czech	14
MAGYAR	Hungarian	15
ELLINIKA	Greek	16

All pa	All parameters				
No.	Name/Value	Description	Def/FbEq		
9902	APPLIC MACRO	Selects the application macro. See chapter <i>Application</i> macros on page 111.			
	ABB STANDARD	Standard macro for constant speed applications	1		
	3-WIRE	3-wire macro for constant speed applications	2		
	ALTERNATE	Alternate macro for start forward and start reverse applications	3		
	MOTOR POT	Motor potentiometer macro for digital signal speed control applications	4		
	HAND/AUTO	 Hand/Auto macro to be used when two control devices are connected to the drive: Device 1 communicates through the interface defined by external control location EXT1. Device 2 communicates through the interface defined by external control location EXT2. EXT1 or EXT2 is active at a time. Switching between EXT1/2 through digital input. 	5		
PID CONTROL		PID control. For applications in which the drive controls a process value, eg pressure control by the drive running the pressure boost pump. Measured pressure and the pressure reference are connected to the drive.	6		
	TORQUE CTRL	Torque control macro	8		
	AC500 MODBUS	AC500 PLC macro. See section AC500 Modbus macro on page 121.	10		
	LOAD FD SET	FlashDrop parameter values as defined by the FlashDrop file. Parameter view is selected by parameter 1611 PARAMETER VIEW.	31		
		FlashDrop is an optional device for fast copying of parameters to unpowered drives. FlashDrop allows easy customization of the parameter list, eg selected parameters can be hidden. For more information, see <i>MFDT-01 FlashDrop user's manual</i> (3AFE68591074 [English]).			
	USER S1 LOAD User 1 macro loaded into use. Before loading, check that the saved parameter settings and the motor model are suitable for the application.		0		
	USER S1 SAVE	Save User 1 macro. Stores the current parameter settings and the motor model.	-1		
	USER S2 LOAD	User 2 macro loaded into use. Before loading, check that the saved parameter settings and the motor model are suitable for the application.	-2		

All pa	All parameters			
No.	Name/Value	Description	Def/FbEq	
	USER S2 SAVE	Save User 2 macro. Stores the current parameter settings and the motor model.	-3	
	USER S3 LOAD User 3 macro loaded into use. Before loading, check the saved parameter settings and the motor model are suitable for the application.		-4	
	USER S3 SAVE	Save User 3 macro. Stores the current parameter settings and the motor model.	-5	
9903	MOTOR TYPE	Selects the motor type. Cannot be changed while the drive is running.	AM	
	AM	Asynchronous motor. Three-phase AC voltage-supplied induction motor with squirrel cage rotor.	1	
	PMSM	Permanent magnet synchronous motor. Three-phase AC voltage-supplied synchronous motor with permanent magnet rotor and sinusoidal back emf voltage.	2	
9904	MOTOR CTRL MODE	Selects the motor control mode.	SCALAR: FREQ	
	VECTOR: SPEED	Sensorless vector control mode. Reference 1 = speed reference in rpm. Reference 2 = speed reference as a percentage. 100% is the absolute maximum speed, equal to the value of parameter 2002 MAXIMUM SPEED (or 2001 MINIMUM SPEED if the absolute value of the minimum speed is greater than the maximum speed value).	1	
	VECTOR: TORQ	Vector control mode. Reference 1 = speed reference in rpm. Reference 2 = torque reference as a percentage. 100% equals nominal torque.	2	
	SCALAR: FREQ	Scalar control mode. Reference 1 = frequency reference in Hz. Reference 2 = frequency reference as a percentage. 100% is the absolute maximum frequency, equal to the value of parameter 2008 MAXIMUM FREQ (or 2007 MINIMUM FREQ if the absolute value of the minimum speed is greater than the maximum speed value).	3	

All pa	All parameters				
No.	Name/Value	Description	Def/FbEq		
9905	MOTOR NOM VOLT	Defines the nominal motor voltage. For asynchronous motors, must be equal to the value on the motor rating plate. For permanent magnet synchronous motors, the nominal voltage is the back emf voltage at nominal speed.	200 V units: 230 V 400 V		
		If the voltage is given as voltage per rpm, eg 60 V per 1000 rpm, the voltage for 3000 rpm nominal speed is $3 \cdot 60 \text{ V} = 180 \text{ V}.$	E units: 400 V 400 V		
		The drive cannot supply the motor with a voltage greater than the input power voltage.	U units: 460 V		
		Note that the output voltage is not limited by the nominal motor voltage but increased linearly up to the value of the input voltage.			
		Output voltage			
		Input voltage — — —			
		9905			
		9907 ► Output frequency			
		WARNING! The stress on the motor insulations depends on the drive supply voltage. This applies also when the motor voltage rating is lower than the rating of the drive and the supply voltage of the drive. The rms voltage can be limited to motor nominal voltage by setting the maximum frequency of the drive (parameter 2008) to the motor nominal frequency.			
	200 V units: 46345 V	Voltage.	1 = 1 V		
	400 V E units: 80600 V				
	400 V U units: 92690 V				
9906	MOTOR NOM CURR	Defines the nominal motor current. Must be equal to the value on the motor rating plate.	I _{2N}		
	0.22.0 · <i>I</i> _{2N} Current				
9907	MOTOR NOM FREQ	Defines the nominal motor frequency, ie the frequency at which the output voltage equals the motor nominal voltage: Field weakening point = Nom. frequency · Supply voltage / Motor nom. voltage	E: 50.0 Hz U: 60.0 Hz		
	0.0600.0 Hz	Frequency	1 = 0.1 Hz		
9908	MOTOR NOM SPEED	Defines the nominal motor speed. Must be equal to the value on the motor rating plate.	Type dependent		
	5030000 rpm	Speed	1 = 1 rpm		

All parameters				
No.	Name/Value	Description	Def/FbEq	
9909	MOTOR NOM POWER	Defines the nominal motor power. Must equal the value on the motor rating plate.	P_{N}	
	0.23.0 · <i>P</i> _N kW	Power	1 = 0.1 kW / 0.1 hp	
9910	ID RUN	This parameter controls a self-calibration process called the Motor ID run. During this process, the drive operates the motor and makes measurements to identify motor characteristics and create a model used for internal calculations.	OFF/IDM AGN	
	OFF/IDMAGN	The Motor ID run process is not run. Identification magnetization is performed, depending on parameter 9904 MOTOR CTRL MODE. In identification magnetization, the motor model is calculated at first start by magnetizing the motor for 10 to 15 s at zero speed (motor not rotating, except that a permanent magnet synchronous motor can rotate a fraction of a revolution). The model is recalculated always at start after motor parameter changes. • Parameter 9904 = 1 (VECTOR: SPEED) or 2 (VECTOR: TORQ): Identification magnetization is performed. • Parameter 9904 = 3 (SCALAR: FREQ): Identification magnetization is not performed.	0	
ON		ID run. Guarantees the best possible control accuracy. The ID run takes about one minute. An ID run is especially effective when: • vector control mode is used (parameter 9904 = 1 [VECTOR: SPEED] or 2 [VECTOR: TORQ]), and • operation point is near zero speed and/or • operation requires a torque range above the motor nominal torque, over a wide speed range, and without any measured speed feedback (ie without a pulse encoder). Note: The motor must be de-coupled from the driven equipment. Note: Check the direction of rotation of the motor before starting the ID run. During the run, the motor will rotate in the forward direction. Note: If motor parameters are changed after ID run, repeat the ID run. WARNING! The motor will run at up to approximately 5080% of the nominal speed during the ID run. ENSURE THAT IT IS SAFE TO RUN THE MOTOR BEFORE PERFORMING THE ID RUN!	1	

All pa	All parameters				
No.	Name/Value	Description	Def/FbEq		
9912	OP912 MOTOR NOM TORQUE Calculated motor nominal torque in N·m (calculation is based on parameter 9909 MOTOR NOM POWER and 9908 MOTOR NOM SPEED values).		0		
	,		1 = 0.1 N·m		
9913	Pair Motor Pole Calculated motor pole pair number (calculation is based on parameter 9907 Motor NOM FREQ and 9908 Motor NOM SPEED values).		0		
- Rea		Read-only	1 = 1		
9914	9914 PHASE INVERSION Inverts two phases in the motor cable. This changes the direction of the motor rotation without having to exchange the positions of two motor cable phase conductors at the drive output terminals or at the motor connection box.		NO		
	NO	Phases not inverted	0		
	YES	Phases inverted	1		

Fieldbus control with embedded fieldbus

What this chapter contains

The chapter describes how the drive can be controlled by external devices over a communication network using embedded fieldbus.

System overview

The drive can be connected to an external control system through a fieldbus adapter or embedded fieldbus. For the fieldbus adapter control, see chapter Fieldbus control with fieldbus adapter on page 337.

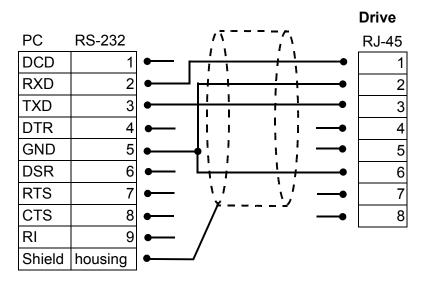
The embedded fieldbus supports Modbus RTU protocol. Modbus is a serial, asynchronous protocol. Transaction is half-duplex.

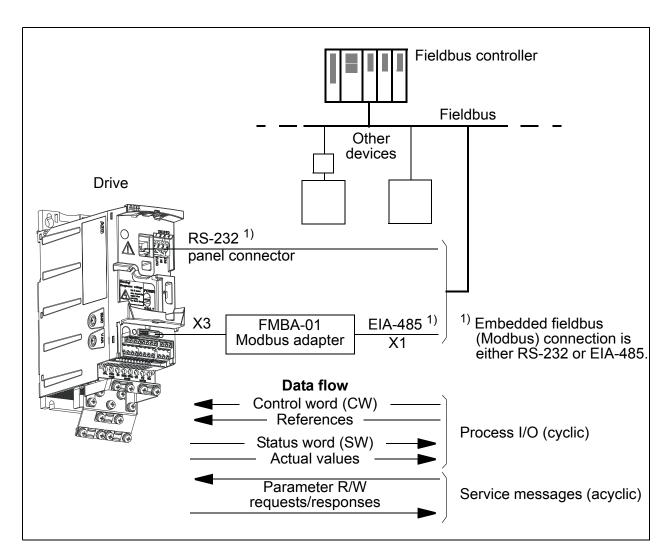
The embedded fieldbus can be connected with either EIA-485 (terminal X1 of the optional FMBA-01 Modbus adapter connected to drive terminal X3) or RS-232 (control panel connector X2).

EIA-485 is designed for a multipoint application (a single master controlling one or more slaves). RS-232 is designed for a point-to-point application (a single master controlling one slave).

For more information on the FMBA-01 Modbus adapter module, see *FMBA-01* Modbus adapter module user's manual (3AFE68586704 [English]).

The pin configuration of the RS-232 connector is shown below. The maximum length of the communication cable with RS-232 is restricted to 3 meters (9.8 ft).





The drive can be set to receive all of its control information through the fieldbus interface, or the control can be distributed between the fieldbus interface and other available sources, for example, digital and analog inputs.

Setting up communication through the embedded Modbus

Before configuring the drive for fieldbus control, the FMBA-01 Modbus adapter (if used) must be mechanically and electrically installed according to the instructions given in section Attach the optional fieldbus module on page 38, and the module manual.

The communication through the fieldbus link is initialized by setting parameter 9802 COMM PROT SEL to STD MODBUS or MODBUS RS232. The communication parameters in group 53 EFB PROTOCOL must also be adjusted. See the table below.

Parameter	Alternative settings	Setting for fieldbus control	Function/Information				
COMMUNICATION IN	COMMUNICATION INITIALIZATION						
9802 COMM PROT SEL	NOT SEL STD MODBUS EXT FBA MODBUS RS232	STD MODBUS (with EIA-485) MODBUS RS232 (with RS-232)	Initializes embedded fieldbus communication.				
ADAPTER MODULE	CONFIGURATION	l					
5302 EFB STATION ID	0247	Any	Defines the station ID address of the RS-232/EIA-485 link. No two stations on line may have the same address.				
5303 EFB BAUD RATE	1.2 kbit/s 2.4 kbit/s 4.8 kbit/s 9.6 kbit/s 19.2 kbit/s 38.4 kbit/s 57.6 kbit/s		Defines the communication speed of the RS-232/EIA-485 link.				
5304 EFB PARITY	8 NONE 1 8 NONE 2 8 EVEN 1 8 ODD 1		Selects the parity setting. The same settings must be used in all on-line stations.				
5305 EFB CTRL PROFILE	ABB DRV LIM DCU PROFILE ABB DRV FULL	Any	Selects the communication profile used by the drive. See section Communication profiles on page 326.				
5310 EFB PAR 10	065535	Any	Selects an actual value to be				
5317 EFB PAR 17			mapped to Modbus register 400xx.				

After the configuration parameters in group 53 EFB PROTOCOL have been set, the drive control parameters (shown in section *Drive control parameters* on page 314) must be checked and adjusted when necessary.

The new settings will take effect when the drive is next powered up, or when parameter 5302 EFB STATION ID setting is cleared and reset.

Drive control parameters

After the Modbus communication has been set up, the drive control parameters listed in the table below should be checked and adjusted when necessary.

The **Setting for fieldbus control** column gives the value to use when the Modbus interface is the desired source or destination for that particular signal. The **Function/Information** column gives a description of the parameter.

Paran	Parameter Setting for fieldbus control		Function/Information	Modbus register address	
CONT	ROL COMMAI	ND SOURCE	SELECTION	ABB DRV	DCU
1001	EXT1 COMMAND S	COMM	Enables 0301 FB CMD WORD 1 bits 01 (STOP/START) when EXT1 is selected as the active control location.		40031 bits 01
1002	EXT2 COMMAND S	COMM	Enables 0301 FB CMD WORD 1 bits 01 (STOP/START) when EXT2 is selected as the active control location.		40031 bits 01
1003	DIRECTION	FORWARD REVERSE REQUEST	Enables the rotation direction control as defined by parameters 1001 and 1002. The direction control is explained in section Reference handling on page 321.		40031 bit 2
1010	JOGGING SEL	COMM	Enables jogging 1 or 2 activation through 0302 FB CMD WORD 2 bits 2021 (JOGGING 1 / JOGGING 2).		40032 bits 2021
1102	EXT1/EXT2 SEL	COMM	Enables EXT1/EXT2 selection through 0301 FB CMD WORD 1 bit 5 (EXT2); with the ABB drives profile 5319 EFB PAR 19 bit 11 (EXT CTRL LOC).	40001 bit 11	40031 bit 5
1103	REF1 SELECT	COMM COMM+AI 1 COMM*AI1	Fieldbus reference REF1 is used when EXT1 is selected as the active control location. See section <i>Fieldbus references</i> on page <i>318</i> for information on the alternative settings.	40002 for REF1	

Paran	neter	Setting for fieldbus control	Function/Information	Modbus r address	egister
1106	REF2 SELECT	COMM COMM+AI 1 COMM*AI1	Fieldbus reference REF2 is used when EXT2 is selected as the active control location. See section <i>Fieldbus references</i> on page <i>318</i> for information on the alternative settings.	40003 for	REF2
OUTP	PUT SIGNAL S	OURCE SELE	ECTION	ABB DRV	DCU
1401	RELAY OUTPUT 1	COMM COMM(-1)	Enables relay output RO control by signal 0134 COMM RO WORD.	40134 for <i>0134</i>	signal
1501	AO1 CONTENT SEL	135	Directs the contents of the fieldbus reference 0135 COMM VALUE 1 to analog output AO.	40135 for signal <i>0135</i>	
SYST	EM CONTROL	INPUTS		ABB DRV	DCU
1601	RUN ENABLE	COMM	Enables the control of the inverted Run enable signal (Run disable) through 0301 FB CMD WORD 1 bit 6 (RUN_DISABLE); with the ABB drives profile 5319 EFB PAR 19 bit 3 (INHIBIT OPERATION).	40001 bit 3	40031 bit 6
1604	FAULT RESET SEL	COMM	Enables fault reset through the fieldbus 0301 FB CMD WORD 1 bit 4 (RESET); with the ABB drives profile 5319 EFB PAR 19 bit 7 (RESET).	40001 bit 7	40031 bit 4
1606	LOCAL LOCK	COMM	Local control mode lock signal through 0301 FB CMD WORD 1 bit 14 (REQ_LOCALLOC)	-	40031 bit 14
1607	PARAM SAVE	DONE SAVE	Saves parameter value changes (including those made through fieldbus control) to permanent memory.	41607	
1608	START ENABLE 1	COMM	Inverted Start enable 1 (Start disable) through 0302 FB CMD WORD 2 bit 18 (START_DISABLE1)	-	40032 bit 18
1609	START ENABLE 2	СОММ	Inverted Start enable 2 (Start disable) through 0302 FB CMD WORD 2 bit 19 (START_DISABLE2)	-	40032 bit 19

Paran	Parameter Setting fieldbu control		Function/Information	Modbus i address	register
LIMIT	S			ABB DRV	DCU
2013	MIN TORQUE SEL	COMM	Minimum torque limit 1/2 selection through 0301 FB CMD WORD 1 bit 15 (TORQLIM2)	-	40031 bit 15
2014	MAX TORQUE SEL	COMM	Maximum torque limit 1/2 selection through 0301 FB CMD WORD 1 bit 15 (TORQLIM2)	-	40031 bit 15
2201	ACC/DEC 1/2 SEL	COMM	Acceleration/deceleration ramp pair selection through 0301 FB CMD WORD 1 bit 10 (RAMP_2)	-	40031 bit 10
2209	RAMP INPUT 0	COMM	Ramp input to zero through 0301 FB CMD WORD 1 bit 13 (RAMP_IN_0); with the ABB drives profile 5319 EFB PAR 19 bit 6 (RAMP_IN_ ZERO)	40001 bit 6	40031 bit 13
COM	MUNICATION F	FAULT FUNC	TIONS	ABB DRV	DCU
3018	COMM FAULT FUNC	NOT SEL FAULT CONST SP 7 LAST SPEED	Determines the drive action in case the fieldbus communication is lost.	43018	
3019	COMM FAULT TIME	0.1 600.0 s	Defines the time between the communication loss detection and the action selected with parameter 3018 COMM FAULT FUNC.	43019	
PID C	ONTROLLER	REFERENCE	SIGNAL SOURCE SELECTION	ABB DRV	DCU
4010/ 4110/ 4210	SET POINT SEL	COMM COMM+AI 1 COMM*AI1	PID control reference (REF2)	40003 for	REF2

Fieldbus control interface

The communication between a fieldbus system and the drive consists of 16-bit input and output data words (with the ABB drives profile) and 32-bit input and output words (with the DCU profile).

Control word and Status word

The Control word (CW) is the principal means of controlling the drive from a fieldbus system. The Control word is sent by the fieldbus controller to the drive. The drive switches between its states according to the bit-coded instructions of the Control word.

The Status word (SW) is a word containing status information, sent by the drive to the fieldbus controller.

References

References (REF) are 16-bit signed integers. A negative reference (eg reverse direction of rotation) is formed by calculating the two's complement from the corresponding positive reference value. The contents of each reference word can be used as the speed, frequency, torque or process reference.

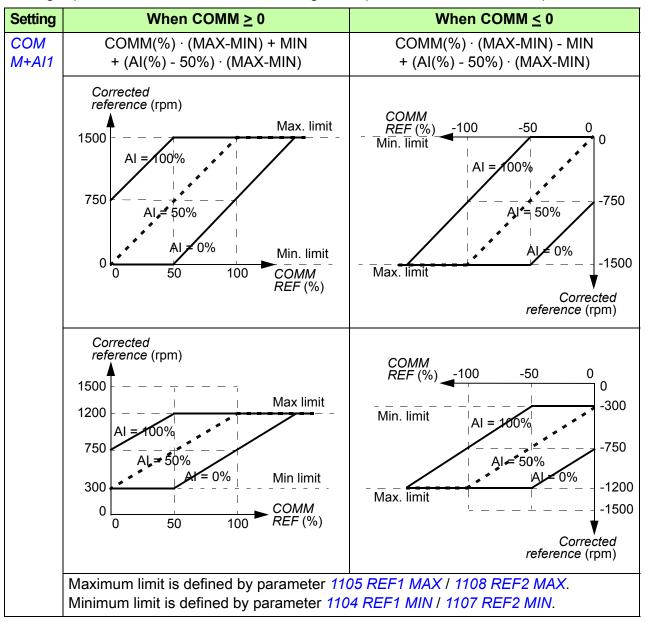
Actual values

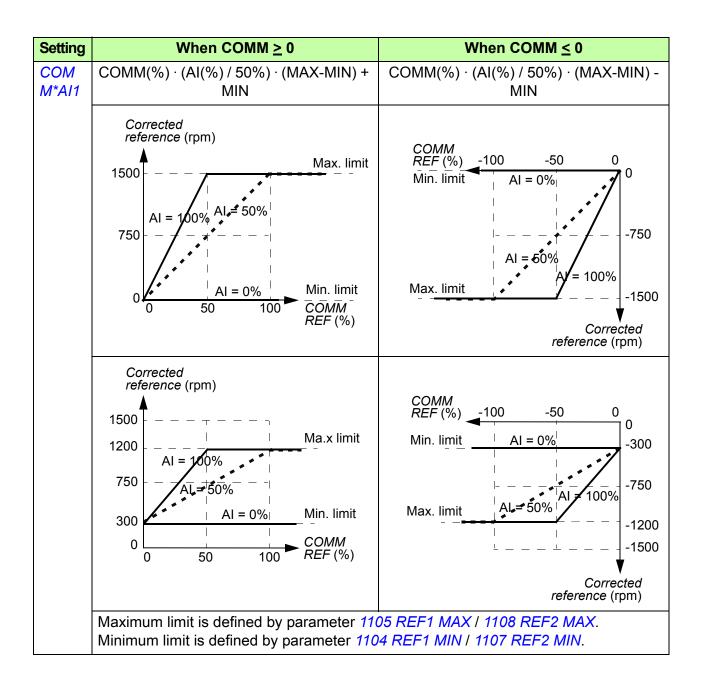
Actual values (ACT) are 16-bit words containing selected values of the drive.

Fieldbus references

Reference selection and correction

Fieldbus reference (called COMM in signal selection contexts) is selected by setting a reference selection parameter - 1103 REF1 SELECT or 1106 REF2 SELECT - to COMM, COMM+AI1 or COMM*AI1. When parameter 1103 or 1106 is set to COMM, the fieldbus reference is forwarded as such without correction. When parameter 1103 or 1106 is set to COMM+AI1 or COMM*AI1, the fieldbus reference is corrected using analog input Al1 as shown in the following examples for the ABB drives profile.





Fieldbus reference scaling

Fieldbus references REF1 and REF2 are scaled for the ABB drives profile as shown in the following table.

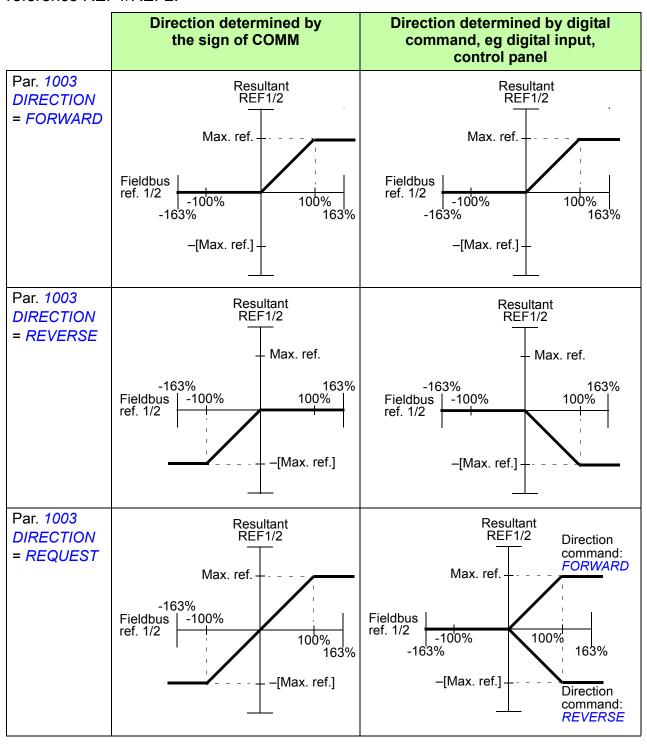
Note: Any correction of the reference (see section *Reference selection and correction* on page 320) is applied before scaling.

Reference	Range	Reference type	Scaling	Remarks
REF1	-32767 +32767	Speed or frequency	-20000 = -(par. 1105) 0 = 0 +20000 = (par. 1105) (20000 corresponds to 100%)	Final reference limited by 1104/1105. Actual motor speed limited by 2001/2002 (speed) or 2007/2008 (frequency).
REF2	-32767 +32767	Speed or frequency	-10000 = -(par. 1108) 0 = 0 +10000 = (par. 1108) (10000 corresponds to 100%)	Final reference limited by 1107/1108. Actual motor speed limited by 2001/2002 (speed) or 2007/2008 (frequency).
		Torque	-10000 = -(par. 1108) 0 = 0 +10000 = (par. 1108) (10000 corresponds to 100%)	Final reference limited by 2015/2017 (torque 1) or 2016/2018 (torque 2).
		PID reference	-10000 = -(par. 1108) 0 = 0 +10000 = (par. 1108) (10000 corresponds to 100%)	Final reference limited by 4012/4013 (PID set 1) or 4112/4113 (PID set 2).

Note: The settings of parameters *1104 REF1 MIN* and *1107 REF2 MIN* have no effect on the reference scaling.

Reference handling

The control of rotation direction is configured for each control location (EXT1 and EXT2) using the parameters in group 10 START/STOP/DIR. Fieldbus references are bipolar, ie they can be negative or positive. The following diagrams illustrate how group 10 parameters and the sign of the fieldbus reference interact to produce the reference REF1/REF2.



Actual value scaling

The scaling of the integers sent to the master as Actual values depends on the selected function. See chapter *Actual signals and parameters* on page *181*.

Modbus mapping

The following Modbus function codes are supported by the drive.

Function	Code hex (dec)	Additional information
Read Multiple Holding Registers	03 (03)	Reads the contents of registers in a slave device. Parameter sets, control, status and reference values are mapped as holding registers.
Write Single Holding Register	06 (06)	Writes to a single register in a slave device. Parameter sets, control, status and reference values are mapped as holding registers.
Diagnostics	08 (08)	Provides a series of tests for checking the communication between the master and the slave devices, or for checking various internal error conditions within the slave.
		The following subcodes are supported: <u>00 Return Query Data:</u> The data passed in the request data field is to be returned in the response. The entire response message should be identical to the request.
		01 Restart Communications Option: The slave device serial line port must be initialized and restarted, and all of its communication event counters cleared. If the port is currently in Listen Only Mode, no response is returned. If the port is not currently in Listen Only Mode, a normal response is returned before the restart.
		<u>04 Force Listen Only Mode:</u> Forces the addressed slave device to Listen Only Mode. This isolates it from the other devices on the network, allowing them to continue communicating without interruption from the addressed remote device. No response is returned. The only function that will be processed after this mode is entered is the Restart Communications Option function (subcode 01).
Write Multiple Holding Registers	10 (16)	Writes to the registers (1 to approximately 120 registers) in a slave device. Parameter sets, control, status and reference values are mapped as holding registers.
Read/Write Multiple Holding Registers	17 (23)	Performs a combination of one read operation and one write operation (function codes 03 and 10) in a single Modbus transaction. The write operation is performed before the read operation.

Register mapping

The drive parameters, Control/Status word, references and actual values are mapped to the area 4xxxx so that:

- 40001...40099 are reserved for drive control/status, reference and actual values.
- 40101...49999 are reserved for drive parameters 0101...9999 (eg 40102 is parameter 0102). In this mapping, the thousands and hundreds correspond to the group number, while the tens and ones correspond to the parameter number within a group.

The register addresses that do not correspond with drive parameters are invalid. If there is an attempt to read or write invalid addresses, the Modbus interface returns an exception code to the controller. See Exception codes on page 325.

The following table gives information on the contents of the Modbus addresses 40001...40012 and 40031...40034.

Modbus register Ac		Access	Information
40001	Control word	R/W	Control word. Supported only by the ABB drives profile, ie when 5305 EFB CTRL PROFILE setting is ABB DRV LIM or ABB DRV FULL. Parameter 5319 EFB PAR 19 shows a copy of the Control word in hexadecimal format.
40002	Reference 1	R/W	External reference REF1. See section <i>Fieldbus</i> references on page 318.
40003	Reference 2	R/W	External reference REF2. See section <i>Fieldbus</i> references on page 318.
40004	Status word	R	Status word. Supported only by the ABB drives profile, ie when 5305 EFB CTRL PROFILE setting is ABB DRV LIM or ABB DRV FULL. Parameter 5320 EFB PAR 20 shows a copy of the Control word in hexadecimal format.
40005 40012	Actual 18	R	Actual value 18. Use parameter 5310 5317 to select an actual value to be mapped to Modbus register 4000540012.
40031	Control word LSW	R/W	0301 FB CMD WORD 1, ie the least significant word of the DCU profile 32-bit Control word.
			Supported only by the DCU profile, ie when 5305 EFB CTRL PROFILE setting is DCU PROFILE.
40032	Control word MSW	R/W	0302 FB CMD WORD 2, ie the most significant word of the DCU profile 32-bit Control word.
			Supported only by the DCU profile, ie when 5305 EFB CTRL PROFILE setting is DCU PROFILE.
40033	Status word LSW	R	0303 FB STS WORD 1, ie the least significant word of the DCU profile 32-bit Status word.
			Supported only by the DCU profile, ie when 5305 EFB CTRL PROFILE setting is DCU PROFILE.

Modbus register		Access	Information
40034	ACS355 Status word MSW		0304 FB STS WORD 2, ie the most significant word of the DCU profile 32-bit Status word.
			Supported only by the DCU profile, ie when 5305 EFB CTRL PROFILE setting is DCU PROFILE.

Note: Parameter writes through standard Modbus are always volatile, ie modified values are not automatically stored to the permanent memory. Use parameter *1607 PARAM SAVE* to save all changed values.

Function codes

Supported function codes for the holding 4xxxx register:

Code hex (dec)	Function name	Additional information
03 (03)	Read 4X Register	Reads the binary contents of registers (4X references) in a slave device.
06 (06)	Preset single 4X register	Presets a value into a single register (4X reference). When broadcast, the function presets the same register reference in all attached slaves.
10 (16)	Preset multiple 4X registers	Presets values into a sequence of registers (4X references). When broadcast, the function presets the same register references in all attached slaves.
17 (23)	Read/Write 4X registers	Performs a combination of one read operation and one write operation (function codes 03 and 10) in a single Modbus transaction. Write operation is performed before the read operation.

Note: In the Modbus data message, register 4xxxx is addressed as xxxx -1. For example, register 40002 is addressed as 0001.

Exception codes

Exception codes are serial communication responses from the drive. The drive supports the standard Modbus exception codes listed in the following table.

Code	Name	Description	
01	Illegal Function	Unsupported command	
02	Illegal Data Address	Address does not exist or is read/write protected.	
03	Illegal Data Value	Incorrect value for the drive:	
		Value is outside minimum or maximum limits.	
		Parameter is read-only.	
		Message is too long.	
		Parameter write is not allowed when start is active.	
		Parameter write is not allowed when factory macro is selected.	

Drive parameter 5318 EFB PAR 18 holds the most recent exception code.

Communication profiles

The embedded fieldbus supports three communication profiles:

- DCU communication profile (DCU PROFILE)
- ABB drives limited communication profile (ABB DRV LIM)
- ABB drives full communication profile (ABB DRV FULL).

The DCU profile extends the control and status interface to 32 bits, and it is the internal interface between the main drive application and the embedded fieldbus environment. The ABB drives limited profile is based on the PROFIBUS interface. The ABB drives full profile (ABB DRV FULL) supports two Control word bits not supported by the ABB DRV LIM implementation.

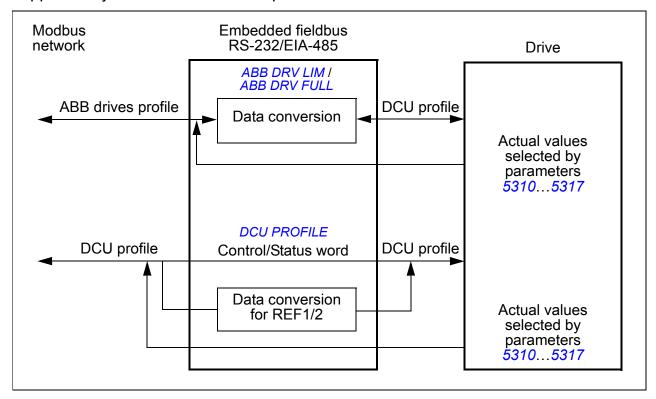


ABB drives communication profile

Two implementations of the ABB drives communication profile are available: ABB drives full and ABB drives limited. The ABB drives communication profile is active when parameter 5305 EFB CTRL PROFILE is set to ABB DRV FULL or ABB DRV **LIM**. The Control word and Status word for the profile are described below.

The ABB drives communication profiles can be used through both EXT1 and EXT2. The Control word commands are in effect when parameter 1001 EXT1 COMMANDS or 1002 EXT2 COMMANDS (whichever control location is active) is set to COMM.

Control word

The table below and the state diagram on page 330 describe the Control word content for the ABB drives profile. The upper case boldface text refers to the states shown in the diagram.

	ABB drives profile Control word, parameter 5319 EFB PAR 19				
Bit	Name	Value	Comments		
0 OFF1		1	Enter READY TO OPERATE.		
	CONTROL 0		Stop along currently active deceleration ramp (2203/2206). Enter OFF1 ACTIVE; proceed to READY TO SWITCH ON unless other interlocks (OFF2, OFF3) are active.		
1	OFF2	1	Continue operation (OFF2 inactive).		
	CONTROL	0	Emergency OFF, drive coast to stop. Enter OFF2 ACTIVE ; proceed to SWITCH-ON INHIBITED .		
2	OFF3 CONTROL	1	Continue operation (OFF3 inactive).		
	CONTROL	0	Emergency stop, drive stops within time defined by par. 2208. Enter OFF3 ACTIVE; proceed to SWITCH-ON INHIBITED.		
			WARNING! Ensure motor and driven machine can be stopped using this stop mode.		
3 INHIBIT OPERATION	INHIBIT OPERATION	1	Enter OPERATION ENABLED . (Note: The Run enable signal must be active; see parameter <i>1601</i> . If par. <i>1601</i> is set to <i>COMM</i> , this bit also activates the Run enable signal.)		
		0	Inhibit operation. Enter OPERATION INHIBITED .		
4	Note: Bit 4 is sup	ported on	ly by ABB DRV FULL profile.		
Z (A	RAMP_OUT_ ZERO (ABB DRV FULL)	1	Enter RAMP FUNCTION GENERATOR: OUTPUT ENABLED.		
		0	Force Ramp function generator output to zero. Drive ramps to stop (current and DC voltage limits in force).		
5	5 RAMP_HOLD		Enable ramp function. Enter RAMP FUNCTION GENERATOR: ACCELERATOR ENABLED.		
		0	Halt ramping (Ramp function generator output held).		
6	RAMP_IN_	1	Normal operation. Enter OPERATING .		
	ZERO	0	Force Ramp function generator input to zero.		
7	RESET	0=>1	Fault reset if an active fault exists. Enter SWITCH-ON INHIBITED . Effective if par. <i>1604</i> is set to <i>COMM</i> .		
		0	Continue normal operation.		
8 9	Not in use				

	ABB drives profile Control word, parameter 5319 EFB PAR 19				
Bit	Name	Value	Value Comments		
10 Note: Bit 10 is supported only			nly by ABB DRV FULL.		
	REMOTE_CMD	1	Fieldbus control enabled.		
	(ABB DRV FULL)	0	Control word ≠ 0 or reference ≠ 0: Retain last Control word and reference. Control word = 0 and reference = 0: Fieldbus control enabled. Reference and deceleration/acceleration ramp are locked.		
11	EXT CTRL LOC	1	Select external control location EXT2. Effective if par. 1102 is set to COMM.		
		0	Select external control location EXT1. Effective if par. 1102 is set to COMM.		
12	Reserved				
 15					

Status word

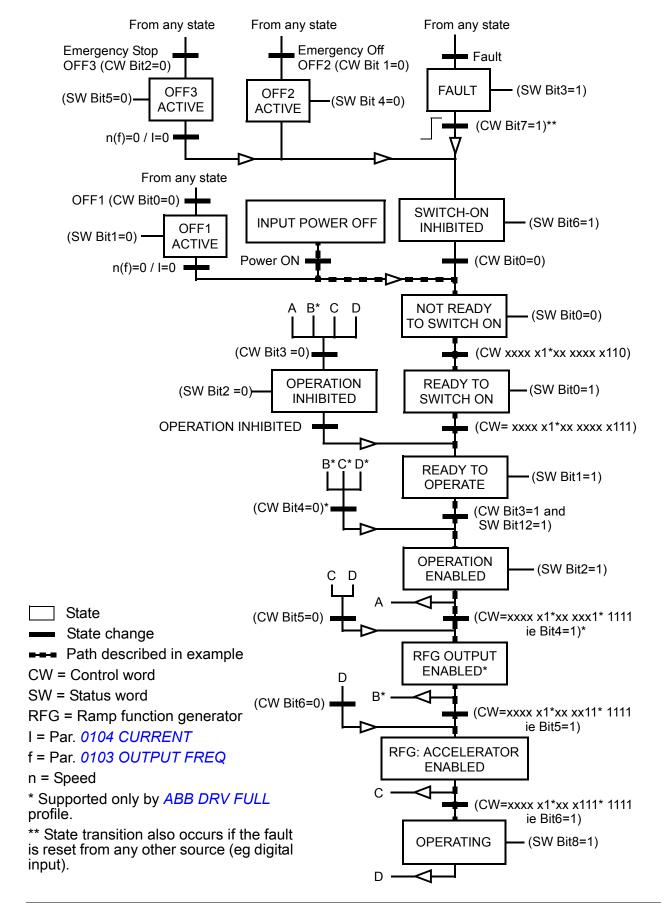
The table below and the state diagram on page 330 describe the Status word content for the ABB drives profile. The upper case boldface text refers to the states shown in the diagram.

Α	ABB drives profile (EFB) Status word, parameter 5320 EFB PAR 20				
Bit	Name	Value	STATE/Description (Correspond to states/boxes in the state diagram)		
0	RDY_ON	1	READY TO SWITCH ON		
		0	NOT READY TO SWITCH ON		
1	RDY_RUN	1	READY TO OPERATE		
		0	OFF1 ACTIVE		
2	RDY_REF	1	OPERATION ENABLED		
		0	OPERATION INHIBITED		
3	TRIPPED	01	FAULT. See chapter Fault tracing on page 347.		
		0	No fault		
4	OFF_2_STA	1	OFF2 inactive		
		0	OFF2 ACTIVE		
5	OFF_3_STA	1	OFF3 inactive		
		0	OFF3 ACTIVE		
6	SWC_ON_INHI	1	SWITCH-ON INHIBITED		
	В	0	Switch-on inhibit not active		
7	ALARM	1	Alarm. See chapter Fault tracing on page 347.		
		0	No alarm		

A	ABB drives profile (EFB) Status word, parameter 5320 EFB PAR 20				
Bit	Name	Value	STATE/Description (Correspond to states/boxes in the state diagram)		
8 AT_SETPOINT		1	OPERATING. Actual value equals reference value (= is within tolerance limits, ie in speed control the difference between the output speed and the speed reference is less than or equal to 4/1%* of the nominal motor speed). * Asymmetric hysteresis: 4% when speed enters the reference area, 1% when speed exits the reference area.		
		0	Actual value differs from reference value (= is outside tolerance limits).		
9	REMOTE	1	Drive control location: REMOTE (EXT1 or EXT2)		
	0		Drive control location: LOCAL		
10	ABOVE_LIMIT	1	Supervised parameter value exceeds the supervision high limit. Bit value is 1 until the supervised parameter value falls below the supervision low limit. See parameter group 32 SUPERVISION, parameter 3201 SUPERV 1 PARAM.		
		0	Supervised parameter value falls below the supervision low limit. Bit value is 0 until the supervised parameter value exceeds the supervision high limit. See parameter group 32 SUPERVISION, parameter 3201 SUPERV 1 PARAM.		
11	EXT CTRL LOC	1	External control location EXT2 selected		
		0	External control location EXT1 selected		
12	EXT RUN	1	External Run enable signal received		
	ENABLE	0	No external Run enable received		
13	Reserved				
 15					

State diagram

The state diagram below describes the start-stop function of Control word (CW) and Status word (SW) bits for the ABB drives profile.



DCU communication profile

Because the DCU profile extends the control and status interface to 32 bits, two different signals are needed for both the Control words (0301 and 0302) and Status words (0303 and 0304).

Control words

The following tables describe the Control word content for the DCU profile.

	DCU profile Control word, parameter 0301 FB CMD WORD 1				
Bit	Name	Value	Information		
0 STOP		1	Stop according to either the stop mode parameter (2102) or the stop mode requests (bits 7 and 8). Note: Simultaneous STOP and START commands result in a stop command.		
		0	No operation		
1	START	1	Start		
			Note: Simultaneous STOP and START commands result in a stop command.		
		0	No operation		
2	REVERSE	1	Reverse direction. The direction is defined by using the XOR operation on bit 2 and 31 (= sign of the reference) values.		
		0	Forward direction		
3	LOCAL	1	Enter local control mode.		
		0	Enter external control mode.		
4	RESET	-> 1	Reset.		
		other	No operation		
5	EXT2	1	Switch to external control EXT2.		
		0	Switch to external control EXT1.		
6	RUN_DISABLE	1	Activate Run disable.		
		0	Activate Run enable.		
7	STPMODE_R	1	Stop along currently active deceleration ramp (bit 10). Bit 0 value must be 1 (<i>STOP</i>).		
		0	No operation		
8	STPMODE_EM	1	Emergency stop. Bit 0 value must be 1 (STOP).		
		0	No operation		
9	STPMODE_C	1	Coast to stop. Bit 0 value must be 1 (STOP).		
		0	No operation		
10	RAMP_2	1	Use acceleration/deceleration ramp pair 2 (defined by parameters 22052207).		
		0	Use acceleration/deceleration ramp pair 1 (defined by parameters 22022204).		

	DCU profile Control word, parameter 0301 FB CMD WORD 1				
Bit	Name	Value	Information		
11	RAMP_OUT_0	1	Force ramp output to zero.		
		0	No operation		
12	RAMP_HOLD	1	Halt ramping (Ramp function generator output held).		
		0	No operation		
13	RAMP_IN_0	1	Force ramp input to zero.		
		0	No operation		
14	REQ_LOCALLO C	1	Enable local lock. Entering the local control mode is disabled (LOC/REM key of the panel).		
		0	No operation		
15	15 TORQLIM2 1		Use minimum/maximum torque limit 2 (defined by parameters 2016 and 2018).		
		0	Use minimum/maximum torque limit 1 (defined by parameters 2015 and 2017).		

	DCU profile Control word, parameter 0302 FB CMD WORD 2			
Bit	Name	Value Information		
16	FBLOCAL_CTL	1	Fieldbus local mode for Control word requested.	
			Example: If the drive is in remote control and the start/stop/direction command source is DI for external control location 1 (EXT1): by setting bit 16 to value 1, the start/stop/direction is controlled by the fieldbus command word.	
		0	No fieldbus local mode	
17	FBLOCAL_REF	1	Fieldbus local mode Control word for reference requested. See the example for bit 16 (<i>FBLOCAL_CTL</i>).	
		0	No fieldbus local mode	
18	START_DISABL	1	No Start enable	
	E1	0	Enable start. Effective if parameter 1608 setting is COMM.	
19	START_DISABL E2	1	No Start enable	
		0	Enable start. Effective if parameter 1609 setting is COMM.	
21	21 JOGGING 1 1		Activate jogging 1. Effective if parameter 1010 setting is COMM. See section Jogging on page 166.	
		0	Jogging 1 disabled	
20	20 JOGGING 2		Activate jogging 2. Effective if parameter 1010 setting is COMM. See section Jogging on page 166.	
		0	Jogging 2 disabled	
22	Reserved			
2 6				

	DCU profile Control word, parameter 0302 FB CMD WORD 2				
Bit	Name	Value	Information		
27	27 REF_CONST 1		Constant speed reference request. This is an internal control bit. Only for supervision.		
		0	No operation		
28	28 REF_AVE 1		Average speed reference request. This is an internal control bit. Only for supervision.		
		0	No operation		
29	LINK_ON	1	Master detected on fieldbus link. This is an internal control bit. Only for supervision.		
		0	Fieldbus link is down.		
30	REQ_STARTIN	1	Start inhibit		
	H	0	No start inhibit		
31	Reserved				

Status words

The following tables describe the Status word content for the DCU profile.

	DCU profile Status word, parameter 0303 FB STS WORD 1				
Bit	Name	Value	Status		
0	READY	1	Drive is ready to receive start command.		
		0	Drive is not ready.		
1	ENABLED	1	External Run enable signal received.		
		0	No external Run enable signal received.		
2	STARTED	1	Drive has received start command.		
		0	Drive has not received start command.		
3	RUNNING	1	Drive is modulating.		
		0	Drive is not modulating.		
4	ZERO_SPEED	1	Drive is at zero speed.		
		0	Drive has not reached zero speed.		
5	ACCELERATE	1	Drive is accelerating.		
		0	Drive is not accelerating.		
6	DECELERATE	1	Drive is decelerating.		
		0	Drive is not decelerating.		
7	AT_SETPOINT	1	Drive is at setpoint. Actual value equals reference value (ie is within tolerance limits).		
		0	Drive has not reached setpoint.		
8	LIMIT	1	Operation is limited by internal protection limits or group 20 LIMITS settings.		
		0	Operation is within internal protection limits and according group 20 LIMITS settings.		

	DCU profile Status word, parameter 0303 FB STS WORD 1				
Bit	Name	Value	Status		
9	SUPERVISION	1	A supervised parameter (group 32 SUPERVISION) is outside its limits.		
		0	All supervised parameters are within limits.		
10	REV_REF	1	Drive reference is in reverse direction.		
		0	Drive reference is in forward direction.		
11	REV_ACT	1	Drive is running in reverse direction.		
		0	Drive is running in forward direction.		
12	PANEL_LOCAL	1	Control is in control panel (or PC tool) local mode.		
		0	Control is not in control panel local mode.		
13	FIELDBUS_LOCAL	1	Control is in fieldbus local mode		
		0	Control is not in fieldbus local mode.		
14	EXT2_ACT	1	Control is in EXT2 mode.		
		0	Control is in EXT1 mode.		
15	FAULT	1	Drive is in a fault state.		
		0	Drive is not in a fault state.		

	DCU profile Status word, parameter 0304 FB STS WORD 2				
Bit	Name	Value	Status		
16	ALARM	1	An alarm is on.		
		0	No alarms are on.		
17	NOTICE	1	A maintenance request is pending.		
		0	No maintenance request		
18	DIRLOCK	1	Direction lock is ON. (Direction change is locked.)		
		0	Direction lock is OFF.		
19	LOCALLOCK	1	Local mode lock is ON. (Local mode is locked.)		
		0	Local mode lock is OFF.		
20	CTL_MODE	1	Drive is in vector control mode.		
		0	Drive is in scalar control mode.		
21	JOGGING ACTIVE	1	Jogging function is active.		
		0	Jogging function is not active.		
22 25	Reserved		•		
26	REQ_CTL	1	Control word requested from fieldbus		
		0	No operation		
27	REQ_REF1	1	Reference 1 requested from fieldbus		
		0	Reference 1 is not requested from fieldbus.		

	DCU profile Status word, parameter 0304 FB STS WORD 2			
Bit	Name	Value	Status	
28	REQ_REF2	1	Reference 2 requested from fieldbus	
		0	Reference 2 is not requested from fieldbus.	
29	REQ_REF2EXT	1	External PID reference 2 requested from fieldbus	
		0	External PID reference 2 is not requested from fieldbus.	
30	ACK_STARTINH	1	Start inhibit from fieldbus	
		0	No start inhibit from fieldbus	
31	Reserved	•		





Fieldbus control with fieldbus adapter

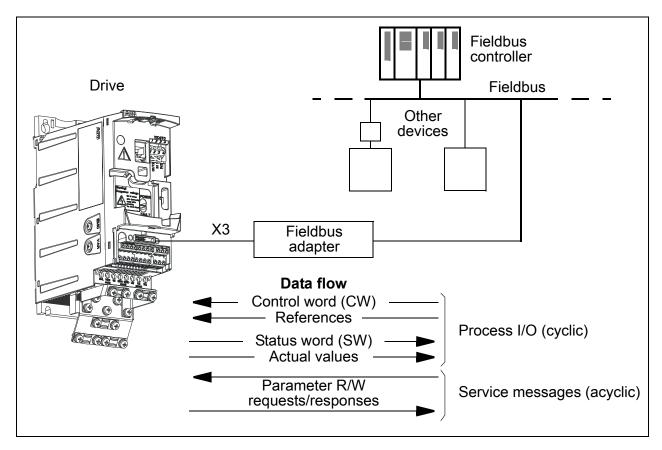
What this chapter contains

The chapter describes how the drive can be controlled by external devices over a communication network through a fieldbus adapter.

System overview

The drive can be connected to an external control system through a fieldbus adapter or embedded fieldbus. For embedded fieldbus control, see chapter Fieldbus control with embedded fieldbus on page 311.

The fieldbus adapter is connected to drive terminal X3.



The drive can be set to receive all of its control information through the fieldbus interface, or the control can be distributed between the fieldbus interface and other available sources, eg digital and analog inputs.

The drive can communicate to a control system through a fieldbus adapter using, for example, the following serial communication protocols. Other protocols may be available; contact your local ABB representative.

- PROFIBUS-DP (FPBA-01 adapter)
- CANopen (FCAN-01 adapter)
- DeviceNet™ (FDNA-01 adapter)
- Ethernet (FENA-01 adapter)
- Modbus RTU (FMBA-01 adapter. See chapter Fieldbus control with embedded fieldbus on page 311.)

The drive detects automatically which fieldbus adapter is connected to the drive terminal X3 (with the exception of FMBA-01). The DCU profile is always used in communication between the drive and the fieldbus adapter (see section Fieldbus control interface on page 342). The communication profile on the fieldbus network depends on the type and settings of the connected adapter.

The default profile settings are protocol-dependent (for example, vendor-specific profile (ABB drives) for PROFIBUS and industry-standard drive profile (AC/DC Drive) for DeviceNet).

Setting up communication through a fieldbus adapter module

Before configuring the drive for the fieldbus control, the adapter module must be mechanically and electrically installed according to the instructions given in section Attach the optional fieldbus module on page 38, and the module manual.

The communication between the drive and the fieldbus adapter module is activated by setting parameter 9802 COMM PROT SEL to EXT FBA. The adapter-specific parameters in group 51 EXT COMM MODULE must also be set. See the table below.

Param	neter	Alternative settings	Setting for fieldbus control	Function/Information
COMN	MUNICATION INITIA	ALIZATION		
9802	COMM PROT SEL	NOT SEL STD MODBUS EXT FBA MODBUS RS232	EXT FBA	Initializes the communication between the drive and the fieldbus adapter module.
ADAP ²	TER MODULE COI	NFIGURATION		
5101	FBA TYPE	-	-	Displays the type of the fieldbus adapter module.
5102	FB PAR 2	•	•	ule-specific. For more
		information, see t parameters are n		. Note that not all of these
5126	FB PAR 26	– parameters are m	ecessarily used.	
5127	FBA PAR REFRESH	(0) DONE (1) REFRESH	-	Validates any changed adapter module configuration parameter settings.

Note: In adapter module, the parameter group number is A (group 1) for group 51 EXT COMM MODULE.

TRAN	TRANSMITTED DATA SELECTION		
5401 5410	FBA DATA IN 1 FBA DATA OUT 10	0 16 1019999	Defines the data transmitted from the drive to the fieldbus controller.
5501 5510	FBA DATA OUT 1 FBA DATA OUT 10	0 16 1019999	Defines the data transmitted from the fieldbus controller to the drive.

Note: In adapter module, the parameter group number is C (group 3) for group 54 FBA DATA IN and B (group 2) for group 55 FBA DATA OUT.

After the module configuration parameters in groups 51 EXT COMM MODULE, 54 FBA DATA IN and 55 FBA DATA OUT have been set, the drive control parameters (shown in section Drive control parameters on page 340) must be checked and adjusted when necessary.

The new settings will take effect when the drive is next powered up, or when parameter 5127 FBA PAR REFRESH is activated.

Drive control parameters

OUTPUT 1

COMM(-1)

After the fieldbus communication has been set up, the drive control parameters listed in the table below should be checked and adjusted where necessary.

The **Setting for fieldbus control** column gives the value to use when the fieldbus interface is the desired source or destination for that particular signal. The **Function/Information** column gives a description of the parameter.

Parameter	Setting for fieldbus control	Function/Information
CONTROL COMMAND	SOURCE SELECT	ON
1001 EXT1 COMMANDS	COMM	Selects the fieldbus as the source for the start and stop commands when EXT1 is selected as the active control location.
1002 EXT2 COMMANDS	COMM	Selects the fieldbus as the source for the start and stop commands when EXT2 is selected as the active control location.
1003 DIRECTION	FORWARD REVERSE REQUEST	Enables the rotation direction control as defined by parameters 1001 and 1002. The direction control is explained in section Reference handling on page 321.
1010 JOGGING SEL	COMM	Enables jogging 1 or 2 activation through the fieldbus.
1102 EXT1/EXT2 SEL	COMM	Enables EXT1/EXT2 selection through the fieldbus.
1103 REF1 SELECT	COMM COMM+AI1 COMM*AI1	Fieldbus reference REF1 is used when EXT1 is selected as the active control location. See section <i>Reference selection and correction</i> on page 344.
1106 REF2 SELECT	COMM COMM+AI1 COMM*AI1	Fieldbus reference REF2 is used when EXT2 is selected as the active control location. See section <i>Reference selection and correction</i> on page <i>344</i> .
OUTPUT SIGNAL SOU	IRCE SELECTION	
1401 RELAY	COMM	Enables relay output RO control by signal 0134

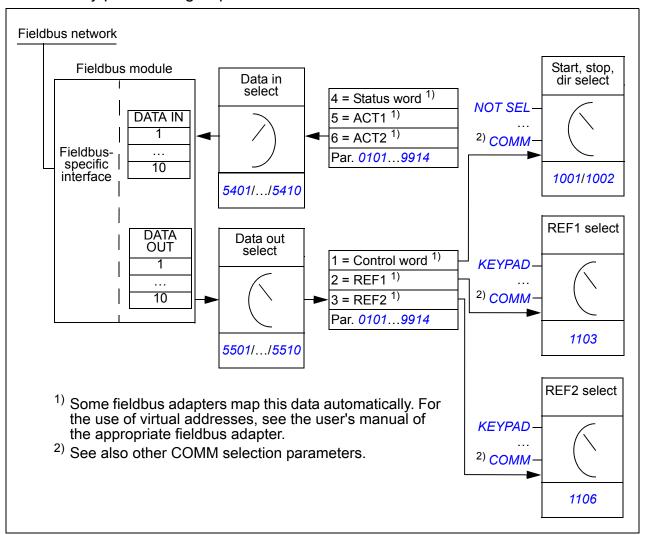
COMM RO WORD.

Paran	neter	Setting for fieldbus control	Function/Information
1501	AO1 CONTENT SEL	135 (ie <i>0135</i> COMM VALUE 1)	Directs the contents of fieldbus reference <i>0135 COMM VALUE 1</i> to analog output AO.
SYST	EM CONTROL IN	PUTS	
1601	RUN ENABLE	СОММ	Selects the fieldbus interface as the source for the inverted Run enable signal (Run disable).
1604	FAULT RESET SEL	COMM	Selects the fieldbus interface as the source for the fault reset signal.
1606	LOCAL LOCK	СОММ	Selects the fieldbus interface as the source for the local lock signal.
1607	PARAM SAVE	DONE SAVE	Saves parameter value changes (including those made through fieldbus control) to the permanent memory.
1608	START ENABLE 1	COMM	Selects the fieldbus interface as the source for the inverted Start enable 1 (Start disable) signal.
1609	START ENABLE 2	COMM	Selects the fieldbus interface as the source for the inverted Start enable 2 (Start disable) signal.
LIMITS	S		
2013	MIN TORQUE SEL	COMM	Selects the fieldbus interface as the source for the minimum torque limit 1/2 selection.
2014	MAX TORQUE SEL	COMM	Selects the fieldbus interface as the source for the maximum torque limit 1/2 selection.
2201	ACC/DEC 1/2 SEL	COMM	Selects the fieldbus interface as the source for acceleration/deceleration ramp pair 1/2 selection
2209	RAMP INPUT 0	COMM	Selects the fieldbus interface as the source for forcing ramp input to zero.
COMN	MUNICATION FAL	JLT FUNCTIONS	
3018	COMM FAULT FUNC	NOT SEL FAULT CONST SP 7 LAST SPEED	Determines the drive action in case the fieldbus communication is lost.
3019	COMM FAULT TIME	0.1 60.0 s	Defines the time between the communication loss detection and the action selected with parameter 3018 COMM FAULT FUNC.
PID C	ONTROLLER RE	FERENCE SIGNAL S	SOURCE SELECTION
4010 /411 0/42 10	SET POINT SEL	COMM COMM+AI1 COMM*AI1	PID control reference (REF2)

Fieldbus control interface

The communication between a fieldbus system and the drive consists of 16-bit input and output data words. The drive supports at the maximum the use of 10 data words in each direction.

Data transformed from the drive to the fieldbus controller is defined by parameter group 54 FBA DATA IN and data transformed from the fieldbus controller to the drive is defined by parameter group 55 FBA DATA OUT.



Control word and Status word

The Control word (CW) is the principal means of controlling the drive from a fieldbus system. The Control word is sent by the fieldbus controller to the drive. The drive switches between its states according to the bit-coded instructions of the Control word.

The Status word (SW) is a word containing status information, sent by the drive to the fieldbus controller.

References

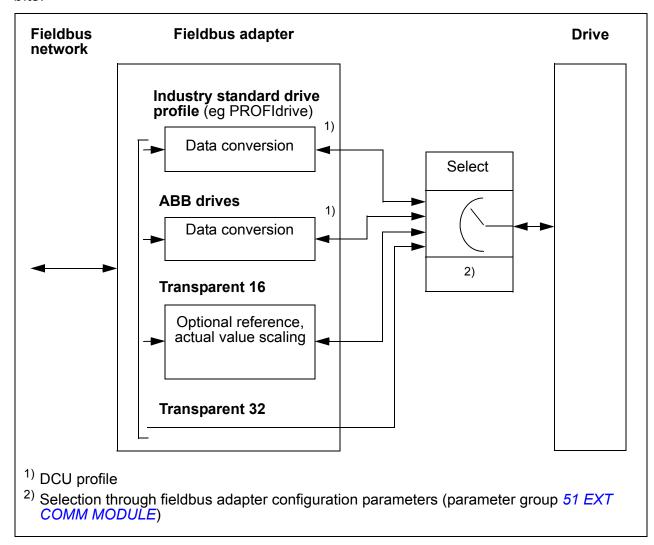
References (REF) are 16-bit signed integers. A negative reference (indicating reversed direction of rotation) is formed by calculating the two's complement from the corresponding positive reference value. The contents of each reference word can be used as speed or frequency reference.

Actual values

Actual values (ACT) are 16-bit words containing information on selected operations of the drive.

Communication profile

The communication between the drive and the fieldbus adapter supports the DCU communication profile. The DCU profile extends the control and status interface to 32 bits.



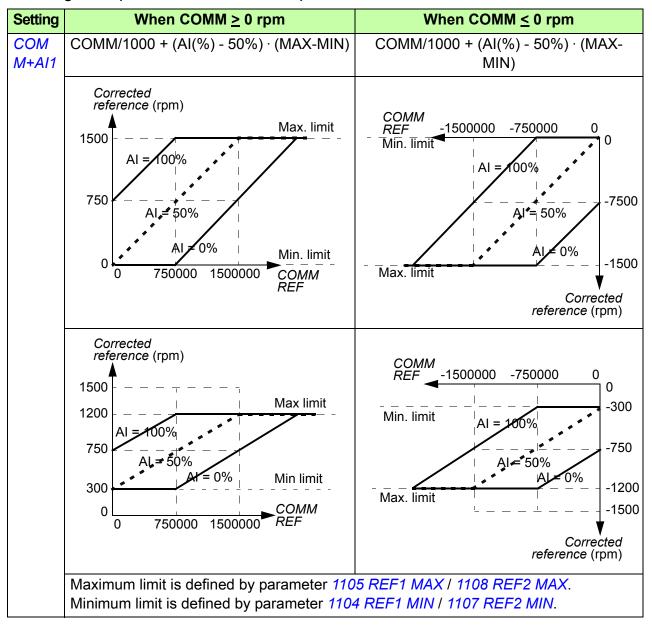
For the DCU profile Control and Status word contents, see section DCU communication profile on page 331.

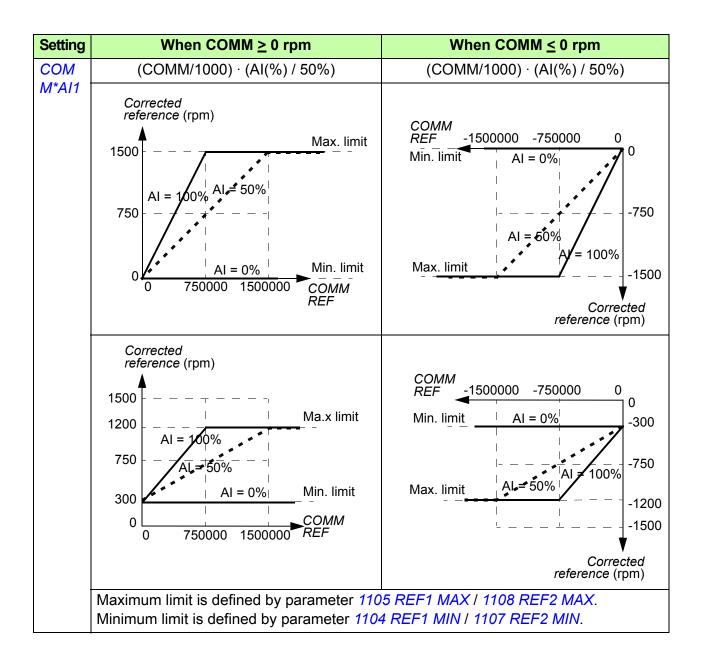
Fieldbus references

Reference selection and correction

Fieldbus reference (called COMM in signal selection contexts) is selected by setting a reference selection parameter - 1103 REF1 SELECT or 1106 REF2 SELECT - to COMM, COMM+AI1 or COMM*AI1. When parameter 1103 or 1106 is set to COMM, the fieldbus reference is forwarded as such without correction. When parameter 1103 or 1106 is set to COMM+AI1 or COMM*AI1, the fieldbus reference is corrected using analog input Al1 as shown in the following examples for the DCU profile.

With the DCU profile the fieldbus reference type can be Hz, rpm or percentage. In the following examples the reference is in rpm.





Fieldbus reference scaling

Fieldbus references REF1 and REF2 are scaled for the DCU profile as shown in the following table.

Note: Any correction of the reference (see section *Reference selection and correction* on page *344*) is applied before scaling.

Reference	Range	Reference type	Scaling	Remarks
REF1	-214783648 +214783647	Speed or frequency	1000 = 1 rpm / 1 Hz	Final reference limited by 1104/1105. Actual motor speed limited by 2001/2002 (speed) or 2007/2008 (frequency).
REF2	-214783648 +214783647	Speed or frequency	1000 = 1%	Final reference limited by 1107/1108. Actual motor speed limited by 2001/2002 (speed) or 2007/2008 (frequency).
		Torque	1000 = 1%	Final reference limited by 2015/2017 (torque 1) or 2016/2018 (torque 2).
		PID reference	1000 = 1%	Final reference limited by 4012/4013 (PID set 1) or 4112/4113 (PID set 2).

Note: The settings of parameters 1104 REF1 MIN and 1107 REF2 MIN have no effect on the reference scaling.

Reference handling

Reference handling is the same for the ABB drives profile (embedded fieldbus) and DCU profile. See section *Reference handling* on page 321.

Actual value scaling

The scaling of the integers sent to the master as Actual values depends on the selected function. See chapter *Actual signals and parameters* on page 181.

Fault tracing

What this chapter contains

The chapter tells how to reset faults and view the fault history. It also lists all alarm and fault messages including the possible cause and corrective actions.

Safety



WARNING! Only qualified electricians are allowed to maintain the drive. Read the safety instructions in chapter *Safety* on page 17 before you work on the drive.

Alarm and fault indications

A fault is indicated with a red LED. See section LEDs on page 370.

An alarm or fault message on the panel display indicates an abnormal drive status. Using the information given in this chapter, most alarm and fault causes can be identified and corrected. If not, contact your local ABB representative.

To display the alarms on the control panel, set parameter 1610 DISPLAY ALARMS to value 1 (YES).

The four-digit code number in parenthesis after the fault is for the fieldbus communication. See chapters *Fieldbus control with embedded fieldbus* on page *311* and *Fieldbus control with fieldbus adapter* on page *337*.

How to reset

The drive can be reset either by pressing the keypad key (basic control panel) or (assistant control panel), through digital input or fieldbus, or by switching the

supply voltage off for a while. The source for the fault reset signal is selected by parameter *1604 FAULT RESET SEL*. When the fault has been removed, the motor can be restarted.

Fault history

When a fault is detected, it is stored in the fault history. The latest faults are stored together with the time stamp.

Parameters 0401 LAST FAULT, 0412 PREVIOUS FAULT 1 and 0413 PREVIOUS FAULT 2 store the most recent faults. Parameters 0404...0409 show drive operation data at the time the latest fault occurred. The assistant control panel provides additional information about the fault history. See section Fault logger mode on page 103 for more information.

Alarm messages generated by the drive

CODE	ALARM	CAUSE	WHAT TO DO
2001	OVERCURRENT 0308 bit 0 (programmable fault function 1610)	Output current limit controller is active. High ambient temperature.	Check ambient conditions. Load capacity decreases if installation site ambient temperature exceeds 40 °C (104 °F). See section <i>Derating</i> on page 373. For more information, see fault 0001 in Fault messages generated by the
2002	OVERVOLTAGE 0308 bit 1 (programmable fault function 1610)	DC overvoltage controller is active.	drive on page 355. For more information, see fault 0002 in Fault messages generated by the drive on page 355.
2003	UNDERVOLTAGE 0308 bit 2	DC undervoltage controller is active.	For more information, see fault 0003 in Fault messages generated by the drive on page 349.
2004	DIR LOCK 0308 bit 3	Change of direction is not allowed.	Check parameter 1003 DIRECTION settings.
2005	IO COMM 0308 bit 4 (programmable fault function 3018, 3019)	Fieldbus communication break	Check status of fieldbus communication. See chapter Fieldbus control with embedded fieldbus on page 311, chapter Fieldbus control with fieldbus adapter on page 337 or appropriate fieldbus adapter manual. Check fault function parameter settings. Check connections. Check if master can communicate.
2006	Al1 LOSS 0308 bit 5 (programmable fault function 3001, 3021)	Analog input AI1 signal has fallen below limit defined by parameter 3021 AI1 FAULT LIMIT.	For more information, see fault 0007 in Fault messages generated by the drive on page 355.
2007	AI2 LOSS 0308 bit 6 (programmable fault function 3001, 3022)	Analog input AI2 signal has fallen below limit defined by parameter 3022 AI2 FAULT LIMIT.	For more information, see fault in 0008 Fault messages generated by the drive on page 355.
2008	PANEL LOSS 0308 bit 7 (programmable fault function 3002)	Control panel selected as active control location for drive has ceased communicating.	For more information, see fault 0010 in Fault messages generated by the drive on page 355.
2009	DEVICE OVERTEMP 0308 bit 8	Drive IGBT temperature is excessive. Alarm limit depends on the drive type and size.	Check ambient conditions. See also section <i>Derating</i> on page 373. Check air flow and fan operation. Check motor power against drive power.

CODE	ALARM	CAUSE	WHAT TO DO
2010	MOTOR TEMP 0308 bit 9 (programmable fault function 30053009 / 3503)	Motor temperature is too high (or appears to be too high) due to excessive load, insufficient motor power, inadequate cooling or incorrect start-up data.	For more information, see fault 0009 in Fault messages generated by the drive on page 355.
		Measured motor temperature has exceeded alarm limit set by parameter 3503 ALARM LIMIT.	
2011	UNDERLOAD 0308 bit 10 (programmable fault function 30133015)	Motor load is too low due to eg release mechanism in driven equipment.	Check for problem in driven equipment. Check fault function parameters. Check motor power against drive power.
2012	MOTOR STALL 0308 bit 11 (programmable fault function 30103012)	Motor is operating in stall region due to eg excessive load or insufficient motor power.	Check motor load and drive ratings. Check fault function parameters.
2013	AUTORESET 0308 bit 12	Automatic reset alarm	Check parameter group 31 AUTOMATIC RESET settings.
2018	PID SLEEP 0309 bit 1 (programmable fault function 1610)	Sleep function has entered sleeping mode.	See parameter groups 40 PROCESS PID SET 1 41 PROCESS PID SET 2.
2019	ID RUN 0309 bit 2	Motor Identification run is on.	This alarm belongs to normal start-up procedure. Wait until drive indicates that motor identification is completed.
2021	START ENABLE 1 MISSING 0309 bit 4	No Start enable 1 signal received	Check parameter 1608 START ENABLE 1 settings. Check digital input connections. Check fieldbus communication settings.
2022	START ENABLE 2 MISSING 0309 bit 5	No Start enable 2 signal received	Check parameter 1609 START ENABLE 2 settings. Check digital input connections. Check fieldbus communication settings.
2023	EMERGENCY STOP 0309 bit 6	Drive has received emergency stop command and ramps to stop according to ramp time defined by parameter 2208 EMERG DEC TIME.	Check that it is safe to continue operation. Return emergency stop push button to normal position.

CODE	ALARM	CAUSE	WHAT TO DO
2024	ENCODER ERROR 0309 bit 7 (programmable fault function 5003)	Communication fault between pulse encoder and pulse encoder interface module or between module and drive.	Check pulse encoder and its wiring, pulse encoder interface module and its wiring and parameter group 50 ENCODER settings.
2025	FIRST START 0309 bit 8	Motor identification magnetization is on. This alarm belongs to normal start-up procedure.	Wait until drive indicates that motor identification is completed.
2026	INPUT PHASE LOSS 0309 bit 9 (programmable fault function 3016)	Intermediate circuit DC voltage is oscillating due to missing input power line phase or blown fuse. Alarm is generated when DC voltage ripple exceeds 14% of nominal DC voltage.	Check input power line fuses. Check for input power supply imbalance. Check fault function parameters.
2029	MOTOR BACK EMF 0309 bit 12	Permanent magnet synchronous motor is rotating, start mode 2 (<i>DC MAGN</i>) is selected with parameter 2101 START FUNCTION, and run is requested. Drive warns that rotating motor cannot be magnetized with DC current.	If start to rotating motor is required, select start mode 1 (AUTO) with parameter 2101 START FUNCTION. Otherwise drive starts after motor has stopped.
2035	SAFE TORQUE OFF 0309 bit 13	STO (Safe torque off) requested and it functions correctly. Parameter 3025 STO OPERATION is set to react with alarm.	If this was not expected reaction to safety circuit interruption, check cabling of safety circuit connected to STO terminals X1C. If different reaction is required, change value of parameter 3025 STO OPERATION. Note: Start signal must be reset (toggled to 0) if STO has been used while drive has been running.

¹⁾ Even when the relay output is configured to indicate alarm conditions (eg parameter 1401 RELAY OUTPUT 1 = 5 (ALARM) or 16 (FLT/ALARM)), this alarm is not indicated by a relay output.

Alarms generated by the basic control panel

The basic control panel indicates control panel alarms with a code, A5xxx.

ALARM CODE	CAUSE	WHAT TO DO
5001	Drive is not responding.	Check panel connection.
5002	Incompatible communication profile	Contact your local ABB representative.
5010	Corrupted panel parameter backup file	Retry parameter upload. Retry parameter download.
5011	Drive is controlled from another source.	Change drive control to local control mode.
5012	Direction of rotation is locked.	Enable change of direction. See parameter 1003 DIRECTION.
5013	Panel control is disabled because start inhibit is active.	Start from panel is not possible. Reset emergency stop command or remove 3-wire stop command before starting from panel.
		See section 3-wire macro on page 115 and parameters 1001 EXT1 COMMANDS, 1002 EXT2 COMMANDS and 2109 EMERG STOP SEL.
5014	Panel control is disabled because of drive fault.	Reset drive fault and retry.
5015	Panel control is disabled because local control mode lock is active.	Deactivate local control mode lock and retry. See parameter 1606 LOCAL LOCK.
5018	Parameter default value is not found.	Contact your local ABB representative.
5019	Writing non-zero parameter value is prohibited.	Only parameter reset is allowed.
5020	Parameter or parameter group does not exist or parameter value is inconsistent.	Contact your local ABB representative.
5021	Parameter or parameter group is hidden.	Contact your local ABB representative.
5022	Parameter is write protected.	Parameter value is read-only and cannot be changed.
5023	Parameter change is not allowed when drive is running.	Stop drive and change parameter value.
5024	Drive is executing a task.	Wait until task is completed.
5025	Software is being uploaded or downloaded.	Wait until upload/download is complete.
5026	Value is at or below minimum limit.	Contact your local ABB representative.
5027	Value is at or above maximum limit.	Contact your local ABB representative.
5028	Invalid value	Contact your local ABB representative.

ALARM CODE	CAUSE	WHAT TO DO
5029	Memory is not ready.	Retry.
5030	Invalid request	Contact your local ABB representative.
5031	Drive is not ready for operation, eg due to low DC voltage.	Check input power supply.
5032	Parameter error	Contact your local ABB representative.
5040	Parameter download error. Selected parameter set is not in current parameter backup file.	Perform upload function before download.
5041	Parameter backup file does not fit into memory.	Contact your local ABB representative.
5042	Parameter download error. Selected parameter set is not in current parameter backup file.	Perform upload function before download.
5043	No start inhibit	
5044	Parameter backup file restoring error	Check that file is compatible with drive.
5050	Parameter upload aborted	Retry parameter upload.
5051	File error	Contact your local ABB representative.
5052	Parameter upload has failed.	Retry parameter upload.
5060	Parameter download aborted	Retry parameter download.
5062	Parameter download has failed.	Retry parameter download.
5070	Panel backup memory write error	Contact your local ABB representative.
5071	Panel backup memory read error	Contact your local ABB representative.
5080	Operation is not allowed because drive is not in local control mode.	Switch to local control mode.
5081	Operation is not allowed because of active fault.	Check cause of fault and reset fault.
5083	Operation is not allowed because parameter lock is on.	Check parameter 1602 PARAMETER LOCK setting.
5084	Operation is not allowed because drive is performing a task.	Wait until task is completed and retry.
5085	Parameter download from source to destination drive has failed.	Check that source and destination drive types are same, ie ACS355. See type designation label of the drive.
5086	Parameter download from source to destination drive has failed.	Check that source and destination drive type designations are the same. See type designation labels of the drives.

ALARM CODE	CAUSE	WHAT TO DO
5087	Parameter download from source to destination drive has failed because parameter sets are incompatible.	Check that source and destination drive information are same. See parameters in group 33 INFORMATION.
5088	Operation has failed because of drive memory error.	Contact your local ABB representative.
5089	Download has failed because of CRC error.	Contact your local ABB representative.
5090	Download has failed because of data processing error.	Contact your local ABB representative.
5091	Operation has failed because of parameter error.	Contact your local ABB representative.
5092	Parameter download from source to destination drive has failed because parameter sets are incompatible.	Check that source and destination drive information are same. See parameters in group 33 INFORMATION.

Fault messages generated by the drive

CODE	FAULT	CAUSE	WHAT TO DO
0001	OVERCURRENT (2310) 0305 bit 0	Output current has exceeded trip level.	
		Sudden load change or stall.	Check motor load and mechanics.
		Insufficient acceleration time.	Check acceleration time (2202 and 2205). Check the possibility of using vector control.
		Incorrect motor data.	Check that motor data (Group 99) is equal to motor rating plate values. If using vector control, perform ID run (9910).
		Motor and/or drive is too small for the application.	Check sizing.
		Damaged motor cables, damaged motor or wrong motor connection (star/delta).	Check motor, motor cable and connections (including phasing).
		Internal fault of the drive. Drive gives an overcurrent fault after start command even when the motor is not connected (use scalar control in this trial).	Replace the drive.
0002	DC OVERVOLT (3210) 0305 bit 1	Excessive intermediate circuit DC voltage. DC overvoltage trip limit is 420 V for 200 V drives and 840 V for 400 V drives.	
		Supply voltage is too high or noisy. Static or transient overvoltage in the input power supply.	Check input voltage level and check power line for static or transient overvoltage
		If the drive is used in a floating network, DC overvoltage fault may appear	In a floating network, remove the EMC screw from the drive.

CODE	FAULT	CAUSE	WHAT TO DO
		If the overvoltage fault appears during deceleration, possible causes are:	
		Overvoltage controller disabled.	Check that overvoltage controller is on (parameter 2005 OVERVOLT CTRL).
		Deceleration time is too short.	Check deceleration time (2203, 2206).
		Faulty or undersized braking chopper.	Check brake chopper and resistor (if used). DC overvoltage control must be deactivated when brake chopper and resistor is used (parameter 2005 OVERVOLT CTRL). Retrofit drive with brake chopper and brake resistor.
0003	DEV OVERTEMP (4210) 0305 bit 2	Drive IGBT temperature is excessive. The fault trip limit depends on the drive type and size.	
		Ambient temperature is too high.	Check ambient conditions. See also section <i>Derating</i> on page 373.
		Airflow though the inverter is not free.	Check air flow and free space above and below the drive (see section <i>Free space around the drive</i> on page 34).
		Fan is not working properly	Check fan operation.
		Overloading of the drive.	50% overload is allowed for one minute in ten minutes. If higher switching frequency (parameter 2606) is used, follow the <i>Derating</i> rules on page 373.
0004	SHORT CIRC (2340) 0305 bit 3	Short-circuit in motor cable(s) or motor.	
		Damaged motor or motor cable.	Check motor and cable insulation. Check motor winding
		Internal fault of the drive. Drive gives an overcurrent fault after start command even when the motor is not connected (use scalar control in this trial).	Replace the drive.
0006	DC UNDERVOLT (3220) 0305 bit 5	Intermediate circuit DC voltage is not sufficient.	Check input power supply and fuses.
		Undervoltage controller disabled.	Check that undervoltage controller is on (parameter 2006 UNDERVOLT CTRL).

CODE	FAULT	CAUSE	WHAT TO DO
		Missing input power line phase.	Measure the input and DC voltage during start, stop and running by using a multimeter or check parameter 0107 DC BUS VOLTAGE.
		Blown fuse	Check the condition of input fuses.
		Rectifier bridge internal fault.	Replace the drive.
0007	Al1 LOSS (8110) 0305 bit 6 (programmable fault function 3001, 3021)	Analog input Al1 signal has fallen below limit defined by parameter 3021 Al1 FAULT LIMIT.	
		Analog input signal is weak or does not exist.	Check the source and wire connections of the analog input.
		Analog input signal is lower than fault limit.	Check parameters 3001 AI <min 3021="" ai1="" and="" fault="" function="" limit.<="" td=""></min>
0008	AI2 LOSS (8110) 0305 bit 7 (programmable fault function 3001, 3022)	Analog input Al2 signal has fallen below limit defined by parameter 3022 Al2 FAULT LIMIT.	•
		Analog input signal is weak or does not exist.	Check the source and wire connections of analog input.
		Analog input signal is lower than fault limit.	Check parameters 3001 AI <min 3021="" ai1="" and="" fault="" function="" limit.<="" td=""></min>

CODE	FAULT	CAUSE	WHAT TO DO
0009	MOT OVERTEMP (4310)	Motor temperature estimation is too high.	
	0305 bit 8 (programmable	Excessive load or insufficient motor power	Check motor ratings, load and cooling.
	fault function	Incorrect start-up data.	Check start-up data.
	30053009 / 3504)		Check fault function parameters 30053009.
			Minimize IR compensation to avoid heating (parameter 2603 IR COMP VOLT).
			Check frequency of the motor (low running frequency of motor with high input current can cause this fault).
			Let the motor cool down. The necessary cooling time period depends on the value of parameter 3006 MOT THERM TIME. Motor temperature estimation is counted down only when the drive is powered on.
		Measured motor	Check value of fault limit.
		temperature has exceeded the fault limit set by parameter 3504 FAULT LIMIT.	Check that actual number of sensors corresponds to value set by parameter 3501 SENSOR TYPE.
			Let the motor cool down. Ensure proper motor cooling: Check the cooling fan, clean cooling surfaces, etc.
0010	PANEL LOSS	as active control location for drive has ceased communicating. grammable It function	Check panel connection.
	(5300)		Check fault function parameters.
	0305 bit 9 (programmable		Check parameter 3002 PANEL COMM ERR.
	fault function 3002)		Check control panel connector. Refit control panel in mounting
			platform.
			If the drive is in external control mode (REM) and is set to accept start/stop, direction commands or references through control panel:
			Check group 10 START/STOP/DIR and 11 REFERENCE SELECT settings.
0011	ID RUN FAIL (FF84) 0305 bit 10	Motor ID run is not completed successfully.	Check motor connection.
			Check start-up data (group 99 START-UP DATA).
			Check maximum speed (parameter 2002). It should be at least 80% of motor nominal speed (parameter 9908).
			Ensure ID run has been performed according to instructions in section ID run procedure on page 71.

CODE	FAULT	CAUSE	WHAT TO DO
0012	MOTOR STALL (7121) 0305 bit 11 (programmable fault function 30103012)	Motor is operating in stall region due to eg excessive load or insufficient motor power.	Check motor load and drive ratings. Check fault function parameters 30103012.
0014	EXT FAULT 1 (9000) 0305 bit 13 (programmable fault function 3003)	External fault 1	Check external devices for faults. Check parameter 3003 EXTERNAL FAULT 1 setting.
0015	EXT FAULT 2 (9001) 0305 bit 14 (programmable fault function 3004)	External fault 2	Check external devices for faults. Check parameter 3004 EXTERNAL FAULT 2 setting.
0016	EARTH FAULT (2330) 0305 bit 15 (programmable fault function 3017)	Drive has detected earth (ground) fault in motor or motor cable.	Check motor. Check motor cable. Motor cable length must not exceed maximum specifications. See section <i>Motor connection data</i> on page <i>381</i> . Note: Disabling earth fault (ground fault) may damage drive.
		Drive internal fault.	Internal short-circuit may cause earth fault indication. This has happened if fault 0001 appears after disabling the earth fault. Replace the drive.
0017	UNDERLOAD (FF6A) 0306 bit 0 (programmable fault function 30133015)	Motor load is too low due to eg release mechanism in driven equipment.	Check for problem in driven equipment. Check fault function parameters 30103012. Check motor power against drive power.
0018	THERM FAIL (5210) 0306 bit 1	Temperature of the drive exceeds the operating level of the thermistor.	Check that the ambient temperature is not too low.
		Drive internal fault. Thermistor used for drive internal temperature measurement is open or short-circuited	Replace the drive.
0021	CURR MEAS (2211) 0306 bit 4	Drive internal fault. Current measurement is out of range.	Replace the drive.

CODE	FAULT	CAUSE	WHAT TO DO
0022	SUPPLY PHASE (3130) 0306 bit 5 (programmable fault function 3016)	Intermediate circuit DC voltage is oscillating due to missing input power line phase or blown fuse.	Check input power line fuses and installation. Check for input power supply imbalance. Check the load.
		Trip occurs when DC voltage ripple exceeds 14% of nominal DC voltage.	Check fault function parameter 2619 DC STABILIZER.
0023	ENCODER ERR (7301) 0306 bit 6 (programmable fault function 5003)	Communication fault between pulse encoder and pulse encoder interface module or between module and drive.	Check pulse encoder and its wiring, pulse encoder interface module and its wiring and parameter group 50 ENCODER settings.
0024	OVERSPEED (7310) 0306 bit 7	Motor is turning faster than 120% of the highest allowed speed due to incorrectly set minimum/maximum speed, insufficient braking torque or changes in load when using torque reference. Operating range limits are set by parameters 2001 MINIMUM SPEED and 2002 MAXIMUM SPEED (in vector control) or 2007 MINIMUM FREQ and 2008 MAXIMUM FREQ (in scalar control).	Check minimum/maximum frequency settings (parameters 2001 MINIMUM SPEED and 2002 MAXIMUM SPEED). Check adequacy of motor braking torque. Check applicability of torque control. Check need for brake chopper and resistor(s).
0027	CONFIG FILE (630F) 0306 bit 10	Internal configuration file error	Replace the drive.
0028	SERIAL 1 ERR (7510) 0306 bit 11 (programmable fault function 3018, 3019)	Fieldbus communication break	Check status of fieldbus communication. See chapter Fieldbus control with embedded fieldbus on page 311, chapter Fieldbus control with fieldbus adapter on page 337 or appropriate fieldbus adapter manual. Check fault function parameter 3018 COMM FAULT FUNC and 3019 COMM FAULT TIME settings. Check connections and/or noise on the line. Check if master can communicate.
0029	EFB CON FILE (6306) 0306 bit 12	Configuration file reading error	Error in reading the configuration files of the embedded fieldbus. See fieldbus user's manual.

CODE	FAULT	CAUSE	WHAT TO DO
0030	FORCE TRIP (FF90) 0306 bit 13	Trip command received from fieldbus	Fault trip was caused by fieldbus. See fieldbus user's manual.
0034	MOTOR PHASE (FF56) 0306 bit 14	Motor circuit fault due to missing motor phase or motor thermistor relay (used in motor temperature measurement) fault.	Check motor and motor cable. Check motor thermistor relay (if used).
0035	OUTP WIRING (FF95) 0306 bit 15 (programmable fault function 3023)	Incorrect input power and motor cable connection (ie input power cable is connected to drive motor connection).	Possible power wiring error detected. Check that input power connections are not connected to drive output. Fault can be declared if input power is delta grounded system and motor cable capacitance is large. This fault can be disabled by parameter 3023 WIRING FAULT.
0036	INCOMPATIBLE SW (630F) 0307 bit 3	Loaded software is not compatible.	Loaded software is not compatible with the drive. Contact your local ABB representative.
0037	CB OVERTEMP (4110) 0305 bit 12	Drive control board overheated. Fault trip limit is 95 °C.	Check for excessive ambient temperature. Check for fan failure. Check for obstructions in air flow. Check the dimensioning and cooling of cabinet.
0044	SAFE TORQUE OFF (FFA0) 0307 bit 4	STO (Safe torque off) requested and it functions correctly. Parameter 3025 STO OPERATION is set to react with fault.	If this was not expected reaction to safety circuit interruption, check cabling of safety circuit connected to STO terminals X1C. If different reaction is required, change value of parameter 3025 STO OPERATION. Reset fault before starting.
0045	STO1 LOST (FFA1) 0307 bit 5	STO (Safe torque off) input channel 1 has not de-energized, but channel 2 has. Opening contacts on channel 1 might have been damaged or there is a short-circuit.	Check STO circuit cabling and opening of contacts in STO circuit.
0046	STO2 LOST (FFA2) 0307 bit 6	STO (Safe torque off) input channel 2 has not de-energized, but channel 1 has. Opening contacts on channel 2 might have been damaged or there is a short-circuit.	Check STO circuit cabling and opening of contacts in STO circuit.

CODE	FAULT	CAUSE	WHAT TO DO
0101	SERF CORRUPT (FF55) 0307 bit 14	Drive internal error.	Replace the drive.
0103	SERF MACRO (FF55) 0307 bit 14		
0201	DSP T1 OVERLOAD (6100) 0307 bit 13	Drive internal error.	If fieldbus is in use, check the communication, settings and contacts. Write down fault code and contact your local ABB representative.
0202	DSP T2 OVERLOAD (6100) 0307 bit 13		
0203	DSP T3 OVERLOAD (6100) 0307 bit 13		
0204	DSP STACK ERROR (6100) 0307 bit 12		
0206	CB ID ERROR (5000) 0307 bit 11	Drive internal error.	Replace the drive.
1000	PAR HZRPM (6320) 0307 bit 15	Incorrect speed/frequency limit parameter setting	Check parameter settings. Check that following applies: • 2001 MINIMUM SPEED < 2002 MAXIMUM SPEED • 2007 MINIMUM FREQ < 2008 MAXIMUM FREQ • 2001 MINIMUM SPEED / 9908 MOTOR NOM SPEED , 2002 MAXIMUM SPEED / 9908 MOTOR NOM SPEED , 2007 MINIMUM FREQ / 9907 MOTOR NOM FREQ and 2008 MAXIMUM FREQ / 9907 MOTOR NOM FREQ are within range.
1003	PAR AI SCALE (6320) 0307 bit 15	Incorrect analog input Al signal scaling	Check parameter group 13 ANALOG INPUTS settings. Check that following applies: • 1301 MINIMUM AI1 < 1302 MAXIMUM AI1 • 1304 MINIMUM AI2 < 1305 MAXIMUM AI2.

CODE	FAULT	CAUSE	WHAT TO DO
1004	PAR AO SCALE (6320) 0307 bit 15	Incorrect analog output AO signal scaling	Check parameter group 15 ANALOG OUTPUTS settings. Check that following applies: • 1504 MINIMUM AO1 < 1505 MAXIMUM AO1.
1005	PAR PCU 2 (6320) 0307 bit 15	Incorrect motor nominal power setting	Check parameter 9909 MOTOR NOM POWER setting. Following must apply: • 1.1 < (9906 MOTOR NOM CURR 9905 MOTOR NOM VOLT · 1.73 / $P_{\rm N}$) < 3.0 Where $P_{\rm N}$ = 1000 · 9909 MOTOR NOM POWER (if units are in kW) or $P_{\rm N}$ = 746 · 9909 MOTOR NOM POWER (if units are in hp).
1006	PAR EXT RO (6320) 0307 bit 15 (programmable fault function 3027)	Incorrect relay output extension parameters	Check parameter settings. Check that following applies: • Output relay module MREL-01 is connected to drive. See parameter 0181 EXT MODULE STATUS. • 1402 RELAY OUTPUT 2, 1403 RELAY OUTPUT 3 and 1410 RELAY OUTPUT 4 have non-zero values. See MREL-01 output relay module user's manual (3AUA0000035974 [English]).
1007	PAR FBUSMISS (6320) 0307 bit 15	Fieldbus control has not been activated.	Check fieldbus parameter settings. See chapter <i>Fieldbus control with fieldbus adapter</i> on page 337.
1009	PAR PCU 1 (6320) 0307 bit 15	Incorrect motor nominal speed/frequency setting	Check parameter settings. Following must apply for induction motor: • 1 < (60 · 9907 MOTOR NOM FREQ / 9908 MOTOR NOM SPEED) < 16 • 0.8 < 9908 MOTOR NOM SPEED / (120 · 9907 MOTOR NOM FREQ / Motor poles) < 0.992 Following must apply for permanent magnet synchronous motor: • 9908 MOTOR NOM SPEED / (120 · 9907 MOTOR NOM FREQ / Motor poles) = 1.0
1015	PAR USER U/F (6320) 0307 bit 15	Incorrect voltage to frequency (U/f) ratio voltage setting.	Check parameter 2610 USER DEFINED U1 2617 USER DEFINED F4 settings.

CODE	FAULT	CAUSE	WHAT TO DO	
1017	PAR SETUP 1 (6320) 0307 bit 15	Only two of the following can be used simultaneously: MTAC-01 pulse encoder interface module, frequency input signal or frequency output signal.	Disable frequency output, frequency input or encoder: • change transistor output to digital mode (value of parameter 1804 TO MODE = 0 [DIGITAL]), or • change frequency input selection to other value in parameter groups	
				11 REFERENCE SELECT, 40 PROCESS PID SET 1, 41 PROCESS PID SET 2 and 42 EXT / TRIM PID, or
			disable (parameter 5002 ENCODER ENABLE) and remove MTAC-01 pulse encoder interface module.	

Embedded fieldbus faults

Embedded fieldbus faults can be traced by monitoring group 53 EFB PROTOCOL parameters. See also fault/alarm SERIAL 1 ERR (0028).

No master device

If there is no master device on line, parameter 5306 EFB OK MESSAGES and 5307 EFB CRC ERRORS values remain unchanged.

What to do:

- Check that the network master is connected and properly configured.
- Check the cable connection.

Same device address

If two or more devices have the same address, parameter 5307 EFB CRC ERRORS value increases with every read/write command.

What to do:

Check the device addresses. No two devices on line may have the same address.

Incorrect wiring

If the communication wires are swapped (terminal A on one device is connected to terminal B on another device), parameter 5306 EFB OK MESSAGESS value remains unchanged and parameter 5307 EFB CRC ERRORS increases.

What to do:

Check the RS-232/EIA-485 interface connection.

Maintenance and hardware diagnostics

What this chapter contains

The chapter contains preventive maintenance instructions and LED indicator descriptions.

Maintenance intervals

If installed in an appropriate environment, the drive requires very little maintenance. The table lists the routine maintenance intervals recommended by ABB.

Maintenance	Interval	Instruction
Reforming of capacitors	Every year when stored	See Capacitors on page 369.
Check of dustiness, corrosion and temperature	Every year	
Replacement of the cooling fan (frame sizes R1R4)	Every three years	See Cooling fan on page 368.
Check and tightening of the power terminals	Every six years	See <i>Power connections</i> on page 369.
Replacement of the battery in the assistant control panel	Every ten years	See Changing the battery in the assistant control panel on page 370.
Testing of Safe torque off (STO) operation and reaction	Every year	See Appendix: Safe torque off (STO) on page 411.

Consult your local ABB Service representative for more details on the maintenance. On the Internet, go to http://www.abb.com/drives and select *Drive Services* – Maintenance and Field Services.

Cooling fan

The life span of the cooling fan depends on the drive usage and ambient temperature. Automatic fan on/off control increases the life span (see parameter 1612 FAN CONTROL).

When the assistant control panel is in use, the Notice handler assistant informs when the definable value of the operating hour counter is reached (see parameter 2901 COOLING FAN TRIG). This information can also be passed to the relay output (see group 14 RELAY OUTPUTS) regardless of the used panel type.

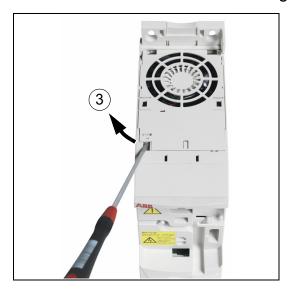
Fan failure can be predicted by the increasing noise from the fan bearings. If the drive is operated in a critical part of a process, fan replacement is recommended once these symptoms start appearing. Replacement fans are available from ABB. Do not use other than ABB specified spare parts.

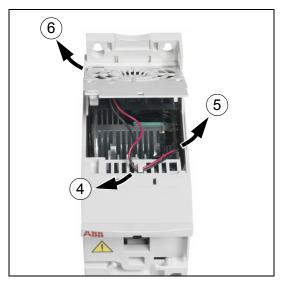
Replacing the cooling fan (frame sizes R1...R4)

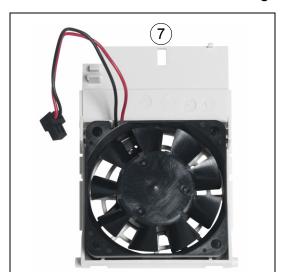
Only frame sizes R1...R4 include a fan; frame size R0 has natural cooling.

WARNING! Read and follow the instructions in chapter *Safety* on page 17. Ignoring the instructions can cause physical injury or death, or damage to the equipment.

- 1. Stop the drive and disconnect it from the AC power source.
- 2. Remove the hood if the drive has the NEMA 1 option.
- 3. Lever the fan holder off the drive frame with eg a screwdriver and lift the hinged fan holder slightly upward from its front edge.
- 4. Free the fan cable from the clip.
- Disconnect the fan cable.
- 6. Remove the fan holder from the hinges.







7. Install the new fan holder including the fan in reverse order.

8. Restore power.

Capacitors

Reforming the capacitors

The capacitors must be reformed if the drive has been stored for a year. See section Type designation label on page 30 for how to find out the manufacturing time from the serial number. For information on reforming the capacitors, refer to Guide for capacitor reforming in ACS50, ACS55, ACS150, ACS310, ACS350, ACS355, ACS550 and ACH550 (3AFE68735190 [English]), available on the Internet (go to http://www.abb.com and enter the code in the Search field).

Power connections

WARNING! Read and follow the instructions in chapter *Safety* on page 17. Ignoring the instructions can cause physical injury or death, or damage to the equipment.

- 1. Stop the drive and disconnect it from the power line. Wait for five minutes to let the drive DC capacitors discharge. Ensure by measuring with a multimeter (impedance at least 1 Mohm) that there is no voltage present.
- 2. Check the tightness of the power cable connections. Use the tightening torques given in section Terminal and lead-through data for the power cables on page 380.
- 3. Restore power.

Control panel

Cleaning the control panel

Use a soft damp cloth to clean the control panel. Avoid harsh cleaners which could scratch the display window.

Changing the battery in the assistant control panel

A battery is only used in assistant control panels that have the clock function available and enabled. The battery keeps the clock operating in memory during power interruptions.

The expected life for the battery is greater than ten years. To remove the battery, use a coin to rotate the battery holder on the back of the control panel. Replace the battery with type CR2032.

Note: The battery is NOT required for any control panel or drive functions, except the clock.

LEDs

There is a green and a red LED on the front of the drive. They are visible through the panel cover but invisible if a control panel is attached to the drive. The assistant control panel has one LED. The table below describes the LED indications.

Where	LED off	LED lit	and steady	LED blinking			
On the front of the drive.	No power	Green	Power supply on the board OK	Green	Drive in an alarm state		
If a control panel is attached to the drive, switch to remote control (otherwise a fault will be generated), and then remove the panel to be able to see the LEDs.		Red	Drive in a fault state. To reset the fault, press RESET from the control panel or switch off the drive power.	Red	Drive in a fault state. To reset the fault, switch off the drive power.		
At the top left corner of the	Panel has no power or no	Green	Drive in a normal state	Green	Drive in an alarm state		
assistant control panel	drive connection.	Red	Drive in a fault state. To reset the fault, press RESET from the control panel or switch off the drive power.	Red	-		

Technical data

What this chapter contains

The chapter contains the technical specifications of the drive, eg ratings, sizes and technical requirements as well as provisions for fulfilling the requirements for CE and other marks.

Ratings

Type	Inp	out ³⁾	Inpu cho	it with oke ³⁾	Output					Frame size
ACS355-	I _{1N}	/ _{1N} (480 V) 4)	I _{1N}	/ _{1N} (480 V) 4)	I _{2N}	I _{2,1} min/10 min 2)	I _{2max}	P	'n	
$x = E/U^{1}$	Α	А	Α	А	Α	Α	Α	kW	hp	
1-phase U _N :	= 200	. 240 V (2	00, 208	3, 220, 23	0, 240	V)				
01x-02A4-2	6.1	-	4.5	-	2.4	3.6	4.2	0.37	0.5	R0
01x-04A7-2	11	-	8.1	-	4.7	7.1	8.2	0.75	1	R1
01x-06A7-2	16	-	11	-	6.7	10.1	11.7	1.1	1.5	R1
01x-07A5-2	17	-	12	-	7.5	11.3	13.1	1.5	2	R2
01x-09A8-2	21	-	15	-	9.8	14.7	17.2	2.2	3	R2
3-phase U _N :	= 200	. 240 V (2	00, 208	3, 220, 23	0, 240	V)				
03x-02A4-2	4.3	-	2.2	-	2.4	3.6	4.2	0.37	0.5	R0
03x-03A5-2	6.1	-	3.5	-	3.5	5.3	6.1	0.55	0.75	R0
03x-04A7-2	7.6	-	4.2	-	4.7	7.1	8.2	0.75	1	R1
03x-06A7-2	12	-	6.1	-	6.7	10.1	11.7	1.1	1.5	R1
03x-07A5-2	12	-	6.9	-	7.5	11.3	13.1	1.5	2	R1
03x-09A8-2	14	-	9.2	-	9.8	14.7	17.2	2.2	3	R2
03x-13A3-2	22	-	13	-	13.3	20.0	23.3	3	3	R2
03x-17A6-2	25	-	14	-	17.6	26.4	30.8	4	5	R2
03x-24A4- 2	41	-	21	-	24.4	36.6	42.7	5.5	7.5	R3
03x-31A0-2	50	-	26	-	31	46.5	54.3	7.5	10	R4
03x-46A2-2	69	-	41	-	46.2	69.3	80.9	11.0	15	R4
3-phase U _N :	= 380	. 480 V (3	80, 400	, 415, 44	0, 460,	480 V)		•		•
03x-01A2-4	2.2	1.8	1.1	0.9	1.2	1.8	2.1	0.37	0.5	R0
03x-01A9-4	3.6	3.0	1.8	1.5	1.9	2.9	3.3	0.55	0.75	R0
03x-02A4-4	4.1	3.4	2.3	1.9	2.4	3.6	4.2	0.75	1	R1
03x-03A3-4	6.0	5.0	3.1	2.6	3.3	5.0	5.8	1.1	1.5	R1
03x-04A1-4	6.9	5.8	3.5	2.9	4.1	6.2	7.2	1.5	2	R1
03x-05A6-4	9.6	8.0	4.8	4.0	5.6	8.4	9.8	2.2	3	R1
03x-07A3-4	12	9.7	6.1	5.1	7.3	11.0	12.8	3	3	R1
03x-08A8-4	14	11	7.7	6.4	8.8	13.2	15.4	4	5	R1
03x-12A5-4	19	16	11	9.5	12.5	18.8	21.9	5.5	7.5	R3
03x-15A6-4	22	18	12	10	15.6	23.4	27.3	7.5	10	R3
03x-23A1-4	31	26	18	15	23.1	34.7	40.4	11	15	R3
03x-31A0-4	52	43	25	20	31	46.5	54.3	15	20	R4
03x-38A0-4	61	51	32	26	38	57	66.5	18.5	25	R4
03x-44A0-4	67	56	38	32	44	66	77.0	22.0	30	R4

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- E = EMC filter connected (metal EMC filter screw installed), U = EMC filter disconnected (plastic EMC filter screw installed), US parametrization.
- 2) Overloading not allowed through Common DC connection.
- Input current is based on the rated motor nominal power (P_N) , supply network, line inductance and load motor.
 - Input values with choke can be met with ABB CHK-xx or typical 5% chokes.
- 480 V values are based on the fact that the motor load current is lower with the same output power.

Definitions

Input

continuous rms input current (for dimensioning cables and fuses) I_{1N}

I_{1N} (480 V) continuous rms input current (for dimensioning cables and fuses) for drives

with 480 V input voltage

Output

 $I_{2\text{max}}$

continuous rms current. 50% overload is allowed for one minute every ten I_{2N}

minutes.

maximum (50% overload) current allowed for one minute every ten minutes *I*_{2.1 min/10 min}

maximum output current. Available for two seconds at start, otherwise as long

as allowed by the drive temperature.

typical motor power. The kilowatt ratings apply to most IEC 4-pole motors. The P_{N}

> horsepower ratings apply to most NEMA 4-pole motors. This is also the maximum load through the Common DC connection and must not be

exceeded.

R0...R4 ACS355 is manufactured in frame sizes R0...R4. Some instructions and other

information that only concern certain frame sizes are marked with the symbol

of the frame size (R0...R4).

Sizing

Drive sizing is based on the rated motor current and power. To achieve the rated motor power given in the table, the rated current of the drive must be higher than or equal to the rated motor current. Also the rated power of the drive must be higher than or equal to compared to the rated motor power. The power ratings are the same regardless of the supply voltage within one voltage range.

Note 1: The maximum allowed motor shaft power is limited to $1.5 \cdot P_N$. If the limit is exceeded, motor torque and current are automatically restricted. The function protects the input bridge of the drive against overload.

Note 2: The ratings apply at ambient temperature of 40 °C (104 °F) for I_{2N} .

Note 3: It is important to check that in Common DC systems the power flowing through the common DC connection does not exceed P_N .

Derating

 I_{2N} : The load capacity decreases if the installation site ambient temperature exceeds 40 °C (104 °F), the altitude exceeds 1000 meters (3300 ft) or the switching frequency is changed from 4 kHz to 8, 12 or 16 kHz.

Temperature derating, I_{2N}

In the temperature range +40 °C...+50 °C (+104 °F...+122 °F), the rated output current (I_{2N}) is decreased by 1% for every additional 1 °C (1.8 °F). The output current is calculated by multiplying the current given in the rating table by the derating factor.

Example: If the ambient temperature is 50 °C (+122 °F), the derating factor is $100\% - 1 \frac{\%}{^{\circ}C} \cdot 10$ °C = 90% or 0.90. The output current is then 0.90 · I_{2N} .

Altitude derating, I_{2N}

In altitudes 1000...2000 m (3300...6600 ft) above sea level, the derating is 1% for every 100 m (330 ft).

For 3-phase 200 V drives, the maximum altitude is 3000 m (9800 ft) above sea level. In altitudes 2000...3000 m (6600...9800 ft), the derating is 2% for every 100 m (330 ft).

Switching frequency derating, I_{2N}

The drive derates itself automatically when parameter 2607 SWITCH FREQ CTRL = 1 (ON).

Switching		Drive voltage rating								
frequency	<i>U</i> _N = 200240 V	<i>U</i> _N = 380480 V								
4 kHz	No derating	No derating								
8 kHz	I _{2N} derated to 90%.	I_{2N} derated to 75% for R0 or to 80% for R1R4.								
12 kHz	I _{2N} derated to 80%.	<i>I</i> _{2N} derated to 50% for R0 or to 65% for R1R4 and maximum ambient temperature derated to 30 °C (86 °F).								
16 kHz	I _{2N} derated to 75%.	I _{2N} derated to 50% and maximum ambient temperature derated to 30 °C (86 °F).								

When parameter 2607 SWITCH FREQ CTRL = 2 (ON (LOAD)), the drive controls the switching frequency towards the selected switching frequency 2606 SWITCHING FREQ if the drive's internal temperature allows.

Power cable sizes and fuses

Cable dimensioning for rated currents (I_{1N}) is shown in the table below together with the corresponding fuse types for short-circuit protection of the input power cable. The rated fuse currents given in the table are the maximums for the mentioned fuse types. If smaller fuse ratings are used, check that the fuse rms current rating is larger than the rated I_{1N} current given in section Ratings on page 372. If 150% output power is needed, multiply current I_{1N} by 1.5. See also section Selecting the power cables on page **41**.

Check that the operating time of the fuse is below 0.5 seconds. The operating time depends on the fuse type, the supply network impedance as well as the crosssectional area, material and length of the supply cable. In case the 0.5 seconds operating time is exceeded with the gG or T fuses, ultra rapid (aR) fuses will in most cases reduce the operating time to an acceptable level.

Note 1: Larger fuses must not be used when the input power cable is selected according to this table.

Note 2: Choose the correct fuse size according to the actual input current which depends on the input line voltage and the input choke selection.

Note 3 : Other fuse types can be used if they meet the ratings and the melting curve
of the fuse does not exceed the melting curve of the fuse mentioned in this table.

Туре	Fu	Size of copper conductor in cablings									
ACS355-	gG	UL Class T or CC (600 V)	Sup (U1, V	oply 1, W1)	Motor) (U2, V2, W2)		PE		Brake (BRK+, BRK-		
x = E/U	А	А	mm ²	AWG	mm ²	AWG	mm ²	AWG	mm ²	AWG	
1-phase U _N =	200240	V (200, 208	3, 220,	230, 24	0 V)						
01x-02A4-2	10	10	2.5	14	0.75	18	2.5	14	2.5	14	
01x-04A7-2	16	20	2.5	14	0.75	18	2.5	14	2.5	14	
01x-06A7-2	16/20 ¹⁾	25	2.5	10	1.5	14	2.5	10	2.5	12	
01x-07A5-2	20/25 ¹⁾	30	2.5	10	1.5	14	2.5	10	2.5	12	
01x-09A8-2	25/35 ¹⁾	35	6	10	2.5	12	6	10	6	12	
3-phase U _N =	200240	V (200, 208	3, 220,	230, 24	0 V)						
03x-02A4-2	10	10	2.5	14	0.75	18	2.5	14	2.5	14	
03x-03A5-2	10	10	2.5	14	0.75	18	2.5	14	2.5	14	
03x-04A7-2	10	15	2.5	14	0.75	18	2.5	14	2.5	14	
03x-06A7-2	16	15	2.5	12	1.5	14	2.5	12	2.5	12	
03x-07A5-2	16	15	2.5	12	1.5	14	2.5	12	2.5	12	
03x-09A8-2	16	20	2.5	12	2.5	12	2.5	12	2.5	12	
03x-13A3-2	25	30	6	10	6	10	6	10	2.5	12	
03x-17A6-2	25	35	6	10	6	10	6	10	2.5	12	
03x-24A4-2	63	60	10	8	10	8	10	8	6	10	
03x-31A0-2	80	80	16	6	16	6	16	6	10	8	
03x-46A2-2	100	100	25	2	25	2	16	4	10	8	

Type	Fuses Size of copper conductor in ca						r in cal	blings		
ACS355-	gG	UL Class T or CC (600 V)		Supply Motor PE I1, V1, W1) (U2, V2, W2)		Έ	Brake (BRK+, BRK-)			
x = E/U	Α	Α	mm ²	AWG	mm ²	AWG	mm ²	AWG	mm^2	AWG
3-phase U _N =	380480	V (380, 400), 415,	440, 46	0, 480	V)				
03x-01A2-4	10	10	2.5	14	0.75	18	2.5	14	2.5	14
03x-01A9-4	10	10	2.5	14	0.75	18	2.5	14	2.5	14
03x-02A4-4	10	10	2.5	14	0.75	18	2.5	14	2.5	14
03x-03A3-4	10	10	2.5	12	0.75	18	2.5	12	2.5	12
03x-04A1-4	16	15	2.5	12	0.75	18	2.5	12	2.5	12
03x-05A6-4	16	15	2.5	12	1.5	14	2.5	12	2.5	12
03x-07A3-4	16	20	2.5	12	1.5	14	2.5	12	2.5	12
03x-08A8-4	20	25	2.5	12	2.5	12	2.5	12	2.5	12
03x-12A5-4	25	30	6	10	6	10	6	10	2.5	12
03x-15A6-4	35	35	6	8	6	8	6	8	2.5	12
03x-23A1-4	50	50	10	8	10	8	10	8	6	10
03x-31A0-4	80	80	16	6	16	6	16	6	10	8
03x-38A0-4	100	100	16	4	16	4	16	4	10	8
03x-44A0-4	100	100	25	4	25	4	16	4	10	8
1) If 50% overload	ad capacity is	s needed, use	e the lar	ger fuse	alternati	ve.			00353	783.xls L

Dimensions, weights and free space requirements

Dimensions and weights

Frame size	Dimensions and weights													
Size		IP20 (cabinet) / UL open												
	Н	l 1	Н	12	Н	13	\	N)	We	ight		
	mm	in	mm	in	mm	in	mm	in	mm	in	kg	lb		
R0	169	6.65	202	7.95	239	9.41	70	2.76	161	6.34	1.2	2.6		
R1	169	6.65	202	7.95	239	9.41	70	2.76	161	6.34	1.4	3.0		
R2	169	6.65	202	7.95	239	9.41	105	4.13	165	6.50	1.8	3.9		
R3	169	6.65	202	7.95	236	9.29	169	6.65	169	6.65	3.1	6.9		
R4	181	7.13	202	7.95	244	9.61	260	10.24	169	6.65	5.2	11.5		

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Frame size										
	ŀ	14	ŀ	15	1	N)	We	ight
	mm	in	mm	in	mm	in	mm	in	kg	lb
R0	257	10.12	280	11.02	70	2.76	169	6.65	1.6	3.5
R1	257	10.12	280	11.02	70	2.76	169	6.65	1.8	3.9
R2	257	10.12	282	11.10	105	4.13	169	6.65	2.2	4.8
R3	260	10.24	299	11.77	169	6.65	177	6.97	3.7	8.2
R4	270	10.63	320	12.60	260	10.24	177	6.97	5.8	12.9

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Symbols

IP20 (cabinet) / UL open

height without fastenings and clamping plate H1

height with fastenings, without clamping plate **H2**

H3 height with fastenings and clamping plate

IP20 / NEMA 1

height with fastenings and connection box **H4**

height with fastenings, connection box and hood **H5**

Weight is calculated as the measured drive weight + cable clamps + 50 g (for component tolerances).

Free space requirements

Frame size	Free space required							
	Above		Ве	low	On the sides			
	mm	in	mm	in	mm	in		
R0R4	75	3	75	3	0	0		

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Losses, cooling data and noise

Losses and cooling data

Frame size R0 has natural convection cooling. Frame sizes R1...R4 are provided with an internal fan. The air flow direction is from bottom to top.

The table below specifies the heat dissipation in the main circuit at nominal load and in the control circuit with minimum load (I/O and panel not in use) and maximum load (all digital inputs in the on state and the panel, fieldbus and fan in use). The total heat dissipation is the sum of the heat dissipation in the main and control circuits.

Туре	Hea	t dissipation	Air	flow		
ACS355-	Main circuit	t Control circuit				
x = E/U	Rated / _{1N} and / _{2N}	Min	Max			
	W	W	W	m ³ /h	ft ³ /min	
1-phase <i>U</i> _N = 2	00240 V (200, 208	3, 220, 230, 24	0 V)			
01x-02A4-2	25	6.1	22.7	-	-	
01x-04A7-2	46	9.5	26.4	24	14	
01x-06A7-2	71	9.5	26.4	24	14	
01x-07A5-2	73	10.5	27.5	21	12	
01x-09A8-2	96	10.5	27.5	21	12	
3-phase $U_N = 2$	00240 V (200, 208	3, 220, 230, 24	0 V)			
03x-02A4-2	19	6.1	22.7	-	-	
03x-03A5-2	31	6.1	22.7	-	-	
03x-04A7-2	38	9.5	26.4	24	14	
03x-06A7-2	60	9.5	26.4	24	14	
03x-07A5-2	62	9.5	26.4	21	12	
03x-09A8-2	83	10.5	27.5	21	12	
03x-13A3-2	112	10.5	27.5	52	31	
03x-17A6-2	152	10.5	27.5	52	31	
03x-24A4- 2	250	16.6	35.4	71	42	
03x-31A0-2	270	33.4	57.8	96	57	
03x-46A2-2	430	33.4	57.8	96	57	

Туре	Hea	t dissipation		Air flow		
ACS355-	Main circuit	Contro	ol circuit	1		
x = E/U	Rated / _{1N} and / _{2N}	Min	Max			
	W	W	W	m ³ /h	ft ³ /min	
3-phase $U_{\rm N}$ = 3	80480 V (380, 400), 415, 440, 46	0, 480 V)			
03x-01A2-4	11	6.6	24.4	-	-	
03x-01A9-4	16	6.6	24.4	-	-	
03x-02A4-4	21	9.8	28.7	13	8	
03x-03A3-4	31	9.8	28.7	13	8	
03x-04A1-4	40	9.8	28.7	13	8	
03x-05A6-4	61	9.8	28.7	19	11	
03x-07A3-4	74	14.1	32.7	24	14	
03x-08A8-4	94	14.1	32.7	24	14	
03x-12A5-4	130	12.0	31.2	52	31	
03x-15A6-4	173	12.0	31.2	52	31	
03x-23A1-4	266	16.6	35.4	71	42	
03x-31A0-4	350	33.4	57.8	96	57	
03x-38A0-4	440	33.4	57.8	96	57	
03x-44A0-4	530	33.4	57.8	96	57	

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Noise

Frame	Noise level			
size	dBA			
R0	<30			
R1	5062			
R2	5062			
R3	5062			
R4	<62			

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Terminal and lead-through data for the power cables

Frame size		Max. meter f	cable or NEM	IA 1	U1, V1, BRK	W1, U2 (+ and		V2,	PE			
		1, W1, 2, W2		+ and RK-	Terminal size		Tightening torque		Clamp size			ening que
	mm	in	mm	in	mm ²	AWG	N·m	lbf∙in	mm ²	AWG	N·m	lbf∙in
R0	16	0.63	16	0.63	4.0/6.0	10	8.0	7	25	3	1.2	11
R1	16	0.63	16	0.63	4.0/6.0	10	8.0	7	25	3	1.2	11
R2	16	0.63	16	0.63	4.0/6.0	10	8.0	7	25	3	1.2	11
R3	29	1.14	16	0.63	10.0/16.0	6	1.7	15	25	3	1.2	11
R4	35	1.38	29	1.14	25.0/35.0	2	2.5	22	25	3	1.2	11

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Terminal and lead-through data for the control cables

Condu	ctor size	Tightening torque		
Min/Max	Min/Max			
mm ²	AWG	N·m	lbf-in	
0.25/1.5	24/16	0.5	4.4	

Electric power network specification

Voltage (U_1) 200/208/220/230/240 V AC 1-phase for 200 V AC drives

200/208/220/230/240 V AC 3-phase for 200 V AC drives

380/400/415/440/460/480 V AC 3-phase for 400 V AC drives

±10% variation from converter nominal voltage is allowed as default.

Short-circuit capacity Maximum allowed prospective short-circuit current at the input power

connection as defined in IEC 60439-1 and UL 508C is 100 kA. The drive is suitable for use in a circuit capable of delivering not more than 100 kA rms symmetrical amperes at the drive maximum rated

voltage.

Frequency 50/60 Hz ± 5%, maximum rate of change 17%/s **Imbalance** Max. ±3% of nominal phase-to-phase input voltage

Motor connection data

Motor type Asynchronous induction motor or permanent

magnet synchronous motor

Voltage (U_2) 0 to U_1 , 3-phase symmetrical, U_{max} at the field weakening point

Short-circuit protection The motor output is short-circuit proof by IEC 61800-5-1 and

(IEC 61800-5-1,

UL 508C.

UL 508C)

0...600 Hz Frequency Frequency resolution 0.01 Hz

Current See section *Ratings* on page 372.

Power limit $1.5 \cdot P_{N}$ Field weakening point 10...600 Hz

Switching frequency 4, 8, 12 or 16 kHz (in scalar control)

Speed control See section Speed control performance figures on page 148. **Torque control** See section Torque control performance figures on page 148.

Operational functionality and motor cable length

The drive is designed to operate with optimum performance with the following maximum motor cable lengths. The motor cable lengths may be extended with output chokes as shown in the table.

Frame	Maximum motor cable length						
size	m	ft					
Standard drive, without external options							
R0	30	100					
R1R4	50	165					
With external output chokes							
R0	60	195					
R1R4	100	330					

Note: In multimotor systems, the calculated sum of all motor cable lengths must not exceed the maximum motor cable length given in the table.

EMC compatibility and motor cable length

To comply with the European EMC Directive (standard IEC/EN 61800-3), use the following maximum motor cable lengths for 4 kHz switching frequency.

All frame	Maximum motor cable length, 4 kHz						
sizes	m	ft					
With internal EMC filt	er						
Second environment (category C3 ¹⁾)	30	100					
With optional externa	With optional external EMC filter						
Second environment (category C3 ¹⁾)	30 (at least) ²⁾	100 (at least) ²⁾					
First environment (category C2 ¹⁾)	30 (at least) ²⁾	100 (at least) ²⁾					
First environment (category C1 ¹⁾)	10 (at least) ²⁾	30 (at least) ²⁾					

¹⁾ See the terms in section *Definitions* on page 387.

Note 1: The internal EMC filter must be disconnected by removing the EMC screw (see the figure on page *50*) while using the low leakage current EMC filter (LRFI-XX).

Note 2: Radiated emissions are according to C2 with and without an external EMC filter.

Note 3: Category C1 with conducted emissions only. Radiated emissions are not compatible when measured with standard emission measurement setup and should be checked or measured on cabinet and machine installations case by case.

²⁾ Maximum motor cable length is determined by the drive's operational factors. Contact your local ABB representative for the

Control connection data

Analog inputs X1A: 2 and 5 (Al1 and Al2)	Current signal,	unipolar pipolar unipolar pipolar erence	0 (2)10 V, R_{in} = 675 kohm -1010 V, R_{in} = 675 kohm 0 (4)20 mA, R_{in} = 100 ohm -2020 mA, R_{in} = 100 ohm 10 V ± 1%, max. 10 mA, R < 10 kohm 0.1% ±2%	
Analog output X1A: 7 (AO)			0 (4)20 mA, load < 500 ohm	
Auxiliary voltage X1A: 9			24 V DC ± 10%, max. 200 mA	
Digital inputs X1A: 1216 (DI1DI5)	Voltage Type Input impedance, X1A: 1215 X1A: 16		1224 V DC with internal or external supply. Max. voltage for digital inputs 30 V DC. PNP and NPN R _{in} = 2 kohm R _{in} = 4 kohm	
Frequency input X1A: 16 (DI5)	X1A: 16 can be use Frequency	ed either a	s a digital or as a frequency input. Pulse train 010 kHz with 50% duty cycle. 016 kHz between two ACS355 drives.	
Relay output X1B: 1719 (RO 1)	Type Max. switching vol Max. switching cur Max. continuous c	rrent	NO + NC 250 V AC / 30 V DC 0.5 A / 30 V DC; 5 A / 230 V AC 2 A rms	
Digital output X1B: 2021 (DO)	Type Max. switching voltage Max. switching current Frequency Resolution Accuracy		Transistor output PNP 30 V DC 100 mA / 30 V DC, short-circuit protected 10 Hz16 kHz 1 Hz 0.2%	
Frequency output X1B: 2021 (FO)	X1A: 2021 can be used either as a digital or as a frequency output.			
STO interface X1C: 2326	See Appendix: Safe torque off (STO) on page 411.			

Clearance and creepage distance between I/O connections and the mains circuit is 5.5 mm (0.20 in), which guarantees the safety insulation of overvoltage category 3 (IEC 60664-1).

Brake resistor connection

(IEC 61800-5-1, IEC 60439-1, UL 508C)

Short-circuit protection The brake resistor output is conditionally short-circuit proof by IEC/EN 61800-5-1 and UL 508C. For correct fuse selection, contact your local ABB representative. Rated conditional short-circuit current as defined in IEC 60439-1 and the Short-circuit test current by UL 508C is 100 kA.

Common DC connection

Maximum power through common DC connection is equal to the drive nominal power. See ACS355 Common DC application guide (3AUA0000070130 [English]).

Efficiency

Approximately 95 to 98% at nominal power level, depending on the drive size and options.

Degrees of protection

IP20 (cabinet installation) / UL open: Standard enclosure. The drive must be installed in a cabinet to fulfil the requirements for shielding from contact.

IP20 / NEMA 1: Achieved with an option kit (MUL1-R1, MUL1-R3 or MUL1-R4) including a hood and a connection box.

Ambient conditions

Environmental limits for the drive are given below. The drive is to be used in a heated indoor controlled environment.

Controlled environment.	T		T =
	Operation	Storage	Transportation
	installed for	in the protective	in the protective
	stationary use	package	package
Installation site altitude	02000 m (6600 ft)	-	-
	above sea level		
	(above 1000 m		
	[3300 ft], see section		
	Derating on page		
	373)		
Air temperature	-10 +50 °C	-40 +70 °C ±2%	-40 +70 °C ±2%
An tomporataro	(14 122 °F).	(-40 +158 °F ±2%)	
	No frost allowed. See	(40 · 100 1 ±2/0)	(40 · 100 1 ±2/0)
	section <i>Derating</i> on		
	page 373.		
Doloth o boomidit		NA 050/	M 050/
Relative humidity	0 95%	Max. 95%	Max. 95%
		red. Maximum allowed	relative humidity is
	60% in the presence o		
Contamination levels	No conductive dust allo	owed.	
(IEC 60721-3-3,	According to	According to	According to
IEC 60721-3-2,	IEC 60721-3-3,	IEC 60721-3-1,	IEC 60721-3-2,
IEC 60721-3-1)	chemical gases:	chemical gases:	chemical gases:
	Class 3C2	Class 1C2	Class 2C2
	solid particles:	solid particles:	solid particles:
	Class 3S2.	Class 1S2	Class 2S2
	Note: The drive must		
	be installed in clean		
	air according to		
	enclosure		
	classification.		
	Note: Cooling air		
	must be clean, free from corrosive		
	materials and		
	electrically conductive		
	dust.		
Sinusoidal vibration	Tested according to	-	-
(IEC 60721-3-3)	IEC 60721-3-3,		
	mechanical		
	conditions: Class 3M4		
	29 Hz, 3.0 mm		
	(0.12 in)		
	9200 Hz, 10 m/s ²		
	(33 ft/s^2)		

Shock	Not allowed	According to	According to
(IEC 60068-2-27,		ISTA 1A.	ISTA 1A.
ISTA 1A)			Max. 100 m/s ²
		(330 ft/s ²), 11 ms.	(330 ft/s ²), 11 ms.
Free fall	Not allowed	76 cm (30 in)	76 cm (30 in)

Materials

Drive enclosure

- PC/ABS 2 mm, PC+10%GF 2.5...3 mm and PA66+25%GF 1.5 mm, all in color NCS 1502-Y (RAL 9002 / PMS 420 C)
- hot-dip zinc coated steel sheet 1.5 mm, thickness of coating 20 micrometers
- · extruded aluminum AlSi.

Package Disposal

Corrugated cardboard.

The drive contains raw materials that should be recycled to preserve energy and natural resources. The package materials are environmentally compatible and recyclable. All metal parts can be recycled. The plastic parts can either be recycled or burned under controlled circumstances, according to local regulations. Most recyclable parts are marked with recycling marks.

If recycling is not feasible, all parts excluding electrolytic capacitors and printed circuit boards can be landfilled. The DC capacitors contain electrolyte, which is classified as hazardous waste within the EU. They must be removed and handled according to local regulations.

For further information on environmental aspects and more detailed recycling instructions, please contact your local ABB distributor.

Applicable standards

The drive complies with the following standards:

• EN ISO 13849-1: 2008

Safety of machinery - Safety related parts of control systems - Part 1: general principles for design

• IEC/EN 60204-1: 2006

Safety of machinery. Electrical equipment of machines. Part 1: General requirements. *Provisions for compliance:* The final assembler of the machine is responsible for installing

an emergency-stop devicea supply disconnecting device.

• IEC/EN 62061: 2005 Safety of machinery – Functional safety of safety-related electrical, electronic and programmable electronic control systems

• IEC/EN 61800-3: 2004

Adjustable speed electrical power drive systems. Part 3: EMC requirements and specific test methods

• IEC/EN 61800-5-1: 2007

Adjustable speed electrical power drive systems – Part 5-1: Safety requirements – Electrical, thermal and energy

• IEC/EN 61800-5-2: 2007

Adjustable speed electrical power drive systems – Part 5-2: Safety requirements. Functional.

UL 508C

UL Standard for Safety, Power Conversion Equipment, third edition

CE marking

The CE mark is attached to the drive to verify that the drive follows the provisions of the European Low Voltage and EMC Directives.

Compliance with the European EMC Directive

The EMC Directive defines the requirements for immunity and emissions of electrical equipment used within the European Union. The EMC product standard (EN 61800-3:2004) covers requirements stated for drives. See section Compliance with EN 61800-3:2004 on page 387.

Compliance with EN 61800-3:2004

Definitions

EMC stands for **E**lectro**m**agnetic **C**ompatibility. It is the ability of electrical/electronic equipment to operate without problems within an electromagnetic environment. Likewise, the equipment must not disturb or interfere with any other product or system within its locality.

First environment includes establishments connected to a low-voltage network which supplies buildings used for domestic purposes.

Second environment includes establishments connected to a network not directly supplying domestic premises.

Drive of category C1: drive of rated voltage less than 1000 V, intended for use in the first environment.

Drive of category C2: drive of rated voltage less than 1000 V and intended to be installed and commissioned only by a professional when used in the first environment.

Note: A professional is a person or organization having necessary skills in installing and/or commissioning power drive systems, including their EMC aspects.

Category C2 has the same EMC emission limits as the earlier class first environment restricted distribution. EMC standard IEC/EN 61800-3 does not any more restrict the distribution of the drive, but the using, installation and commissioning are defined.

Drive of category C3: drive of rated voltage less than 1000 V, intended for use in the second environment and not intended for use in the first environment.

Category C3 has the same EMC emission limits as the earlier class second environment unrestricted distribution.

Category C1

The emission limits are complied with the following provisions:

- 1. The optional EMC filter is selected according to the ABB documentation and installed as specified in the EMC filter manual.
- 2. The motor and control cables are selected as specified in this manual.
- 3. The drive is installed according to the instructions given in this manual.
- 4. For the maximum motor cable length with 4 kHz switching frequency, see page 382.

WARNING! In a domestic environment, this product may cause radio inference, in which case supplementary mitigation measures may be required.

Category C2

The emission limits are complied with the following provisions:

- 1. The optional EMC filter is selected according to the ABB documentation and installed as specified in the EMC filter manual.
- 2. The motor and control cables are selected as specified in this manual.
- 3. The drive is installed according to the instructions given in this manual.
- 4. For the maximum motor cable length with 4 kHz switching frequency, see page 382.

WARNING! In a domestic environment, this product may cause radio inference, in which case supplementary mitigation measures may be required.

Category C3

The immunity performance of the drive complies with the demands of IEC/EN 61800-3, second environment (see page 387 for IEC/EN 61800-3 definitions).

The emission limits are complied with the following provisions:

- 1. The internal EMC filter is connected (the metal screw at EMC is in place) or the optional EMC filter is installed.
- 2. The motor and control cables are selected as specified in this manual.
- 3. The drive is installed according to the instructions given in this manual.
- 4. With the internal EMC filter: motor cable length 30 m (100 ft) with 4 kHz switching frequency. For the maximum motor cable length with an optional external EMC filter, see page 382.

WARNING! A drive of category C3 is not intended to be used on a low-voltage public network which supplies domestic premises. Radio frequency interference is expected if the drive is used on such a network.

Note: It is not allowed to install a drive with the internal EMC filter connected on IT (ungrounded) systems. The supply network becomes connected to ground potential through the EMC filter capacitors which may cause danger or damage the drive.

Note: It is not allowed to install a drive with the internal EMC filter connected on a corner-grounded TN system as this would damage the drive.

UL marking

See the type designation label for the valid markings of your drive.

The UL mark is attached to the drive to verify that it meets UL requirements.

UL checklist

Input power connection – See section *Electric power network specification* on page 381.

Disconnecting device (disconnecting means) – See Selecting the supply disconnecting device (disconnecting means) on page 40.

Ambient conditions – The drives are to be used in a heated indoor controlled environment. See section *Ambient conditions* on page 385 for specific limits.

Input cable fuses – For installation in the United States, branch circuit protection must be provided in accordance with the National Electrical Code (NEC) and any applicable local codes. To fulfil this requirement, use the UL classified fuses given in section Power cable sizes and fuses on page 375.

For installation in Canada, branch circuit protection must be provided in accordance with Canadian Electrical Code and any applicable provincial codes. To fulfil this requirement, use the UL classified fuses given in section Power cable sizes and fuses on page 375.

Power cable selection – See section Selecting the power cables on page 41.

Power cable connections – For the connection diagram and tightening torques, see section Connecting the power cables on page 51.

Overload protection – The drive provides overload protection in accordance with the National Electrical Code (US).

Braking – The drive has an internal brake chopper. When applied with appropriately sized brake resistors, the brake chopper will allow the drive to dissipate regenerative energy (normally associated with quickly decelerating a motor). Brake resistor selection is discussed in *Appendix: Resistor braking* on page 401.

C-Tick marking

See the type designation label for the valid markings of your drive.

C-Tick marking is required in Australia and New Zealand. A C-Tick mark is attached to the drive to verify compliance with the relevant standard (IEC 61800-3:2004 – Adjustable speed electrical power drive systems – Part 3: EMC product standard including specific test methods), mandated by the Trans-Tasman Electromagnetic Compatibility Scheme.

The Trans-Tasman Electromagnetic Compatibility Scheme (EMCS) was introduced by the Australian Communication Authority (ACA) and the Radio Spectrum Management Group (RSM) of the New Zealand Ministry of Economic Development (NZMED) in November 2001. The aim of the scheme is to protect the radio frequency spectrum by introducing technical limits for emission from electrical/electronic products.

For fulfilling the requirements of the standard, see section *Compliance with EN 61800-3:2004* on page 387.

TÜV NORD Safety Approved mark

The presence of the TÜV NORD Safety Approved mark verifies that the drive has been evaluated and certified by TÜV NORD according to the following standards for the realization of the Safe torque off function (STO): IEC 61508-1:1998, IEC 61508-2:2000; SIL3, IEC 62061:2005 and ISO 13849-1:2006. See *Appendix:* Safe torque off (STO).

RoHS marking

The RoHS mark is attached to the drive to verify that the drive follows the provisions of the European RoHS Directive. RoHS = the restriction of the use of certain hazardous substances in electrical and electronic equipment.

Compliance with the Machinery Directive

The drive is a machinery component that can be integrated into a wide range of machinery categories as specified in European Commission's Guide to application of the Machinery Directive 2006/42/EC 2nd Edition – June 2010.



Dimension drawings

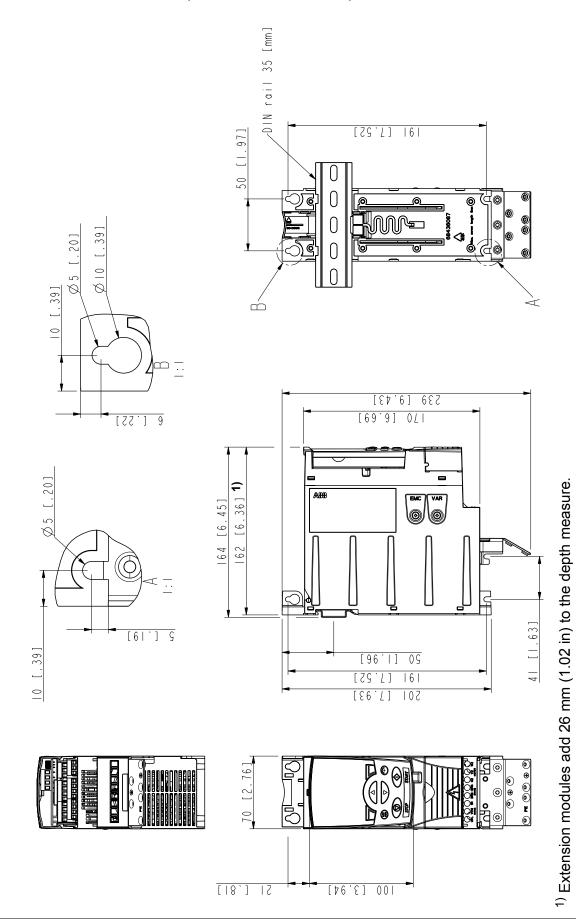
What this chapter contains

This chapter contains the dimension drawings of the drive.

Dimension drawings of the ACS355 are shown below. The dimensions are given in millimeters and [inches].

Frame sizes R0 and R1, IP20 (cabinet installation) / UL open

R1 and R0 are identical except for the fan at the top of R1.



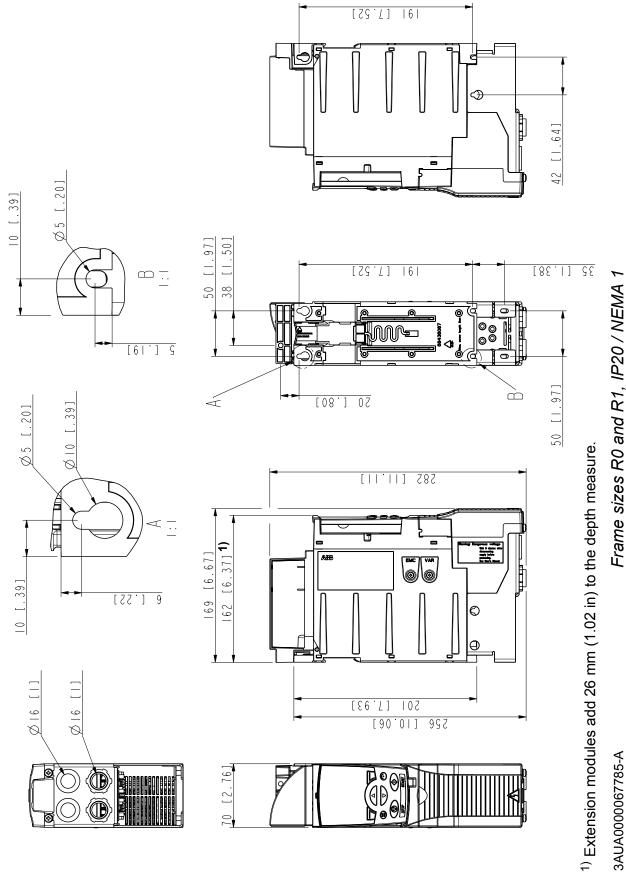
Frame sizes R0 and R1, IP20 (cabinet installation) / UL open

3AUA0000067784-A

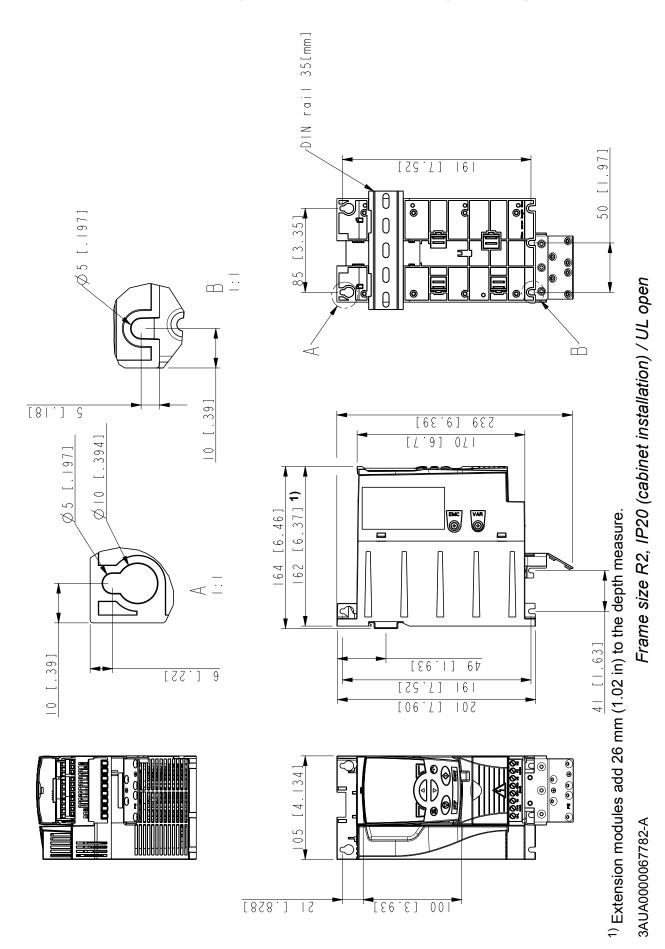
Frame sizes R0 and R1, IP20 / NEMA 1

Frame sizes R0 and R1, IP20 / NEMA 1

R1 and R0 are identical except for the fan at the top of R1.

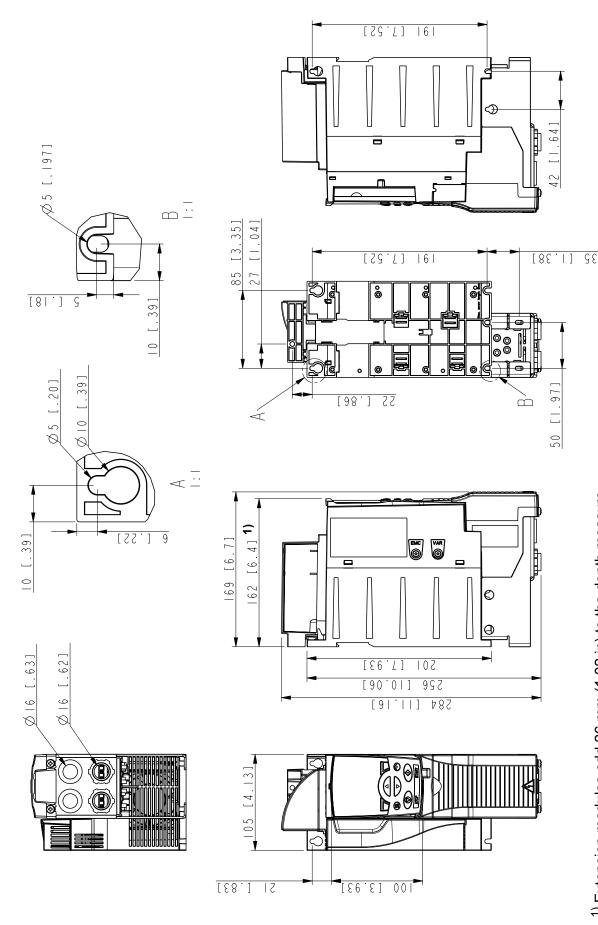


Frame size R2, IP20 (cabinet installation) / UL open



Frame size R2, IP20 / NEMA 1

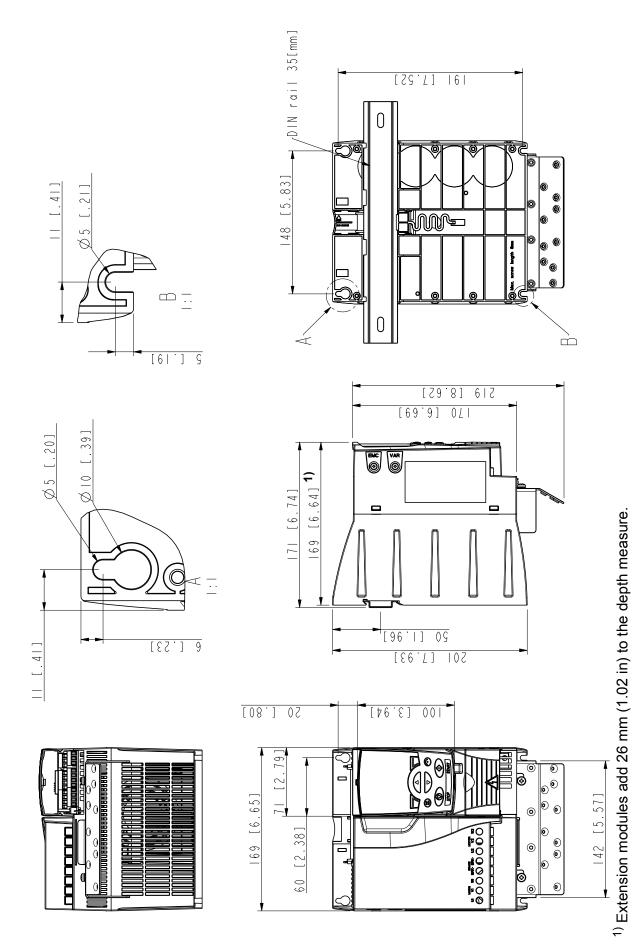
Frame size R2, IP20 / NEMA 1



1) Extension modules add 26 mm (1.02 in) to the depth measure.

3AUA0000067783-A

Frame size R3, IP20 (cabinet installation) / UL open

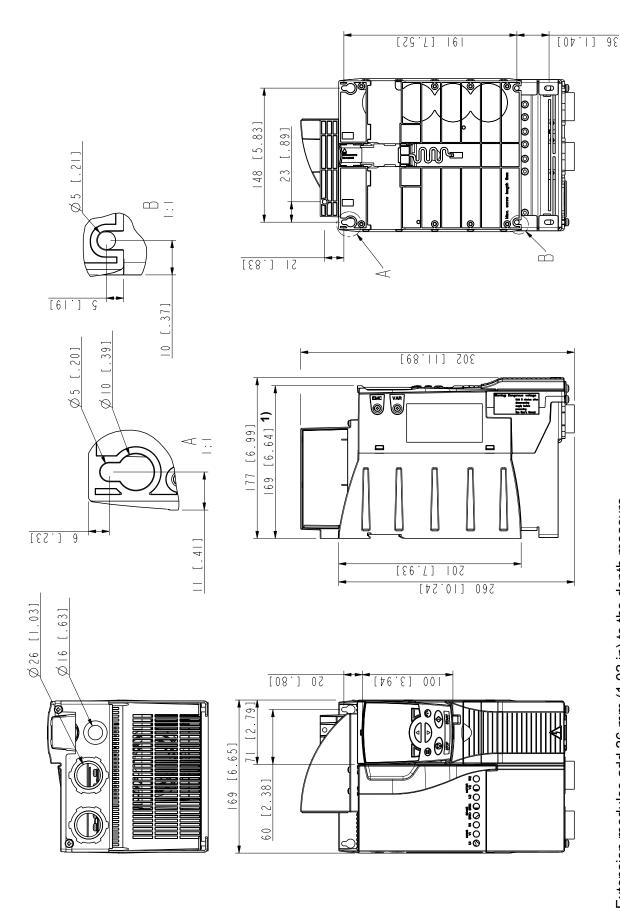


Frame size R3, IP20 (cabinet installation) / UL open

3AUA0000067786-A

Frame size R3, IP20 / NEMA 1

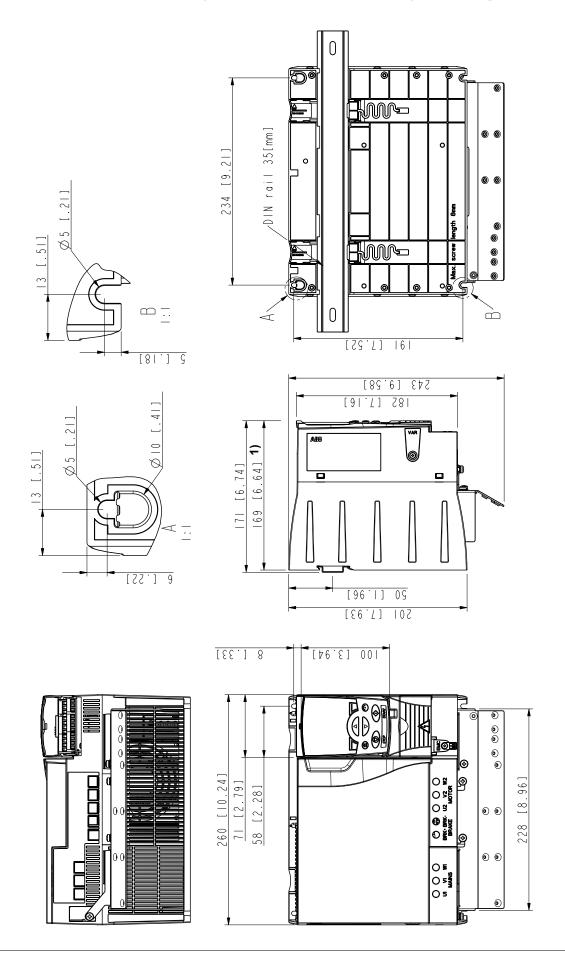
Frame size R3, IP20 / NEMA 1



1) Extension modules add 26 mm (1.02 in) to the depth measure.

3AUA0000067787-A

Frame size R4, IP20 (cabinet installation) / UL open

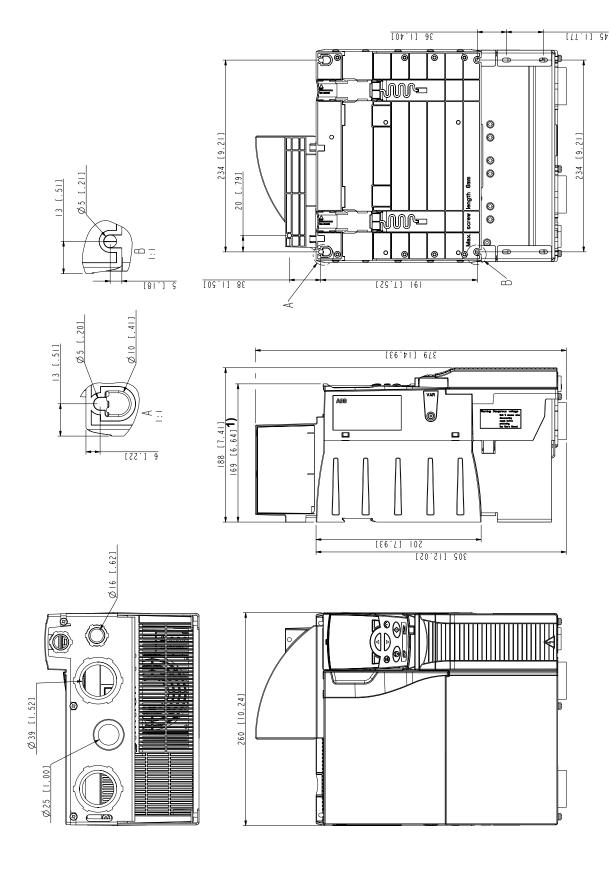


Frame size R4, IP20 (cabinet installation) / UL open 1) Extension modules add 26 mm (1.02 in) to the depth measure.

3AUA0000067836-A

Frame size R4, IP20 / NEMA 1

Frame size R4, IP20 / NEMA 1



1) Extension modules add 26 mm (1.02 in) to the depth measure.

3AUA0000067883-A

Appendix: Resistor braking 401



Appendix: Resistor braking

What this chapter contains

The chapter tells how to select the brake resistor and cables, protect the system, connect the brake resistor and enable resistor braking.

Planning the braking system

Selecting the brake resistor

ACS355 drives have an internal brake chopper as standard equipment. The brake resistor is selected using the table and equations presented in this section.

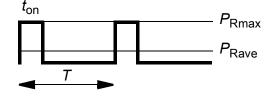
- 1. Determine the required maximum braking power P_{Rmax} for the application. P_{Rmax} must be smaller than P_{BRmax} given in the table on page 402 for the used drive type.
- 2. Calculate resistance R with Equation 1.
- 3. Calculate energy E_{Rpulse} with Equation 2.
- 4. Select the resistor so that the following conditions are met:
 - The rated power of the resistor must be greater than or equal to P_{Rmax} .
 - Resistance R must be between R_{\min} and R_{\max} given in the table for the used drive type.
 - The resistor must be able to dissipate energy E_{Roulse} during the braking cycle T.

Equations for selecting the resistor:

Eq. 1.
$$U_{\text{N}} = 200...240 \text{ V}$$
: $R = \frac{150000}{P_{\text{Rmax}}}$

$$U_{\text{N}} = 380...415 \text{ V}$$
: $R = \frac{450000}{P_{\text{Rmax}}}$

$$U_{\text{N}} = 415...480 \text{ V}$$
: $R = \frac{615000}{P_{\text{Rmax}}}$



Eq. 2.
$$E_{\text{Rpulse}} = P_{\text{Rmax}} \cdot t_{\text{on}}$$

Eq. 3.
$$P_{\text{Rave}} = P_{\text{Rmax}} \cdot \frac{t_{\text{on}}}{T}$$

For conversion, use 1 hp = 746 W.

where

R = selected brake resistor value (ohm)

 P_{Rmax} = maximum power during the braking cycle (W) P_{Rave} = average power during the braking cycle (W)

 E_{Rpulse} = energy conducted into the resistor during a single braking pulse (J)

 t_{on} = length of the braking pulse (s) T = length of the braking cycle (s).

Resistor types shown in the table are pre-dimensioned resistors using the maximum braking power with cyclic braking shown in the table. Resistors are available from ABB. Information is subject to change without further notice.

Type	R _{min}	R _{max}	P _{BRmax}			Selection table by resistor type					stor type
ACS355-						CBR-V / CBT-H					Braking time ²⁾
$x = E/U^{1)}$	ohm	ohm	kW	hp	160	210	260	460	660	560	s
1-phase U _N	= 200	.240 V	(200, 2	08, 220,	230,	240 \	/)				
01x-02A4-2	70	390	0.37	0.5	•						90
01x-04A7-2	40	200	0.75	1	•						45
01x-06A7-2	40	130	1.1	1.5	•						28
01x-07A5-2	30	100	1.5	2	•						19
01x-09A8-2	30	70	2.2	3	•						14
3-phase U _N	3-phase <i>U</i> _N = 200240 V (200, 208, 220, 230, 240 V)										
03x-02A4-2	70	390	0.37	0.5	•						90
03x-03A5-2	70	260	0.55	0.75	•						60
03x-04A7-2	40	200	0.75	1	•						42
03x-06A7-2	40	130	1.1	1.5	•						29
03x-07A5-2	30	100	1.5	2	•						19
03x-09A8-2	30	70	2.2	3	•						14
03x-13A3-2	30	50	3.0	4			•				16
03x-17A6-2	30	40	4.0	5			•				12
03x-24A4- 2	18	25	5.5	7.5						•	45
03x-31A0-2	7	19	7.5	10						•	35
03x-46A2-2	7	13	11.0	15						•	23

Type	R _{min}	R _{max}	P _{BF}	Rmax		S	elect	ion ta	ble b	y resi	stor type
ACS355-						CBR-V / CBT-H					Braking time ²⁾
$x = E/U^{1)}$	ohm	ohm	kW	hp	160	210	260	460	660	560	S
3-phase U _N	= 380	.480 V	(380, 4	00, 415,	440,	460,	480 V	<u>')</u>			
03x-01A2-4	200	1180	0.37	0.5		•					90
03x-01A9-4	175	800	0.55	0.75		•					90
03x-02A4-4	165	590	0.75	1		•					60
03x-03A3-4	150	400	1.1	1.5		•					37
03x-04A1-4	130	300	1.5	2		•					27
03x-05A6-4	100	200	2.2	3		•					17
03x-07A3-4	70	150	3.0	4				•			29
03x-08A8-4	70	110	4.0	5				•			20
03x-12A5-4	40	80	5.5	7.5				•			15
03x-15A6-4	40	60	7.5	10				•			10
03x-23A1-4	30	40	11	15					•		10
03x-31A0-4	16	29	15	20						•	16
03x-38A0-4	13	23	18.5	25						•	13
03x-44A0-4	13	19	22.0	30						•	10

E=EMC filter connected (metal EMC filter screw installed), U=EMC filter disconnected (plastic EMC filter screw installed), US parametrization.

00353783.xls K

Symbols

= minimum allowed brake resistor that can be connected to the brake chopper R_{\min}

= maximum allowed brake resistor that allows P_{BRmax}

P_{BRmax} = maximum braking capacity of the drive, must exceed the desired braking power.

Ratings by resistor type	CBR-V	CBR-V	CBR-V	CBR-V	CBR-V	СВТ-Н
	160	210	260	460	660	560
Nominal power (W)	280	360	450	790	1130	2200
Resistance (ohm)	70	200	40	80	33	18

WARNING! Never use a brake resistor with a resistance below the minimum value specified for the particular drive. The drive and the internal chopper are not able to handle the overcurrent caused by the low resistance.

Selecting the brake resistor cables

Use a shielded cable with the conductor size specified in section *Power cable sizes* and fuses on page 375. The maximum length of the resistor cable(s) is 5 m (16 ft).

Braking time = maximum allowed braking time in seconds at P_{BRmax} every 120 seconds, at 40 °C (104 °F) ambient temperature.

Placing the brake resistor

Install all resistors in a place where they will cool.

WARNING! The materials near the brake resistor must be non-flammable. The surface temperature of the resistor is high. Air flowing from the resistor is of hundreds of degrees Celsius. Protect the resistor against contact.

Protecting the system in brake circuit fault situations

Protecting the system in cable and brake resistor short-circuit situations

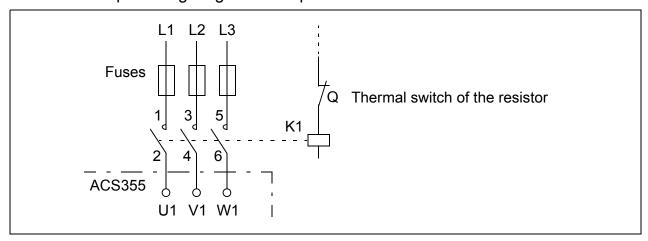
For short-circuit protection of the brake resistor connection, see *Brake resistor connection* on page *384*. Alternatively, a two-conductor shielded cable with the same cross-sectional area can be used.

Protecting the system in brake resistor overheating situations

The following setup is essential for safety – it interrupts the main supply in fault situations involving chopper shorts:

- Equip the drive with a main contactor.
- Wire the contactor so that it opens if the resistor thermal switch opens (an overheated resistor opens the contactor).

Below is a simple wiring diagram example.



Electrical installation

For the brake resistor connections, see the power connection diagram of the drive on page *51*.

Start-up

To enable resistor braking, switch off the drive's overvoltage control by setting parameter 2005 OVERVOLT CTRL to 0 (DISABLE).



Appendix: Extension modules

What this chapter contains

The appendix describes common features and mechanical installation of the optional extension modules for the ACS355: MPOW-01 auxiliary power extension module, MTAC-01 pulse encoder interface module and MREL-01 output relay module.

The appendix also describes specific features and electrical installation for the MPOW-01; for information on the MTAC-01 and MREL-01, refer to the corresponding user's manual.

Extension modules

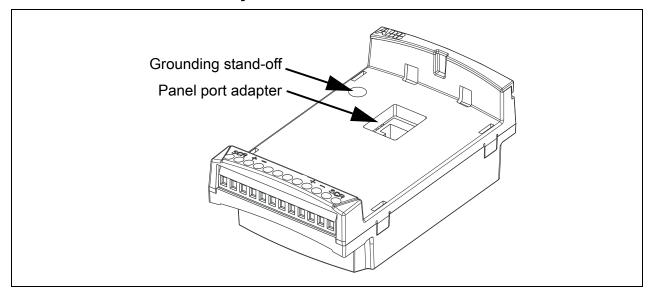
Description

Extension modules have similar enclosures and they are mounted between the control panel and the drive. Therefore, only one extension module can be used for a drive. ACS355 IP66/67 / UL Type 4X drives are not compatible with extension modules due to space restrictions.

The following optional extension modules are available for the ACS355. The drive automatically identifies the module (parameter 0181 EXT MODULE STATUS shows the value), which is ready for use after the installation and power-up.

- MTAC-01 pulse encoder interface module
- MREL-01 output relay module
- MPOW-01 auxiliary power extension module.

Generic extension module layout



Installation

Checking the delivery

The option package contains:

- · extension module
- grounding stand-off with an M3 × 12 screw
- panel port adapter (fixed to the MPOW-01 module at the factory).

Installing the extension module



WARNING! Follow the safety instructions given in chapter *Safety* on page 17.

To install the extension module:

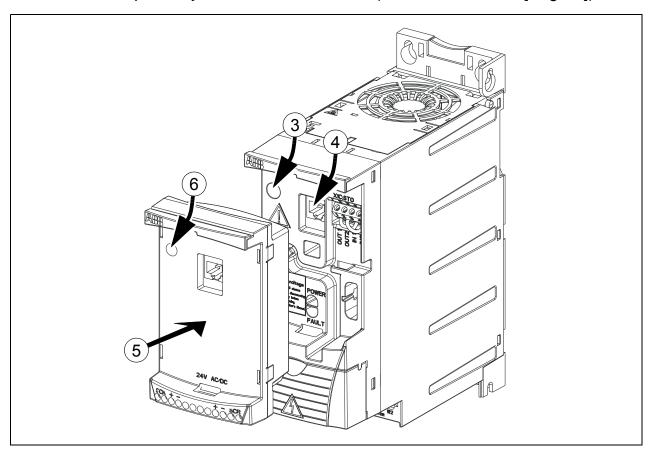
- 1. If not already off, remove input power from the drive.
- 2. Remove the control panel or panel cover: remove the terminal cover by simultaneously pushing the recess and sliding the cover off the frame.
- 3. Remove the grounding screw in the top left corner of the drive's control panel slot and install the grounding stand-off in its place.
- 4. For the MREL-01 and MTAC-01, ensure that the panel port adapter is attached to either the panel port of the drive or the mate part of the extension module. The adapter of the MPOW-01 is already fixed to the extension module at the factory.
- 5. Gently and firmly install the extension module to the drive's panel slot directly from the front.

Note: The signal and power connections to the drive are automatically made through a 6-pin connector.

6. Ground the extension module by inserting the screw removed from the drive in the top left corner of the extension module. Tighten the screw using a torque of 0.8 N·m (7 lbf·in).

Note: Correct insertion and tightening of the screw is essential for fulfilling the EMC requirements and proper operation of the extension module.

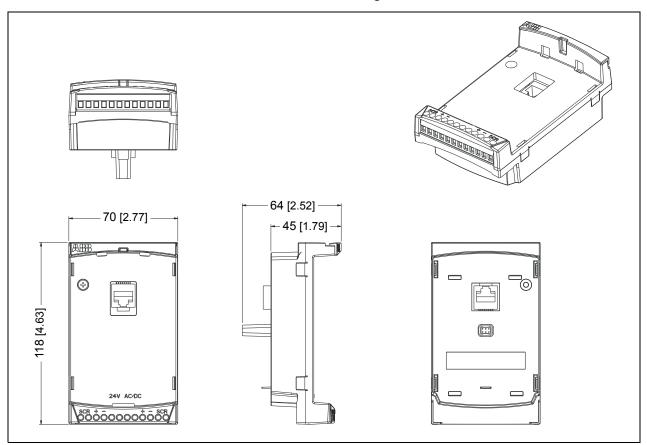
- 7. Install the control panel or panel cover on the extension module.
- 8. Electrical installation is module-specific. For MPOW-01, see section *Electrical* installation on page 409. For MTAC-01, see MTAC-01 pulse encoder interface module user's manual (3AFE68591091 [English]), and for MREL-01, see MREL-01 output relay module user's manual (3AUA0000035957 [English]).



Technical data

Dimensions

Extension module dimensions are shown in the figure below.



Generic extension module specifications

- Enclosure degree of protection: IP20
- All materials are UL/CSA-approved.
- When used with ACS355 drives, the extension modules comply with EMC standard EN/IEC 61800-3:2004 for electromagnetic compatibility and EN/IEC 61800-5-1:2005 for electrical safety requirements.

MTAC-01 pulse encoder interface module

See MTAC-01 pulse encoder interface module user's manual (3AFE68591091 [English]) delivered with this option.

MREL-01 output relay module

See MREL-01 output relay module user's manual (3AUA0000035957 [English]) delivered with this option.

MPOW-01 auxiliary power extension module

Description

The MPOW-01 auxiliary power extension module is used in installations where the drive's control part is required to be powered during network failures and maintenance interruptions. The MPOW-01 provides auxiliary voltages to the control panel, fieldbus and I/O.

Note: If you change any of the drive parameters when the drive is powered through the MPOW-01, you have to force parameter saving with parameter 1607 PARAM SAVE by setting the value to (1) SAVE...; otherwise all changed data will be lost

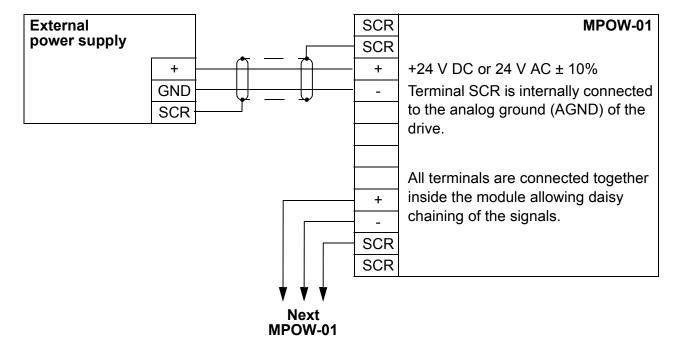
Electrical installation

Wiring

- Use 0.5...1.5 mm² (20...16 AWG) shielded cable.
- Connect the control wires according to the diagram in section *Terminal* designations below. Use a tightening torque of 0.8 N·m (7 lbf·in).

Terminal designations

The diagram below shows the MPOW-01 terminals and how the MPOW-01 module is connected to the external power supply and how the modules are daisy chained.



Technical data

Specifications

- Input voltage: +24 V DC or 24 V AC ± 10%
- Maximum load 1200 mA rms
- · Power losses with maximum load 6 W
- Designed lifetime of the MPOW-01 module is 50 000 hours in the specified ambient conditions of the drive (see section Ambient conditions on page 385).



Appendix: Safe torque off (STO)

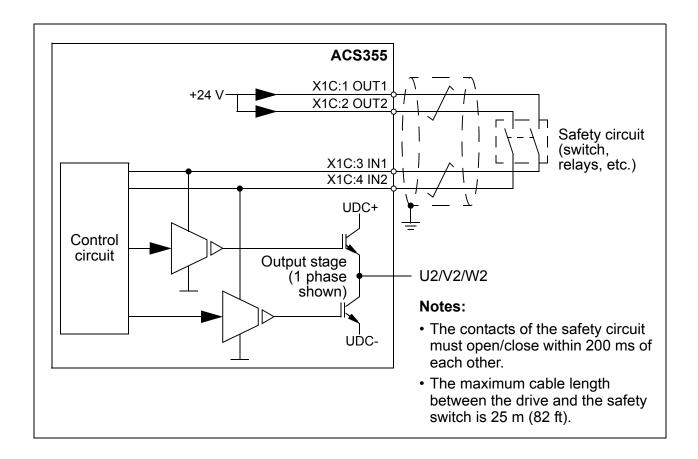
What this appendix contains

The appendix describes the basics of the Safe torque off function (STO) for the ACS355 drive. In addition, application features and technical data for the safety system calculation are presented.

Basics

The drive supports the Safe torque off (STO) function according to standards EN 61800-5-2; EN/ISO 13849-1:2006, IEC/EN 60204-1:1997; EN 61508:2002, EN 1037:1996, and IEC 62061:2005 (SILCL 3). The function also corresponds to an uncontrolled stop in accordance with category 0 of IEC 60204-1.

The STO may be used where power removal is required to prevent an unexpected start. The function disables the control voltage of the power semiconductors of the drive output stage, thus preventing the inverter from generating the voltage required to rotate the motor (see the diagram below). With this function, short-time operations (like cleaning) and/or maintenance work on non-electrical parts of the machinery can be performed without switching off the power supply to the drive.



WARNING! The STO function does not disconnect the voltage of the main and auxiliary circuits from the drive. Therefore maintenance work on electrical parts of the drive or the motor can only be carried out after isolating the drive system from the main supply.

Note: It is not recommended to stop the drive using the STO. If a running drive is stopped with this function, the drive will trip and stop by coasting. If this is not acceptable eg, it causes danger, the drive and machinery must be stopped using the appropriate stopping mode before using this function.

Note: Permanent magnet synchronous motor drives in case of a multiple IGBT power semiconductor failure: In spite of the activation of the STO function, the drive system can produce an alignment torque which maximally rotates the motor shaft by 180/p degrees, where *p* denotes the pole pair number.

Program features, settings and diagnostics

Operation of the STO function and its diagnostics function

When both STO inputs are energized, the STO function is in the standby state and the drive operates normally. If either of the STO inputs is de-energized, the STO function awakes, stops the drive and disables start. Start is possible only after the

STO inputs have been energized, and any of the drive reactions have been reset. Drive event can be parametrized according to the table below.

Parameter	Selection values	Explanation
3025 STO OPERATION	(1) ONLY FAULT	Drive event on successful STO operation is fault SAFE TORQUE OFF. The fault bit is updated.
	(2) ALARM&FAULT	Drive event on successful STO operation is alarm SAFE TORQUE OFF when stopped and fault SAFE TORQUE OFF when running. Fault and alarm bits are updated.
	(3) NO & FAULT	Drive event on successful STO operation is no alarm when stopped and fault SAFE TORQUE OFF when running. The fault bit is updated.
	Default: (4) ONLY ALARM	Drive event on successful STO operation is alarm SAFE TORQUE OFF. The alarm bit is updated. Start command must be toggled to continue running the drive.

If the operation delay between the inputs is excessive or only one STO input is deenergized, an event is always considered a fault (STO1 LOST or STO2 LOST). This event cannot be changed. De-energizing of only one STO input is not considered normal operation since the safety integrity level would decrease if only one channel is used.

STO status indications

When both STO inputs are energized, the STO function is in the standby state and the drive operates normally. If either of the STO inputs or both are de-energized, the STO function is executed in a safe manner and corresponding reaction is updated according to the table below.

STO event	Fault name	Description	Status
Fault 0044	SAFE TORQUE OFF	STO functions correctly and the fault must be reset before starting.	0307 FAULT WORD 3 bit 4
Fault 0045	STO1 LOST	STO input channel 1 has not de- energized, but channel 2 has. Opening contacts on channel 1 might have been damaged or there is a short-circuit.	0307 FAULT WORD 3 bit 5
Fault 0046	STO2 LOST	STO input channel 2 has not de- energized, but channel 1 has. Opening contacts on channel 2 might have been damaged or there is a short-circuit.	0307 FAULT WORD 3 bit 6
Alarm 2035	SAFE TORQUE OFF	STO functions correctly.	0309 ALARM WORD 2 bit 13

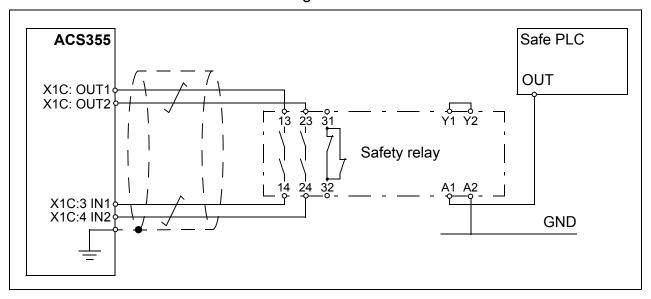
STO function activation and indication delays

STO activation delay is below 1 ms. STO indication delay (time from the deenergization of any STO input to the updating of the status bit) is 200 ms.

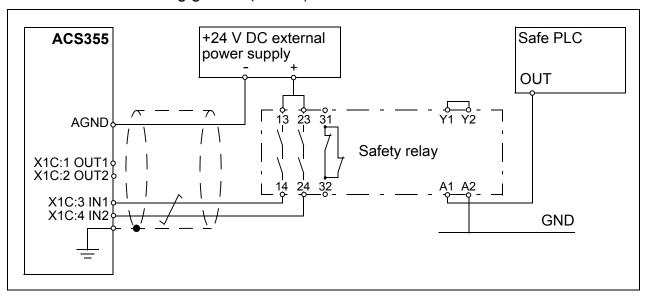
Note: If any STO channel is toggled very fast, it is possible that the drive trips to overcurrent or short-circuit.

Installation

Connect the cables as shown in the diagram below.



STO input channels can also be supplied with an external power supply. The required supply current is maximum 15 mA for each STO channel, and the voltage requirement is 24 V DC +/-10%. The negative terminal of the power supply must be connected to the analog ground (AGND) of the drive.



STO can also be daisy-chained from drive to drive, so that several drives are behind one safety switch. If STO outputs (OUT1 and OUT2) are used to supply the STO circuit, maximum five drives can be supplied. The number of drives depends on the

24 V auxiliary voltage load (I/O, panel load, used fieldbus or STO circuits; max. 200 mA) of the drive supplying the STO circuit (see section *Control connection data* on page 383). When using external supply, all analog grounds (AGND) of the drives must be chained together.

Note: Daisy chaining lowers the total system safety integrity level, which needs to be calculated case by case for each system.

Start-up and commissioning

Always test the operation and reaction of the STO function before commissioning.

Technical data

STO components

STO safety relay type

General requirements	IEC 61508 and/or EN/ISO 13849-1
Output requirements	
No. of current paths	2 independent paths (one for each STO path)
Switching voltage capability	30 V DC per contact
Switching current capability	100 mA per contact
Maximum switching delay	200 ms
between contacts	
Example 1	Simple SIL3 approved safety relay
Type and manufacturer	PSR-SCP- 24UC/ESP4/2X1/1X2 by Phoenix Contacts
Approvals	EN 954-1, cat 4; IEC 61508, SIL3
Example 2	Programmable safety logic
Type and manufacturer	PNOZ Multi M1p by Pilz
Approvals	EN 954-1, cat 4; IEC 61508, SIL3; and ISO 13849-1, PL e

Note: SIL/PL classified safety devices typically perform diagnostic test pulsing for their semiconductor outputs. To avoid unnecessary tripping in ACS355 STO caused by the test pulses, an optional PNOZelog Terminal block filter 1 can be used.

STO connection

Input for external STO supply	24 V DC ± 10%, load 25 mA
Input impedance	R _{in} = 2 kohm
Load	12 mA / channel
Output	Maximum load 200 mA depending on I/O load

STO cable

Туре	2×2 cables, low voltage, single shielded, twisted pair cable
Conductor size	1.50.25 mm ² (1624 AWG)
Maximum length	Max. 25 m between STO inputs and the operating contact
Tightening torque	0.5 N·m (4.4 lbf·in)

Data related to safety standards

IEC 61508					
SIL	3				
PFH	6.48E-09 (6.48 FIT)				
HFT	1				
SFF	91%				

EN/ISO 13849-1					
PL	е				
Category	3				
MTTFd	470 years				
DC	99%				

IEC 62061					
SILCL	3				

Abbreviations

Abbreviation	Reference	Description
CCF	EN/ISO 13849-1	Common Cause Failure (%)
DC	EN/ISO 13849-1 Annex E, table E.1	Diagnostic Coverage
FIT		Failure In Time: 1E-9 hours
HFT	IEC 61508	Hardware Fault Tolerance
MTTFd	EN/ISO 13849-1	Mean Time To dangerous Failure: (The total number of life units) / (the number of dangerous, undetected failures) during a particular measurement interval under stated conditions
PFHd	IEC 61508	Probability of Dangerous Failures per Hour
PL	EN/ISO 13849-1	Performance Level: Corresponds SIL, Levels a-e
SFF	IEC 61508	Safe Failure Fraction (%)
SIL	IEC 61508	Safety Integrity Level
STO	EN 61800-5-2	Safe Torque Off

Maintenance

Test the operation and reaction of the STO function every year.



Appendix: Permanent magnet synchronous motors (PMSMs)

What this chapter contains

This chapter gives basic guidelines on how the ACS355 drive parameters should be set when using permanent magnet synchronous motors (PMSMs). In addition, some hints are given for tuning the motor control performance.

Setting the parameters

With PMSMs special attention must be paid on setting the motor nominal values correctly in parameter group 99 START-UP DATA. It is always recommended to use vector control. If the nominal back-emf of the motor is not available, a full ID run should be performed for improving performance.

The following table lists the basic parameter settings needed for permanent magnet synchronous motors.

No.	Name	Value	Description
9903	MOTOR TYPE	2	Permanent magnet synchronous motor
9904	MOTOR CTRL MODE	1	VECTOR: SPEED
		2	VECTOR:TORQ
			Note : Scalar control mode (3) can also be selected, but it is not recommended because in the scalar control mode the permanent magnet synchronous motor may get unstable and damage either the process, the motor or the drive.
9905	MOTOR NOM VOLT		Note : If the back emf voltage of the motor is not available, set the rated value here and run the ID run. If the voltage is given as a proportional value, such as 103 V/1000 rpm in a 3000 rpm motor, set 309 V here. Sometimes the value is given as the peak value. In this case, divide the value by the square root of 2 (1.41).
			Note : It is recommened to use the back emf voltage. If it is not used, a full ID run must be performed.
9906	MOTOR NOM CURR		Rated current of the motor. Do not use the peak value.
9907	MOTOR NOM FREQ		Rated electrical frequency of the motor. If the frequency is not given in the motor rating plate, it can be calculated using the following formula:
			frequency [Hz] = speed [rpm] x (number of pole pairs) / 60
9908	MOTOR NOM		Rated mechanical speed of the motor. If it is not given, it can be calculated using the following formula:
	SPEED		speed [rpm] = frequency [Hz] x 60 / (number of pole pairs)
9909	MOTOR NOM POWER		Motor nominal power. If it is not given, it can be calculated using the following formula:
			Power [kW] = Rated torque [Nm] x 2 x pi x rated speed [rpm] / 60000
2102	STOP FUNCTION	RAMP	It is recommended to use ramp stop with a PMSM.

Start mode

The default value of parameter 2101 START FUNCTION is 1 (AUTO). In most cases this is suitable for starting the rotation. If fast start with low inertia is required, it is recommended to set parameter 2101 START FUNCTION to 2 (DC MAGN).

Smooth start

The Smooth start function can be used if the motor is not able to start or when rotation at low speeds needs to be improved. The following table lists the needed parameter settings.

No.	Name	Value	Description	Default
2621	SMOOTH START	0	Disabled	0
		1	Enabled always	
		2	Start only	
2622	SMOOTH START CUR	10100%	Current applied to the motor when the Smooth start is active. Increasing the current helps enable starting with a load or with a large inertia. Decreasing the current can prevent the rotor from turning into a wrong direction during the start.	50%
2623	SMOOTH START FRQ	2100%	Set the smooth start frequency range as small as possible. This should be tuned so that the rotation is stable throughout the whole speed range.	10%

Speed controller tuning

In vector control mode, it is recommended to tune the speed controller. In applications where the motor can be rotated freely, automatic tuning can be used. See parameter 2305 AUTOTUNE RUN for more information.

Usually it is enough to adjust the proportional gain (parameter 2301 PROP GAIN) of the speed controller to a higher value. The default value is 5 which results in rather conservative speed controller tuning. Increase the proportional gain value by 5 until the performance is satisfactory. If the application becomes unstable, divide the last gain value by 2, and you have reached rather robust speed controller tuning.

Note: It is recommended to use encoder feedback if accurate torque control, high torque production, or sustained operation is required at low speeds (below 20% of the motor nominal speed).

420	Appendix: Permanent magnet synchronous motors (PMSMs)						

Further information

Product and service inquiries

Address any inquiries about the product to your local ABB representative, quoting the type designation and serial number of the unit in question. A listing of ABB sales, support and service contacts can be found by navigating to www.abb.com/drives and selecting Sales, Support and Service network.

Product training

For information on ABB product training, navigate to www.abb.com/drives and select Training courses.

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