MITSUBISHI

Mitsubishi AC Servo MDS-A-SVJ Series

Servo Parameter Manual

BNP-B3882B-ENG

This manual pertains to the following system:

MDS-A-SVJ Series

BND-511W000-C1

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1. Introduction

This manual describes servo parameters and alarms pertaining to the MDS-A-SVJ Series. Any parameter not covered in this manual must be set to zero. Any parameters added, changed, or deleted due to software revisions are marked accordingly in this manual.

The following documents are also provided for reference and should be used in conjunction with this manual:

Mitsubishi Personal Machine Controller

Servo Selection Manual

BNP-B3783

Mitsubishi Personal Machine Controller

Servo Maintenance and Adjustment Manual

BNP-B2057

Functions & Related Parameters

2. Functions and Related Parameters

By software (hereafter abbreviated to "S/W") version, functions have been added or revised as shown below.

S/W ver- sion	Date of revision	Addition/revision	Relate	ed para	ameter
AO	'93-12-27	New			
во	'94 4-11 A	bsolute position control enabled	SVo17		
		Made compatible with HA93N-E30-, HA-FH**-Y-, and HA-ME-series motors	sv019	sv020	sv025
		HA**N-E33- and HA**N-A33- series (high-speed serial detector-type) added	sv025		
		New overload detection method utilized. Servo monitor overload display now shows current actual load level.	SVo21	svo22	
		Alarm 1F detection added			
В1	194- 7-11	D/A output amplification rate settings changed	SV063		
		Alarm 28 (absolute position overspeed) detection deleted			
В2	'94-10-24	Regeneration resistors (MR-RB064, MR-RB34) added	SV036		
В3	'94-12-12 M	ade compatible with 100V units. 100V and 200V units operable using same S/W.			
		Regeneration resistors (MR-RB063, MR-RB064, two series) added	sv036		
		Alarm 10 (insufficient amp voltage) added			
В4	'95- 2-27 H	A**N-E33 and HA**N-E30 parameters made common	sv025		
со	195- 6-23	Acceleration feedforward control added	SV015		
		Induced voltage correction added (compatible with HA**N motors only)	SVo47		
		Emergency-stop ready maintenance control (thrust axis drop prevention control) added	SV048		
Cl	195- 7-26	None			

3, Servo Parameters

Servo parameter settings and display methods differ according to the controller used. For details, please refer to the relevant instruction manual.

	[]	1/4	Set-	Туре	0-4-5	Mini-	Maxi-		Туре	
Name	Abbrevi- ation	Description	ting	of change	Setting unit	mum value	mum value		Servo configu-	Adjust- ment
	1			- 1				ration	ration	IIICITC
S V 001	PC1	Motor-side gear ratio	Con- figu- ration	Ini- tial		1	32767	0		
SV002	PC2	Machine-side gear ratio	Con- figu- ration	Ini- tial		1	32767	0		
SV003	PGN1	Position loop gain 1	Con- figu- ration		1/Sec	1	200		0	
SV004	PGN2	Position loop gain 2	Adjust- ment		1/Sec	0	999			0
SV005	VGN1	Velocity loop gain 1	Adjust- ment			1	999			0
SV006				ļ						
SV007			<u> </u>			1	9999	ļ		
SV008	VIA	Speed loop lead com- pensation	Adjust- ment							0
SV009	IQA	Current loop q-axis lead compensation				1	20480		0	
SV010	IDA	Current loop d-axis lead compensation				1	20480		0	
SV011	IQG	Current loop q-axis				1	2560		0	
SV012	IDG	Current loop d-axis gain				1	2560		0	
SV013	ILMT	Current limit			% of rated current	0	999			0
SV014	ILMTsp	Special operation cur- rent limit			% of rated current	0	999			0
SV015	FFC	Acceleration feedfor- ward gain	Adjust ment		%	0	999			0
SV016	LMC1	Lost motion correction	Adjust ment		%, % of rated cur- rent	-1	200			0
SV017	SPEC	Servo configuration	Con- figu- ration	Ini- tial	HEX setting	*	*	0	0	
SV018	PIT	Ball screw lead	Con- figu- ration		win	1		0		
SV019	RNG1	Position detector resolution	Con- figu- ration		kp/rev	1			0	
SV020	RNG2	Speed detector resolu- tion	Con- figu- ration	Ini- tial	kp/rev	1	9999		0	
SV021	OLT	Overload detection time constant			sec	1	80	İ	O.	·
SV022	OLL	Overload detection level			% of rated current	32		1	0	
sv023	OD1	Servo ON • excessive error detection range			mm	0	1	0		
SV024	INP	In-position detection range			μm	0	32767	0		
SV025	MTYP	Motor/detector type	Con- figu- ration		HEX setting		*		0	
SV026	OD2	Servo OFF • excessive error detection range			mm	0	32767	0		
SV027	SSF1	Special servo function selection 1	Con- figu- ration	1	HEX setting	*	*			0

			1 0	I n. = -		Mini-	Maxi-		Туре	
Name	Abbrevi- ation	Description	Set- ting	Type of	Setting unit	mum	mum	Machine configu-	Servo configu-	Adjust-
	acton		screen	change:	unit	value	value	ration	ration	ment
SV028										
SV029										
SV030				<u> </u>					ļ	
SV031 SV032	TOF	Torque offset	Adjust-		% of rated	-100	100			
			ment Con-		current	*				0
SV033	SSF2	Special servo function selection 2	figu- ration		HEX setting				0	
SV034	SSF3	Special servo function selection 3		Ini- tial	HEX setting				0	
SV035	SSF4	Special servo function selection 4			HEX setting	*	*		0	
SV036	PTYP	Regeneration resistor type	Con- figu- ration	Ini- tial	HEX setting	*	*		0	
SV037				L			2000	ļ		
SV038	FHZ	Mechanical resonance suppression filter centre frequency	Adjust ment		Hz	0	3000			0
SV039			. 32			0	100			
SV040	LMCT	Lost motion correction dead zone	Adjust ment	}	μm		100			0
SV041	LMC2	Lost motion correction 2	Adjust ment		%, % of rated cur- rent	-1	200			0
SV042										
SV043						ļ			ļ	
SV044 SV045			ļ	L	<u> </u>	<u> </u>		↓	ļ	
SV045			 	 		 		├	 	
SV047	EC	Induced voltage correction	Adjust ment		%	0	200			0
SV048	EMGrt	Emergency stop ready maintenance time	Adjust ment		msec	0	1000			0
sv049	PGN1sp	Special operation • position loop gain 1			1/sec	1	200			0
SV050	PGN2sp	Special operation • position loop gain 2			1/sec	0	999			0
SV051										
SV052 SV053	OD3	Special operation • excessive error detection range			mm	0	32767			0
SV054				↓		- 0	5000		ļ	ļ
SV055	EMGdt	Maximum deceleration control delay time			msec		5000	0		
SV056	EMGt	Deceleration control time constant			msec	0	5000	0		
SV057	SHGC	SHG control gain	-	 	1/sec	0	999	 	 	0
SV058	SHGCsp	Special operation • SHG control gain			1/sec	"	999			0
SV059	ļ		<u> </u>	ļ	ļ	1	ļ	 	ļ	
SV060	DAINO	D/A output channel data	 		 		7		 	+
SV061	DYTMO	DIA Output Channel data	 	+	 	 	 	 		
SV062	DAlmpy	D/A output channel amplification rate	†		1/256	-32768	32767			
SV064	1		1		1	1	1	T		

Parameter Descriptions

3.1 Parameter Descriptions

1000 × 10

			Sett	ing
	Abbrevi-		rar	ıge
lame	ation	Description .	Mini-	Maxi-
			mum	mum
V001	PC1	Sets motor-side gear ratio	1	32767
V002	PC2	Sets machine-side gear ratio	1	32767
V003	PGN1	Sets position loop gain. Normally set to 33	1	200
V004	PGN2	Set together with SV057:SHGC when SHG control is used. Set to zero when not in use.	0	999
V005	VGN1	Sets speed loop gain. Can be increased to up to 5 times the standard value in steps of 20-30% of the standard value. Higher settings provide increased response but cause greater vibration and noise.	1	999
V006		Must be set to zero.		
V007 V008	1	Must be set to zero. Sets speed loop lead compensation. Setting is fixed according to motor type used (see Standard Parameters by Motor Type table).	1	9999
V009	IQA	Internal current loop compensation. Setting is fixed according to motor type used (see Standard Parameters by Motor Type table).	1	20480
V010	IDA	Internal current loop compensation. Setting is fixed according to motor type used (see Standard Parameters by Motor Type table).	1	2560
:V011	IQG	Internal current loop compensation. Setting is fixed according to motor type used (see Standard Parameters by Motor Type table).	1	2560
W012	IDG	Internal current loop compensation. Setting is fixed according to motor type used (see Standard Parameters by Motor Type table).		
:V013	ILMT	Sets current limit. Setting is a percentage of rated current. Set to standard value if motor is used to maximum torque (may be limited by amp specifications). Limit applies in + and - directions.	0	999
V014	ILMTsp		0	999
3V015	FFC	Set when overshoot is significant under feedforward control or when relative error is significant under synchronous control. Set to zero when not in use.	0	999
₹V016	LMC1	Set when arc quadrant changeover projections are large (occurs when friction, torsion, or backlash causes a dead zone). Effective only when lost motion correction (SV027:lmcl, lmx2) is selected.	-1	200
		Type 1 SV027:SSF1/lmcl=1, lmc2=0 Setting unit: % This type of correction eliminates projections with low-spee d interpolation. A setting of zero gives no correction gain; a setting of 100 gives 100% correction.	0	200
		Type 2 SV027:SSF1/lmc1=0, lmc2=1 Setting unit: % of rated current This type is standard with the MDS-A-SVJ series. use when type-1 correction is insufficient, e.g., with high-speed, high-precision interpolation. Set as a % of rated current.	0	100
		For setting different correction gain (type-1) or correction amount (type-2) for each command direction. Set together with SV041:LMC2 when a different value setting is desired for each command direction. To change the command speed from - to + (with clockwise command direction), set value to SV016:LMC1. To change the command speed from + to - (with clockwise command direction), set value to SV041:LMC2.		
		If -1 is set, correction is not carried out during command speed direction changes.		

lame	bṛevi						Des	cript	ion								ang	
	tion		- '				Des	CIIPC								Mini- mum		Maxi- mum
V017	PEC	ervo con:	figur 14	ation	12	11	10	9	8	7	6	5	4	3	2	1	0	
						<u> </u>				abs		vdir						
			bit	Name	Fun	ctio	n wher	n set	to	zero	Fu	nction	ı whe	n set	to	1		
																	_	
			4														_	
		ı	5	vdir	Detec	ctor	mount:	ing d	irec	tion	Detect BD	or n	nounti	ng (direc	tion		
			6	-1	D - 1 -						351-		!-!		3-4	L		
			7	abs	кета	tive	posit	ion a	etec	tion	Absolu	ite p	ositi	on o	letec	tion		
			9														-	
			11														-	
			12															
			1 /															
																Į.		*****
V018	PIT	Sets ball Setting is												ews.]	L	32767
V019	iNG1	ets number of 1,000			es pe	r on	e revo	lutic	n of	moto	r-end	detec	tor i	n un	its	1		9999
		Set SV019	:RNG	l and												ļ.,		0001
V020	uNG2	ets number of 1,000	pulse	es.	_						r-ena (detec	tor 1	n un	ıts	1	_	999!
V021	OLT :	Set SV019							valu	е						1	+	8(
V022		ets over	Load	curre	nt de	tect	ion le	evel a								32	2	180
		Determines tector ty	/pe (S	sv025:	MTYP)	Th	e serv	vo moi	nito:	r load	l is di	splay	ed or	ı the				
		basis tha rated cor											, is	the				
V023	001	ets exces											a se	ttin	g	(0	3276
		Standar	d se	tting	form	ula:					_		, 1 \					
			wher		L = S	VU26:	0D2 =	5005.	טט: ט	3 = F	/ (60	X PGI	11) X	0.5				
						_	trave		_		nm);							
W024	INP	Sets in-p					oop ga range.	ın ı	(1/5	ec).							0	3276
₩025	4TYP	Motor/det 15	ector 14			2	11	10	9	8	7 6	5	4	3	2	1	0	
						ΣP				Ĭ	, ,		mt			-		
				Name							iption							
			0	mcyp	Sets	moto	or typ	e (se	ee M	otor '	Types t	able)	•					
			2]														
			4	1														
			5															
			7	1														
			9	ecyp	Sets	dete	ector	type	(see	e Dete	ctor T	ypes	table	·) •				
•			10]														
			12	-														
			13	-														
			15	1													i	
					1													

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lame	brevi	Description	ra	ting nge
	tion		Mini-	Maxi- mum
V026	DD2	ets excessive error detection range when servo is OFF. With a setting f zero, excessive error detection does not take place. Normally set to ame value as SV023:0D1.	0	32767
V027	SF1	pecial servo function selection 1	1	
		15 14 13 12 11 10 9 8 7 6 5 4 3 2	1	0
		bit Name Function when set to zero Function when set to	1	
		2		
		4 vfctl 00: Jitter correction dis- 10: Jitter correction abled pulse	2	
		5 Vfct2 01: Jitter correction 1 11: Jitter correction pulse	3	
		6		
		8 lmcl 00: Lost motion correction 10: Lost motion correc	tion	
		disabled type 2	1	
		9 lmc2 01: Lost motion correction 11: Prohibited type 1		
		10		
		12		
		13 14 zrn2 Reference point return type Reference point return	time	
		14 zrn2 Reference point return type Reference point return 1 2 15	суре	
V028_ vo29		lust be set to zero.	-	-
V030		lust be set to zero.		
V031	TOF	Lust be set to zero. lets unbalance torque for vertical axes and other axes with unbalance	-100	100
	707	<pre>.orque as a % of rated current. /sed when SV027:SSF1/lmc1, lmc2 are set.</pre>	-100	100
V033	SSF2	pecial servo function selection 2 15 14 13 12 11 10 9 8 7 6 5 4 3 2	1	0
		15, 14 13 12 11 10 9 8 7 6 5 4 3 2		
		bit Name Function when set to zero Function when set to	1	
		2		
		3 4		
		5		
		6 7		
		8		
		9		
		10		
		12		
		13		
		14 15		
		1000h must be set.		

AND COMM

								MD	S-A-SVJ			
									Parameter	Descri	tion	s
											Se	tting
Name '	Abbrevi ation					Descr	iption				r Mini-	ange Maxi-
											mum	mum
V034	SSF3 S	pecial se 15	rvo i	functi 13	on select: 12 11		9 8	7	6 5 4	3 2	1	0
		15	14			10	, ,		0 5 4	3 2	 	
		<u> </u>	bit	Name	Function	when :	set to	zero	Function wh	en set to	1	
			0									
			2									
			3									
			5									
			6									
			7									
			9									
			10									
			12									
			13							···		
			15									
		0000h mus	t be	set.								
V035	SSF4 S	pecial se	rvo :	funct	ion select	ion 4						
		15	14	13	12 11	10	9 8	7	6 5 4	3 2	1	0
		L	1						1			imon
			Dit	Name imon					Function wh Feedback curre			
									play			
			1 2						<u>:</u>			
			3									
			4 5						}	··-		
			6									
			7 8						<u> </u>			
			9									
			10	ļ								
			12									
			13 14									
			15									
v036	PTYP I	Regenerati	ion r	esist	or type							
		15	14	13 mp		10 rtyr	9 8	7	6 5 4	3 2	1	0
		L			1				<u> </u>			
			0	Name	Function	wnen	set to	zero	Function wh	en set to	1	
			1									
			3	┼	<u> </u>							
			4									
			5	-					 			
			7									
			8	rtyp	Regenerat							
			10	1	Types tab							
			11	amp	Sets amp	type "	umber 1					
			13		secs amp	cype III	mwer 1					
			14 15	4	1							
			حت		l							j

BNP-B3882B

MDS-A-SVJ

Parameter Descriptions

Name	Abbrevi- ation	Description	Setting Minimum	range
svo37	402011	Must be set to zero.	MITITINGIN	Maximum
SV038	FHz	Sets mechanical vibration suppression frequency if mechanical vibration suppression is required. Must be set over 100Hz. Set to zero when not in use.	0	3000
svo39		Must be set to zero.		
SV040	LMCT	Sets lost motion correction dead zone. Normally set to zero. Set only if lost motion correction timing is incorrect when feed- forward control is used.	0	100
svo41	LMC2	Normally set to zero. Set together with SV016:LMC1 only when different setting values are desired for lost motion correction gain (type 1) or correction amount (type 2) according to the command direction. To change the command speed from - to + (with clockwise command direction), set value to SV016:LMC1. To change the command speed from + to - (with clockwise command direction), set value to SV041:LMC2. If -1 is set, correction is not carried out during command speed direction changes. Only effective when lost motion correction (SV027:lmc1, lmc2) is selected.	-1	200
SV042		Must be set to zero.		
svo43		Must be set to zero.		
svo44		Must be set to zero.		
svo45		Must be set to zero.		
SV046		Must be set to zero.		
svo47	EC	Sets effective gain for induced voltage correction. Compatible only with HA**N HA053, and HA13 motors. Using this function, the feedback current's ability to follow the command current can be increased and the deceleration torque increased. The standard setting is 100, but the following adjustments must be made: Set bit 0 of SV035:SSF4 to 1 and thus display the command current peak in the MAX current 1 display on the servo monitor and the feedback current peak in the MAX current 2 display. Next, carry out acceleration/deceleration and set adjust the setting such that the feedback current peak is 5-10% smaller, than the command current peak.	0	200
SV048	EMGrt	Sets time between an emergency stop (caused by an external emergency stop input, insufficient voltage, or alarm) and ready ON. Used to prevent vertical axes from dropping after an emergency stop. Note that the time set by this parameter becomes ready-ON even if a deceleration-controllable alarm occurs. Generally, this parameter should be set to the minimum value that enables the electromagnetic brake to operate for the required time. This parameter's time setting must be smaller than that of SV055:EMGdt.	0	1000

MDS-A-SVJ

Parameter Descriptions

	bbrevi-		Setting	range
Name	ation	Description	inimum	Maximum
SV049	PGN1sp	Sets position loop gain during special operation, e.g., with synchronous tap, main axis C-axis interpolation. Normally sets main axis position loop gain.	1	200
sv050	PGN2sp	Set together with SV058:SHGCsp if SHG control is carried out during special operation, e.g with synchronous tap, main axis C-axis interpolation. Set to zero when not in use.	0	999
SV051		Must be set to zero.		
SV052		Must be set to zero.		
SV053	OD3	Sets excessive error detection range for special operation. e.g., absolute position initial setting or at machine end stopper method. With a setting of zero, excessive error detection does not take place when the servo is ON during special operation.		32767
svo54		Must be set to zero.	0	5000
sv056	EMGC	Sets time in ms from start of deceleration control to application of dynamic braking. Normally set to same value as SV056:EMGt. A setting of zero is taken as an input of 2,000 ms. Set to 1 if dynamic braking is selected without deceleration control. Dynamic braking selection takes precedence over position loop step stopping. For axes with brakes, select position loop step stopping or dynamic braking. This parameter's time setting must be larger than that of SV048:EMGrt. Sets time taken to stop from maximum rapid traversing speed (RAPID: axis configuration parameter) following an emergency stop (caused by an external emergency stop input, insufficient voltage, or alarm).		5000
SV057	SHGC	From other speeds, deceleration control takes place in direct proportion to the parameter setting. Normally set to same value as rapid traverse time constant. A setting of zero sets position loop step stopping. Reset NC power supply after changing RAPID (axis configuration parameteri. Set together with SV004:PGN2 when SHG control is used.	0	999
54037	J	Set to zero when not in use.	•	
SV058		Set together with SV050:PGN2sp if SHG control is used during special operation, e.g., with synchronous tap, main axis C-axis interwlation.		
SV059		Must be set to zero.		
SV060		Must be set to zero.		
SV061	DAINO	Sets output data number of D/A output channel.	0	7
SV062		Must be set to zero.		
sv063	DA1MPY	Sets output amplification rate of D/A output channel. Output amplification rate = setting value / 256. A setting of zero is taken as a setting value of 256 (output amplification rate = 1).	-32768	32767
SV064		Must be set to zero.		

MDS-A-SVJ Motor Types

3.2 Motor Types

Set the mtyp value for SV025:MTYP in accordance with the following tables.

Motor series	NC motor 2,000 rpm (standard)						NC motor 3,000 rpm (special)	General- purpose, low-capac ity, low-
Number	0×	1x	2×	3x	4×	5x	6×	inertia 7x
x0	HA40N							HA-FE/ FH43
×1	HA80N						1	HA-FE/ FH63
x 2	HA100N							11.05
x 3								
x4	†							,
x5	 							1
x 6					1			
x 7					†		1	
x 8								
×9			··· •·· •		 			
хA					 			
хB				-				
хC								HA-FE/ FE053
жD			· · · · · · · · · · · · · · · · · · ·					HA-FE/ FH13
жE							HA23N	HA-FE/ FH23
хF							HA33N	HA-FE/ FH33
Motor series	NC motor 3,000 rpm (standard)	General- purpose, low-capac- ity, extra-low-						
		extra-low- inertia						
Number	8×	9×	Ах	Bx	Cx	Dx	Ex	Fx
ж0	HA43N	HA-ME43						
x1	HA83N	HA-ME73						
x 2								
x 3								
х4								
x 5								
x 6								
x 7								
x 8								
×9								
хA	наязи							
хB								
хC	HA053	HA-ME053						
жD	HA13	HA-ME13		1				
		1	i	1		1		7
×Ε	İ	HA-ME23		1.				

MDS-A-SVJ
Detector Types/Regeneration Resistors

3.3 Detector Types

international states

Set the etyp value for SV025:MTYP in accordance with the following table.

Number	Detector system	Motor type (detector type)	Detector	RNG1/2 setting	Remarks
00	ABZ + WW (with OHM)	HA**N-E30	25000	25	
	High-speed serial	HA**N-E33	25000	25	
11	No setting	•	•		
22	High-speed serial	HA**N-E33	25000	25	
		HA**N-A33	25000	25	
		HA-FH	8000	8	
33	ABZ + ww (without	HA053/13-E30	10000	10	
	OHM)	HA-FE	4000	4	-
		HA-ME	4000	4	

3.4 Regeneration Resistors Types

Connectable regeneration resistor combinations depend on the servo amp capacity, as shown in the following table. Set SV036:PTYP to the number corresponding to the regeneration resistor combination that is connected.

Regenera- tion resistor type	Connection arrangement	Total resis- tance	Regen- erative capac- ity	SV036	MDS- A-SVJ-01	MDS- A-SVJ-03	MDS- A-SVJ-06	MDS- A-SVJ-10	MDS- A-SVJ-20
No resis- tor				1000	0				
MR-RB013	1	52 Ω	18 W	1100	0	0	0		
MR-RB033	1	52 Ω	36 W	1200	0	0	0		
	2 X paral- lel	26 Ω	72 W	1200				0	
	4 × paral- lel	13 Ω	144 W	1200					0
MR-RB064	1	26 Ω	72 W	1300				0	0
	2 × paral- lel	13 Ω	144 W	1300					0
	2 X serial	52 Ω	144 W	1F00	0	0	0		
MR-RB34	1	26 Ω	300 W	1400				0	0
	2 x paral- lel	13	Ω 600	W 1400					0
MR-RB063	1	52	Ω 72 τ	1500	0	0	0		
	2 x paral- lel	26	Ω 144	w 1500				0	0
	4 x paral-	13 🕻	288 v	1500					0

(NOTE) \odot : Standard resistor selection; 0: Possible resistor selection.

* Resistor selection: If the servo is used on a vertical axis, select resistors of one or two grades higher than the standard selection.

MDS-A-SVJ D/A Output

3.5 D/A Output Channel

La horista

The servo amp has one monitor output channel for servo adjustment purposes. This output is provided via a special connector at the top of the amp's front panel.

D/A output specifications are as follows:

Number of channels :1

Resolution : 7 bits (full-scale 128 resolution)

Output voltage range : 0 to 10 V

Sampling cycle : 3.55 ms

Set SV061:DA1N0 in accordance with the following table.

Number	Description	Unit	Number	Description	Unit
0	Speed feedback	rpm	4	Speed feedback	rpm
1	Current command (torque command)	% of rating	5	0 output	
2	Current command (torque command)	% of rating	6	Position droop (lower)	inter- polation unit
3	Current feedback (actual torque)	% of rating	7	Position droop (upper)	unit

The output voltage is determined according to the formula below. To alter the output voltage, adjust the output amplification rate. Note that if SV063 is zero, the output is determined on the assumption that this parameter is set to 256.

Data
$$\times \frac{SV063}{256} \times \frac{10}{256} + 5.00 = \text{output voltage [V]}$$

Example: With settings of SV061 = 0 and SV063 = 8 and a motor speed of 3,000 rpm, the output voltage is as follows:

$$3000 \times \frac{8}{256} \times \frac{10}{256} + 5.00 = 8.66 \text{ [V]}$$

MDS-A-SVJ Electronic Gearing

3.6 Electronic Gearing

By correctly setting the ball screw lead, step-down ratio, step-up ratio, and detector resolution, it is possible to make amounts of machine movement consistent with those required by commands. The matching of these two amounts of movement is termed electronic gearing and determined by the following parameters:

Parameters Related to Electronic Gearing:

SV001 : PC1 SV018: PIT svoo2 : PC2

SV019 : RNG1

SV020 : RNG2

Set the machine constant such that the reduced numerator and denominator are less than 32767. If this condition is not satisfied, an alarm 37, abnormal parameter number 2301 (101 with M500-type NCs) will be output.

ELG1 < 32767, ELG2 < 32767

ELG1 is a reduction of PC2 X RANG PC1 X PIT X IUNIT

Note that RANG = RNG1 = RNG2.

A STATE OF

IUNIT is related to the interpolation unit as follows:

0.5 μ m : IUNIT = 2, 0.05 μ m: IUNIT = 20

MDS-A-SVJ
Parameter Changes/Command Polarity

3.7 Parameter Changes

For safety, parameters must be changed with the system in an emergency stop condition. The time at which parameter changes become effective depends on the parameter. For details, refer to the Servo Parameters table. Changes to parameters marked "Initial" in the Servo Parameters table are effective the next time the controller power is switched ON. Changes to parameters with no "Initial" entry are effective immediately.

3.8 Command Polarity

🕶 Walena 🚶

With commands executed in the + direction, the motor direction (and thus the command direction) is termed

CW if the motor turns clockwise and CCW if the motor turns counter-clockwise, as seen from the load side.

The direction of rotation can be changed using the controller parameters. Note that with some parameters, the +/- motor direction relationship is reversed. Servo parameters that are affected by the CW/CCW direction are as follows:

SV016:LMC1 SV041:LMC2

(assuming different values other than zero are set for SV016 and SV041) $\label{eq:sv041}$

Standard Parameters

3.9 Standard Parameters by Motor Type

يامارا فيمام والمجولا

Motor	HA40N	HA80N	HA100N	HA053	HA13	HA23N	наззи	HA43N	HA83N	HA93N
Amp capacity	06	10	20	01	01	03	03	06	10	20
SV001	-		-	-						-
SV002			_	-		-	-	_		
SV003 SV004	33	33	33	33	33	33	33	33	33	33
SV004 SV005	100	100	150	70	70	70	70	100	100	150
SV006		0	0	0	0	0	0	0	0	0
SV007	0	0	0	0	0	0	0	0	0	0
SV008	1364	1364	1364	1364	1364	1364	1364	1364	1364	1364
SV009 SV010	2048	2048 2048	2048 2048	2048 2048	2048	2048	2048 2048	2048 2048	2048	2048 2048
SV010	512	512	256	256	256	256	256	256	256	256
SV012	512	512	512	256	256	256	256	512	512	512
SV013	500	500	500	500	500	500	500	500	500	500
SV014	500	500 0	500	500	500	500 0	500	500	500 0	500
SV015 SV016	0	0	0	0		0	0	0	0	0
SV017	0000	0000	0000	0000	0000	0000	0000	0000	0000	0000
SV018	-	-	-	-	-			-		
SV019	25	25	25	10	10	25	25	25	25	25
SV020	25	25 60	25 60	10 60	10 60	25 60	25 60	25 60	25 60	25 60
SV021 SV022	60 150	150	150	150	150	150	150	150	150	150
SV023			-	-			-			
SV024	50	50	50	50	50	50	50	50	50	50
SV025	x x00	xx01	xx02	338C	338D	xx6E	xx6F	xx80	xx81	A8xx
SV026 SV027	4000	4000	4000	4000	4000	4000	4000	4000	4000	4000
SV027	4000	4000	2000	4000	4000	0	4000	000	4000	000
SV029	0	0	Ö	0	0	0	0	0	0	0
SV030	0	0	0	0	0	0	0	0	0	0
SV031	0	0	0	0	0	0	0	0	0	0
SV032 SV033	0000	0000	0000	0000	0000	0000	0000	0000	0000	0000
SV033	0000	0000	0000	0000	0000	0000	0000	0000	0000	0000
SV035	0000	0000	0000	0000	0000	0000	0000	0000	0000	0000
SV036	1100	1200	1200	1000	1000	1100	1100	1100	1200	1200
SV037	0	0	0	0	0	0	0	0	0	0
SV038 SV039	0	0	0	0	0	0	0	0	0	- 0
SV040	Ö	0	Ö	0	0	0	- 0	Ö	0	ō
SV041	0	0	0	0	0	0	0	.0	0	0
SV042	0	0	0	0	0	0	0	0	0	0
SV043 SV044	0	0	0	. 0	0	Ó	0	0	0	0
SV044	- 0	0	0	0	0	0	0	0	0	0
SV046	0	0	0	ő	- 0	0	0	0	ō	0
SV047	100	100	100	100	100	100	100	100	100	100
SV048	0	0	0	0	0	0	0	0	0	0
SV049 SV050	15	15	15	15	15	15	15	15	15	15
SV050	0	0	0	0	0	0	0	0	0	0
SV052	0	0	0	0	0	0	0	0	0	0
SV053	0	0	0	0	0	0	0	0	0	0
SV054	0	0	0	0	0	0	0	0	0	0
SV055 SV056	0	0	0	0	0	0	0	0	0	0
SV056	0	0	0	0	0			0	0	0
SV058	0	0	0	0	0	Ö	Ö	0	_ 0	0
SV059	0	0	0	0	0	0	0	0	0	0
SV060	0	0	0	0	0	0	0	0	0	0
SV061 SV062	0	0	0	0	0	0	0	0	0	0
SV062 SV063	0	0	0	0	0	0	0	- 0	1 0	0
SV064	0	0	0	0	0	0		0	0	0

(NOTE) Parameters marked "-" are determined according to the machine configuration.

Motor	HA-FE053 (HA- FH053)	HA-FE13 (HA- FH13)	HA-FE23 (HA- FH23)	HA-FE33 (HA- FH33)	HA-FE43 (HA- FH43)	HA-FE63 (HA- FH63)				
Amp capacity	01	01	03	03	06	06				
SV001			-							
SV002			-							
SV003	33	33	33	33	33	33				
SV004 SV005	15	15	15	15	15	15				
SV005	0	0	0	0	1.0	0				
SV007	- 6	0	0	0	0	0				
SV008	1364	1364	1364	1364	1364	1364				
SV009	2048	2048	2048	2048	2048	2048				
SV010	2048	2048	2048	2048	2048	2048				
SV011	256	256	512	512	768	768				
SV012	256	256	512	512	768	768				
SV013	500	500	500	500	500	500				
SV014	500	500	500	500	500	500				
SV015	0	0	0	0	0	0				
SV016	0	0	0	0	0	0				
SV017	0000	0000	0000	0000	0000	0000				
SV018	-			- 4 (0)		- 4 (0)				
SV019	4(8)	4 (8)	4(8)	4(8)	4(8)	4(8)				
SV020	4(8)	4(8)	4(8)	4(8)	4(8)	4(8)				
SV021	60	60	60	60	60	60				
SV022	150	150	150	150	150	150				
SV023 SV024	50	50	50	50	50	50				
SV025	337C	337D	337E	337F	3370	3371				
30023	(227C)	(227D)	(227E)	(227F)	(2270)	(2271)				
SV026	-				<u> </u>					
SV027	4000	4000	4000	4000	4000	4000				
SV028	0	0	0	0	0	0				
SV029	ō	0	0	0	Ö	0				
SV030	0	0	Ö	0	0	0				
SV031	0	0	0	0	0	0				
SV032	0	0	0	0	0	0				
SV033	0000	0000	0000	0000	0000	0000				
SV034	0000	0000	0000	0000	0000	0000				
SV035	0000	0000	0000	0000	0000	0000	}			
SV036	1000	1000	1100	1100	1100	1100				
SV037	0	0	0	0	0	0				
SV038	0	0	0	0	0	0				
SV039	0	0	0	0	0	0				
SV040	0	0	0	0	0	0				
SV041	0	0	0	0	0	0				
SV042 SV043	0	0	- 0	0	0	0				
SV043	0	0	0	0	0	0	 			
SV045	0	- 0	0	- 6	0	0	 			
SV046	6			1 0	 		 			
SV047	 	0	- 0	0	ŏ	0	 			
SV048	Ö	Ö	Ö	Ö	0	ō	 			
SV049	15	15	15	15	15	15				
SV050	0	0	0	0		0	1			
SV051	0	0	0	0	0	0				
SV052	0	0	0	0		0				
SV053	0	0	0	0	0	0				
SV054	0	0	0	0	0	0				
SV055	0	0	0	0	1	0				
SV056	0	0	0	0		0			ļ	
SV057	0	0	0	0	1	0	L			
SV058	0	0	0	0		0	<u> </u>			
SV059	0	0	0	0	1	0				
SV060	0	0	0	0	J	0	ļ			ļ
SV061	0	0		0		0	 		ļ	
SV062	0	0	1	0		0		 		
SV063	0	0	4	0		0	1		 	
SV064	0	0	1	1 0	0	0	<u> </u>	1		

 \cdot (NOTE) Parameters marked "-" are determined according to the machine configuration.

MDS-A-SV	J
standard	Parameters

Motor	HA-ME053	HA-ME13	HA-ME23	HA-ME43	HA-ME73	1	· · · · · · · · · · · · · · · · · · ·			
Amp				03	06					
capacity	01	01	03	03						
SV001	-		-							
SV002	-		-	-						
SV003	33	33	33 0	33	33		·			
SV004 SV005	8	8	8	8	8					
SV005	0	0	0	0	0					
SV007	0	0	0	0	0					
SV008	1364	1364	1364	1364	1364					
SV009	2048	2048	2048	2048	2048					
SV010	2048	2048	2048	2048	2048					
SV011	256	256	512	512	512 512					
SV012 SV013	256 500	256 500	512 500	512 500	500					
SV013	500	500	500	500	500					
SV015	0	0	0	0	0					
SV016	0	0	0	0	0					
SV017	0000	0000	0000	0000	0000					
SV018			-	-	•	`				
SV019	4	4	4	4	4					
SV020	4	4	4	4	4					
SV021 SV022	60 150	60 150	60 150	60 150	60 150					
SV022	- 130	- 130	130	-	-					
SV024	50	50	50	50	50					
SV025	339C	339D	339E	3390	3391		-			
SV026		-	-	-	-					
SV027	4000	4000	4000	4000	4000					
SV028	0	0	0	0	0					
SV029	0	0	0	0	0					
SV030 SV031	0	0	0	0	0					
SV032	0	0	- 6	 	0					
SV033	0000	0000	0000	0000	0000					
SV034	0000	0000	0000	0000	0000					
SV035	0000	0000	0000	0000	0000					
SV036	1000	1000	1100	1100	1100				ļ	
SV037	0	0	0	0	0					-
SV038	0	0	0	0	0					
SV040	0	0	- 0	0	0					 -
SV041	0	 	- 0	0	0					
SV042	0	ō	0	0	0					1
SV043	0	0	0	0	. 0					
SV044	0	0	0	0	0					
SV045	0	0	0	0	0		 			
SV046	0	0	0	0	0				ļ	
SV047 SV048	0	0	0	0	- 0	-	· · · · · ·			
SV048	15	15	15	15	15			 	 	
SV050	0	0	0	0	0					
SV051	0	0	0		0					
SV052	0	0	0	0	.0					
SV053	0	0	0						<u> </u>	
SV054	0	0	0	0	0				ļ	ļ
SV055	0	0	0		0			 		
SV056	0	0	1		1			 	-	
SV057	- 0	0	1		0	 		 	 	1
SV059	0	0			0				<u> </u>	
SV060	0	0	0	41	0					
SV061	0	0	0		.1					
SV062	0	0	1		I				ļ	1
SV063	0	0			4			ļ	-	
SV064	0	0	0	0	0	<u> </u>	l	1	<u> </u>	<u> </u>

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(NOTE) Parameters marked "-" are determined according to the machine configuration.

MDS-A-SVJ

Servo Alarms & Warnings

4. Servo Alarms and Warnings

and supplying the

Num- ber	Abbrevi- ation	Name	Stopping method		ber	Abbrevi- ation	Name	Stopping method	Reset
10	υv	Amp insufficient	Decel-	PR	40				
		voltage	eration		41				
-,-			control		42	FE1	Feedback error	Decel- eration	PR
11	ME	Memory error	Initial	AR				control	
12	ME	Memory error	error	AA	43				-
13	SWE	S/W error	Dynamic	PR	44				
14					45				1
15					46	OHM	Motor overheat	Decel-	NR
16	RD1	Magnetic pole posi-	Decel-	PR				eration	1 1
		tion detection error	eration					control	
1.			control		47			ļ	1
17 18	ADE RD2	A/D converter error Serial detector • ini-	Dynamic Initial	PR PR	48			 	├
10	KD2	tial communication	error	FR	4A				1
		error			4B				1
19	-				4C				
1A					4D				
1B					4E				
1C				l	4F				ļ. <u></u>
1D					50	OL1	Overload detection 1	Decel- eration	NR
1E 1F	PIDE	Power P board ID	Initial	AR				control	1 1
11	FIDE	error	error	, AA	51	OL2	Overload detection 2	Dynamic	NR
20	NS1	No feedback signal	Dynamic	PR	52	OD1	Excessive error 1	Dynamic	NR
21					1		(servo ON)]	
22					53	OD2	Excessive error 2	Dynamic	NR
23					<u> </u>		(servo OFF)		
24					54				
25	1000		*****	- 10	55				1
26	ABSE	Absolute position lost	Initial error	AR	56	ļ		 	
27		1032	error		58			 	
28			 	 	59			ł	
29			 	 	5A			· -	<u> </u>
2A					5в		I	i	†
2B	SMEN	'Seria etector . CPU	Initia	AR		1	-		a
		error	error		5D		<u> </u>	ļ	
2c	SDAT	Serial detector . data	Dynamic	PR	5E			<u> </u>	i
2D	SLED	error	Domania	PR	61	1	1	1	
20	מפתפ	Serial detector .data	Dynamic	FK	62			 	
2E		62262		İ	63	 -	1	 	1 -
2F	STRE	Serial detector • com-	Dynamic	PR	64			1	
		munication error	-		65			1	
30	OR	Over-regeneration	Decel-	PR	66				
İ			eration	i	67				
<u></u>			control		68		ļ <u>.</u>	_	
31	os	Overspeed	Decel- eration	PR	69 6A			\	1
1	ĺ	{	control		6B	 			
32	PMOC	Power module error	Dynamic	PR	6C	 	 	 	
"		(excessive current)	-3		6D			 	
33	ov	Excessive voltage.	Dynamic	PR	6E	 		 	T
34	DP	CRC error	Decel-	PR	6F	T			
	1		eration	1	70				
	<u> </u>		control		71				
35	DE	Data error	Decel-	PR	72			1	
	1		eration	1	73	ļ			
36	TE	Communication error	Decel-	PR	75	 	 	 	+
1 30	1	COMMUNICACION CITOR	eration	FR	76	 	 	+	+
1		1	control	1	77	 		 	+
37	PE	Initial parameter	Initial	PR	78	 		T	1
		error	error		79				
38	TP1	Protocol error 1	Decel-	PR	7A	<u> </u>			
	1		eration	(7B			1	
<u> </u>	1	D-14-2-3	control		7C	ļ		1	
39	TP2	Protocol error 2	Decel- eration	PR	7D	 	 	 	-
]	control	1	7E 7F	 	 	+	
3A	l oc	Excessive current	Dynamic	PR	80	1	 	+	+
3B	PMOH	Power module error	Dynamic	PR	81	 	1	 	+
1		(overheat)		1	82	 	1	1	
3C					83			I	
35	T		1	1	84	1			1
3D	1	<u> </u>					<u> </u>		
3E 3F			1		85				

MDS-A-SVJ				
Servo	Alarms 8	ç	Warnings	

Num- ber	Abbrevi- ation	Name	Stopping method	Reset	Num- ber	Abbrevi- ation	Name	Stopping method	Reset
87									<u> </u>
88	WD	Watchdog	Dynamic	AR					
89									<u> </u>
8A									<u> </u>
8B	1 1								<u> </u>
8C									<u> </u>
8D									
8E					L				
8F						l			

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BNP-B3882B

	bbrevi- I	Name	Reset		Abbrevi- ation	N a m e	Reset
ber 90	ation			Der	acton	Servo OFF	
91				CE		bervo orr	
92				CF			
93	WAM	Initial absolute position	PR	DO	U	Servo ON	
		2 latenil+sm.		D1			#1
94				D3			#2
. 96			 	D4			# 3
97			+	D5			άe
98				D6			#6
99				7ס			#7
9A				D8			
9B			ļ	<u>D9</u>	l		\vdash
9C 9D		-	 	DA DB			
9E	WAR		*	DC			
72	WZIIC	lution counter error		DD			
9F	WAB	LOW battery voltage	*	DE			
A0			 	DF	1100	Over meaning	+ +
A1			 	E0 E1	WOR WOL	Over-regeneration warning Overload warning	+ +
A2			 	E2	WOL	Overioad warning	+
A3 A4			+	E3	WAC	Absolute position counter	*
A5			1	1		warning	
A6				E4	WPE	Parameter error warning	*
A7				E5			-
8A				E6	AXE	Controlled axis removed warn- ing	"
A9		Initial communication • wait-	+	E7	NCE	External emergency stop	+
AA		ing for phase 1 (controller		E8	INCE	Excelled emergency scop	-
1		OFF)	}	<u> </u>			
AB		Initial communication • wait-	1	EA			
1		ing for phase 1	<u> </u>	EB			
AC		Initial communication • wait-	1	EC			
ļ		ing for phase 2		ED			
AD	İ	Initial communication • wait- ing for phase 3	1.	EF	 		1
AE		Initial communication • wait-	+	FO	 	Alarm • warning controlled	1
^E		ing for phase 4	1	F1	i	axis display	#1
AF		Reserved		F2	1		#2
В0		Ready OFF		F3			#3
B1]		#1	F4	4		#4
B2	4	·	#2	F5	-		#6
B3 B4	4		#4	F7	1		#7
B5	1		#5	F8	1		
B6	1		#6	F9	1		
B7	1		#7	FA	1		
B8]			FB			
В9]		<u> </u>	FC	4		
BA	4		<u> </u>	FD	4		
BB	· ·	Î		FF	┪		-
BD			 	100	1		
BE	1	· ·		01	1	Flash programming error	+
BF	1			02]	Flash deletion error	
€6	·	Servo OFF		03		Vpp error	
C1	!		#1	04	-	Check sum error	
62	1		#2	05	During	Compare error	
C3	-		#4	07	soft-		
C5	ή		#5	08	ware	Bank designation error	
<u>C6</u>	1		#6	09	ewrit- ing	Initial address error	
	7		#7	A0		Bank switching error	
C7				0B	i .	Address error	
C8	1				-		
C8	1			0C	1	Receipt timeout	
C8 C9 CA				OC OD	-		
C8				0C	- - -		

(NOTE) NR: Reset executed by controller reset command;

.. e .:*.

PR: Reset executed by turning controller power OFF;

AR: Reset executed by turning servo amp power ${\tt OFF.}$

MDS-A-SVJ Alarm Descriptions

4.1 Alarm Descriptions

Num- ber	Abbrevi- ation	Name	Description	stop- ping method	Reset
10	υv	Amp insufficient voltage	Servo amp's internal PN power supply voltage is too low. Servo amp waits for initial controller communication. No record is kept of this alarm.	Decel- eration control	PR
12	ME	Memorv error	Error detected in memory IC/FB IC during self- diagnostic checks after servo amp power ON. No record is kept of this alarm.	Initial error	AR
13	SWE	S/W error	Software data processing not completed within designated time.	Dynamic	PR
16	RD1	Magnetic pole posi- tion detection error	Abnormality detected in UVW phase of magnetic pole position detection signal (with HA**N-E30, HA053, HA13, HA-FE, or HA-ME).	Decel- eration control	PR
17	ADE	A/D converter error	Abnormality found in current detection A/D converter during self-diagnostic checks after servo amp power ON.	Dynamic	PR
18	RD2	Serial detector . initial communication error	Initial communication with detector cannot take place (with HA**N-E33, HA**N-A33, or HA-FH).	Initial error	PR
1F	PIDE	Power P board ID arror	Servo amp internal power unit is SVJ-type.	Initial error	AR
20	NS1	No feedback sional	Feedback signal lost (with HA**N-E30, HA053, HA13, HA-FE; or HA-ME).	Dynamic	PR
25	ABSE	Absolute position lost	Low voltage on absolute position detector's internal backup battery. can't guarantee accuracy of absolute position.	Initial error	AR
2B	SMEN	Serial detector . CPU error	Error detected in data in detector's internal EEPROM (with HA**N-E33, HA**N-A33).	Initial error	AR
2C	SLED	Serial detector .LED error	Deterioration sensed in detector LED (with HA**N-E33 or HA**N-A33).	Dynamic	PR
2D	SDAT	Serial detector . data error	Abnormality sensed in detector's internal position control in one revolution (with HA**N-E33 or HA**N-A33).	Dynamic	PR
2F	STRE	Serial detector . communication error	Communication with detector interrupted (with HA**N-E33, HA**N-A33, or HA-FH).	Dynamic	PR
30	OR	Over-regeneration	Overheating in regeneration resistors detected. Cannot be reset if regeneration load is over 40%. Do not force-reset by turning servo amp power OFF and ON.	Decel- eration control	PR
31	os	Overspeed	Motor speed detected in excess of motor's permissible speed (1.2 X maximum motor speed).	Decel- eration control	PR
32	PMOC	Power module error (excessive current)	Excessive current detected by IPM used with inverter.	Dynamic	PR
33	ov	Excessive voltage	Excessive voltage detected on servo amp's internal PN power supply.	Dynamic	PR
34	DP	CRC error	Error detected in data sent from controller to servo amp.	Decel- eration control	PR

MDS-A-SVJ	
Alarm	Descriptions

Num- ber	Abbrevi- ation	Name	Description	Stop- ping method	Reset
35	DE	Data error	Error detected in movement command data sent from controller.	Decel- eration control	PR
36	TE	Communication error	Communication from controller interrupted. Dece eraticontr		PR
37	PE	Initial parameter error	Illegal parameter detected in parameters sent following controller power ON.		PR
38	TP1	Protocol error 1	Error detected in communication frame sent from controller. Deceration		PR
39	TP2	Protocol error 2	Error detected in axis status data sent from controller.	Decel- eration control	PR
3A	oc	Excessive current	Excessive level detected in motor drive current.	Dynamic	PR
3B	РМОН	Power module error (overheat)	Overheating detected in IPM used with inverter.	Dynamic	PR
42	FE1	Feedback error	Missing feedback pulse or abnormality in Z phase detected (with HA**N-E30, HA053, HA13, HA-FE, or HA-ME).		PR
46	ОНМ	Motor overheat	Thermal protector operated in motor or detector.	Decel- eration control	NR
50	OL1	Overload detection 1	Overload detection level current (SV022:OLL) flowed for overload time constant period (SV021:OLT), or load exceeded motor rating. Cannot be reset if load level is over 40%.	Decel- eration control	NR
51	OL2	Overload detection 2	detection 2 Current command of more than 95% of servo amp's maximum capacity continued for over 1 second.		NR
52	OD1	Excessive error 1 (servo ON)	With servo ON, discrepancy between ideal position and actual position exceeded parameter SV023:0D1 (or SV053:0D3).		NR
53	OD2	Excessive error 1 (servo OFF)	With servo OFF, discrepancy between ideal position and actual position exceeded parameter SV026:0D2.		NR
88	WD	Watchdog	Servo system not functioning normally.	Dynamic	AR'

MDS-A-SVJ
Warning Descriptions

4.2 Warning Descriptions

age to extend the 1840

Num- ber	Abbrevi- ation	Name	Description	Reset
93	MAM	Initial absolute posi- tion fluctuation Position moved by more than permissible amount from absolute position detected at controller power ON.		PR
9E	WAR	Serial detector • mul- ti-revolution counter error	Abnormality detected in multi-revolution counter; can't guarantee accuracy of absolute position (with HA**N-A33).	•
9F	WAB	Low battery voltage	Low voltage detected on absolute position detector battery.	•
EO	WOR	Over-regeneration warn- ing	Regeneration of 80% of over-regeneration alarm level detected.	•
El	WOL	Overload warning	Loading of 80% of overload alarm level detected.	*
E3	WAC	Absolute position counter warning	Discrepancy detected between absolute position and relative position; can't guarantee accuracy of absolute position.	•
E4	WPE	Parameter error warning	Parameter setting detected outside permissible range.	*
E6	AXE	Controlled axis removed warning	Controlled axis removed.	*
El	NCE	External emergency stop	External emergency stop input received.	*

MDS-A-SVJ			
Error	Parameter	Numbers	

4.3 Initial Parameter Error Numbers

Whenever an initial parameter error (alarm 37) occurs, the parameter causing the error is identified on the controller's diagnostic screen. Note that the format in which erroneous parameters are displayed differs according to the controller. For details, please refer to the relevant instruction manual. Parameter numbers are as follows:

Parameter Numbers

M500-type CNC

:1 to 64

MSO-type CNC, machine controller model N

:2201 to 2264

If and when an initial parameter error occurs, first check the parameter setting range. If the setting is within the permissible range, the cause of the error is probably as shown below.

Number		Probable cause
M500	M50	
19	2219	Detector resolution setting does not match currently connected detector. (If detector is incremental type, also check SV025.)
20	2220	SV020 setting value does not match SV019.
25	2225	Motor type setting is for motor type that is not recognized. Detector type designation is incorrect. Absolute position system is set with detector type setting of 00. Motor type HA053 or HA13 is set with detector type setting of 00 (should be 33).
27	2227	Lost motion correction types 1 and 2 are enabled simultaneously.
36	2236	Regeneration resistor type setting is for regeneration resistor that is not recognized.
55	2255	SV055 setting value (input of 0 is taken as 2000) is smaller than SV048 setting value.

Parameter errors with the numbers shown below are caused by more than one parameter.

Number		Probable cause	Related parameters
M500	M50	1	1
101	2301	Electronic gearing constant is greater than machine constant. Check that all related parameters are set correctly.	SV001:PC1, SV002:PC2, SV018:PIT SV019:RNG1, SV020:RNG2
102	2302	Absolute position detection parameter is ON with HA**N-E33 connected. Turn absolute position detection parameter OFF. To carry out absolute position detection, replace incremental-type detector with absolute position-type.	SV017:SPEC, SV025:MTYP

MDS-A-SVJ 100V Servo Amps

4.4 100V Servo Amps

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A low power supply voltage can limit maximum operating capacity.

The MDS-A-SVJ-OIW (100W) and MDS-A-SVJ-03W (300W) normally have an instantaneous operating capacity of 300% of the rated motor output (excluding HA**N motors). If the power supply voltage is below 90V, however, the MDS-A-SVJ-03W's maximum instantaneous operating capacity is limited to 4.75A (250% of the HA-FE33's rated output). With this limitation, excessive error 1 (OD1) alarms are liable to occur. To prevent excessive error 1 alarms, increase the excessive error detection range settings (SV023 and SV053).

Note that the MDS-A-SVJ-01W (100W) is not thus affected.

<<NOTE>> The MDS-A-SVJ-OlW and MDS-A-SVJ-03W are designed for use with a single-phase, 100V power supply. Never apply a 200V power supply. Use of a 200V power supply would damage the amp.

vision number	Date of revision (S/W)	Details of revision
	'95- 2-27 (B4)	First edition of manual released.
A	' 95- 6-23 (CO)	Servo parameters added. Regeneration Resistor Types table created. D/A output specifications and output voltage calculation formula added. Causes of initial parameter errors grouped according to error parameter number.
В	'95- 1-26 (C1)	Electronic Gearing notes (section 3.6) revised. Front cover title changed from *Mitsubishi Personal Machine Controller" to Mitsubishi AC Servo.