



DS2-AS series servo drive

User manual

Xinje Electric Co., Ltd.

Serial No. SC02 201205813 1.1

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Safety Precautions

Be sure to review this section carefully before use this product. In precondition of security, wire the product correctly.

The following defines the symbols used in this manual to indicate varying degrees of safety precautions and to identify the corresponding level of hazard inherent to each. Failure to follow precautions provided in this manual can result in serious, possibly even fatal, injury, and/or damage to the persons, products, or related equipment and systems.



CAUTION

Indicates a potentially hazardous situation, which, if not heeded, could result in death or serious injury



WARNING

Indicates a potentially hazardous situation, which, if not avoided, may result in minor or moderate injury.

● Checking Products upon Delivery



CAUTION

1. DO NOT install any drive which is damaged, lack of accessories or not the same with the model ordered.
Doing so may result in electric shock.

● Installation



WARNING

1. Cut off external power supply before installation.
Not doing so may result in electric shock.



CAUTION

1. Always use the servomotor and servo amplifier in one of the specified combinations.
Never use the products in an environment subject to water, corrosive gases, inflammable gases, or combustibles.
Doing so may result in electric shock, fire or malfunction.
2. DO NOT touch any metallic part.
Doing so may result in malfunction.

● Wiring



WARNING

1. Cut off external power supply before wiring.
Not doing so may result in electric shock.
2. Connect AC power supply to the corresponding terminals.
Faulty wiring may result in fire.



CAUTION

1. Do not connect a three-phase power supply to the U, V, or W output terminals.
Doing so may result in injury or fire.
2. Use 2mm² wire to grounding the ground terminals.
Not doing so may result in electric shock.
3. Securely fasten the power supply terminal screws and motor output terminal screws.
Not doing so may result in fire.

● Operation



WARNING

1. Never touch any rotating motor parts while the motor is running.
Doing so may result in injury.
2. DO NOT touch the inside the drive.
Doing so may result in electric shock.
3. Do not remove the panel cover while the power is ON.
Doing so may result in electric shock.
4. Do not touch terminals for five minutes after the power has been turned OFF.
Residual voltage may cause electric shock.



CAUTION

1. Conduct trial operation on the servomotor alone with the motor shaft disconnected from machine to avoid any unexpected accidents.
Not doing so may result in injury.
2. Before starting operation with a machine connected, change the settings to match the parameters of the machine.
Starting operation without matching the proper settings may cause the machine to run out of control or malfunction.
3. Before starting operation with a machine connected, make sure that an emergency stop can be applied at any time.
Not doing so may result in injury.
4. Do not touch the heat sinks during operation.
Not doing so may result in burns due to high temperatures.
5. Do not attempt to change wiring while the power is ON.
Doing so may result in electric shock or injury

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Preface

This chapter describes the constitution of this manual, the intended user, and how to acquire this manual.

Constitution of This Manual

This manual is divided into 7 chapters.

1. Checking Product and Part Names

This chapter describes the procedure for checking products upon delivery as well as names for product parts.

2. Installation

This chapter describes precautions for servomotor and servo drive installation.

3. Wiring

This chapter describes the procedure used to connect DS2-AS Series products to peripheral devices and gives typical examples of main circuit wiring as well as I/O signal connections.

4. Parameter Settings and Functions

This chapter describes the procedure for setting and applying parameters.

5. Use Digital Panel

This chapter describes the basic operation of the digital panel and the features it offers.

6. Ratings and Characteristics

This chapter provides the ratings, torque-speed characteristics diagrams, and dimensional drawings of the DS2-AS series servo drives and MS series servomotors.

7. Alarm Information

This chapter describes the alarm information of DS2-AS series servo drives.

Intended User

This manual is intended for the following users.

- Those designing DS2-AS Series servodrive systems.
- Those installing or wiring DS2-AS Series servodrives.
- Those performing trial operation or adjustments of DS2-AS Series servodrives.
- Those maintaining or inspecting DS2-AS Series servodrives.

How to Acquire This Manual

1. Electrical Manual

- (1) Log on Xinje official website www.xinje.com to download.
- (2) Acquire this manual on a CD from an authorized distributor.

1 Checking Product and Part Names

1-1. Checking Products on Delivery

Use the following checklist when products are delivered.

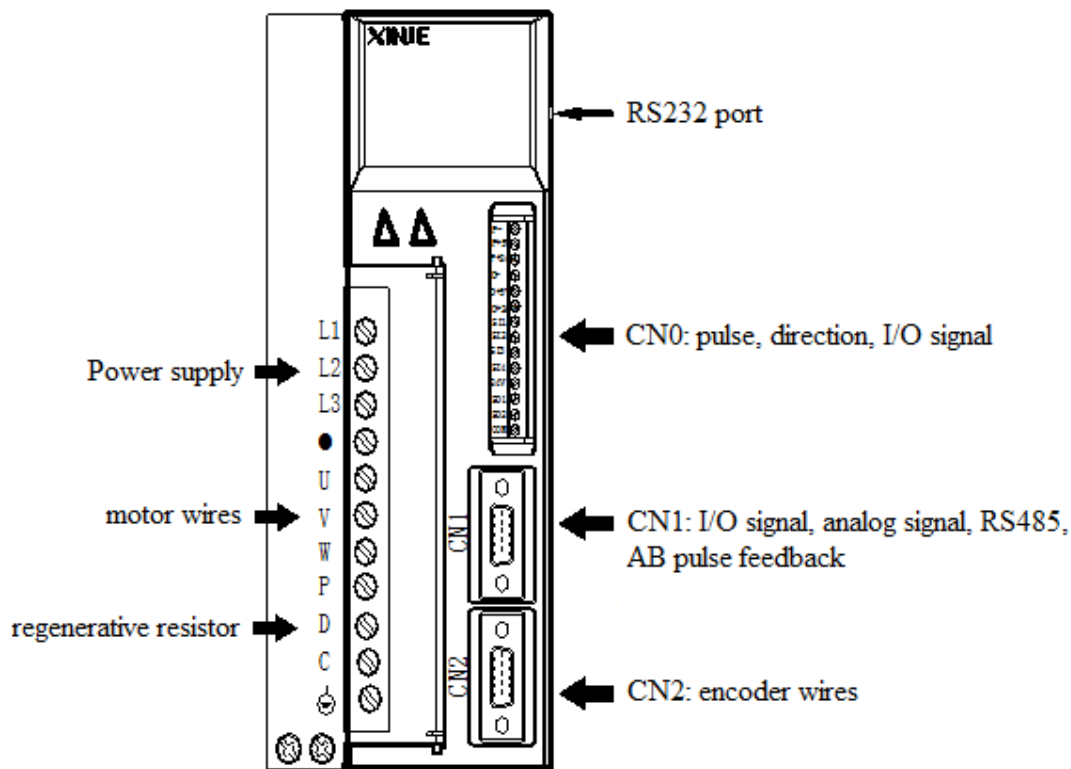
Items	Comments
Are the delivered products the ones that were ordered?	Check the model numbers marked on the nameplates of the servomotor and servo drive.
Does the servomotor shaft rotate smoothly?	The servomotor shaft is normal if it can be turned smoothly by hand. Servomotors with brakes, however, cannot be turned manually.
Is there any damage?	Check the overall appearance, and check for damage or scratches that may have occurred during shipping.
Are there any loose screws?	Check screws for looseness using a screwdriver.
Is the motor code the same with the code in drive?	Check the motor code marked on the nameplates of the servomotor and the parameter F0-00 on the servo drive.

If any of the above is faulty or incorrect, contact Xinje or an authorized distributor.

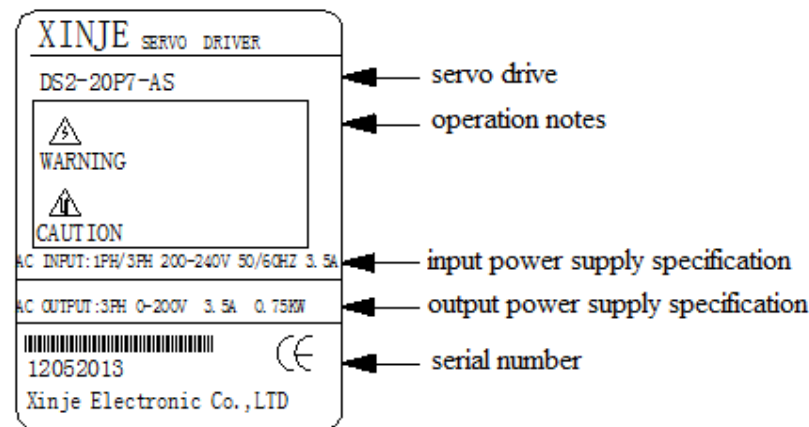
1-2. Product appearance and name rule

■ DS2-2□P□-AS

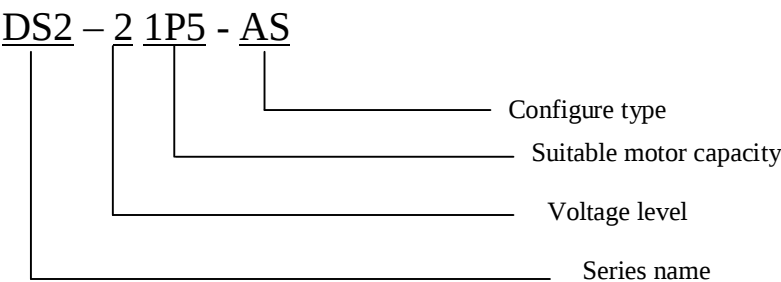
(1) Appearance and nameplate



Servo drive nameplate



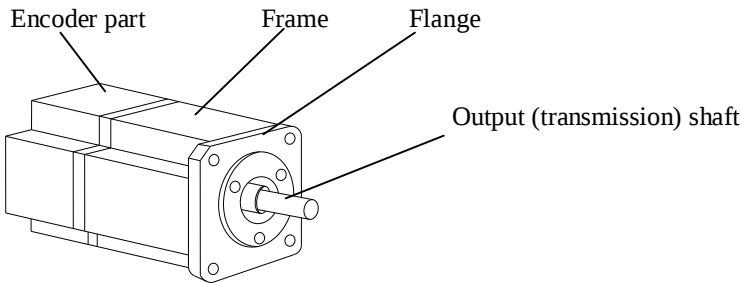
(2) Naming rule



configuration	AS series (differential mode encoder feedback)	
Voltage level	2	220V
	4	380V
Suitable motor capacity	0P2	0.2KW
	0P4	0.4KW
	0P7	0.75KW
	1P5	1.5KW
	2P3	2.3KW

■ Servo motor

(1) Appearance and nameplate



XINJE				
MS-80ST-M02430B-20P7				
KW	N. M	A	rpm	IP
0.7	2.4	3.0	3000	65
MOTOR CODE:0011				
				
DB2012052013				
Xinje Electronic Co., LTD				

servo motor model

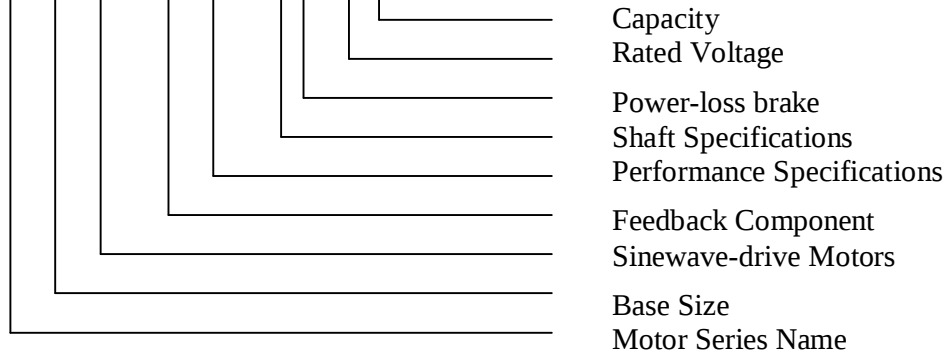
flange, torque, speed, power

motor code

serial number

(2) Naming rule

MS -80 ST - M 02430 A Z- 2 0P7



Base number	60, 80, 90, 110, 130	
Feedback component no.	M	Optical pulse encoder
Performance parameter no.	First 3 bits mean rated torque, last 2 bits mean rated speed Such as: 00630: rated torque 0.6N.m, rated speed 3000rpm 06025: rated torque 6.0N.m, rated speed 2500rpm 19015: rated torque 19.0N.m, rated speed 1500rpm	
Shaft spec	A	No bond
	B	With bond
Power-loss brake	Vacant	No
	Z	With DC99V power-off brake
Voltage level	2	220V
	4	380V
Power	Such as: 0P4: 0.4kW 0P7: 0.75kW 1P5: 1.5KW 2P3: 2.3KW	

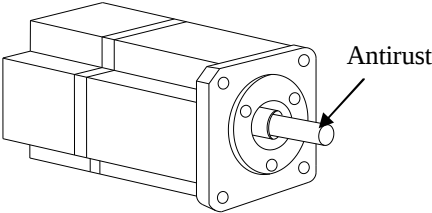
1-3. Adaptation table of servo drive and motor

Servo drive	Motor model	Motor code	Voltage level
DS2-20P2-AS	MS-60ST-M00630-20P2	1003	Single/3 phase 220V
DS2-20P4-AS	MS-60ST-M01330-20P4	0004	
DS2-20P7-AS	MS-80ST-M02430-20P7	0011	
	MS-80ST-M03520-20P7	0012	
	MS-90ST-M02430-20P7	0021	
DS2-21P5-AS	MS-110ST-M04030-21P2	0031	3 phase 220V
	MS-110ST-M05030-21P5	0032	
	MS-130ST-M06025-21P5	0042	
	MS-130ST-M10015-21P5	0044	
DS2-22P3-AS	MS-130ST-M07725-22P0	0043	3 phase 220V
	MS-130ST-M15015-22P3	0046	
DS2-41P5-AS	MS-110ST-M04030-41P2	00131	3 phase 380V
	MS-110ST-M05030-41P5	00132	
	MS-130ST-M06025-41P5	00142	
	MS-130ST-M10015-41P5	00144	

2 Installations

2-1. Servomotor

MS series servomotors can be installed either horizontally or vertically. The service life of the servomotor can be shortened or unexpected problems might occur if it is installed incorrectly or in an inappropriate location. Follow these installation instructions carefully.

 CAUTION
1. The end of the motor shaft is coated with antirust. Before installing, carefully remove all of the paint using a cloth moistened with paint thinner. 2. Avoid getting thinner on other parts of the servomotor.


2-1-1. Storage Temperature

Store the servomotor within $-20\sim+60\text{ }^{\circ}\text{C}$ as long as it is stored with the power cable disconnected.

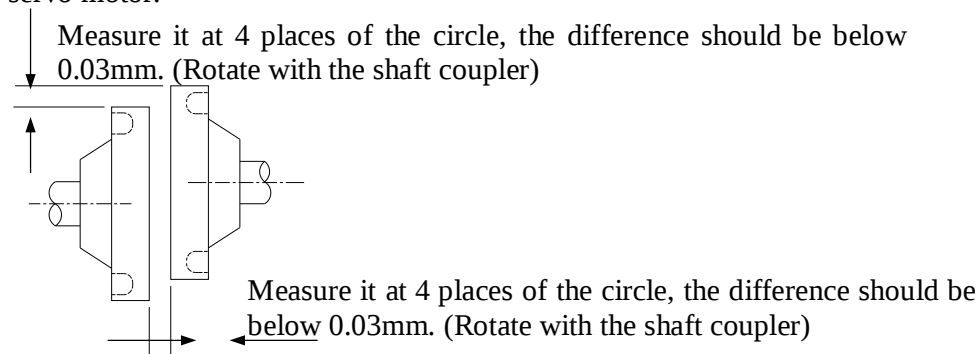
2-1-2. Installation Site

MS series servomotors are designed for indoor use. Install the servomotor in environments that satisfy the following conditions.

- Free of corrosive or explosive gases.
- Well-ventilated and free of dust and moisture.
- Ambient temperature of 0° to 50°C .
- Relative humidity (r.h.) of 20 to 80% with no condensation.
- Accessible for inspection and cleaning.

2-1-3. Concentricity

Please use coupling when connecting to machine; keep the shaft center of servo motor and machine at the same line. It should be accord to the following diagram when installing the servo motor.



Note: (1) If the concentricity is not enough, it will cause the vibration and bearing

damage.

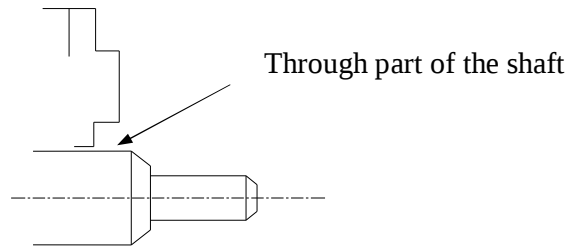
(2) When installing the coupler, prevent direct impact to the shaft. This can damage the encoder mounted on the shaft end at the opposite side of the load.

2-1-4. Orientation

MS series servomotors can be installed either horizontally or vertically.

2-1-5. Handling Oil and Water

Install a protective cover over the servomotor if it is used in a location that is subject to water or oil mist. Also use a servomotor with an oil seal when needed to seal the through-shaft section.



2-1-6. Cable Stress

Make sure that the power lines are free from bends and tension. Be especially careful to wire signal line cables so that they are not subject to stress because the core wires are very thin, measuring only 0.2 to 0.3mm².

2-2. Servo Drive

The DS2-AS series servo drives are compact model. Incorrect installation will cause problems. Follow the installation instructions below

2-2-1. Storage Conditions

Store the servo drive within -20~+85°C, as long as it is stored with the power cable disconnected.

2-2-2. Installation Site

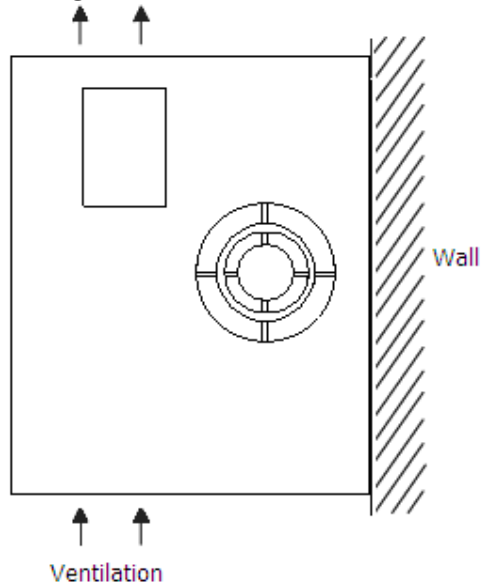
The following precautions apply to the installation site.

Situation	Installation Precaution
Installation in a Control Panel	Design the control panel size, unit layout, and cooling method so the temperature around the servo drives does not exceed 50°C.
Installation Near a Heating Unit	Minimize heat radiated from the heating unit as well as any temperature rise caused by natural convection so the temperature around the servo drives does not exceed 50°C.
Installation Near a Source of Vibration	Install a vibration isolator beneath the servo drive to avoid subjecting it to vibration.
Installation at a Site Exposed to Corrosive Gas	Corrosive gas does not have an immediate effect on the servo drives, but will eventually cause electronic components and terminals to malfunction. Take appropriate action to avoid corrosive gas.

Other Situations	Do not install the servo drive in hot and humid locations or locations subject to excessive dust or iron powder in the air.
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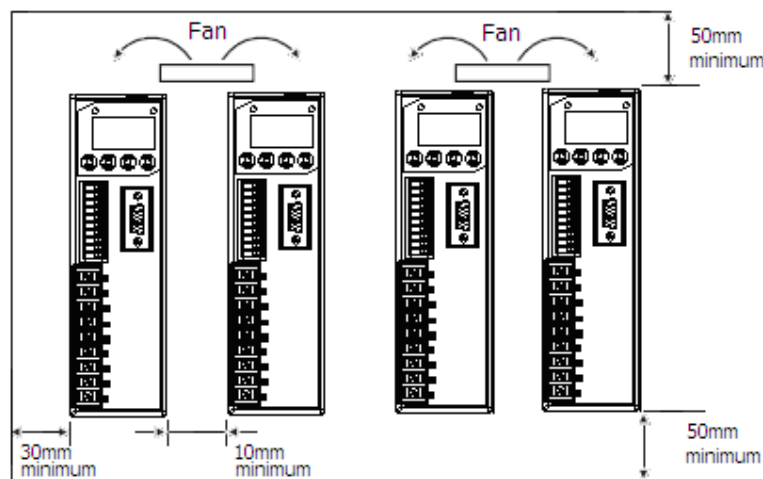
2-2-3. Orientation

Install the servo drive perpendicular to the wall as shown in the figure. The servo drive must be oriented this way because it is designed to be cooled by natural convection or by a cooling fan.



2-2-4. Installation

Follow the procedure below to install multiple servo drives side by side in a control panel.



■ Servo Drive Orientation

Install the servo drive perpendicular to the wall so the front panel containing connectors faces outward.

■ Cooling

As shown in the figure above, allow sufficient space around each servo drive for cooling by cooling fans or natural convection.

■ Side-by-side Installation

When install servo drives side by side as shown in the figure above, make at least 10mm between and at least 50mm above and below each servo drive. Install cooling fans above the servo drives to avoid excessive temperature rise and to maintain even temperature inside the control panel.

■ **Environmental Conditions in the Control Panel**

- Ambient Temperature: 0~50 °C
- Humidity: 90%RH or less
- Vibration: 4.9m/s²
- Condensation and Freezing: None
- Ambient Temperature for Long-term Reliability: 50°C maximum

3 Wiring

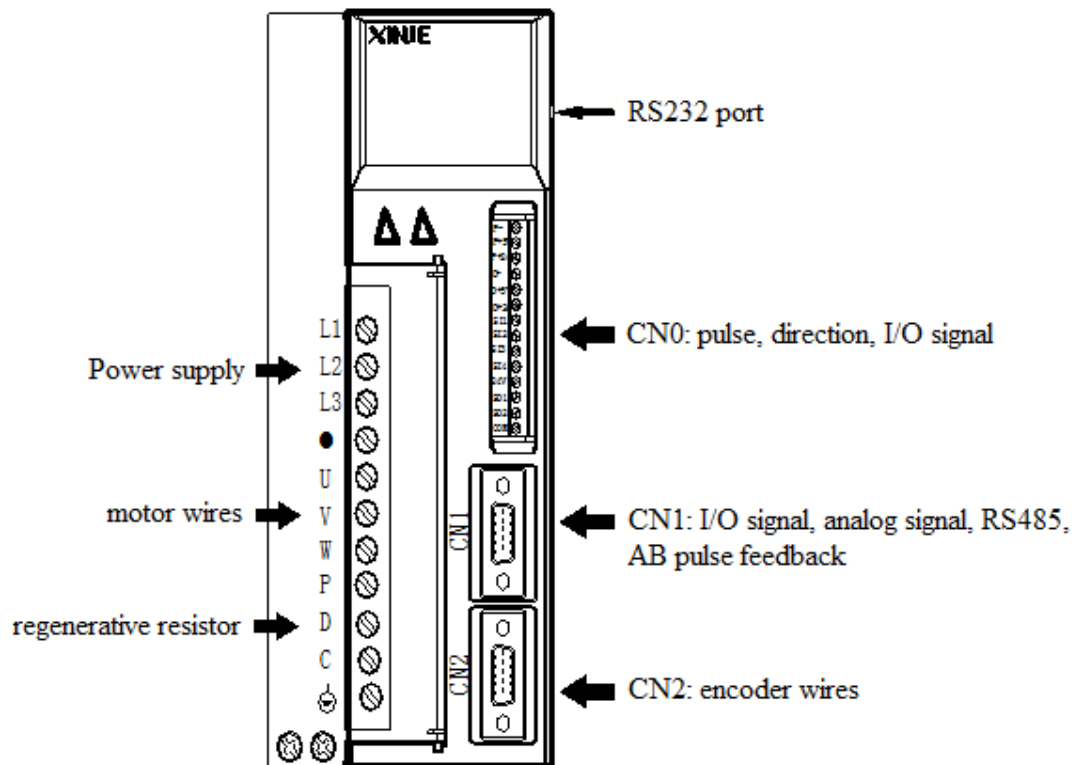
3-1. Main Circuit Wiring



Caution

1. Do not bundle or run power and signal lines together in the same duct. Keep power and signal lines separated by at least 11.81inch(30cm)
2. Use twisted pair wires or multi-core shielded-pair wires for signal and encoder (PG) feedback lines.
The maximum length is 118.11 inch (3m) for reference input lines and is 787.40 inch (20m) for encoder (PG) feedback lines.
3. Do not touch the power terminals for 5 minutes after turning power OFF because high voltage may still remain in the servo amplifier.
Please make sure to check the wiring after the CHARGE light is going off.
4. Avoid frequently turning power ON and OFF. Do not turn power ON or OFF more than once per minute.
Since the servo amplifier has a capacitor in the power supply, a high charging current flows for 0.2s when power is turned ON. Frequently turning power ON and OFF causes main power devices like capacitors and fuses to deteriorate, resulting in unexpected problems.

3-1-1. The terminal arrangement



3-1-2. Main circuit terminals

L1

L2

L3

P+

PB

U

V

W

DS2-20P2-AS, DS2-20P4-AS, DS2-20P7-AS

Terminal	Function	Explanation										
L1/L2/L3	Power supply input of main circuit	Single or 3 phase AC 200 ~ 240V, 50/60Hz										
	Ground	Connect to ground terminal of motor										
P+, PB	Regenerative resistor	Connect regenerative resistor between P+ and PB										
U、V、W	Motor terminals	Connect the motor										
		<table><tr><th>Terminal</th><th>Color</th></tr><tr><td>U</td><td>brown</td></tr><tr><td>V</td><td>black</td></tr><tr><td>W</td><td>blue</td></tr><tr><td>PE</td><td>Yellow green</td></tr></table>	Terminal	Color	U	brown	V	black	W	blue	PE	Yellow green
		Terminal	Color									
		U	brown									
		V	black									
W	blue											
PE	Yellow green											
	Ground	Connect to ground terminal of motor										

L1

L2

L3

U

V

W

P

D

C

DS2-21P5-AS/ DS2-22P3-AS /DS2-41P5-AS

Terminal	Function	Explanation										
L1/L2/L3	Power supply input of main circuit	Single or 3 phase AC 200 ~ 240V, 50/60Hz										
	Vacant											
U、V、W	Motor terminals	Connect the motor										
		<table><tr><th>Terminal</th><th>Color</th></tr><tr><td>U</td><td>brown</td></tr><tr><td>V</td><td>black</td></tr><tr><td>W</td><td>blue</td></tr><tr><td>PE</td><td>Yellow green</td></tr></table>	Terminal	Color	U	brown	V	black	W	blue	PE	Yellow green
		Terminal	Color									
		U	brown									
		V	black									
W	blue											
PE	Yellow green											
P、D、C	Internal regenerative resistor	Short P and D, disconnect P and C										
	External regenerative resistor	Connect regenerative resistor between P and C, disconnect P and D										
	Ground	Connect to ground terminal of motor										

3-1-3. Winding Terminals on Servo motor

Symbol	60, 80, 90 Series	110, 130 Series
PE	4	1
U	1	2
V	3	3
W	2	4
Terminal for brake	1: +24V 2: GND	

3-1-4. CN0, CN1, CN2 terminals

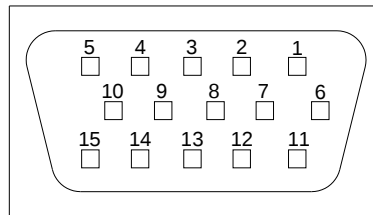
■ CN0 terminals

No.	Name	Explanation	No.	Name	Explanation
1	P-	Pulse input PUL-	8	SI2	Input 2
2	P+5V	5V difference input	9	SI3	Input 3
3	P+24V	Open collector input	10	SI4	Input 4
4	D-	Direction input DIR-	11	+24V	Input +24V
5	D+5V	5V difference input	12	SO1	Output 1
6	D+24V	Open collector input	13	SO2	Output 2
7	SI1	Input 1	14	COM	Ground of output

■ CN1 (DB15) terminals

No.	Name	Explanation	No.	Name	Explanation
1	NC	Reserved	9	Z-	Encoder output Z-
2	NC	Reserved	10	B+	Encoder output B+
3	SI5	Input 5	11	T-REF	Torque analog input
4	SO3	Output 3	12	V-REF	Speed analog input
5	B-	Encoder output B-	13	GND	模拟量输入用 GND
6	A+	Encoder output A+	14	A	RS485+
7	A-	Encoder output A-	15	B	RS485-
8	Z+	Encoder output Z+			

■ CN2 terminals

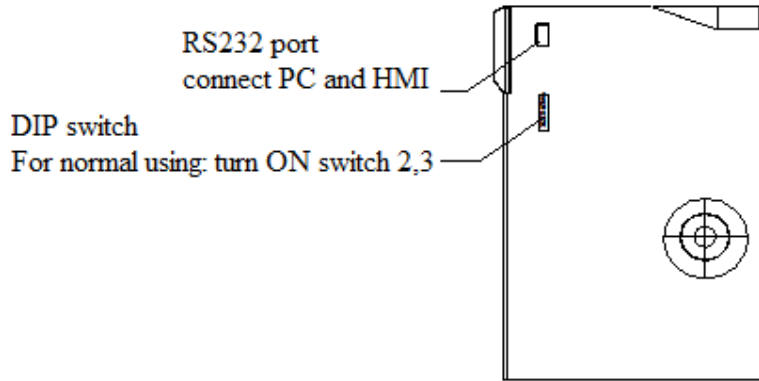


⇔ CN2: encoder port

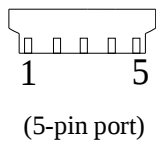
Drive port	Motor encoder port		Name	Drive port	Motor encoder port		Name
	60、80、90 series	110、130、180 series			60、80、90 series	110、130、180 series	
1	9	4	A+	2	4	5	B+
3	7	6	Z+	4	6	10	U+
5	11	12	W+	6	13	7	A-
7	14	8	B-	8	5	9	Z-
9	8	13	U-	10	15	15	W-
11	1	1	Connect to shield layer	12	3	3	GND
13	2	2	5V	14	10	11	V+
15	12	14	V-				

3-1-5. Communication port

■ RS-232 communication



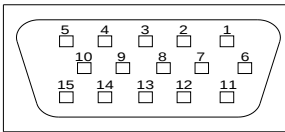
DS2-2□P□-AS, DS2-4□P□-AS



Pin no.	Name	Explanation
1	TXD	RS232 send
2	RXD	RS232 receive
	GND	RS232 ground

■ RS-485 port

DS2-2□P□-AS, DS2-4□P□-AS



Pin no.	Name
CN1-14	A
CN1-15	B



- (1) Please use the cable provide by XINJE Company.
- (2) For above servo drives, RS232 (COM1) and RS485 (COM2) cannot be used at the same time.
- (3) The communication parameters of COM1and COM2 will be changed at the same time.

P0-03, P0-04 set communication parameters

Parameter	Function	Default setting	Setting range
P0-04.0	Baud rate	6	0~9 0: 300 1: 600 2: 1200 3: 2400 4: 4800 5: 9600 6: 19200 7: 38400 8: 57600 9: 115200
P0-04.1	Data bit	0	0: 8

P0-04.2	Stop bit	2	0: 2 bits; 2: 1 bit
P0-04.3	Parity bit	2	0~2 0: no parity 1: odd parity 2: even parity

Parameter	Function	Default setting	Setting range	Effective time
P0-03	Modbus station no.	1	1~255	Power on again

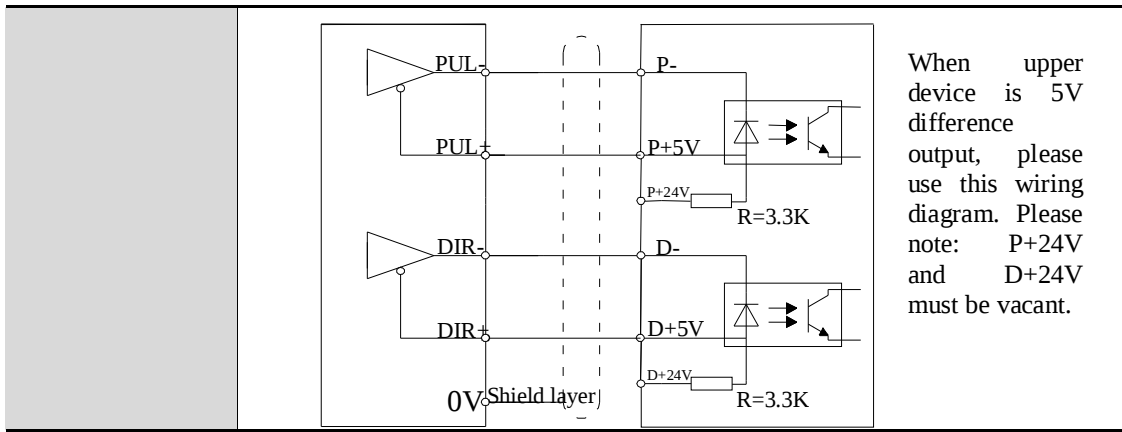
3-2. Signal terminals

3-2-1. Pulse signal

Input terminal	Function	Reference chapter
P- P+5V P+24V	P2-00=0: CW, CCW two pulses mode P2-00=2: pulse + direction mode	5-3-2
D- D+5V D+24V	P2-00=0: CW, CCW two pulses mode P2-00=2: pulse + direction mode	5-3-2

The interface circuit of Pulse + direction and CW, CCW mode:

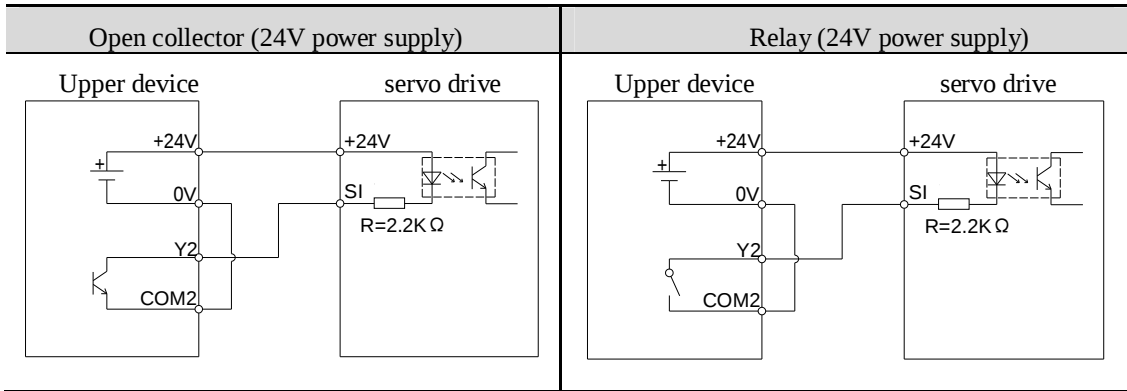
DS2-2□P□-AS DS2-4□P□-AS	Open collector (24V)	
	PLC, SCM, etc servo drive When upper device is open collector output, please use this wiring diagram. Please note: P+5V and D+5V must be vacant.	
DS2-2□P□-AS DS2-4□P□-AS	Difference mode (5V)	
	PLC, SCM, etc	servo drive



3-2-2. SI input signal

Please use relay or open collector transistor to connect. When using relay, please choose micro-current relay. Otherwise, the contact will be not good.

Type	Input terminal	Function	Reference chapter
Digital input	SI1~SI5	Multi-functional input	5-12-1

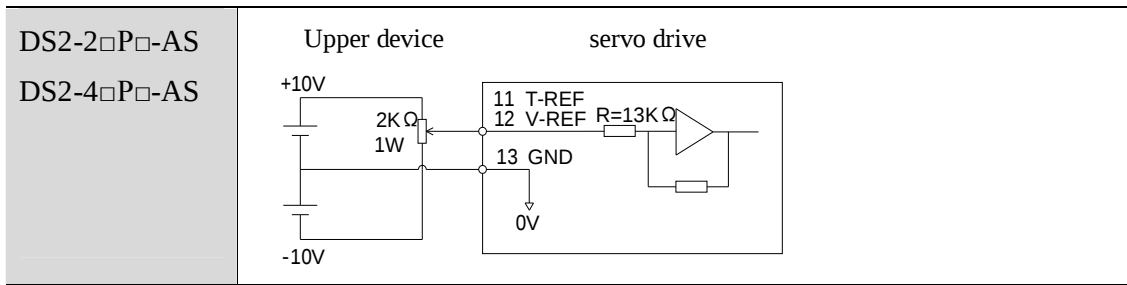


Note: the max allowable voltage and current of open collector output circuit:

Voltage: max DC30V

Current: max DC50mA

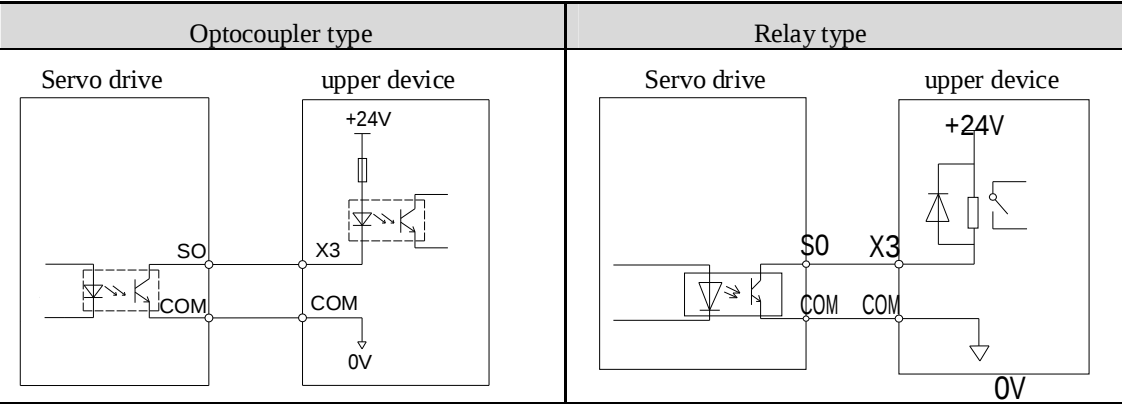
3-2-3. Analog input circuit



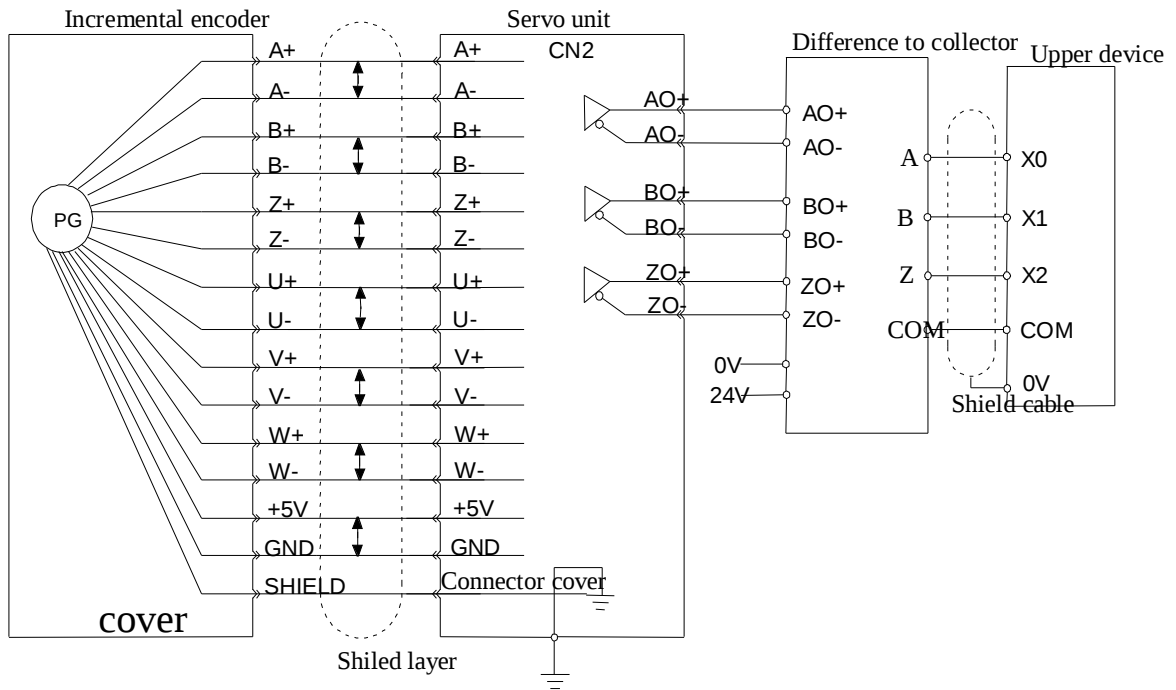
	Analog signal is speed command or torque command. Input impedance: • speed command input: about 13KΩ • torque command input: about 13KΩ • max allowable voltage of input signal is $\pm 10V$
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3-2-4. Output signal

Type	Output terminal	Function	Reference chapter
Optocoupler output	SO1~SO3	Multi-functional output terminal	5-12-3



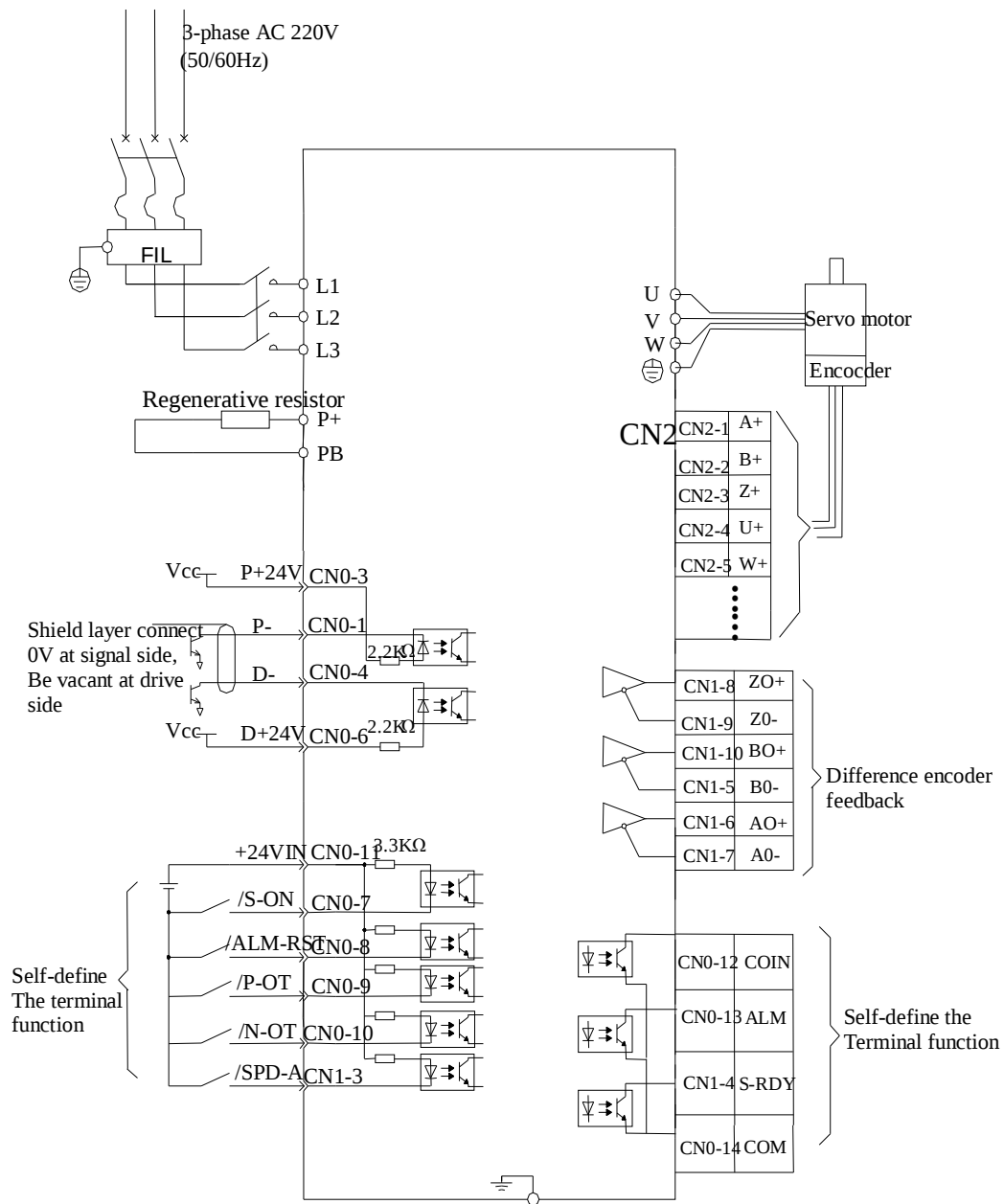
3-2-5. Encoder feedback signal



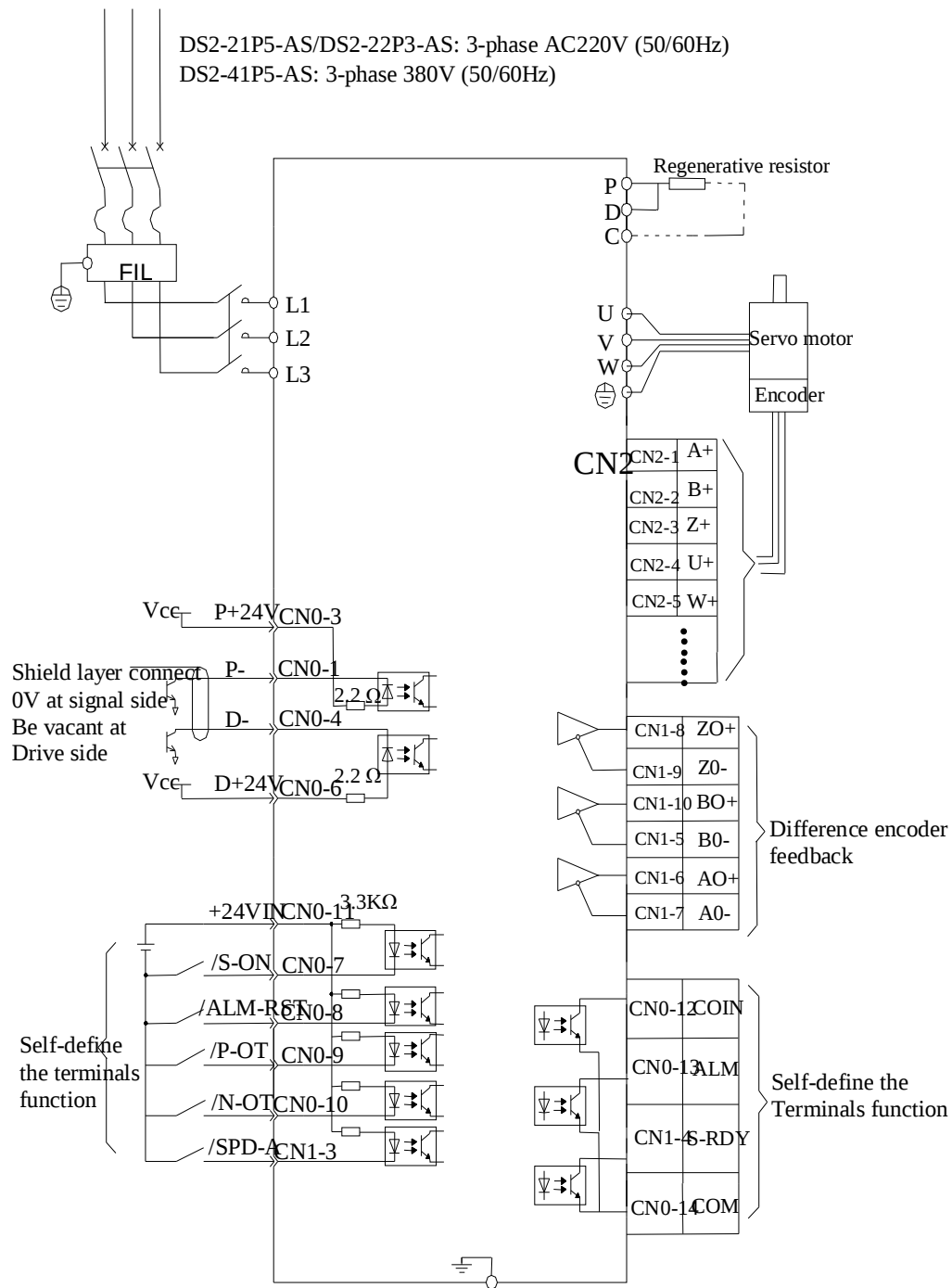
3-3. Standard wiring example

3-3-1. Position Control Mode

■ DS2-20P2-AS, DS2-20P4-AS and DS2-20P7-AS



■ DS2-21P5-AS/ DS2-22P3-AS/ DS2-41P5-AS



3-4. Regenerative Resistor

When the servo motor operates in generator mode, power is returned to the servo drive side. This is called regenerative power. The regenerative power is absorbed by charging the smoothing capacitor, but when the capacitor's charging limit is exceeded, the regenerative power needs to be reduced by the regenerative resistor.

The servomotor is driven in regeneration (generator) mode in the following conditions:

- From decelerating to stop for acceleration/deceleration operation.
- The load on the vertical axis.
- Continuous running of the servo motor at the load side (negative load).

Servo drive	Regenerative resistor connection terminals
DS2-20P2/4/7-AS	For external regenerative resistor, please connect resistor between P+ and PB
DS2-21P5-AS	for internal regenerative resistor: short P and D, disconnect P and C
DS2-22P3-AS	for external regenerative resistor: connect resistor between P and C, disconnect P and D
DS2-41P5-AS	

Parameter	Signal name	Setting	Meaning	Effective
P0-10	Choose regenerative resistor	0	Use internal regenerative resistor	Power on again
		1	Use external regenerative resistor (resistor type please refer to the following table)	

The type of regenerative resistor:

Servo drive	Internal regenerative resistor	External regenerative resistor (recommend value)	External regenerative resistor power (recommend value)
DS2-20P4/DS2-20P7	-	40-60Ω	100W-200W
DS2-20P4-A/B/AS DS2-20P7-A/B/AS	-	30-60Ω	100W-200W
DS2-21P5	-	40-60Ω	200W-300W
DS2-21P5-A/B	-	30-60Ω	200W-300W
DS2-21P5-AS DS2-22P3-AS DS2-41P5-AS	100Ω 100W	30-60Ω	200W-300W
DS2-22P3-A	-	30-60Ω	200W-300W
DS2-23P0-A		30-60Ω	300W-
DS2-45P5-A		30-50Ω	400W-
DS2-47P5-A		30-50Ω	400W-



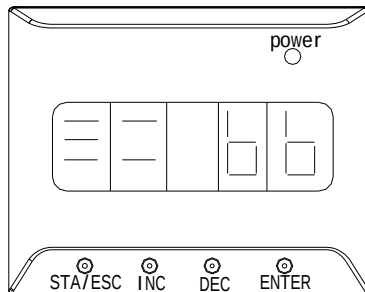
The temperature will be very high when the regenerative resistor is discharging, please using heat-resistant non-flammable wire. Don't touch the regenerative resistor when wiring.

4 Use the operate panel

4-1. Basic Operation

4-1-1. Functions of operate panel

- 5-bit LED: Displaying parameter settings, status or alarm.
- Power LED POWER: The LED is on when the servo drive is powered on.

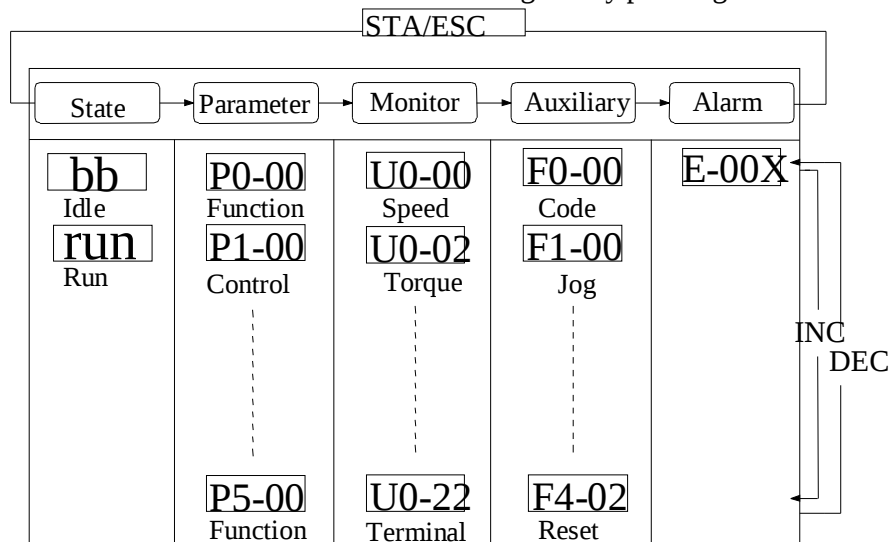


Key Name	Function
STATUS/ESC	Press: Status switch, status return
INC	Press: Increase the value; Press and hold: Increase the value continuously
DEC	Press: Decrease the value; Press and hold: Decrease the value continuously
ENTER	Press: Shift the editing digit; Press and hold: Enter a status, Enter

4-1-2. Basic Mode Switching

The operate panel can display the status, set parameter and run the command by switching the basic mode.

The running status, auxiliary function, parameter setting, and monitoring are the basic modes. The modes switch as the below diagram by pressing STATUS/ESC.



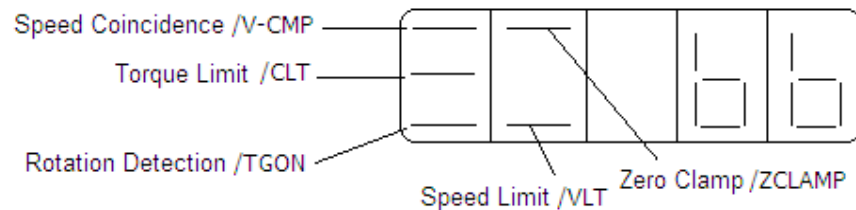
Display mode:

- Monitor Function U— XX: XX means the number of the monitor function.
- Auxiliary Function FX—XX: The first X means group No., the last two X means the

- member No. in the group.
- Parameter Setting PX—XX: The first X means group No., the last two X means the member No. in the group.
- Alarm E—XXX: XXX means the alarm code.

4-2. Running status mode

➤ Speed and Torque Control Mode



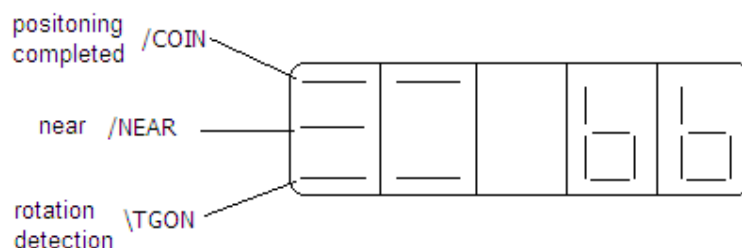
A. Bit contents:

Bit Data	Description
P5-29 Speed Coincidence (/V-CMP)	Light when the motor actual speed and command speed is the same. Speed coincidence signal checking width: P5-03 (unit: rpm)
P5-32 Torque Limit (/CLT)	Light when actual torque exceeds preset value. Forward Torque Limit: P4-02 Reverse Torque Limit: P4-03
P5-30 Rotation Detection (/TGON)	Light when the motor speed exceeds the rotation detection speed. Rotation Detection Speed Level: P5-02(Unit: rpm)
P5-21 Zero Clamp (/ZCLAMP)	Light when zero clamp signal is ON.
P5-33 Speed Limit (/VLT)	Light when actual speed exceeds preset value. Speed Limit during Torque Control: P4-07

B. The code contents:

Code	Description
	Standby Servo OFF (motor power OFF)
	Run Servo ON (motor power ON)
	Forward Run Prohibited P-OT is OFF. Please refer to 5-2-3 “Overtravel Limit”
	Reverse Run Prohibited N-OT is OFF. Please refer to 5-2-3 “Overtravel Limit”

➤ Position Control Mode



A. The bit contents:

Bit Data	Description
P5-28 Positioning Completed (/COIN)	Light when set position and actual position is the same. Positioning accomplishment width: P5-00 (unit: command pulse)
P5-36 Near (/NEAR)	Light when set position and actual position is the same. Near signal width: P5-04
P5-30 Rotation Detection (/TGON)	Light when the motor speed exceeds the rotation detection speed. Rotation detection speed: P5-02(unit: rpm)

B. The code contents:

Code	Description
	Standby Servo OFF (motor power OFF)
	Run Servo ON (motor power ON)
	Forward Run Prohibited P-OT is OFF. Please refer to 5-2-4 "Overtravel Limit"
	Reverse Run Prohibited N-OT is OFF. Please refer to 5-2-4 "Overtravel Limit"

4-3. Monitoring Mode

■ Display contents of Monitoring Mode

Number	Monitor Display		Unit
U-00	Actual speed of motor		Rpm
U-01	Input speed command		Rpm
U-02	Internal torque command		%
U-03	Rotate angle (mechanism angle)		0.1°
U-04	Rotate angle (electrical angle)		0.1°
U-05	Bus voltage		V
U-06	Module temperature		0.1℃
U-07	Input command pulse speed		Rpm
U-08	Pulse value of shift	(0000~9999)*1	Command pulse
U-09	command	(0000~9999)*10000	
U-10	Rotate angle (encoder value)	(0000~9999)*1	encoder pulse
U-11		(0000~9999)*10000	
U-12	Pulse value of input command	(0000~9999)*1	Pulse command
U-13		(0000~9999)*10000	
U-14	Pulse value of feedback command	(0000~9999)*1	Pulse command
U-15		(0000~9999)*10000	
U-16	Current position (Accumulated)	(0000~9999)*1	encoder pulse
U-17		(0000~9999)*10000	
U-18	Current, 1-bit decimal		0.1A
U-19	Analog input V-REF		0.01V
U-20	Analog input T-REF		0.01V
U-21	I/O signals status		
U-22	I/O terminals status		

■ U-21 displays I/O signals status

The following diagram describes the input and output signals status displayed in U-21.

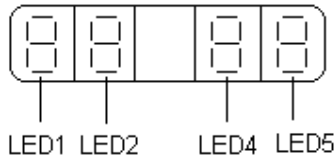


Diagram 1

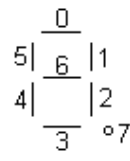


Diagram 2

In diagram 1, LED4 and LED5 stand for input signals status, and LED1 and LED2 stand for output signals status. In diagram 2 there shows the segment No. of each LED.

➤ Input signals status

Segment	Description	Segment	Description
LED4_0	/SPD-A internal set speed selection	LED5_0	/S-ON servo signal
LED4_1	/SPD-B internal set speed selection	LED5_1	/P-CON proportion action command
LED4_2	/C-SEL control mode selection	LED5_2	/P-OT forward prohibit
LED4_3	/ZCLAMP zero clamp	LED5_3	/N-OT reverse prohibit
LED4_4	/INHIBIT prohibit pulse command	LED5_4	/ALM-RST clear the alarm
LED4_5	/G-SEL switch the gain	LED5_5	/P-CL external torque limit at forward side
LED4_6	/CLR clear the pulse	LED5_6	/N-CL external torque limit at reverse side
LED4_7	/CHGSTP change the step	LED5_7	/SPD-D internal set speed selection

➤ Output signals status

Segment	Description	Segment	Description
LED1_0	/NEAR near	LED2_0	/COIN positioning completed
LED1_1	/ALM alarm output	LED2_1	/V-CMP speed synchronization checking
LED1_2	/Z encoder Z phase output	LED2_2	/TGON rotate checking
		LED2_3	/S-RDY ready
		LED2_4	/CLT torque limit
		LED2_5	/VLT speed limit checking
		LED2_6	/BK brake lock
		LED2_7	/WARN warn

■ U-22 displays I/O terminals status

The following diagram describes the input and output terminals status:

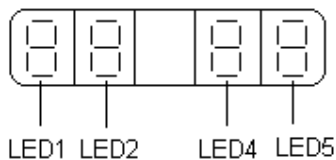


Diagram 1

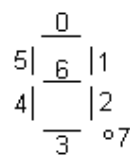


Diagram 2

In diagram 1, LED5 stands for input signals status, and LED2 stands for output signals status. In diagram 2 there shows the segment No. of each LED.

Input terminals		Output terminals	
Segment	Description	Segment	Description
LED5_0	Input status of SI1	LED2_0	Output status of SO1
LED5_1	Input status of SI2	LED2_1	Output status of SO2
LED5_2	Input status of SI3	LED2_2	Output status of SO3
LED5_3	Input status of SI4		
LED5_4	Input status of SI5		
LED5_5	Input status of SI6		

4-4. Auxiliary Function

Use the operate panel to do application in auxiliary function mode.

Group No.	Content
F0-**	Check system information, display the system code and data
F1-**	Auxiliary run mode, display the auxiliary run command and result
F2-**	Set the motor code
F3-**	Check the alarm information, clear the alarm
F4-00	Reset parameters to default value
F5-00	External communication monitoring

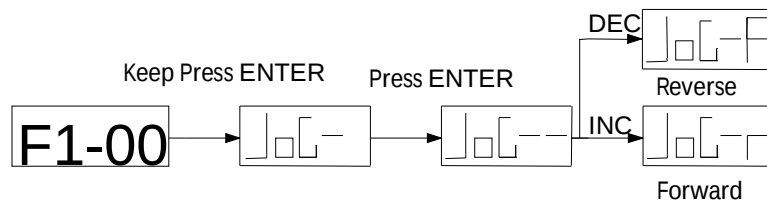
4-4-1. F0-XX

Function No.	Description	Function No.	Description
F0-00	Motor Code	F0-01	Servo Series
F0-02	Servo Model	F0-03	Produce Date: Year
F0-04	Produce Date: Month	F0-05	Produce Date: Day
F0-06	Software Version	F0-07	Hardware Version

4-4-2. F1-XX

1. Jog (F1-00)

Make sure that the motor shaft is not connected to the machine before jogging!



P3-04	JOG speed					
	Unit	Default	Setting range	Suitable mode	Change	Effective
	Rpm	100	0~1000	JOG	Servo OFF	Immediately

2. Trial Operation (F1-01)

Make sure that the motor shaft is not connected to the machine before trial operation!

When servo drive is connected with non-original encoder line or power line, trial operation must be run first to ensure that the encoder line or power line is connected correctly.

Set the display to F1-01, and press and hold ENTER key to enter trial operation mode. The operate panel displays:



If correctly wired, the motor would rotate in 5 seconds in forward direction (fixed to counter-clockwise), otherwise the motor would shock or vibrate, raising an alarm for worse. In this case the power must be switched off immediately and check the wiring again.

Press STATUS/ESC key to return.

3. Current Offset Auto-Adjustment (F1-02)

After the servo drive is updated to latest software version, or the motor does not revolve smoothly for long time, the current offset auto-adjustment is recommended.



Press STATUS/ESC to exit.

4. Speed command offset auto-adjustment (F1-03)



Press STATUS/ESC key to exit.

5. Torque command offset Auto-Adjustment (F1-04)



Press STATUS/ESC key to exit.

6. Forced Servo enables (F1-05)

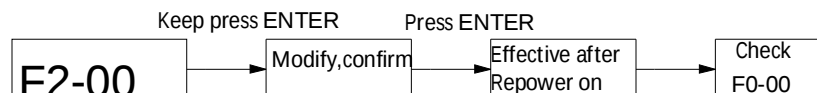
F1-05 = 0: Cancel forced servo enables

F1-05 = 1: Forced servo enables

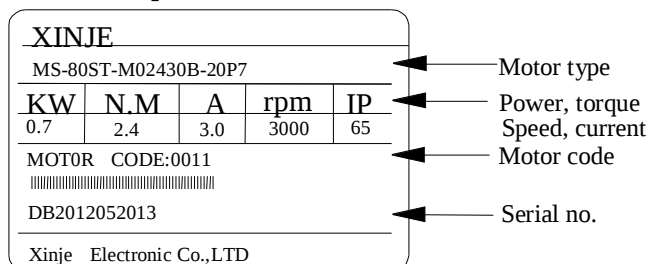
The forced servo enable will invalid after repower on.

4-4-3. Change the motor type (F2-00)

The servo drive can match multi-servo-motor with close power classes printed on the nameplate of each motor. Please confirm the motor code F0-00 match the nameplate.



Motor nameplate



4-4-4. Check Alarm Information (F3-XX)

Member No.	Description	Unit
F3-00	Current alarm code ※1	
F3-01	Current warn code ※2	
F3-02	Alarm/warn code 1 when alarm	
F3-03	U phase current when alarm	A
F3-04	V phase current when alarm	A
F3-05	DC bus-voltage when alarm	V
F3-06	IGBT module temperature when alarm	°C
F3-07	Speed when alarm	rpm
F3-08	Internal torque command when alarm	%
F3-09	V-REF value when alarm	V
F3-10	T-REF value when alarm	V
F3-11	Alarm/warn code 2 when alarm	
F3-12	Alarm/warn code 3 when alarm	
F3-13	Alarm/warn code 4 when alarm	
F3-14	Alarm/warn code 5 when alarm	
F3-15	Alarm/warn code 6 when alarm	
F3-16	Alarm/warn code 7 when alarm	

※1: F3-00=0 indicates that there is no alarm.

※2: F3-01=0 indicates that there is no warn.

4-4-5. Reset Parameters to Default (F4-XX)

Reset to default value: F4-00 = 1.

Please make the servo OFF before the operation.

4-4-6. External monitoring (F5-XX)

Select F5-00 in auxiliary function, the panel displays “C-OUT” which means external monitoring mode, COM1 is effective, operate panel is ineffective. At this time user can debug the servo via PC.

Press STATUS/ESC to return.

4-5. Alarm (E-XX)

The alarm code will show when there is error in the drive. Press ENTER to reset the alarm.

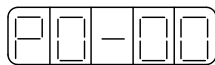
If the servo is OFF caused by alarm, it is no need to reset the alarm.

Note: please find out the alarm reason before reset the alarm.

4-6. Example

The example below shows how to change parameter P3-09 from 2000 to 3000.

1. Press the STATUS/ESC key to select the parameter setting mode.



2. At this time the second LED is blinking, and press INC or DEC key to set the group No. to 3. Press ENTER key to confirm.



3. At this time the last LED is blinking, and press INC or DEC key to set the member No.

to 9. Press and hold ENTER key to confirm.

P3-09

4. At this time the panel displays the value in P3-09, and the last decimal “0” is blinking. Press ENTER to left shift the blinking decimal. Press INC, DEC or ENTER key to modify the value to 3000, and press and hold ENTER to confirm.

3000

The parameter in P3-09 in changed from 2000 to 3000.

Repeat steps 2 to 4 to change the parameter again.

5. Press STATUS/ESC key to return.

5 Run the servo system

5-1. Control mode selection

DS2-AS series servo has one main mode and two sub modes. Sub mode 1 and 2 can be switched to each other via /C-SEL signal.

Parameter		Control mode	Reference
P0-00	0	Testing mode, users cannot change!	
P0-01 Sub mode1	0	Idle mode The motor will not power on even if the servo drive enables.	
	1	Torque control (internal setting) Control the output torque of servo motor via operating panel or communication.	5-9
	2	Torque control (analog voltage command) Control the output torque of servo motor via analog voltage command. It is mostly used to close-loop torque control with upper device, such as tension control. (If servo drive doesn't have analog input port, it cannot use this mode.)	5-8
	3	Speed control (internal speed setting) Use /SPD-D, /SPD-A, /SPD-B to select the speed which is set in the servo drive. The servo drive can set 3 speeds.	5-6
	4	Speed control (analog voltage command) Control the speed of servo motor via analog voltage command. It is mostly used to close-loop speed control with upper device.	5-5
	5	Position control (internal position command) Control the position via internal position command; it can set pulse quantity and torque.	5-4
	6 (default value)	Position control (external pulse command) Control the position of servo motor via pulse command. Control the position via pulse quantity; control the speed via pulse frequency.	5-3
	7	Speed control (pulse frequency command) Control the speed of servo motor via pulse frequency, but not control the position.	5-7
P0-02 Sub mode2	Same as sub mode 1	The servo will enter sub mode2 when /C-SEL signal is effective.	5-10

5-2. Basic function setting

Parameter	Name	Reference
P5-10	Servo ON setting /S-ON	5-2-1
P0-05	Switch the motor rotate direction	5-2-2
P0-06	Motor stop mode setting	5-2-3
P4-06	Servo immediately stop torque	5-2-3
P5-12	Prohibit forward running /P-OT	5-2-4
P5-13	Prohibit reverse running /N-OT	5-2-4
P5-34	Power-loss brake /BK	5-2-5
P5-37	Alarm output	5-2-6
P0-20	Run time	5-2-7
P0-21	Alarm times	

P4-11	Forward torque	5-2-8
P4-12	Reverse torque	
P4-13	Overlimit time	

5-2-1. Servo ON setting

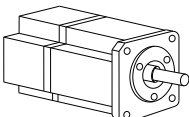
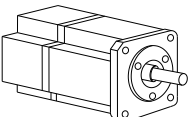
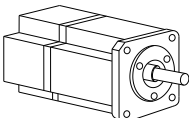
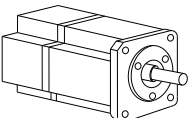
When servo ON signal is ineffective, the servo motor cannot run.

Parameter	Signal	Setting	Explanation	Range
P5-10	/S-ON	n.0001 (default value)	When SI1 is ON, servo motor powers on and enables to run.	0001~0015
		n.0010	Always effective, no need to wiring.	
/S-ON signal can be set to other input via parameter P5-10, please refer to chapter 5-12-1.				

5-2-2. Switch the motor rotate direction

Change the motor rotate direction without changing the motor wiring. The standard forward rotate direction is “CCW rotate” look at the load side.

“Reverse mode” will change the motor rotate direction.

Mode	Forward rotate	Reverse rotate
Standard setting: CCW is forward rotate		
Reverse mode: CW is forward rotate		

■ Set the rotate direction

Parameter	Setting	Explanation
P0-05	0 (default)	Standard setting (CCW is forward)
	1	Reverse mode (CW is forward)

5-2-3. Motor stop mode when use overtravel signal

When use overtravel signal, please set the motor stop mode as the below table:

Parameter	Function	Setting range	Default value	Modify	Effective
P0-06.H	Motor stop mode when use overtravel signal	0~3	2	Servo OFF	Repower on

P0-06.H value	Explanation
0~1	Inertia stop. Keep on inertia motion after stop.
2	Decelerate stop. Change to zero clamp state after stop. Torque setting: P4-06 urgent stop torque
3	Decelerate stop. Change to inertia motion state after stop. Torque setting: P4-06 urgent stop torque.

Notes: (1) P0-06.H=0,1, servo enable signal will be forced OFF when overtravel signal arrives.
P0-06.H=3, servo enable signal will be forced OFF after motor stop when overtravel signal arrives. P0-06.H=2, servo enable signal will not be forced OFF as long as the servo enable

signal is always effective. (2) stop condition depends on rotate checking speed P5-02, unit rpm.
--

Related parameter settings:

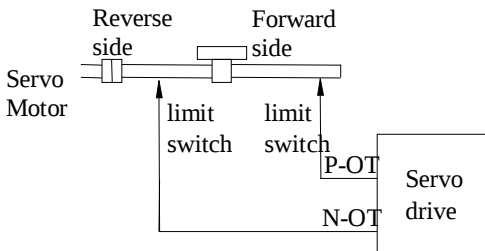
P4-06	Urgent stop torque					
	Unit	Default value	Range	Suitable mode	Modify	Effective
	1% rated torque	300	0~300	All the modes	Servo OFF	Immediately

Notes: if this parameter set too small, the motor will stop slowly.

5-2-4. Overtravel Limit (P-OT & N-OT)

(1) Use the overtravel signal

Please connect P-OT and N-OT to the limit switch. Make sure to wiring as the following diagram when linear driving to avoid machine damage.



(2) Set the overtravel signal

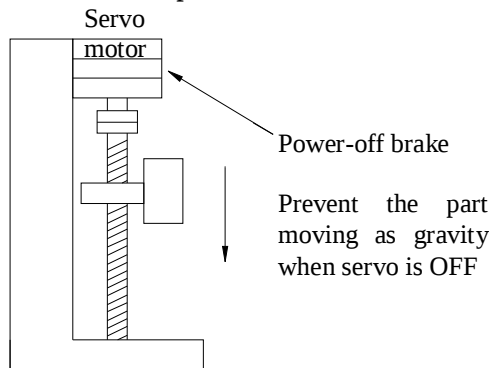
Parameter	Signal	设定	意义	Modify
P5-12	/P-OT	n.0003 (default)	SI3=ON, prohibit the forward running	Range: 0000-0015
		n.0013	SI3=ON, allow the forward running	
P5-13	/N-OT	n.0004 (default)	SI4=ON, prohibit the reverse running	Range: 0000-0015
		n.0014	SI4=ON, allow the reverse running	

Note:

1. /P-OT, /N-OT can be changed to other terminal input via parameter P5-12 and P5-13.
2. In position control, there is position offset pulse when stop the motor via overtravel signal. Please input clear signal /CLR to clear the offset.
3. In position control, if the servo still can receive pulse when stop the motor via overtravel signal, these pulses will accumulate until the servo alarm.
4. The input terminals function cannot be the same. Please refer to chapter 5-12-1.

5-2-5. Power-off Brake (BK)

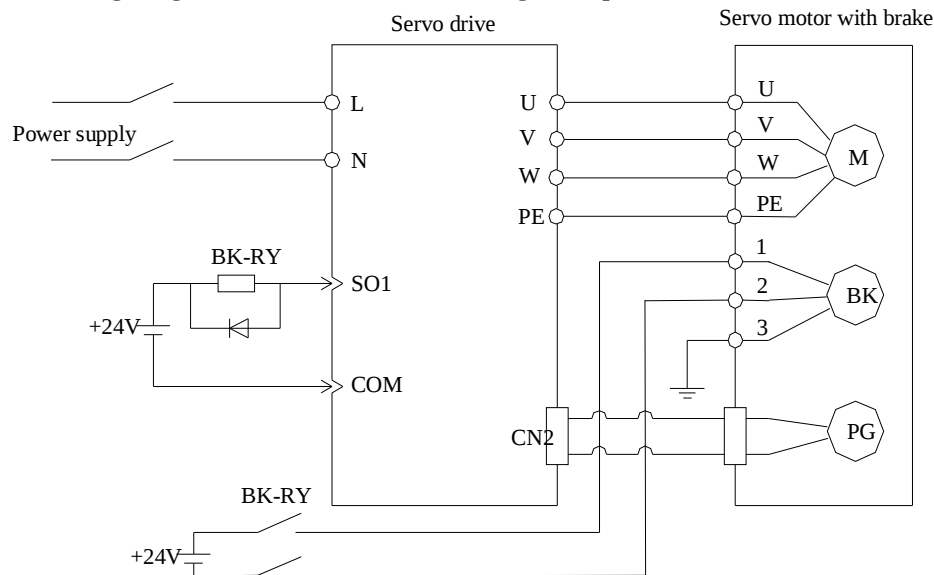
It is used when servo drive controls the vertical shaft. The function of power-off brake is the moveable part will not shift when servo is OFF.



The brake built into the MS series servomotor with brakes is a de-energization brake, which is used only to hold and cannot be used for braking. Use the holding brake only to hold a stopped motor. Brake torque is about 120% of the rated motor torque.

(1) Wiring Example

The ON/OFF circuit of brake includes sequence signal /BK and brake power. The following diagram shows a standard wiring example.



Note: the working voltage of brake is DC 24V, current is about 0.6A.

(2) Brake signal

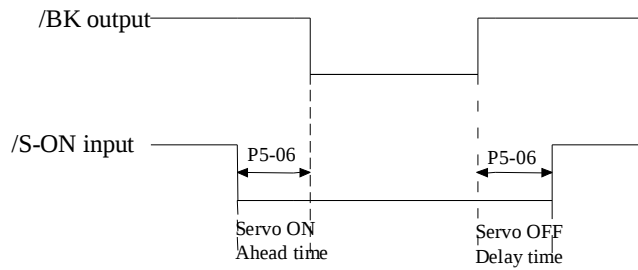
Parameter	Signal	Type	Default	Explanation	Modify
P5-34	/BK	Output	n.0000	Need to distribute	Range 0000-0013
/BK signal can output from output terminal via setting parameter P5-34, please refer to chapter 5-12-3. When set P5-34=0001, it means output from SO1 terminal.					

(3) Servo OFF delay time (after servo motor stop)

If the machine moves slightly due to gravity because of the brake has action delay time. Please adjust the time as below parameter.

P5-06	Servo OFF delay time (brake command)					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1ms	0	0~500	All the modes	Servo OFF	Immediately

This parameter is used to set the output time from the brake control signal /BK to the servo OFF operation (servomotor output stop).



The above diagram shows the action time of /BK signal and servo ON signal. Before brake is OFF, servo already power on; after brake is ON, servo is OFF.

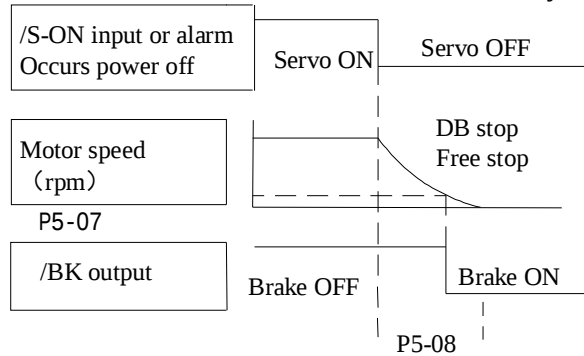
(4) Brake ON parameter (When servo motor is rotating)

the motor will power OFF when alarm occurs. The machine will move as gravity until the brake action.

Set below parameters in order to use brake when motor speed decreases to setting value or waiting time ends.

P5-07	Brake command output speed					
	Unit	Default	Range	Suitable mode	Modify	Effective
	rpm	100	0~5000	All the modes	Servo OFF	Immediately
P5-08	Brake command waiting time					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1ms	500	10~1000	All the modes	Servo OFF	Immediately

Set the brake time when servo OFF caused by /S-ON signal or alarm.



The brake is used to protect the position. The brake must be effective at suitable time when servo motor stop. Users can adjust the parameters according to the machine action.

The /BK signal from ON to OFF under either of the following conditions:

1. Motor speed drops below the value of P5-07 after servo OFF.
2. over the time of P5-08 after servo OFF.

The real speed is max speed (P3-09) even set the speed higher than max in P5-07.

5-2-6. Alarm output

Parameter	Signal	Default	Meaning	Modify
P5-37	Alarm output	n.0002 (default)	SO2 and COM pass through when servo alarm	Range: 0000-0013 Distribute the signal to output terminal through P5-37. P5-37=0001, it outputs from SO1.
		n.0012	SO2 and COM cut off when servo alarm	



- (1) Servo unit is forced OFF when alarm. The motor will move with external force. If the motor needs to hold the position, please choose motor with power loss brake and use /BK signal. Please refer to chapter 5-2-5.
- (2) The output terminals distributed by function parameters cannot be same. Please refer to chapter 5-12-3.

P0-21	Alarm times	
	Default value	Meaning
	0	Record the servo alarm times.

5-2-7. Running time

P0-20	Running time	
	Default value	Meaning
	0	Record the servo running time. It can be cleared when reset.

5-2-8. Torque over-limit

P4-11	Forward torque comparison value
P4-12	Reverse torque comparison value
P4-13	Torque over-limit time
Note: P4-13>0, this function is effective. Motor output torque U-02>P4-11/12, in the time of P4-13, it shows alarm E-019.	

5-3. Position mode (external pulse command)

Basic parameter		
Parameter	Name	Reference
P0-01	Control mode selection	5-3-1
P2-00	Pulse command mode	5-3-2
P2-02	Electronic gear ratio (numerator)	5-3-3
P2-03	Electronic gear ratio (denominator)	
P5-10	Servo ON signal /S-ON	5-2-1

Other available parameters			
Key words	Parameter	Name	Reference
Command filter	P2-01	Position command filter selection	5-3-4
Clear error pulse	P5-24	Pulse error clear	5-3-5
Positioning finish	P5-28	Positioning finish signal output /COIN	5-3-6
	P5-00	Positioning finish width	
Positioning near	P5-36	Positioning near signal output /NEAR	5-3-7
	P5-04	Positioning near signal width	
Prohibit pulse	P5-22	Command pulse prohibition /INHIBIT	5-3-8

5-3-1. Control mode selection

Parameter	Setting value	Meaning	Modify	Effective
P0-01	6	Position control (external pulse)	Servo OFF	Immediately
Function: control the position by the external pulse command				

5-3-2. Pulse command

1. Pulse command mode

Parameter	Setting	Command mode	Suitable mode	Modify	Effective
P2-00 xx□x	0	Falling edge is effective	6, 7	Immediately	Repower on
	1	Rising edge is effective			

Parameter	Setting	Command mode	Suitable mode	Modify	Effective
P2-00 xxx□	0	CW, CCW mode	6, 7	Immediately	Repower on
	2	Pulse + direction			



DS2-AS v3.2 and higher version cannot support AB phase pulse input.

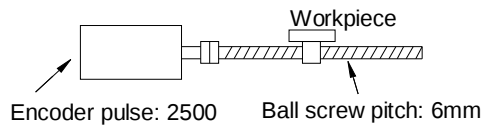
2. Details explanation of pulse command mode

Command pulse mode	Electrical specification	Remark
Direction+pulse (DIR+PUL signal) Max frequency: Bus drive is 500kbps. Transistor open circuit is 200kbps.	$t1, t2 \leq 0.1\mu s$ $t3, t7 \leq 0.1\mu s$ $t4, t5, t6 > 3\mu s$ $\tau \geq 2.5\mu s$ $(\tau/T) \times 100 = 40\% \sim 60\%$	Direction (DIR) 1= forward command 0= reverse command
CW, CCW mode Max frequency: Bus drive is 500kbps. Transistor open circuit is 200kbps.	$t1, t2 \leq 0.1\mu s$ $\tau \geq 2.5\mu s$ $(\tau/T) \times 100 = 40\% \sim 60\%$	CW: PUL=pulses DIR=0 CCW: PUL=0 DIR=pulses

5-3-3. Electronic gear ratio

The electronic gear function is set any value for motor moving quantity corresponding to input pulse command. The host device which sends command doesn't need to consider the machine deceleration ratio and encoder pulse quantity.

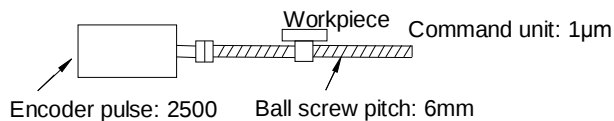
Not use electronic gear



The workpiece moves 10mm

One rotation is 6mm
 $10 \div 6 = 1.6666$
 2500×4 pulse finishes one rotation
 Command input 16666 pulses
 Calculate these values in the host controller

Use electronic gear



Define the machine condition and command unit by electronic gear

The workpiece moves 10mm

Command unit is 1 μm

$$\frac{10\text{mm}}{1\mu\text{m}} = 10000 \text{ pulse}$$

P2-02	Electronic gear (numerator)					
	Unit	Default	Range	Suitable mode	Modify	Effective
	—	1	1~65535	6	Any	Immediately
P2-03	Electronic gear (denominator)					
	Unit	Default	Range	Suitable mode	Modify	Effective
	—	1	1~65535	6	Any	Immediately

1. Calculate the electronic gear ratio (B/A) using the following steps:

Step	Content	Explanation
1	Confirm the machine specification	Confirm the deceleration ratio, ball screw distance, pulley diameter
2	Confirm the encoder pulse	Confirm the servo motor encoder pulses
3	Set the reference unit	Set the actual distance or angle corresponding to 1 pulse of the command controller
4	Calculate the moving value the load shaft rotates 1 circle	Calculate the actual unit value the load shaft rotates 1 circle based on reference unit
5	Calculate the electronic gear ratio	Calculate the electronic gear ratio based on the formula (B/A)
6	Set the parameters	Set the result as the electronic gear ratio
1. Formula:		

Suppose the machine deceleration ratio of motor shaft and load shaft is m/n, calculate the electronic gear ratio as the below formula:

(when servo motor shaft rotates m circles, load shaft rotates n circles)

$$\text{Electronic gear ratio} = \frac{B}{A} = \frac{P2-02}{P2-03} \\ = \frac{\text{Encoder pulses} \times 4}{\text{unit value of load shaft rotates 1 circle}} \times \frac{m}{n}$$

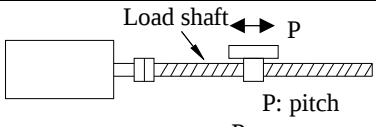
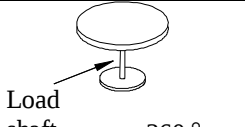
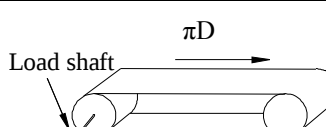
If it exceeds the setting range, please reducible the molecular and denominator in the setting range. The reducible will not affect the using.

2. Reference unit doesn't mean the precision

Refine the reference unit based on machine precision can improve the servo positioning precision. For example: in the application of screw, the machine precision can up to 0.01mm, so the reference unit 0.01mm is more accurate than 0.1mm.

2. Example of setting the electronic gear

The example for different loads:

Step	Ball screw	Round table	Belt + pulley
	 1 rotate = $\frac{P}{\text{Reference unit}}$	 1 rotate = $\frac{360^\circ}{\text{Reference unit}}$	 1 rotate = $\frac{\pi D}{\text{Reference unit}}$
1	Ball screw pitch: 6mm Machine deceleration ratio: 1/1	1-circle rotate angle: 360° Deceleration ratio: 3/1	Pulley diameter: 100mm Deceleration ratio: 2/1
2	2500P/R	2500P/R	2500P/R
3	1 reference unit: 0.001mm	1 reference unit: 0.1°	1 reference unit: 0.02mm
4	6mm/0.001mm = 6000	360/0.1 = 3600	314mm/0.02mm = 15700
5	$\frac{B}{A} = \frac{2500 \times 4}{6000} \times \frac{1}{1}$	$\frac{B}{A} = \frac{2500 \times 4}{3600} \times \frac{3}{1}$	$\frac{B}{A} = \frac{2500 \times 4}{15700} \times \frac{2}{1}$
6	$\frac{P2-02}{P2-03} = \frac{10000}{6000} = \frac{5}{3}$	$\frac{P2-02}{P2-03} = \frac{30000}{3600} = \frac{25}{3}$	$\frac{P2-02}{P2-03} = \frac{20000}{15700} = \frac{200}{157}$

5-3-4. Position command filter

The servo can filter the command pulse at certain frequency.

Filter mode selection: select the filter as the following parameters

P2-01	Select the position command filter					
	Unit	Default	Range	Suitable mode	Modify	Effective
	—	0	0~1	6	Servo OFF	Re-power on

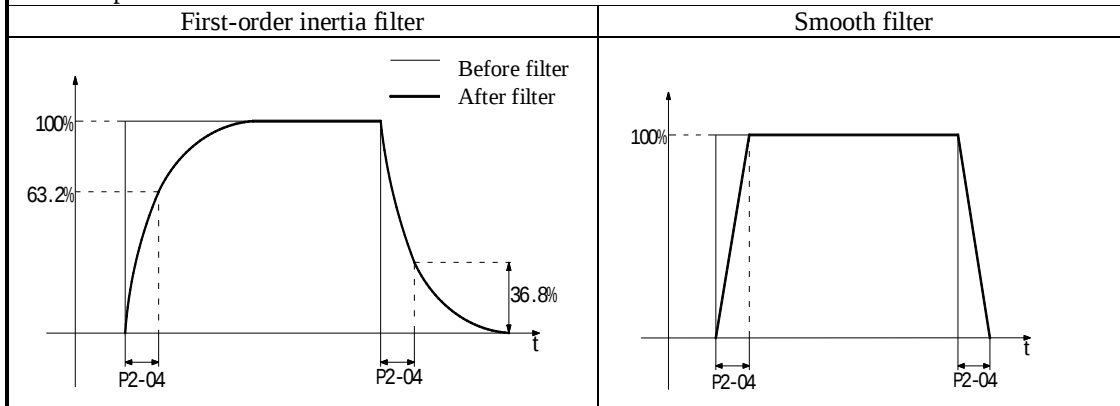
Select 1-time delay feature or moving average filter.

P2-01	Content
0	First-order inertia filter
1	Smooth filter

Set the filter time:

P2-04	Position command filter time parameters					
	Unit	Default	Range	Suitable mode	Modify	Effective
	ms	0	0~100	6	Servo OFF	Re-power on

The comparison of P2-04 in First-order inertia filter and smooth filter mode:



Pulse error: the difference between command pulse of controller (such as PLC) and feedback pulse of servo in position mode. Its unit is 1 reference unit; it is related to the reference unit of electronic gear ratio.

Parameter	Signal	Default	Meaning	Modify
P5-24	/CLR	n.0000	Need distribution	Range: 0000-0015. Distribute to output terminal through P5-24. When it set to 0001, output the signal from SI1.



 The input terminal distributed by function parameter cannot be same. Please refer to chapter 5-12-1.

Use the signal when the controller needs to confirm the completion of positioning.

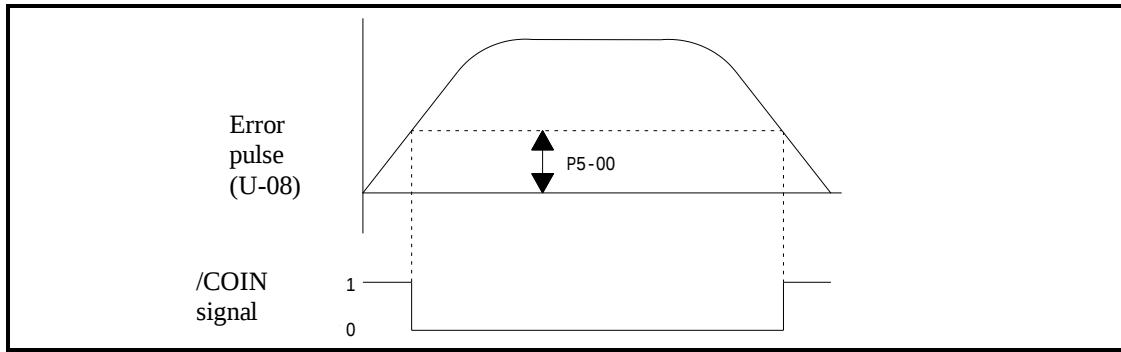
Parameter	Signal	Default	Meaning	Modify
P5-28	/COIN	n.0001	Output positioning complete signal from SO1	Range: 0000-0013, distribute to output terminal through P5-28. When it set to 0002, it means output from SO2.
		n.0011	SO1 and COM cut off when positioning complete	



 The output terminal distributed by function parameter cannot be same. Please refer to chapter 5-12-3.

P5-00	Width of positioning complete					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1 reference unit	7	0~250	5, 6	Servo OFF	Immediately

Function: when the pulse error value is lower than P5-00, output /COIN signal. Monitor the pulse error value via U-08.



5-3-7. Positioning near (/NEAR)

Positioning near signal means the servo motor is near the positioning complete. It prompts the device to prepare the next operation.

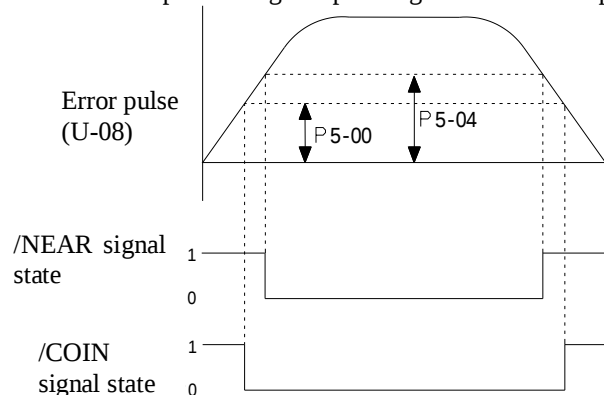
Parameter	Signal	Default	Meaning	Modify
P5-36	/NEAR	n.0000	Need to distribute	Range: 0000-0013, distribute to output terminal via P5-36. When it set to 0001, it means output from SO1.

Note: /NEAR can be output from terminal by setting P5-36, please see chapter 5-12-3.

P5-04	Width of positioning near signal					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1 reference unit	50	0~10000	5, 6	Servo OFF	Immediately

Function: when the pulse error signal is lower than P5-04, output /NEAR signal.

Set the parameter wider than positioning complete signal. Monitor the pulse error value via U-08.



Note: here is signal state, but not terminal state.

5-3-8. Command pulse prohibition (/INHIBIT)

To stop the command pulse input in position control mode. When /INHIBIT signal is ON, the command pulse stop counting.

Input signal setting:

Parameter	Signal	Default	Meaning	Modify
P5-22	/INHIBIT	n.0000	Need to distribute	Range: 0000-0015. When it set to 0001, it means input from S11.

Note: /INHIBIT can be input from input terminal by setting P5-22. Please refer to chapter 5-12-1

5-4. Position mode (internal position mode)

Parameter		
Parameter	Name	Reference
P0-01	Control mode selection	5-4-1
P2-10	Internal position given mode	5-4-2
P2-11~P2-90	Internal 1~16 segment position parameters	5-4-3
P5-25	Change the step signal /CHGSTP	5-4-4
P5-22	Pause current signal /INHIBIT	5-4-5
P5-21	Skip current signal /Z-CLAMP	5-4-6
P5-10	Servo ON signal /S-ON	5-2-1

Other parameters			
Key words	Parameter	Name	Reference
Find the origin	P2-94	The quantity pass through the Z phase signal after leaving the limit switch	5-4-7
	P2-95	The speed near the limit switch	
	P2-96	The speed leave the limit switch	
	P5-17	/SPD-D: define the origin in position mode	
	P5-18	/SPD-A: find the reference origin at forward side in position mode	
	P5-19	/SPD-B: find the reference origin at reverse side in position mode	
Pulse error clear	P5-24	Pulse error clear	5-3-5
Positioning complete	P5-28	Positioning complete signal output /COIN	5-3-6
	P5-00	Positioning complete width	
Positioning near	P5-36	Positioning near signal output /NEAR	5-3-7
	P5-04	Positioning near signal width	
Set segment no. through communication	P2-97	Any setting of 16 segments position	5-4-8

5-4-1. Control mode selection

Parameter	Default	Meaning	Modify	Effective
P0-01	5	Internal position mode control	Servo OFF	Immediately
Function: control the position with the value in servo internal register				

5-4-2. Internal position mode

Parameter	Content	Unit	Default	Suitable mode	Modify	Effective
P2-10	Internal position mode setting	—	n.0000	5	Servo OFF	Re-power on
	Parameter setting	Function	Default	Range		
	n.□xxx	No meaning				
	n.x□xx	Wait mode	0	0~1		
	n.xx□x	Change step mode	0	0~3		
	n.xxx□	Positioning mode	0	0~1		

Mode explanation:

(1) Wait mode

n.X□XX	Meaning
0	Wait for the completion of positioning
1	Not wait for the completion of positioning

Notes: the wait mode means whether the drive waiting for the completion of positioning in internal position setting mode. This is effective in any change step mode.

Wait mode = 0, adjust time = 0ms	Wait mode = 0, adjust time > 0ms
----------------------------------	----------------------------------

After the drive output 1-segment position command, it will wait for the completion of motor positioning, and then start the next position command at once. T1 is positioning time, which means the time from pulse output complete to the output of positioning completion signal.

After the drive output 1-segment position command, it will wait for the completion of motor positioning, and pass the adjust time, then start the next position command. T1 is positioning time, T2 is adjust time. Refer to parameter P2-14.

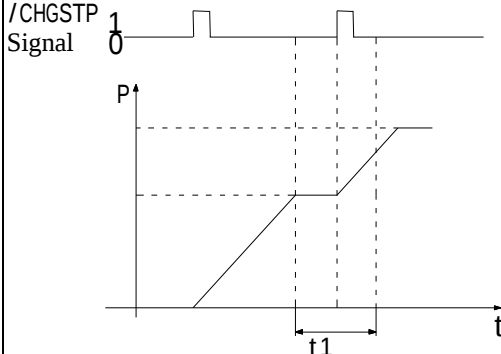
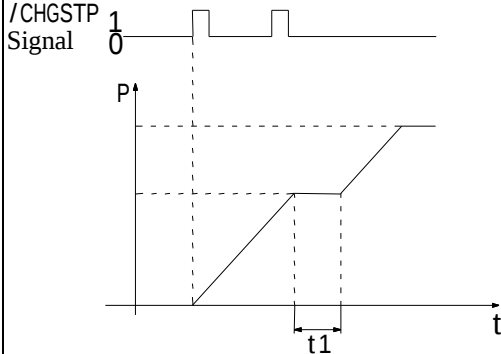
Wait mode = 1, adjust time = 0ms	Wait mode = 1, adjust time > 0ms
----------------------------------	----------------------------------

After the drive output 1-segment position command, it will not wait for the completion of motor positioning, and start the next position command at once.

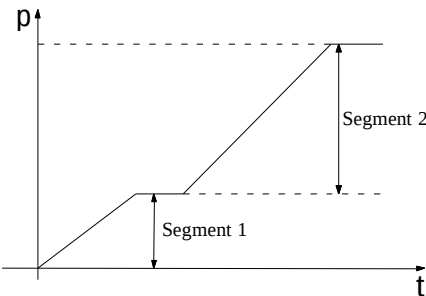
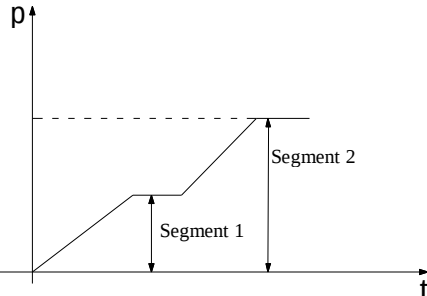
After the drive output 1-segment position command, it will not wait for the completion of motor positioning, but pass the adjust time, and then start the next position command. T2 is adjust time. Refer to parameter P2-14.

(2) Change step mode

n.XX□X	Explanation
0: Change the step when signal is ON, recycling	/CHGSTP 1 Signal 0 t1=P2-14, t2=P2-19 - If /CHGSTP is ON, servo will run segment 1 and 2. - If /CHGSTP is OFF in one segment, servo will finish this segment and stop

	running the next segment.
1: Change the step at the rising edge of the signal, single-step run	 Suppose there are 2 segments. $t_1 = P2-14$ In this mode, the adjust time is ineffective. The servo will run the next command once the current pulse is finished.
2: Start at the rising edge of the signal, sequential run all, not recycling	 Suppose there are 2 segments. $t_1 = P2-14$ /CHGSTP signal is ineffective when one cycle has not been finished, such as the second /CHNGSTP signal in the diagram.
3: set segment no. through communication	Servo is ON, set parameter P2-97=0, then set the running segment.

(3) Positioning mode

n.xxx□	Meaning
0	Relative positioning
1	Absolute positioning
0: relative positioning	1: absolute positioning (take the accumulate position origin as the absolute positioning origin)
	

5-4-3. Position parameters from segment 1 to 16

P2-5(n+1)+1	Pulse number (low bit)					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1 pulse	0	-9999~9999	5	Servo OFF	Immediately
P2-5(n+1)+2	Pulse number (high bit)					
	Unit	Default	Range	Suitable mode	Modify	Effective
	10000 pulses	0	-9999~9999	5	Servo OFF	Immediately
P2-5(n+1)+3	Speed					
	Unit	Default	Range	Suitable mode	Modify	Effective
	0.1rpm	0	0~50000	5	Servo OFF	Immediately
P2-5(n+1)+4	Adjust time					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1ms	0	0~65535	5	Servo OFF	Immediately
P2-5(n+1)+5	Filter time					
	Unit	Default	Range	Suitable mode	Modify	Effective
	0.1ms	0	0~65535	5	Servo OFF	Immediately

Notes: 1. Set pulse number = pulse number (high bit) × 10000 + pulse number (low bit).
2. In formula P2-5(n+1) + 1, n is the segment no. of internal position; the range is 1~16.
3. If one of the segment speed is zero, servo will skip this segment and run the next segment.
4. In relative positioning mode, if one segment speed is not zero but the pulse number is zero, the motor will not run, but the wait mode is effective. The servo will run the next segment when the adjust time is out.
5. In absolute positioning mode, if one segment speed is not zero but the pulse number is zero, the motor will return to the reference origin with the speed of this segment.
6. In absolute positioning mode, if 2 consecutive segments speed are not zero, but the pulse number is the same, the servo motor will not run but the wait mode is effective.

5-4-4. Change step (/CHGSTP)

Parameter	Signal	Type	Default	Meaning	Modify
P5-25	/CHGSTP	Input	n.0000	Need distribute	Range: 0000-0015. Distribute to input terminal through P5-25. When it set to 0001, it means input from SI1.

Note: /CHGSTP can be distributed to other input terminal by setting the parameter P5-25. Refer to chapter 5-12-1.

5-4-5. Pause current signal (/INHIBIT)

When /INHIBIT signal is ON, the internal position pulse will stop in internal position mode. When /INHIBIT signal is OFF, the motor will continue running this stage.

Input signal setting:

Parameter	Signal	Default setting	Meaning	Modify
P5-22	/INHIBIT	n.0000	Need to distribute	Range: 0000-0015. Distribute to input terminal through P5-22. When it set to 0001, it means input from SI1.

1./INHIBIT signal is distributed to I/O terminal via P5-22, refer to chapter 5-12-1.

5-4-6. Skip current signal (/ZCLAMP)

/Z-CLAMP signal	Change step mode	Execution
	0	Cancel current stage, execute the next stage at once
	1	Cancel current stage, execute the next stage when the change step signal is ON
	2	Cancel current stage, execute the next stage at once
	3	Cancel current stage, execute the next stage at once

Parameter	Signal	Default	Meaning	Modify
P5-21	/Z-CLAMP	n.0000	Need to distribute	Range: 0000-0015. Distribute to input terminal through P5-21. When it set to 0001, it means input from SI1.

5-4-7. Reference origin

(1) Find the reference origin

To find out the physical origin of working table and make it as the coordinates origin of point position control. Users can select finding reference origin at forward or reverse side.

Function setting:

P2-94 n.xx□x	Unit	Default	Range	Suitable mode	Modify	Effect
	-	0	0~1	5, 6	ServoOFF	Re-power on

Note: P2-94=0, find reference origin function is invalid. P2-94=n.001x, this function is valid.

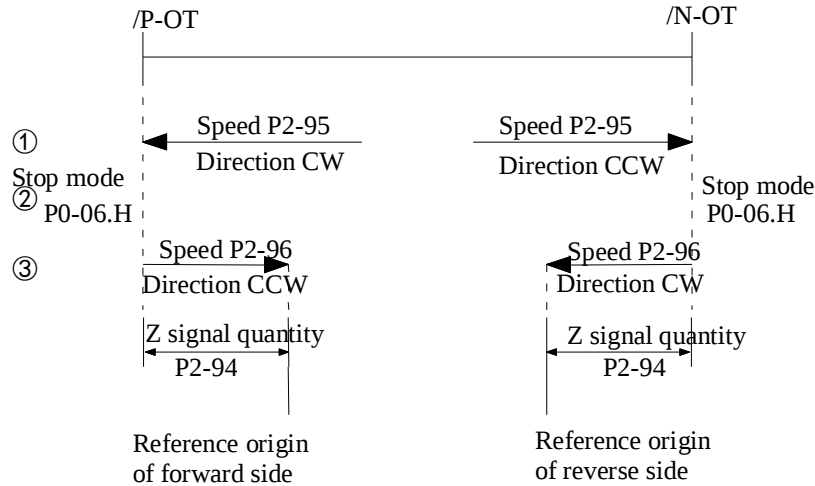
Signal setting:

Parameter	Signal	Default	Meaning	Modify
P5-18	/SPD-A	n.0005	Mode 3: input internal speed signal from SI5	Range: 0000-0015, distributes to input terminal through P5-18. When it set to 0001, it means input signal from SI1.
			Mode 5/6: input signal from SI5. Find origin point at forward direction	
P5-19	/SPD-B	n.0000	Mode 3: not distribute the terminal, internal speed signal	Range: 0000-0015, distributes to input terminal through P5-19. When it set to 0001, it means input signal from SI1.
			Mode 5/6: not distribute the terminal, find origin point at forward direction	

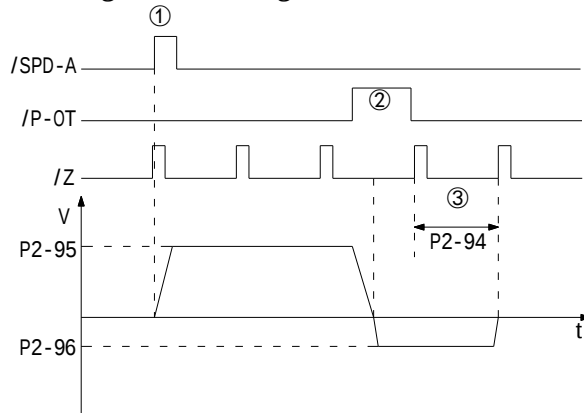
Related parameter setting:

P2-94 n.xxx□	The quantity pass the Z phase signal after leaving the limit switch					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1	2	1~F	5, 6	Servo OFF	Immediately
P2-95	The speed hitting the proximity switch					
	Unit	Default	Range	Suitable mode	Modify	Effective
	0.1rpm	600	0~50000	5, 6	Servo OFF	Immediately
P2-96	The speed leaving the proximity switch					
	Unit	Default	Range	Suitable mode	Modify	Effective
	0.1rpm	100	0~50000	5, 6	Servo OFF	Immediately

Detailed explanation:
Find reference origin diagram:



The timing diagram of finding reference origin of forward side:



Steps:

1. Install limit switch at forward and reverse side. At the rising edge of /SPD-A, motor runs forward at the speed of P2-95 to find the reference origin of forward side.
2. After the working table hit the limit switch, the motor stop as the mode set by parameter P0-06.H.
3. Motor leaves the limit switch at the speed of P2-96. After the working table left the limit switch, the motor run at the Z phase signal position of No.n optical encoder. This position is considered as the coordinates origin, n is decided by parameter P2-94.

(2) Define the reference origin

Parameter	Signal	Default	Meaning	Modify
P5-17	/SPD-D	n.0000	Mode 1,2,3,4: not distribute to the terminal. To switch the rotation direction.	Range: 0000-0015. Distribute to input terminal through P5-17. When it set to 0001, it means input signal from S11.
			Mode 5,6: not distribute to the terminal. To define the current point to origin.	

5-4-8. Set segment through communication

P2-97 n.xx□□	Unit	Default	Range	Suitable mode	Modify	Effective
	-	0	0~16	5	Anytime	Immediately
This parameter is set to certain segment, it will execute this segment. No need step change signal. This parameter can be changed through communication. For example: execute segment 2. Set P2-97=0, then set P2-97=02.						

5-5. Speed control (analog voltage command)

Basic parameters		
Parameter	Name	Reference
P0-01	Select the control mode	5-5-1
P3-00	Analog value of rated speed	5-5-2
P5-10	Servo ON signal /S-ON	5-2-1

Other parameters			
Key words	Parameter	Name	Reference
Zero drift adjustment	F1-03	Analog voltage speed command offset auto-adjustment	5-5-3
Proportion action	P5-11	P-CON	5-5-4
Zero clamp	P5-21	Zero clamp /ZCLAMP	5-5-5
	P5-01	Zero clamp speed	
Speed coincidence checking	P5-29	/V-CMP speed coincidence checking	5-5-6
	P5-03	Coincidence speed signal checking width/V-CMP	
Torque limit	P4-02	Forward torque limit	5-5-7
	P4-03	Reverse torque limit	
	P0-07	T-REF distribution	
	P4-04	Forward external torque limit	
	P4-05	Reverse external torque limit	
	P5-15	Forward external torque limit /P-CL	
	P5-16	Reverse external torque limit /N-CL	
	P5-32	Output when torque reaches limit value /CLT	
Soft start	P3-05	Soft start acceleration time	5-5-8
	P3-06	Soft start deceleration time	
Filter	P3-07	Speed command filter time	5-5-9
	P3-08	Speed feedback filter time	
Death area	P3-10	Speed command death area input voltage	5-5-10
/SPD-D direction selection	P5-17	Change the direction	5-6-3

5-5-1. Control mode selection

Parameter	Set value	Meaning	Modify	Effective
P0-01	4	Analog voltage command speed control	Servo OFF	Immediately
Function: control the speed by the signal (analog voltage command) input from V-REF terminal				

5-5-2. Analog value of rated speed

P3-00	Analog value of rated speed					
	Unit	Default	Range	Suitable mode	Modify	Effective
	0.01V/rated speed	1000	150~3000	4	Servo OFF	Immediately
Function: the speed command voltage (V-REF) to run the servo motor at rated speed. Such as: P3-00=500 means the motor run at rated speed when analog input voltage = 5.00V P3-00=800 means the motor run at rated speed when analog input voltage = 8.00V.						

Analog command input please refers to chapter 3-2-3.

5-5-3. Speed command offset auto-adjustment (F1-03)

When the servo is in analog voltage speed mode, even if the command voltage is 0V, motor will run at very low speed. The micro-motion will happen when the command voltage micro-offset (mV) of host controller or external circuit occurs. Auto-adjust the command offset by operate panel of servo. Refer to chapter 4-4-2.

5-5-4. Proportion action command (/P-CON)

Parameter	Signal	Type	Default	State	Meaning	Modify	Effective
P5-11	/P-CON	Input	n.0000	Effective	Run in P control mode	Any	Re-power on
				Ineffective	Run in PI control mode		
1. /P-CON is the speed control mode signal selected from PI (proportion integral) and P (proportion). 2. If set to P control mode, the motor rotate and micro-vibration caused by speed command input drift can be decreased. But the servo stiffness will decrease. 3. /P-CON signal can be distributed to input terminal via parameter P5-11. Refer to chapter 5-12-1.							

5-5-5. Zero clamp (/ZCLAMP)

(1) Function

This function is used when host controller uses speed command input and the servo system isn't configured the position loop. In other words, the function will be used when the motor must stop and enter lock state even the V-REF input voltage is not zero. After the zero clamp function is ON, servo will configure the temporary position loop inside, motor will clamp in ± 1 pulse. Motor will return to zero clamp position even the motor is rotating with external force.

(2) Input signal setting

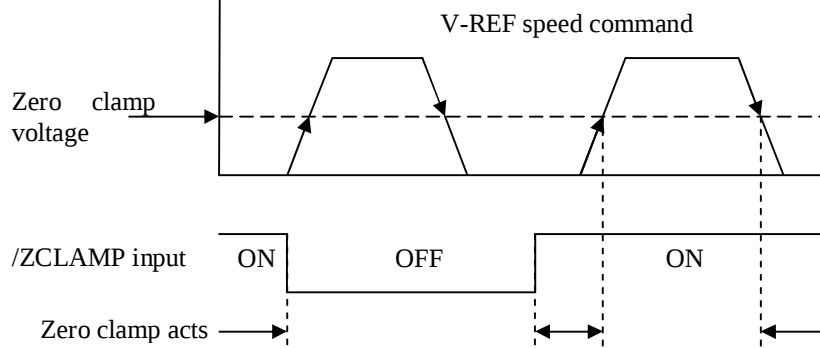
Parameter	Signal	Type	Default	Meaning	Modify
P5-21	/Z-CLAMP	Input	n.0000	Need to distribute	Range: 0000-0015.
Note: /Z-CLAMP signal is distributed to input terminal by parameter P5-21, refer to chapter 5-12-1.					

(3) Parameter setting

P5-01	Speed of zero clamp					
	Unit	Default	Range	Suitable mode	Modify	Effective
	Rpm	10	0~300	3, 4, 7	Servo OFF	Immediately

Zero clamp will act when meets the following conditions:

- Speed control (submode 3 or 4)
- Set ON /ZCLAMP
- Speed command value is less than the value of P5-01



5-5-6. Speed coincidence checking (/V-CMP)

When motor speed is equal to the command speed, servo outputs speed coincidence signal (V-CMP).

Parameter	Signal	Default	Meaning	Modify
P5-29	/V-CMP	n.0000	Need to distribute	Range: 0000-0013. Distribute to output terminal through P5-29. When it set to 0002, it means output from SO2.

P5-03	Speed coincidence signal width					
	Unit	Default	Range	Suitable mode	Modify	Effective
	rpm	10	1~250	3, 4, 7	Servo OFF	Immediately

If the difference between motor speed and command speed is less than the value of P5-03, servo outputs /V-CMP signal.

5-5-7. Torque limit

5-5-7-1. Internal torque limit (output torque max value limit)

The function is to limit the max output torque by parameters.

P4-02	Forward torque limit					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1%	300	0~300	All modes	Servo OFF	Immediately
P4-03	Reverse torque limit					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1%	300	0~300	All modes	Servo OFF	Immediately

1. This parameter is always effective, if this parameter value is less than external torque limit value, the final limit value is this parameter.
2. The unit is percent of the motor rated torque; the default value is 300%. The real output torque is different for each type.

5-5-7-2. External torque limit (via input signal)

This function is used in machine motion or timing torque limit. For example: press stop action or robot workpiece protection.

The torque limit value will be effective when the input signal is ON.

P4-04	Forward external torque limit					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1%	100	0~300	All modes	Servo OFF	Immediately
P4-05	Reverse external limit					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1%	100	0~300	All modes	Servo OFF	Immediately
The unit is the percent of motor rated torque; the default value is 100%.						

Parameter	Signal	Type	Default	Meaning	Modify
P5-15	/P-CL	Input	n.0000	Need to distribute	Range: 0000-0015.
P5-16	/N-CL	Input	n.0000	Need to distribute	Range: 0000-0015.

Notes: /P-CL, /N-CL can be distributed to input terminal by parameter P5-15, P5-16. Refer to chapter 5-12-1.

Function realization:

Signal	State	Meaning	Effective limit value
/P-CL	0	Forward external torque limit OFF	P4-02
	1	Forward external torque limit ON	Min value between P4-02 and P4-04
/N-CL	0	Reverse external torque limit OFF	P4-03
	1	Reverse external torque limit ON	Min value between P4-03 and P4-05

5-5-7-3. External torque limit (via analog voltage command)

T-REF terminal is used as analog voltage command terminal. Please note in external analog torque control mode, this function cannot be used.

Parameter	Function	Set value	Meaning	Modify	Effective
P0-07	Distribute function to T-REF	1	Make T-REF as external torque limit input	Servo OFF	Re-power on

1. For analog voltage command input of torque limit. Get the absolute value of the voltage, the torque limit value based on the absolute value is suitable for forward and reverse direction.
2. When it is used as torque limit, the value is related to voltage command and P4-00. For example, P4-00=1000, T-REF voltage command is 5.0V, the torque limit value is 50% of rated torque.

5-5-7-4. External torque limit (via external input + analog voltage)

External torque limit via external input and analog voltage can be used together.

Input analog voltage signal from T-REF. the torque limit function cannot be used when servo is in analog command torque control mode.

Use /P-CL and /N-CL signal when limit torque via external input.

(1) Parameters

Parameter	Function	Set value	Meaning	Modify	Effective
P0-07	T-REF function distribution	3	When P-CL, N-CL is ON, make T-REF as external torque limit input.	Servo OFF	Re-power on

P4-04	Forward external torque limit					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1%	100	0~300	All modes	Servo OFF	Immediately
P4-05	Reverse external torque limit					
	Unit	Default	Range	Suitable mode	Modify	Effective

	1%	100	0~300	All modes	Servo OFF	Immediately
Note: the unit is the percent of motor rated torque, the default value if 100%.						

(2) Input signal setting

Parameter	Signal	Type	Default	Meaning	Suitable mode	Modify	Effective
P5-15	/P-CL	Input	n.0000	Need to distribute	All modes	Any	Re-power on
P5-16	/N-CL	Input	n.0000	Need to distribute	All modes	Any	Re-power on
Note: /P-CL, /N-CL signal can be distributed to input terminal by parameter P5-15, P5-16. Refer to chapter 5-12-1.							

(3) Function realization

Signal	State	Meaning	Limit value
/P-CL	0	Forward external torque limit OFF	P4-02
	1	Forward external torque limit ON	The min value among P4-02, P4-04 and analog voltage command
/N-CL	0	Reverse external torque limit OFF	P4-03
	1	Reverse external torque limit ON	The min value among P4-03, P4-05 and analog voltage command

5-5-7-5. Output torque up to limit value signal

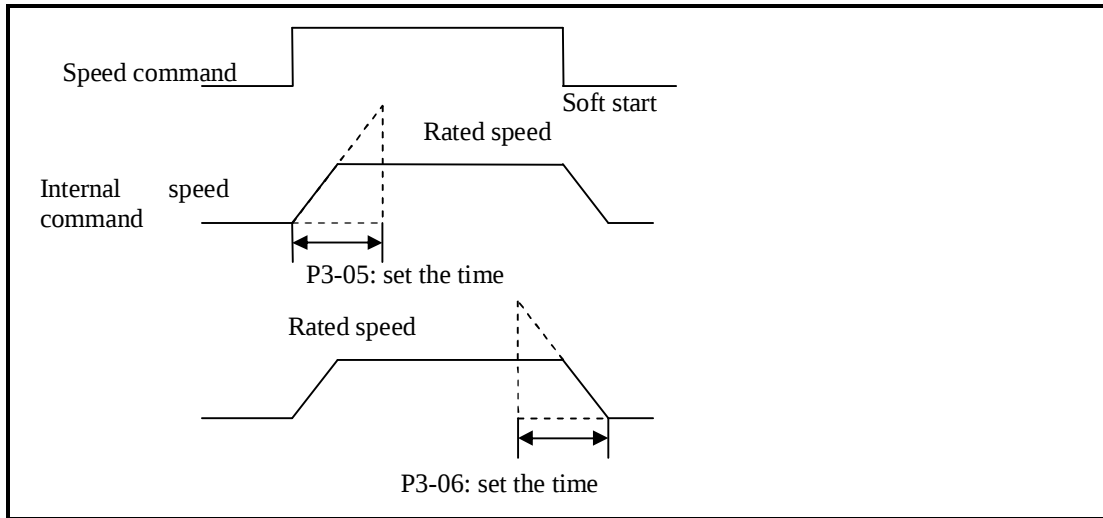
The signal means the motor output torque reaches limit value.

Parameter	Signal	Type	Default	Meaning	Modify
P5-32	/CLT	Output	n.0000	Need to distribute	Range: 0000-0013.
Note: /CLT signal can be distributed to output terminal by parameter P5-32. Refer to chapter 5-12-3.					

5-5-8. Soft start

Soft start can transform the step speed command to command with acceleration/deceleration.

P3-05	Soft start acceleration time					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1ms	0	0~65535	3, 4, 7	Servo OFF	Immediately
P3-06	Soft start deceleration time					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1ms	0	0~65535	3, 4, 7	Servo OFF	Immediately
1. Enable to do smooth speed control when input step speed command or choose internal speed. Other cases please set to 0. 2. acceleration/deceleration time is from stop state to rated speed but not from current speed to target speed. P3-05: the time from stop state to rated speed. P3-06: the time from rated speed to stop state.						



5-5-9. Filter

P3-07	speed command filter time					
	Unit	Default	Range	Suitable mode	Modify	Effective
	0.01ms	0	0~65535	3, 4, 5, 6, 7	Servo OFF	Immediately
The speed command passes the 1-time delay filter and become smooth speed command. If set it too large, the reponse will be slow.						
P3-08	speed feedback filter time					
	Unit	Default	Range	Suitable mode	Modify	Effective
	0.01ms	0	0~65535	3, 4, 5, 6, 7	Servo OFF	Immediately
Smooth filter the speed feedback. If set it too large, the speed feedback will distort and affect the control result.						

5-5-10. Speed command input dead voltage

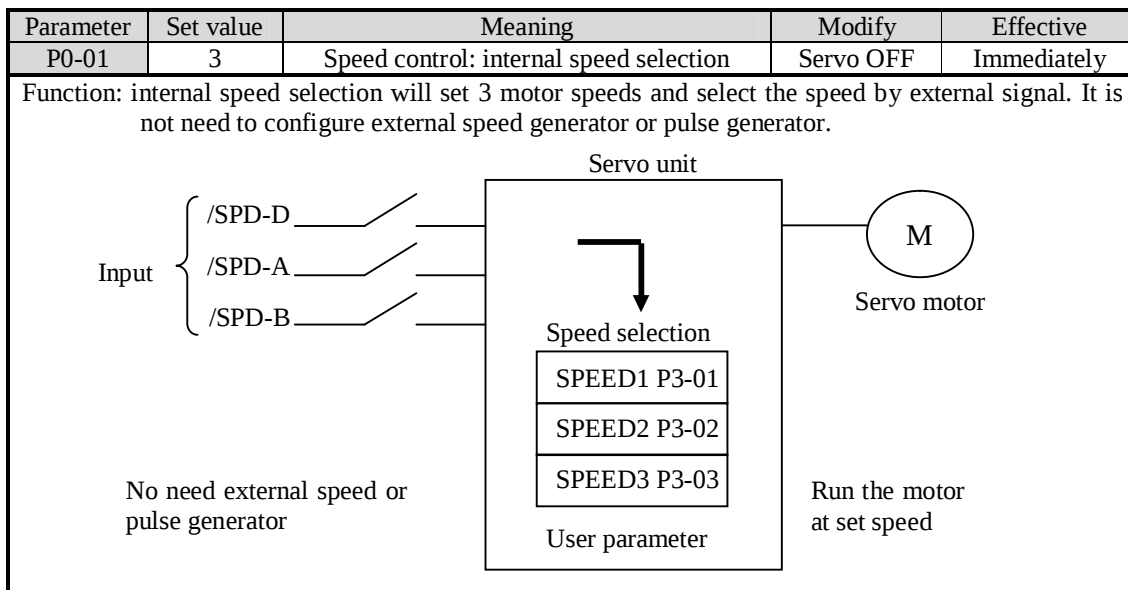
P3-10	Speed command input dead voltage					
	Unit	Default	Range	Suitable mode	Modify	Effective
	0.01V	0	0~100	4	Servo OFF	Immediately
Note: if the input speed command voltage is in the range of this parameter, the input voltage is considered to be 0.						

5-6. Speed control (internal speed)

Basic parameter		
Parameter	Name	Reference
P0-01	Control mode selection	5-6-1
P5-10	Servo ON signal /S-ON	5-2-1
P3-01	Internal speed 1	5-6-2
P3-02	Internal speed 2	
P3-03	Internal speed 3	
P5-17	/SPD-D internal speed direction selection	5-6-3
P5-18	/SPD-A internal speed selection	
P5-19	/SPD-B internal speed selection	

Other parameters			
Key word	Parameter	Name	Reference
Proportion action	P5-11	Proportion action command /P-CON	5-5-4
Zero clamp	P5-21	Zero clamp /ZCLAMP	5-5-5
	P5-01	Zero clamp speed	
Speed coincidence checking	P5-29	/V-CMP speed coincidence checking	5-5-6
	P5-03	speed coincidence checking signal width /V-CMP	
Torque limit	P4-02	forward torque limit	5-5-7
	P4-03	reverse torque limit	
	P1-07	T-REF distribution	
	P4-04	Forward external torque limit	
	P4-05	Reverse external torque limit	
	P5-15	Forward external torque limit /P-CL	
	P5-16	Reverse external torque limit /N-CL	
	P5-32	Torque up to limit value output /CLT	
Soft start	P3-05	soft start acceleration time	5-5-8
	P3-06	soft start deceleration time	
Filter	P3-07	Speed command filter time	5-5-9
	P3-08	Speed feedback filter time	

5-6-1. Control mode selection



5-6-2. Internal speed setting

P3-01	Internal speed 1					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1rpm	100	-5000 ~ +5000	3	Any	Immediately
P3-02	Internal speed 2					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1rpm	200	-5000 ~ +5000	3	Any	Immediately
P3-03	Internal speed 3					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1rpm	200	-5000 ~ +5000	3	Any	Immediately

5-6-3. Input signal setting

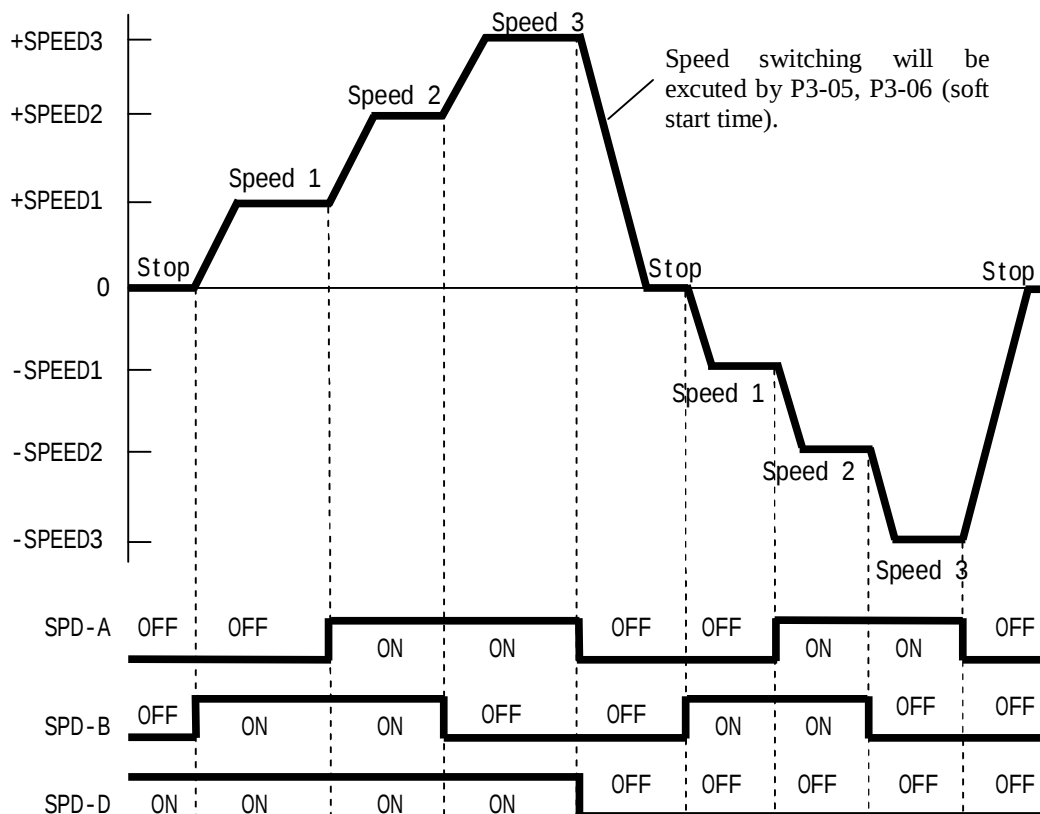
Switch the running speed by below input signal:

Parameter	Signal	Default	Meaning	Modify
P5-17	/SPD-D	n.0000	Need to distribute	Range: 0000-0015. Distribute to input terminal through P5-17.
P5-18	/SPD-A	n.0000	Need to distribute	Range: 0000-0015. Distribute to input terminal through P5-18.
P5-19	/SPD-B	n.0000	Need to distribute	Range: 0000-0015. Distribute to input terminal through P5-19.

(1) Function realization

Input signal			Direction	Running speed
/SPD-D	SPD-A	SPD-B		
0	0	0	Forward	Internal speed is zero
	0	1		P3-01: SPEED1
	1	1		P3-02: SPEED2
	1	0		P3-03: SPEED3
1	0	0	Reverse	Internal speed is zero
	0	1		P3-01: SPEED1
	1	1		P3-02: SPEED2
	1	0		P3-03: SPEED3

(2) Running example



5-7. Speed control (pulse frequency command)

Basic parameter			
Parameter	Name		Reference
P0-01	Control mode selection		5-7-1
P5-10	Servo ON signal /S-ON		5-2-1
P2-00	Pulse command form		5-3-2
P2-06	Command pulse frequency at rated speed		5-7-3
P2-07	Speed command pulse filter time		5-7-4
Other parameters			
Key words	Parameter	Name	Reference
Proportion	P5-11	Proportion action command /P-CON	5-5-4
Zero clamp	P5-21	Zero clamp /ZCLAMP	5-5-5
	P5-01	Zero clamp speed	
Speed coincidence checking	P5-29	Speed coincidence checking /V-CMP	5-5-6
	P5-03	Coincidence speed checking signal width /V-CMP	
Torque limit	P4-02	Forward torque limit	5-5-7
	P4-03	Reverse torque limit	
	P1-07	T-REF distribution	
	P4-04	Forward external torque limit	
	P4-05	Reverse external torque limit	
	P5-15	Forward external torque limit /P-CL	
	P5-16	Reverse external torque limit /N-CL	
	P5-32	Torque up to limit value output /CLT	
Filter	P3-08	Speed feedback filter time	5-5-9

5-7-1. Control mode selection

Parameter	Set value	Meaning	Modify	Effective
P0-01	7	Speed control: pulse frequency speed command	Servo OFF	Immediately
Function: speed command is decided by external pulse frequency, but not related to pulse quantity. The wiring is the same as position command. Select CW, CCW mode or direction + pulse mode.				

5-7-2. Pulse frequency command

Pulse frequency command is the same as external pulse command position control (mode 6), refer to chapter 5-3-2.

5-7-3. Command pulse frequency at rated speed

P2-06	command pulse frequency at rated speed					
	Unit	Default	Range	Suitable mode	Modify	Effective
	100Hz	5000	1~10000	7	Servo OFF	Immediately
Note: the unit is 100Hz. Example: P2-06=1000, command pulse frequency at rated speed=100kHz; P2-06=300, command pulse frequency at rated speed= 30kHz.						

5-7-4. Speed command pulse filter time

P2-07	speed command pulse filter time					
	Unit	Default	Range	Suitable mode	Modify	Effective
	0.1ms	20	0~1000	7	Servo OFF	Immediately

When the command pulse frequency is low, setting a suitable value for this parameter can decrease the speed fluctuation.

5-8. Torque control (analog voltage command)

Parameter		
Parameter	Name	Reference
P0-01	Control mode selection	5-8-1
P4-00	The analog value of rated torque	5-8-2
P5-10	Servo ON signal /S-ON	5-2-1

Other parameters			
Key words	Parameter	Name	Reference
Zero drift adjustment	F1-04	Torque command offset auto-adjustment	5-8-3
Filter	P4-01	Torque command filter time	5-8-4
Speed limit	P4-07	internal speed limit in torque control mode	5-8-5
	P3-09	Max speed control (MAX speed)	
	P0-08	V-REF function distribution	
	P5-33	Speed up to limit value output	
Dead area	P4-10	Torque command input dead area voltage	5-8-6
/SPD-D direction selection	P5-17	Speed direction changing	5-6-3

5-8-1. Control mode selection

Parameter	Set	Function	Modify	Effective
P0-01	2	Torque control: analog voltage command	Servo OFF	Immediately

Function: Control the torque by the analog voltage signal input from T-REF terminal.

5-8-2. The analog value of rated torque

P4-00	The analog value of rated torque					
	Unit	Default	Range	Suitable mode	Modify	Effective
	0.01V/rated torque	1000	150~3000	2	Servo OFF	Immediately

Function: set the speed command voltage (T-REF) to run the servo motor at rated speed
 Example: P4-00=500, motor run at rated torque when analog input voltage is 5.00V
 P4-00=800, motor run at rated torque when analog input voltage is 8.00V

Refer to chapter 3-2-4 for analog torque command input.

5-8-3. Torque command offset autoadjustment (F1-04)

The motor will run at microspeed even the command voltage is 0V in analog voltage torque mode. This situation will happen when host controller or the command voltage of external circuit has micro-offset (mV). Use the operate panel to auto-adjust the offset. Refer to chapter 4-4-2.

5-8-4. Torque command filter time

P4-01	torque command filter time					
	Unit	Default	Range	Suitable mode	Modify	Effective
	0.01ms	0	0~65535	1, 3, 4, 5, 6, 7	Servo stop	Immediately
1-time delay filter will smooth the torque command. If set the value too large, the reponse will be decreased.						

5-8-5. Torque limit

5-8-5-1. Internal speed limit

Limit the speed of torque control by setting below parameters:

P4-07	internal speed limit in torque control mode					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1rpm	2000	0~5000	1, 2	Servo OFF	Immediately
Note: the actual speed is max speed even this parameter speed is larger than the max speed.						

P3-09	max speed limit					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1rpm	1500:2000 2500:3000 3000:4000	0~5000	All modes	Servo OFF	Immediately
Note: 1. P3-09 is effective in all modes. 2. Default setting is different for each type. For example: max speed is 2000 for rated speed 1500 motor, max speed is 4000 for rated speed 3000 motor. 3. This parameter is related to E-008 and E-010. If motor speed is larger than max speed+200, servo will show E-008 over-speed. If the pulse frequency converts to motor speed, the speed is larger than max speed; but the actual motor speed is max speed. Then the pulse offset will accumulate, servo will show E-010 alarm.						

5-8-5-2. External speed limit

Limit the speed output of torque control mode by the analog voltage command input from V-REF terminal.

Parameter	Function	Set value	Meaning	Modify	Effective
P0-08	V-REF function distribution	1	Make V-REF as external speed limit input	Servo stop	Immediately
1. The analog voltage has no polarity. The absolute value of the voltage is suitable for forward and reverse direction. 2. The parameter value is related to voltage command and P3-00 when it is used as speed limit value. For example: P3-00=500 (voltage of rated speed is 5.0V), T-REF voltage command is 1.0V, the speed limit is 20% of rated speed. 3. P0-08=1, the actual limit value is the smaller value among V-REF speed limit input and P4-07.					

5-8-5-3. Speed up to limit value output

Parameter	Signal	Default	Meaning	Modify
P5-33	/VLT	n.0000	Need to distribute	Range: 0000-0013. Distribute to output terminal through P5-33. When it set to 0001, it means output from SO1.

5-8-6. Torque command input dead area voltage

P4-10	Torque command input dead area voltage					
	Unit	Default	Range	Suitable mode	Modify	Effective
	0.01V	0	0~100	2	Servo OFF	Immediately

Note: if the input torque command voltage is smaller than this parameter, the torque command is 0.

5-9. Torque control (internal setting)

Basic parameter		
Parameter	Name	Reference
P0-01	Control mode selection	5-9-1
P5-10	Servo ON signal /S-ON	5-2-1
P4-09	Internal torque command	5-9-2

Other parameters			
Key words	Parameter	Name	Reference
Filter	P4-01	Torque command filter time	5-8-4
Speed limit	P4-07	Internal speed limit of torque control	5-8-5
	P3-09	Max speed limit (max speed)	
	P0-08	V-REF function distribution	
	P5-33	Speed up to limit value output	
/SPD-D direction selection	P5-17	Speed direction change	5-6-3

5-9-1. Control mode selection

Parameter	Set value	Function	Modify	Effective
P0-01	1	Torque control: internal setting	Servo OFF	Immediately

Function: Control the torque by internal torque command.

5-9-2. Internal torque command

P4-09	Internal torque command					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1% rated torque	0	-300~+300	1	Servo OFF	Immediately

The unit of this parameter is 1% of the rated torque.
For example: P4-09=50, motor forward run with 50% of the rated torque;
P4-09= -20, motor reverse run with 20% of the rated torque.

5-10. Switch the control mode

Servo can switch between submode 1 and 2 by external input signal.

(1) Switch signal

Parameter	Signal	Type	Default	Meaning	Modify
P5-20	/C-SEL	Input	n.0000	Need to distribute	Range: 0000-0015.
Note: /C-SEL can be distributed to input terminal via parameter P5-20, refer to chapter 5-12-1.					

(2) Function realization

Signal	State	Control mode
/C-SEL	0	P0-01: submode 1
	1	P0-02: submode 2

5-11. Other output signals

5-11-1. /ALM and /ALM-RST

■ Servo alarm output /ALM

Parameter	Signal	Type	Default	Meaning
P5-37	/ALM	Output	n.0002	Output always open signal from SO2

■ Alarm reset /ALM-RST

Parameter	Signal	Type	Default	Meaning	Range
P5-14	/ALM-RST	Input	n.0002	Input always open signal from SI2	0000-0015
- Find the alarm reason and fix it, then clear the alarm via this signal. /ALM-RST can be distributed to input terminal via this parameter. As the alarm signal is related to the safe running of servo, /ALM-RST signal cannot be set to always effective. (n.0010); - The alarm related to encoder such as E-013, E-014 cannot be reset via /ALM-RST. /ALM-RST can be distributed to input terminal via parameter P5-14, refer to chapter 5-12-1.					

5-11-2. /WARN

Parameter	Signal	Type	Default	Meaning	Range
P5-35	/WARN	Output	n.0000	Need to distribute	0000-0013
When the warning happens, servo will not be forced OFF but output the warning.					

5-11-3. Rotation checking (/TGON)

(1) Signal setting

Parameter	Signal	Type	Default	Meaning	Range
P5-30	/TGON	Output	n.0000	Need to distribute	0000-0013
- The servo will be considered in the rotation when the servo motor speed is higher than P5-02. - The application function related to /TGON is /BK power-off brake. /TGON can be distributed to output terminal via parameter P5-30, refer to chapter 5-12-3.					

(2) Parameter setting

P5-02	Internal torque command setting					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1rpm	20	1~1000	All modes	Servo OFF	Immediately
Set the range of rotation checking output. If servo motor speed is up to P5-02, the servo motor is considered to be running and output rotation checking signal (/TGON).						

5-11-4. Servo ready (/S-RDY)

Parameter	Signal	Default	Meaning	Range
P5-31	/S-RDY	n.0003	SO3 and COM pass through when servo is ready	0000-0013
		n.0013	SO3 and COM cut off when servo is ready	

5-11-5. Encoder Z phase output (/Z)

DS2-AS series servo supports encoder (Z phase) signal output.

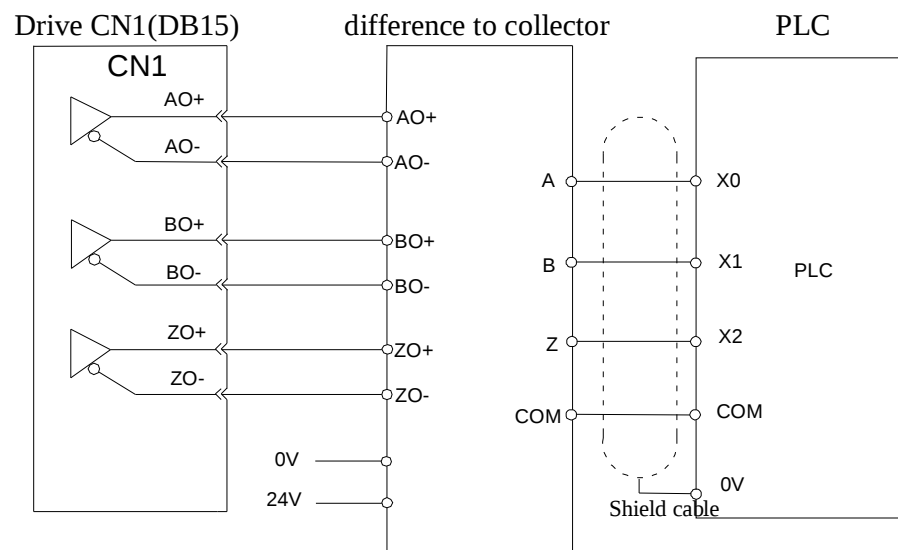
Parameter	Signal	Type	Default	Meaning	Range
P5-38	/Z	Output	n.0000	Need to distribute	0000-0013

1. /Z can be distributed to output terminal via parameter P5-38, refer to chapter 5-12-3.
2. Z phase signal is single pulse output mode. Pulse width is about 1.5ms and not related to motor rotation speed.

5-11-6. AB phase feedback signal of encoder

DS2-2□P□-AS and DS2-4□P□-AS support open collector output AB phase feedback signal.

Please see the following wiring diagram of DS2-21P5-AS and Xinje PLC XC3-32RT-E.



AB phase feedback signal doesn't have parameters to set; it is motor encoder signal 1:1

output, 2500 pulse/circle.

5-12. I/O signal distribution

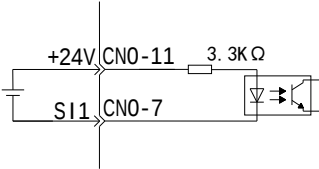
5-12-1. Input signal distribution

DS2-2□P□-AS, DS2-4□P□-AS: P5-10~P5-25

Parameter	Set value	Meaning	Terminal voltage	Terminal state	Signal state
n.00 y x 00: no meaning y: 0 always open 1 always close x: input terminal no.	n.0000	Not distribute to terminal input	-	-	0
	n.000x	Input always open signal from SIx	H	Disconnect to 0V	0
			L	Connect to 0V	1
	n.0010	Set the signal to be always valid	-	-	1
	n.001x	Input always close signal from SIx	H	Disconnect to 0V	1
			L	Connect to 0V	0

Note: if the distributed terminal has other signal, set the signal to other terminal or set to unused.

Example: take the input signal /CLR (P5-24) of DS2-21P5-AS as an example to explain the terminal distribution.

Wiring example of input signal				
 DS2-21P5-AS: CN0-11 is +24V terminal, CN0-7 is SI1 terminal. For the example, distribute /CLR signal to SI1.				
Parameter	Set value	Terminal state	Signal state	Meaning
P5-24	n.0001	Disconnect to 0V	0	Clear the pulse offset at the moment of SI2 and 0V pass through
		Connect to 0V	1	
	n.0011	Disconnect to 0V	1	Clear the pulse offset at the moment of SI2 and 0V cut off
		Connect to 0V	0	

Note: the default input of SI1 is /SON, make sure to distribute P5-10(/SON) to other terminal or set to unused.

5-12-2. Default setting of input terminal

Input Type	SI1	SI2	SI3	SI4	SI5
DS2-2□P□-AS DS2-4□P□-AS	/S-ON	/ALM-RST	/P-OT	/N-OT	/SPD-A

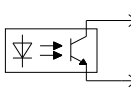
5-12-3. Output terminal distribution

DS2-2□P□-AS, DS2-4□P□-AS: P5-28~P5-38

Parameter meaning	Set value	Meaning	Signal state	Terminal state
n.00 y x 00: pointless y: 0 always open 1 always close x: output terminal no.	n.0000	Not distribute to terminal input	-	-
	n.000x	Output always open signal from SOx	0	Cut off with COM
			1	Pass through with COM
	n.0010	Set the signal to be always valid	-	-
	n.001x	output always close signal from SOx	0	Pass through with COM
			1	Cut off with COM

Note: If the distributed terminal has other signal, please set the signal to other terminal or set to unused.

Example: take /CLT signal of DS2-21P5-AS as an example to explain output terminal distribution.

Output terminal wiring example				
 DS2-21P5-AS: SO1 is CN0-12, COM is CN0-14.				
Parameter	Set value	/CLT	Terminal state	Meaning
P5-32	n.0001	0	SO1 and COM pass through	Output limit signal when motor torque reaches the set value
		1	SO1 and COM cut off	Output limit signal when motor torque reaches the set value

Note: the default output of SO1 is /COIN. Set the P5-28 (/COIN) to other terminal or unused in order to avoid terminal signal conflict.

5-12-4. Default setting of output terminal

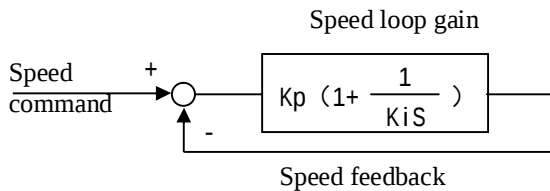
Output terminal Type	SO1	SO2	SO3
DS2-2□P□-AS DS2-4□P□-AS	/COIN	/ALM	/S-RDY

6 Servo gain adjustment

6-1. Gain setting of speed loop

Gain parameters about speed loop:

P1-00	Speed loop gain (Kp)					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1Hz	100	1~5000	3, 4, 5, 6, 7	Any	Immediately
P1-01	Speed loop integral time constant (Ki)					
	Unit	Default	Range	Suitable mode	Modify	Effective
	0.1ms	400	1~5000	3, 4, 5, 6, 7	Any	Immediately



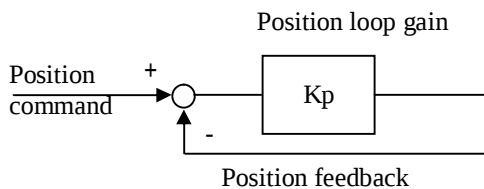
To set the speed loop gain larger and the speed integral time constant smaller can realize high response speed controlling. But servo will restrict by machine performance.

6-2. Gain setting of position loop

Gain parameter about position loop:

P1-02	Position loop gain (Kp)					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1/s	100	1~2000	5, 6	Any	Immediately

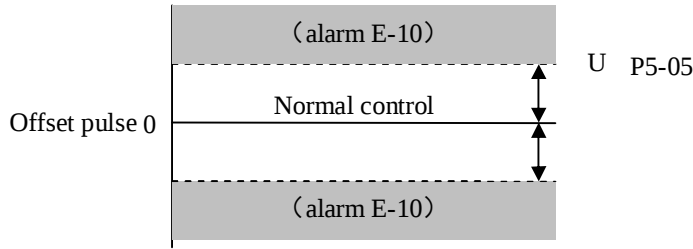
To do position control with high response and less offset needs to set the position loop gain larger. But servo will restrict by machine performance.



In position control mode, the servo will alarm when the offset pulse over the limit value. The value is offset pulse limit parameter:

P5-05	Offset pulse limit					
	Unit	Default	Range	Suitable mode	Modify	Effective
	256*command pulse	1000	0~65535	5, 6	Servo OFF	Immediately

The offset pulse will not be checked when offset pulse limit value is 0.



P1-09	position loop feedforward gain (Kp)					
	Unit	Default	Range	Suitable mode	Modify	Effective
	1%	0	1~100	5, 6	Any	Immediately
The unit is 1% of offset pulse. To increase the feedforward gain of position loop in the case that requires quick response of position loop. If set it too large, the speed loop will overshoot.						
P1-10	feedforward filter time					
	Unit	Default	Range	Suitable mode	Modify	Effective
	0.01ms	0	0~65535	5, 6	Any	Immediately

6-3. The experience of parameter adjustment

First, it is important to know the mechanical structure. Common synchronous machine with driving has less rigidity, decrease the servo rigidity to match it. Large inertia mechanical system has long response time, it needs to decrease the servo rigidity and set more acceleration/deceleration time for speed command. For the mechanical system with small load inertia and strong rigidity such as coupling, it needs to increase the servo rigidity to improve the positioning efficiency.

Servo parameter adjustment method in position mode for typical mechanical system:

(1) Mechanical system: synchronous with coupling, large load inertia.

Servo system: decrease the rigidity, increase speed loop integral time (P1-01), decrease the position loop gain (P1-02). If the response is not enough after adjusting, increase the speed loop gain (P1-00).

Typical setting: P1-00=200, P1-01=2000, P1-02=50.

(2) Mechanical system: synchronous with coupling, small load inertia and load torque.

Servo system: follow the default parameter.

(3) Mechanical system: rigidity coupling, large load inertia.

Servo system: same to (1).

Typical setting: P1-00=100, P1-01=1000, P1-02=80.

(4) Mechanical system: rigidity coupling, small load inertia, strong rigidity.

Servo system: P1-00=100, P1-01=300, P1-02=150. If it cannot meet the requirements, please increase the position loop feedforward, for example set P1-09 to 20.

Note: above typical settings only show the direction to adjust the parameters. The settings cannot be suitable for all the conditions.

6-4. Proportion action command (P-CON)

Input signal /P-CON is switch for P/PI control of speed loop.

P control means proportion control; this mode is called proportion action command.

Input terminal selection of /P-CON:

Parameter	Signal	Type	Default	State	Meaning	Modify	Effective
P5-11	/P-CON	Input	n.0000	1	Run in P control mode	Any	Re-power on
				0	Run in PI control mode		
/P-CON can be distributed to input terminal via parameter P5-11. Refer to chapter 5-12-1.							

This command is suitable for the following cases:

- (1) When the host device sends speed command to the servo and runs with it at the same time, it only selects P mode running under special conditions. The overrange can be deleted by this method and the adjustment time can be shortened.
- (2) When there is command offset in speed controlling, servo will not stop and run at low speed even getting zero speed command in PI control mode. If select P control mode, the servo will stop.

6-5. Gain switch (G-SEL)

This function can switch the gain online.

For example, set different first and second gain by the external signal when the motor is running or stop.

Select the input terminal for /G-SEL signal:

Parameter	Signal	Type	Default	Meaning	Suitable mode	Modify	Effective
P5-23	/G-SEL	Input	n.0000	Need to distribute	3, 4, 5, 6, 7	Any	Re-power on
/G-SEL can be distributed to input terminal via parameter P5-23. Refer to chapter 5-12-1.							

Function realization:

Input signal	Signal state	Gain group
/G-SEL	0	P1-00, P1-01, P1-02
	1	P1-04, P1-05, P1-06
Note: the 0, 1 is signal state but not terminal state.		

7 Specification and dimension

7-1. Servo motor

7-1-1. Servo motor specification

Please refer to this chapter when selecting the servo drive.

Voltage level		220V				
Motor type MS-		60ST-		80ST-		90ST-
		M00630	M01330	M02430	M03520	M02430
		□□-20P2	□□-20P4	□□-20P7		
Motor code		1003	0004	0011	0012	0021
Rated power (KW)		0.2	0.4	0.75	0.75	0.75
Rated current (A)		1.8	2.5	3.0	3.0	3.0
Rated speed (rpm)		3000	3000	3000	2000	3000
Max speed (rpm)		4000	4000	4000	2500	4000
Rated torque (N·m)		0.637	1.27	2.39	3.5	2.4
Peak torque (N·m)		1.91	3.8	7.1	10.5	7.1
Back EMF constat (V/krpm)		26	28	48	71	51
Torque coefficient (N·m/A)		0.37	0.5	0.8	1.17	0.8
Rotor inertia (Kg·m ²)		0.18×10 ⁻⁴	0.438×10 ⁻⁴	0.24×10 ⁻³	0.3×10 ⁻³	0.24×10 ⁻³
Winding resistor (Ω)		3.5	3.49	2.88	3.65	3.2
Winding inductance (mH)		8.38	8.47	6.4	8.8	7.0
Electrical time constant (ms)		2.38	2.4	2.22	2.4	2.2
Weight (Kg)		1.1	1.78	2.86	3.7	3.4
Encoder ppr (PPR)		2500				
Pole pairs		4				
Motor insulation level		Class B (130℃)				
Protection level		IP64		IP65		
Ambient	Temperature	-20℃ ~ +50℃				
	Humidity	Relative humidity < 90% (no condensation)				

Voltage level	220V					
Motor type MS-	110ST-		130ST-			
	M04030	M05030	M06025	M10015	M07725	M15015
	□□-21P2	□□-21P5	□□-21P5		□□-22P0	□□-22P3
Motor code	0031	0032	0042	0044	0043	0046
Rated power (KW)	1.2	1.5	1.5	1.5	2.0	2.3
Rated current (A)	5.0	6.0	6.0	6.0	7.5	9.5
Rated speed (rpm)	3000	3000	2500	1500	2500	1500
Max speed (rpm)	3500	3500	3000	2000	3000	2000
Rated torque (N·m)	4	5	6	10	7.7	15
Peak torque (N·m)	12	15	18	30	22	30
Back EMF constan (V/krpm)	54	62	65	103	68	114

Torque coefficient (N·m/A)		0.8	0.83	1.0	1.67	1.03	1.58
Rotor inertia (Kg·m ²)		0.54×10 ⁻³	0.63×10 ⁻³	1.26×10 ⁻³	1.94×10 ⁻³	1.53×10 ⁻³	2.77×10 ⁻³
Winding resistor (Ω)		1.09	1.03	1.01	1.29	1.01	1.1
Winding inductance (mH)		3.3	3.43	2.94	5.07	2.94	4.45
Electrical time constant (ms)		3.0	3.33	3.8	3.93	3.8	4.05
Weight (Kg)		5.5	6.1	10	11.5	10	14.4
Encoder ppr (PPR)		2500					
Pole pairs		4					
Motor insulation level		Class B (130℃)					
Protection level		IP64		IP65			
Ambient	Temperature	-20℃~+50℃					
	Humidity	Relative humidity < 90% (no condensation)					

■ 60, 80 and 90 series servomotors winding connector

Motor Winding connector	Winding Name	U	V	W	PE
	Connector	1	3	2	4

■ 60, 80 and 90 series servo motor encoder connector

Signal	5V	0V	B+	Z-	U+	Z+	U-	A+	V+	W+	V-	A-	B-	W-	PE
Connector	2	3	4	5	6	7	8	9	10	11	12	13	14	15	1

■ 110, 130, 180 series servo motor winding connector

Motor Winding connector	Winding Name	U	V	W	PE
	Connector	2	3	4	1

■ 110, 130, 180 series servo motor encoder connector

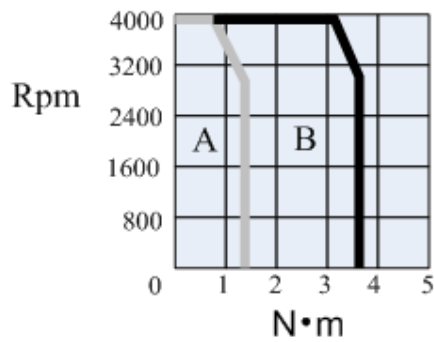
Signal	5V	0V	A+	B+	Z+	A-	B-	Z-	U+	V+	W+	U-	V-	W-	PE
Connector	2	3	4	5	6	7	8	9	10	11	12	13	14	15	1

7-1-2. Torque-Speed Feature

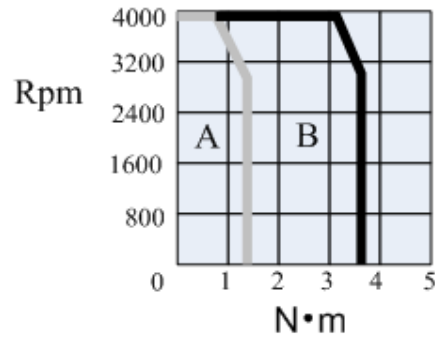
A: continuous use area

B: repeated use area

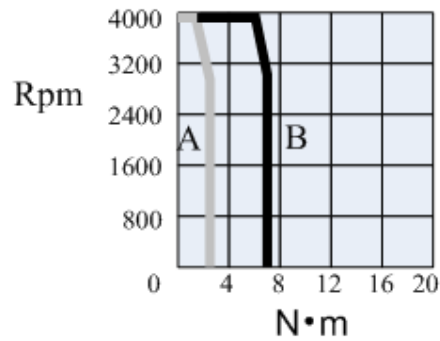
MS-60ST-M00630□□-20P2



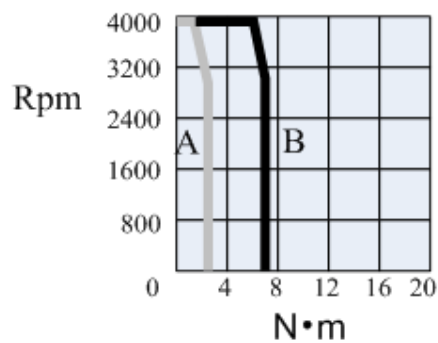
MS-60ST-M01330□□-20P4



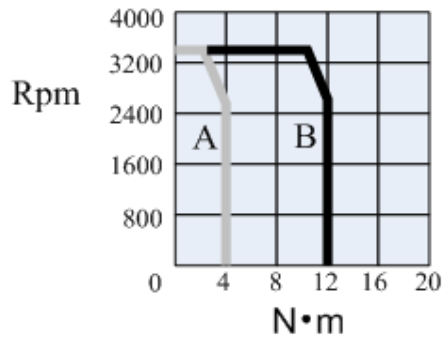
MS-80ST-M02430□□-20P7



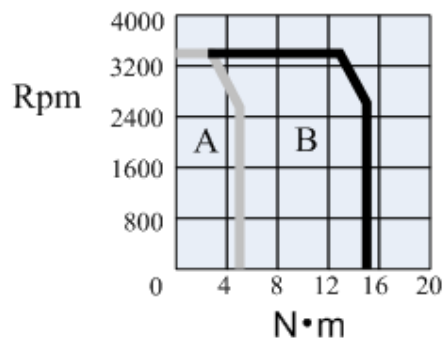
MS-90ST-M02430□□-20P7



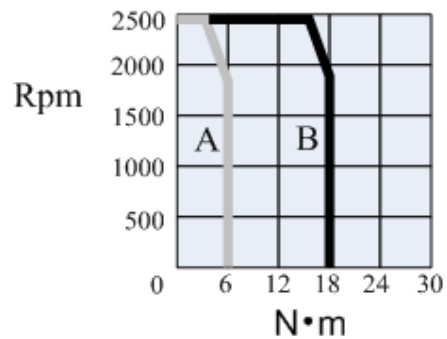
MS-110ST-M04030□□-21P2



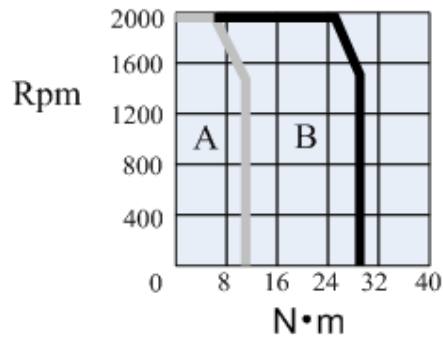
MS-110ST-M05030□□-21P5



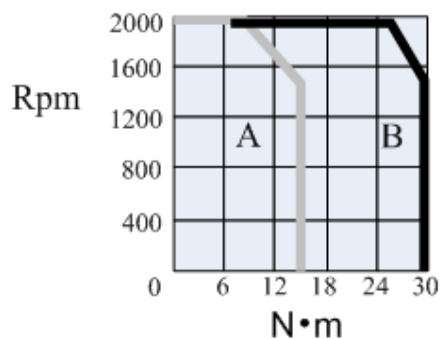
MS-130ST-M06025□□-21P5



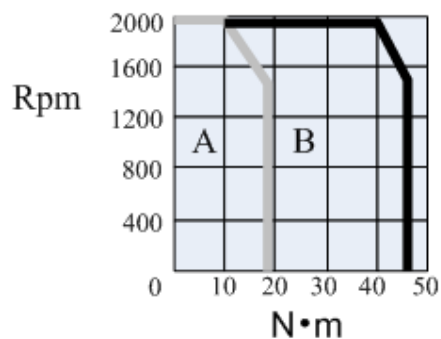
MS-130ST-M10015□□-21P5



MS-130ST-M15015□□-22P3

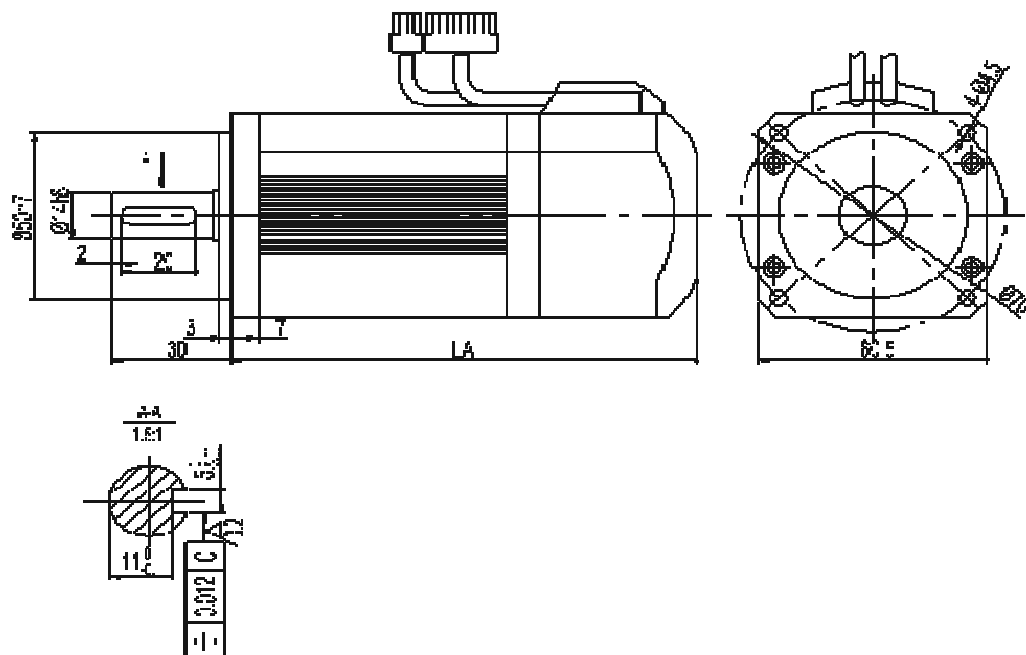
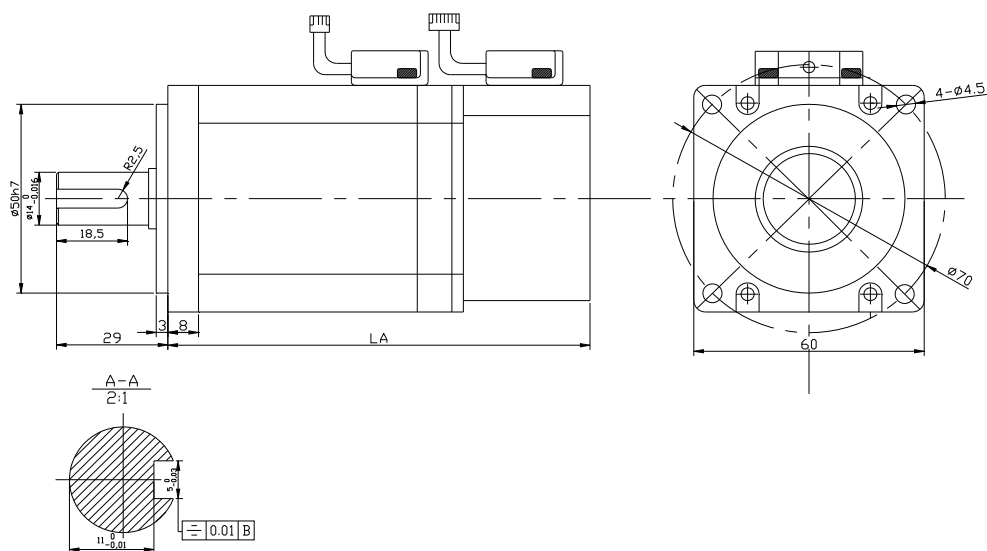


MS-180ST-M19015□□-23P0



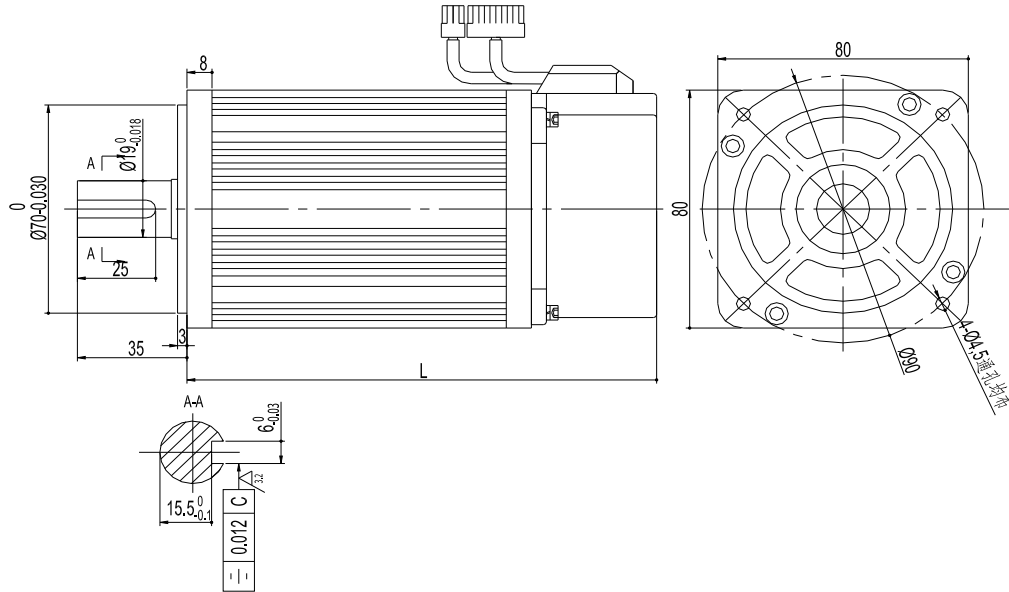
7-1-3. Servo motor dimensions

■ Dimensions of 60 series servo motors (unit: mm)



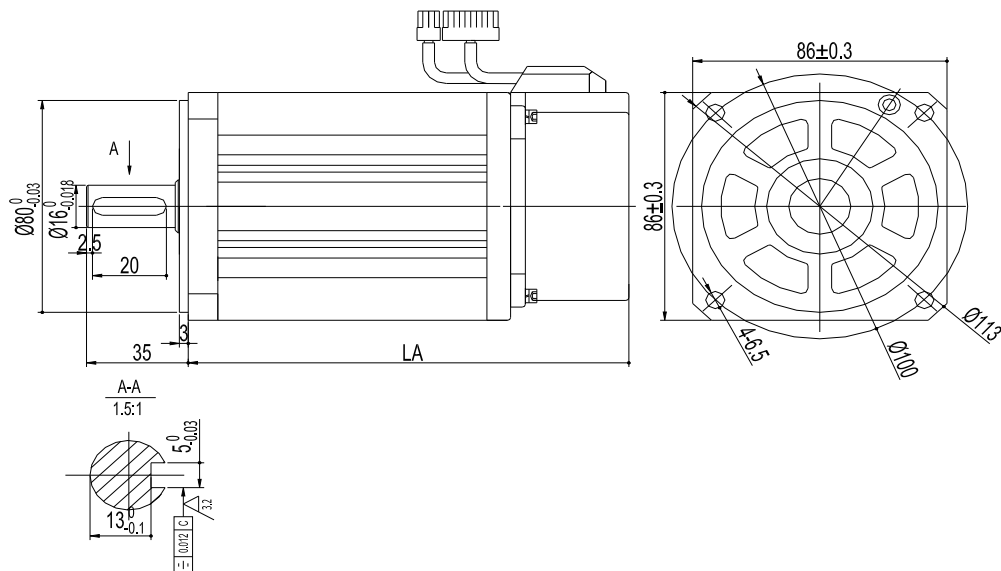
Motor type	LA	
	Normal	With brake
MS-60ST-M00630□□-20P2	110	189
MS-60ST-M01330□□-20P4	146	

■ Dimensions of 80 series servo motors (unit: mm)



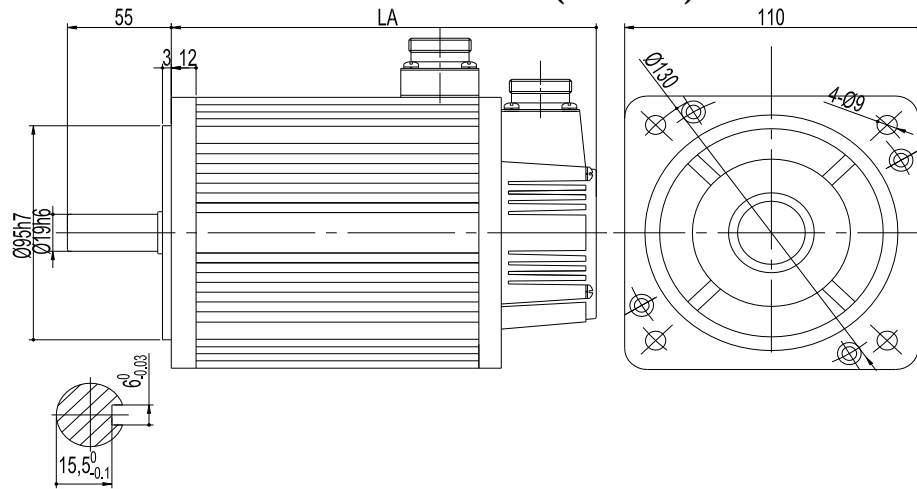
Type	LA	
	Normal	with brake
MS-80ST-M02430□□-20P7	150	191
MS-80ST-M03520□□-20P7	178	219

■ Dimensions of 90 series servo motors (unit: mm)



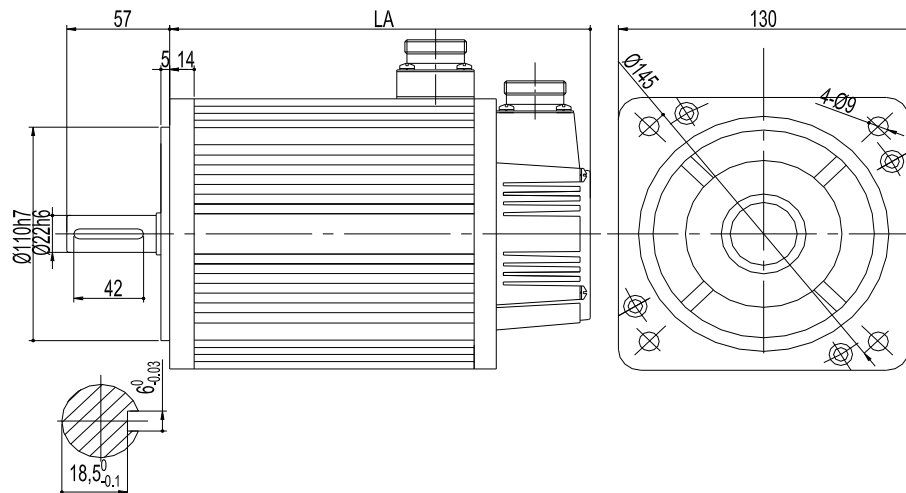
Type	LA	
	Normal	with brake
MS-90ST-M02430□□-20P7	149	194

■ Dimensions of 110 series servo motors (unit: mm)



Type	LA	
	Normal	With brake
MS-110ST-M04030□□-21P2	189	263
MS-110ST-M05030□□-21P5	204	278

■ Dimensions of 130 series servo motors (unit: mm)



Type	LA	
	Normal	Band-type brake
MS-130ST-M06025□□-21P5	179	236
MS-130ST-M10015□□-21P5	213	270
MS-130ST-M07725□□-22P0	192	249
MS-130ST-M15015□□-22P3	241	298

7-2. Servo drives

7-2-1. General specification

Servo unit		DS2-AS series 220V servo drive
Encoder		Incremental encoder (2500 ppr)
Input power		DS2-2□P□-AS: 3-phase AC200~240V, 50/60Hz DS2-4□P□-AS: 3-phase AC380V, 50/60Hz
Control mode		3-phase full-wave rectifier control IPM PWM sine-wave current dirve
Using	Temperature	0 ~ +50 °C / -20 ~ +85 °C
	Humidity	Below 90% RH (no condensation)
	Vibration /impact resistance	4.9m/s ² / 19.6m/s ²
Structure		Base installation

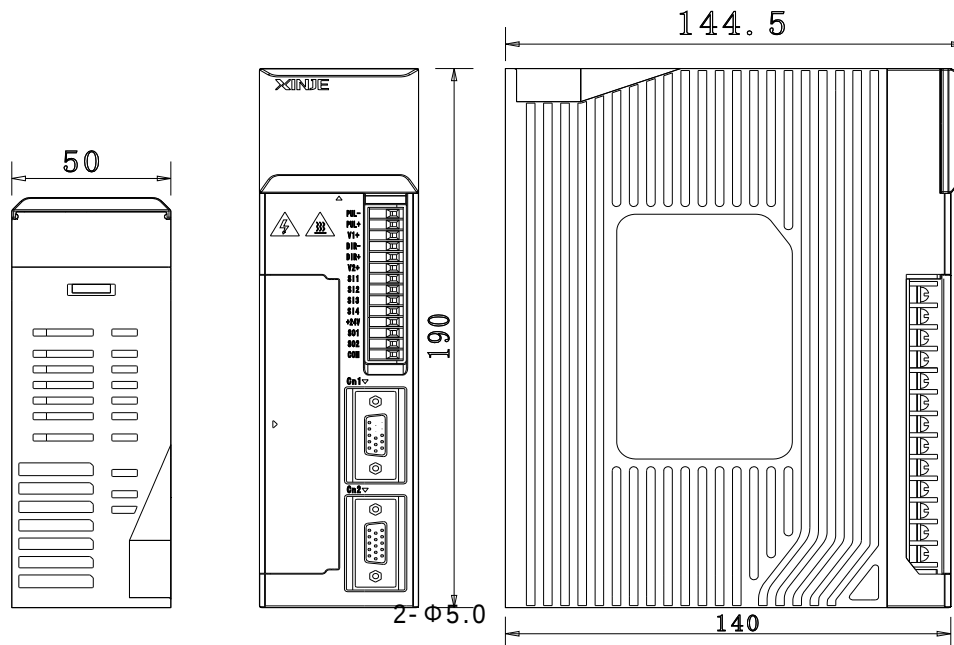
7-2-2. Performance specification

Servo drive type				DS2-2□P□-AS/ DS2-4□P□-AS		
Speed torque control mode	Performance	Speed control range		1: 4000 (the lower limit of speed control range, not stop at rated load torque)		
		Speed change rate	Load change rate	0~100% load: below ±0.01% (rated speed)		
			Voltage change rate	Rated voltage ±10% : 0% (rated speed)		
			Temperature change rate	20±25°C: below ±0.1% (rated speed)		
		Frequency feature		250Hz (JL≤JM)		
		Soft start time		0～65535ms (set acceleration, deceleration individually)		
	Input signal			RS485		
Position control mode	Performance		Feedforward compensation	0～100% (resolution is 1%)		
			Positioning finished width	0～250 command unit (resolution is 1 command unit)		
	Input signal		Command pulse	Input pulse type	Sign+pulse, CW, CCW mode	
				Input pulse state	Collector (+24V), support differential signal input	
				Input pulse frequency	Open collector input: 200kbps Differential input: 500kbps	
			Control signal		Clear signal (/CLR)	
I/O signal	Position output			Difference mode output		
	Input signal		External input	5		
			Changeable signal distribution	/S-ON, /P-CON, /P-OT, /N-OT, /ALM-RST, /PCL, /NCL, /SPD-D, /SPD-A, /SPD-B, /C-SEL, /ZCLAMP, /CLR, /G-SEL, /CHGSTP		
	Output signal		External output	3		
			Changeable signal	/COIN, /V-CMP, /TGON, /S-RDY, /CLT, /VLT, /BK, /WARN, /NEAR, /ALM, /Z		

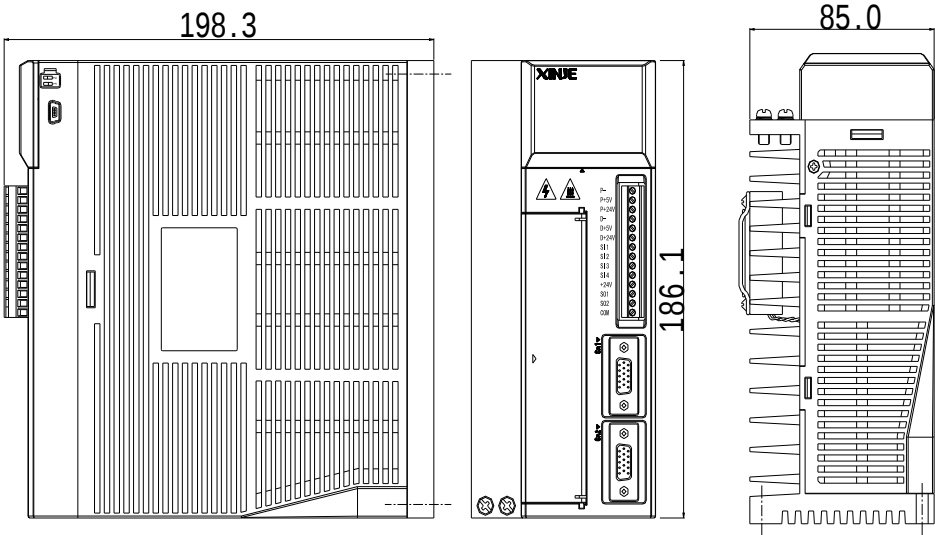
		distribution	
Built-in function	Dynamic brake (DB)		No
	Regeneration		DS2-20P2-AS/DS2-20P4-AS/DS2-20P7-AS: Built-in regeneration unit, no internal regenerative resistor. DS2-21P5-AS/DS2-22P3-AS/DS2-41P5-AS: internal regenerative unit, internal regenerative resistor
	Regenerative frequency (s/minute discharging)		DS2-2□P□-AS: 2.5 S/min DS2-4□P□-A S: 0.6 S/min
	Over range (OT) protection		For P-OT, N-OT action, deceleration stop or inertia stop
	Electronic gear		$0.01 \leq B/A \leq 100$
	Protection		Program error, parameter error, overvoltage, undervoltage, regeneration error, overtemperature, overcurrent, overspeed, analog input error, position offset overflow, output shorting, current error, encoder cut, encoder error, overload, power off when running, write parameter error...
	LED display		Charge, power supply, 7-segment LED ×5 (built-in digital operate)
	communication	COM1	Connector RS232, connect to PC
			Serial parameter Baud rate 19200; data bit 8; stop bit 1; communication protocol: ModbusRTU slave; Modbus station No.1
			Function Debug online
		COM2	Connector RS485, connect to PLC, HMI, PC and other devices
			Serial parameter Serial parameter can be set; communication protocol: Modbus RTU slave; Modbus station No. can be set
			Function State display, user constant setting, monitor display, alarm display, alarm display, special control, online debug

7-2-3. Servo drive dimensions

- DS2-20P2-AS, DS2-20P4-AS, DS2-20P7-AS (unit: mm)



■ DS2-21P5-AS, DS2-22P3-AS, DS2-41P5-AS (unit:mm)



8 Alarm Information

Alarm Code	Description	Reason	Solution
E-001	Program damage	program self-test failed	Re-download the program or contact Xinje or an authorized distributor
E-002	Parameter damage	Parameter self-test failed	Restart the drive to reset the parameters. If it occurs for many times please contact Xinje or an authorized distributor
E-003	Bus over-voltage	Power grid is over voltage or need a regenerative resistor; the regenerative resistor damage or its value is too large	Check the power grid; connect and check the regenerative resistor
E-004	Bus under voltage	Power grid is under voltage	Check the power grid
E-005	Regenerative resistor error	Regenerative resistor is ineffective	Check the connection of regenerative resistor
E-006	Module over temperature	Run with large load for long time	Reduce the load, and enhance the cooling system, or check if the fan is revolving when motor is ON; cool down the ambient temperature
E-007	Over current	UVW of drive is short circuit or the motor is error	Replace the damaged motor; check the UVW wiring.
E-008	Over speed	Motor speed is too fast, motor UVW connection is error	Check if there is other device that make motor revolve too fast; check the UVW wiring.
E-009	Analog input error	Input voltage error when 2-channel analog zero calibrating	Input correct voltage when zero calibration for analog
E-010	Position offset too large	The difference between set position and actual position exceeds the limit value	Check if the motor stalled, decrease the set position speed, increase offset pulse limit value P5-05
E-011	Motor UVW is short circuit	External is short circuit when first self-test	Check the UVW wiring of motor, or replace the damaged motor
E-012	Motor UVW current error	Current collection circuit error	Check the UVW wiring of motor, or replace the damaged drive
E-013	Encoder UVW wire break	Encoder wiring error, encoder broken, encoder is not connected	Check the wiring of encoder, and re-connect the encoder after power-off, or replace the damaged encoder
E-014	Encoder ABZ wire break	Encoder wiring error, encoder broken,	Check the wiring of encoder, and re-connect the encoder after

		encoder is not connected	power-off, or replace the damaged encoder
E-015	Speed changes too fast (encoder feedback error)	The encoder wiring is error, or the encoder has interference	Check the wiring of encoder, or add shield layer for the encoder wire
E-016	Overload	Run overload for long time	Reduce the overload running time, change a motor with larger rated power
E-017	Power off when running	Bus voltage is too low when running	Re-power on after the bus voltage is normal
E-018	Erase parameter error	Voltage is too low when power on, cannot erase the parameter	Check the power supply and re-power on
E-031	Motor code error	Motor code cannot match to drive type	Set the motor code in F2-00 again
E-032	Initialization error	System chip is damaged	Contact Xinje or an authorized distributor

Appendix 1 Parameter list

○ means the parameter can be modified when the servo is OFF, and effective when servo is ON.

● means the parameter can be modified any time, and effective when re-power on the servo.

√ means the parameter can be modified any time, and effective immediately.

Adding “n.” before the parameter means the value is hex.

Parameter: PX-XX= n.xx xx

PX-XX.H ← → PX-XX.L

P0: function selection

Modbus address: 0000~00FF

P0-	Function	Unit	Default	Range	Effective	Suitable mode	Chapter
00	Main mode	-	0	0		-	5-1
01	Submode 1 0: idle 1: torque (command) 2: torque (analog) 3: speed (command) 4: speed (analog) 5: position (internal) 6: position (pulse) 7: speed (pulse)	-	6	0~7	○	All the modes	5-1
02	Submode 2 0~7: same as submode 1	-	0	0~7	○	All the modes	5-1
03	Modbus station of serial port 2	-	1	1~255	●	All the modes	3-5-2
04	Parameter of serial port 2	-	n.2206	n.0000 ~ n.2209	●	All the modes	3-5-2
05	Rotation direction selection	-	0	0, 1	●	2,4, 6,7	5-2-2
06	06.L: stop mode when servo OFF or alarm. DS2 series default is inertia stop. Keep the inertia motion after stop.	-	2	0~2	●	All the modes	5-2-4
	06.H: over range (OT) stop mode 0~1: inertia stop. Keep inertia motion after stop. 2: deceleration stop. Change to zero clamp after stop. Torque: P4-06 urgent stop torque. 3: deceleration stop. Change to inertia motion after stop. Torque: P4-06 urgent stop torque.	-	2	0~3	●	All the modes	5-2-3
07	T-REF distribution 0: undefined. 1: make T-REF as external torque limit input 2: undefined. 3: when P-CL, N-CL is ON, make T-REF as external torque limit input.	-	0	0~3	○	3,4,5,6,7	5-5-7
08	V-REF distribution 0: - 1: make V-REF as external speed limit input.	-	0	0, 1	○	1,2	5-8-5
09	Forced input terminal 0:- 1: SO1 terminal has signal output 2: SO2 terminal has signal output 3: SO3 terminal has signal output	-	0	0-3	√	All the modes	5-8-5
20	Running time	-	0		Monitor value, cannot change		

21	Alarm times	-	0		Monitor value, cannot change
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P1: control parameters

Modbus address: 0100~01FF

P1-	Name	Unit	Default	Range	Effective	Suitable mode	Chapter
00	The gain of speed loop	1Hz	100	1~5000	√	3,4,5,6,7	6-1-1
01	Speed loop integral time	0.1ms	400	1~50000	√	3,4,5,6,7	6-1-1
02	The gain of position loop	1/s	100	1~2000	√	5,6	6-1-2
03	Reserved						
04	The gain of second speed loop	1Hz	250	1~5000	√	3,4,5,6,7	6-1-5
05	Integral time of second speed loop	0.1ms	10000	1~50000	√	3,4,5,6,7	6-1-5
06	The gain of second position loop	1/s	250	1~2000	√	5,6	6-1-5
07	Reserved						
08	Reserved						
09	The gain of position loop feedforward	1%	0	0~100	√	5,6	6-1-2
10	Feedforward filter time	0.01ms	0	0~65535	√	5,6	6-1-2

P2: position control

Modbus address: 0200~02FF

P2-	Function	Unit	Default	Range	Effective	Suitable mode	Chapter
00	Command pulse state	-	2	0, 2	●	6,7	5-3-2
01	Position command filter selection	-	0	0, 1	●	6	5-3-4
02	Electronic gear ratio (molecular)	-	1	1~65535	√	6	5-3-3
03	Electronic gear ratio (denominator)	-	1	1~65535	√	6	5-3-3
04	Position command filter time	1ms	0	0~128	●	6	5-3-4
05	Reserved						
06	Command pulse frequency at rated speed	100Hz	5000	1~10000	○	7	5-7-3
07	Speed command pulse filter time	0.1ms	20	0~1000	√	7	5-7-4
08	Reserved						
09	Reserved						
10	Internal position mode setting	-	n.0000		○	5	5-4-2
11	First segment pulse (low bit)	1	0	-9999~+9999	√	5	5-4-3
12	First segment pulse (high bit)	1	0	-9999~+9999	√	5	5-4-3
13	First segment speed	0.1rpm	0	0~50000	√	5	5-4-3
14	First segment adjustment time	1ms	0	0~65535	√	55	5-4-3
15	First segment command filter time	0.1ms	0	0~65535	√		5-4-3
P2-16~P2-90 are 2~16 segments parameter setting.							
94. xx□ x	Find the original point 0: invalid 1: valid	-	0	0~1	○	5,6	5-4-7
94.	The signal quantity pass	-	2	1~F (Hex)	○	5,6	5-4-7

xxx □	the Z phase signal at the direction of leaving the limit switch						
95	The speed of closing the proximity switch	0.1rpm	600	0~50000	√	5,6	5-4-7
96	The speed of leaving the proximity switch	0.1rpm	100	0~50000	√	5,6	5-4-7
97	Set segment through communication	-	00	00-16	√	5,6	

P3: speed control

Modbus address: 0300~03FF

P3-	Name	Unit	Default	Range	Effective	Suitable mode	Chapter
00	Analog value of rated speed	0.01V	1000	150~3000	○	4	5-5-2
01	Internal setting speed 1	rpm	100	-5000~+5000	√	3	5-6-2
02	Internal setting speed 2	rpm	200	-5000~+5000	√	3	5-6-2
03	Internal setting speed 3	rpm	300	-5000~+5000	√	3	5-6-2
04	JOG speed	rpm	100	0~1000	√	All the modes	4-4-2
05	Soft start acceleration time	1ms	0	0~65535	○	3,4	5-5-8
06	Soft start deceleration time	1ms	0	0~65535	○	3,4	5-5-8
07	Speed command filter time	0.01ms	0	0~65535	√	3,4,5,6,7	5-5-9
08	Speed feedback filter time	0.01ms	20	0~65535	√	3,4,5,6,7	5-5-9
09	Max speed limit (MAX speed)	rpm	Different for each type	0~5000	●	All the modes	5-8-5
10	Speed command input dead area voltage	0.01V	0	0~100	○	4	5-5-10

P4: torque control

Modbus address: 0400~04FF

P4-	Name	Unit	Default	Range	Effective	Suitable mode	Chapter
00	Analog value of rated torque	0.01V	1000	150~3000	○	2	5-8-2
01	Torque command filter time	0.01ms	20	0~65535	√	1,2	5-8-4
02	Forward torque limit	1%	300	0~300	√	All the modes	5-5-7
03	Reverse torque limit	1%	300	0~300	√	All the modes	5-5-7
04	Forward external torque limit	1%	100	0~300	√	All the modes	5-5-7
05	Reverse external torque limit	1%	100	0~300	√	All the modes	5-5-7
06	Urgent stop torque	1%	300	0~300	○	All the	5-2-3

						modes	
07	Internal speed limit when torque controlling	rpm	2000	0~5000	√	1	5-8-5
08	Reserved						
09	Internal torque command setting	1%	0	-300~300	√	1	5-9-2
10	Torque command input dead area voltage	0.01V	0	0~100	○	2	5-8-6
11	Forward torque	1%	300	0~300	√	3,4,5,6,7	5-2-8
12	Reverse torque	1%	300	0~300	√	3,4,5,6,7	5-2-8
13	Over limit time	1ms	0	0-60000	√	3,4,5,6,7	5-2-8

P5: signal parameter setting

Modbus address: 0500~05FF

P5-	Name	Unit	Default	Range	Effective	Suitable mode	Chapter
00	Positioning finished width /COIN	Command pulse	7	0~250	○	5,6	5-3-6
01	Zero clamp speed /ZCLAMP	rpm	10	0~300	○	3,4	5-5-5
02	Rotation checking speed /TGON	rpm	20	1~1000	○	All the modes	5-11-3
03	Coincide speed checking signal width /V-CMP	rpm	10	1~250	○	All the modes	5-5-6
04	Near output signal width /NEAR	Command pulse	50	0~10000	○	5,6	5-3-7
05	Offset pulse limit value	256* command pulse	1000	0~65535	○	5,6	6-1-2
06	Servo OFF delay time (brake command)	1ms	0	0~500	○	All the modes	5-2-5
07	Brake command output speed	rpm	100	0~5000	○	All the modes	5-2-5
08	Brake command wait time	1ms	500	10~1000	○	All the modes	5-2-5
09	Input filter time	5ms	0	0~100	√	All the modes	
10	/S-ON servo signal 0000: signal is always ineffective 0001: input positive signal to SI1 0002: input positive signal to SI2 0003: input positive signal to SI3 0004: input positive signal to SI4 0005: input positive signal to SI5 0006: input positive signal to SI6 0010: signal is always effective 0011: input negative signal to SI1 0012: input negative signal to SI2 0013: input negative signal to SI3	—	※1	※3	●	All the modes	5-2-1

	0014: input negative signal to SI4 0015: input negative signal to SI5 0016: input negative signal to SI6						
11	/P-CON proportion action command ditto	—	※1	※3	●	All the modes	5-5-4
12	/P-OT forward drive prohibition ditto	—	※1	※3	●	All the modes	5-2-3
13	/N-OT reverse drive prohibition ditto	—	※1	※3	●	All the modes	5-2-3
14	/ALM-RST alarm reset ditto	—	※1	※3	●	All the modes	5-11-1
15	/P-CL forward external torque limit ditto	—	※1	※3	●	All the modes	5-5-7-2
16	/N-CL reverse external torque limit ditto	—	※1	※3	●	All the modes	5-5-7-2
17	/SPD-D internal speed selection ditto	—	※1	※3	●	1,2,3,4	5-6-3
18	/SPD-A internal speed selection Same to above	—	※1	※3	●	3,5,6	5-6-3
19	/SPD-B internal speed selection ditto	—	※1	※3	●	3,5,6	5-6-3
20	/C-SEL control mode selection ditto	—	※1	※3	●	All the modes	5-10
21	/ZCLAMP zero clamp ditto	—	※1	※3	●	3,5	5-5-5
22	/INHIBIT command pulse prohibition ditto		※1	※3	●	5,6	5-3-8
23	/G-SEL gain switch ditto	—	※1	※3	●	All the modes	6-1-5
24	/CLR clear pulse offset ditto	—	※1	※3	●	5,6	5-3-5
25	/CHGSTP step change signal ditto	—	※1	※3	●	5	5-4-4
26	Reserved						
27	Reserved						
28	/COIN positioning finished 0000: not output to the terminal 0001: output positive signal from SO1 0002: output positive signal from SO2 0003: output positive signal from SO3 0011: output negative signal from SO1 0012: output negative signal	—	※2	※4	●	5,6	5-3-6

	from SO2 0013: output negative signal from SO3						
29	/V-CMP speed coincide checking ditto	—	※2	※4	●	All the modes	5-5-6
30	/TGON rotation checking ditto	—	※2	※4	●	All the modes	5-11-3
31	/S-RDY ready ditto	—	※2	※4	●	All the modes	5-11-4
32	/CLT torque limit ditto	—	※2	※4	●	3,4,5,6,7	5-5-7-5
33	/VLT speed limit checking ditto	—	※2	※4	●	1,2,5,6	5-8-5-3
34	/BK brake lock ditto	—	※2	※4	●	All the modes	5-2-5
35	/WARN warn ditto	—	※2	※4	●	All the modes	5-11-2
36	/NEAR near ditto	—	※2	※4	●	5,6	5-3-7
37	/ALM alarm ditto	—	※2	※4	●	All the modes	5-11-1
38	/Z encoder Z signal ditto		※2	※4	●	All the modes	5-11-5

※1 servo drives input terminal default value: refer to chapter 5-12-2.

※2 servo drive output terminal default value: refer to chapter 5-12-4.

※3 servo drive input terminal distribution: refer to chapter 5-12-1.

※4 servo drive output terminal distribution: refer to chapter 5-12-3.

Modbus address (Hex)

■ Parameter address

Parameter	Modbus address	Parameter	Modbus address	Parameter	Modbus address	Parameter	Modbus address
P0-00	0x0000	P1-00	0x0100	P2-00	0x0200	P3-00	0x0300
P0-01	0x0001	P1-01	0x0101	P2-01	0x0201	P3-01	0x0301
P0-02	0x0002	P1-02	0x0102	P2-02	0x0202	P3-02	0x0302
P0-03	0x0003	P1-03	0x0103	P2-03	0x0203	P3-03	0x0303
P0-04	0x0004	P1-04	0x0104	P2-04	0x0204	P3-04	0x0304
P0-05	0x0005	P1-05	0x0105	P2-05	0x0205	P3-05	0x0305
P0-06	0x0006	P1-06	0x0106	P2-06	0x0206	P3-06	0x0306
P0-07	0x0007	P1-07	0x0107	P2-07	0x0207	P3-07	0x0307
P0-08	0x0008	P1-08	0x0108	P2-10	0x020A	P3-08	0x0308
P0-09	0x0009	P1-09	0x0109	P2-11~P2-90	0x020B~0x025A	P3-09	0x0309
P0-10	0x000A	P1-10	0x010A	P2-94	0x025E	P3-10	0x030A
				P2-95	0x025F		
				P2-96	0x0260		
				P2-97	0x0261		
Parameter	Modbus address	Parameter	Modbus address	Parameter	Modbus address	Parameter	Modbus address
P4-00	0x0400	P5-00	0x0500	P5-13	0x050D	P5-26	0x051A
P4-01	0x0401	P5-01	0x0501	P5-14	0x050E	P5-27	0x051B
P4-02	0x0402	P5-02	0x0502	P5-15	0x050F	P5-28	0x051C
P4-03	0x0403	P5-03	0x0503	P5-16	0x0510	P5-29	0x051D
P4-04	0x0404	P5-04	0x0504	P5-17	0x0511	P5-30	0x051E
P4-05	0x0405	P5-05	0x0505	P5-18	0x0512	P5-31	0x051F
P4-06	0x0406	P5-06	0x0506	P5-19	0x0513	P5-32	0x0520
P4-07	0x0407	P5-07	0x0507	P5-20	0x0514	P5-33	0x0521

P4-08	0x0408	P5-08	0x0508	P5-21	0x0515	P5-34	0x0522
P4-09	0x0409	P5-09	0x0509	P5-22	0x0516	P5-35	0x0523
P4-10	0x040A	P5-10	0x050A	P5-23	0x0517	P5-36	0x0524
P4-11	0x040B	P5-11	0x050B	P5-24	0x0518	P5-37	0x0525
P4-12	0x040C	P5-12	0x050C	P5-25	0x0519	P5-38	0x0526
P4-13	0x040D						

■ Monitor state address

Item	Modbus address	Item	Modbus address
U-00 Motor speed	0x0700	F3-00 current alarm code	0x0716
U-01 Speed command	0x0701	F3-01 Current warn code	0x0717
U-02 Internal torque command	0x0702	F3-02 Alarm/warn code 1	0x0718
U-03 Rotation angle (physical angle)	0x0703	F3-03 U phase current when alarming	0x0719
U-04 Rotation angle (electricity angle)	0x0704	F3-04 V phase current when alarming	0x071A
U-05 Bus voltage	0x0705	F3-05 DC bus voltage when alarming	0x071B
U-06 Module temperature	0x0706	F3-06 IGBT temperature when alarming	0x071C
U-07 Input command pulse speed	0x0707	F3-07 The speed when alarming	0x071D
U-08 Offset pulse value (low 16 bits)	0x0708	F3-08 Internal torque command when alarming	0x071E
U-09 Offset pulse value (high 16 bits)	0x0709	F3-09 V-REF value when alarming	0x071F
U-10 Rotation angle (low 16 bits)	0x070A	F3-10 T-REF value when alarming	0x0720
U-11 Rotation angle (high 16 bits)	0x070B	F3-11 Alarm/warn code 2	0x0728
U-12 Input command pulse (low 16 bits)	0x070C	F3-12 Alarm/warn code 3	0x0729
U-13 Input command pulse (high 16 bits)	0x070D	F3-13 Alarm/warn code 4	0x072A
U-14 Feedback pulse (low 16 bits)	0x070E	F3-14 Alarm/warn code 5	0x072B
U-15 Feedback pulse (high 16 bits)	0x070F	F3-15 Alarm/warn code 6	0x072C
U-16 Current accumulated position (low 16 bits)	0x0710	F3-16 Alarm/warn code 7	0x072D
U-17 Current accumulated position (high 16 bits)	0x0711		
U-18 Present current	0x0712		
U-19 Analog input (speed)	0x0713		
U-20 Analog input (torque)	0x0714		

■ Input signal state

Item	Modbus address	Item	Modbus address
/S-ON servo signal	0x0800	/SPD-A internal speed selection	0x0808
/P-CON proportion action command	0x0801	/SPD-B internal speed selection	0x0809
/P-OT forward drive prohibition	0x0802	/C-SEL control mode selection	0x080A
/N-OT reverse drive prohibition	0x0803	/ZCLAMP zero clamp	0x080B
/ALM-RST reset alarm	0x0804	/INHIBIT command pulse prohibition	0x080C
/P-CL forward external torque limit	0x0805	/G-SEL gain switch	0x080D
/N-CL reverse external torque limit	0x0806	/CLR pulse clear	0x080E
/SPD-D internal speed selection	0x0807	/CHGSTP change step	0x080F

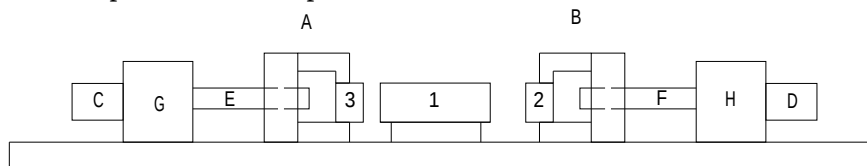
Note: for example, /S-ON signal address 0x0800=1, this function is effective; 0x0800=0, this function is ineffective.

■ Output state signal

Item	Modbus address	Item	Modbus address
Positioning finished (/COIN)	0x0812	Brake lock (/BK)	0x0818
Coincidence speed checking (/V-CMP)	0x0813	Warn (/WARN)	0x0819
Rotation checking (/TGON)	0x0814	Near (/NEAR)	0x081A
Ready (/S-RDY)	0x0815	Alarm output (/ALM)	0x081B
Torque limit (/CLT)	0x0816	Encoder Z signal (/Z)	0x081C
Speed limit checking (/VLT)	0x0817		

Appendix 2 Application

Mode 6: pulse command position mode



Equipment introduction:

This is a welder. Workpiece 1, 2, 3 are the object to be operated. 2 and 3 is fixed on B and A individually. A and B can whole move and be pushed by ball screw E and F. The screw pitch is 5mm. C and D is servo motor. G and H is reducer. The deceleration ratio is 40.

It needs to adjust the machine with standard dimension workpiece and find the origin of A and B.

Workpiece 1 lies on the worktable and moves left and right. Its dimension is positive tolerance, cannot shorter than standard workpiece. The process to put the workpiece is random. It requires that the left and right soldering is symmetrical.

A and B move toward 1 with 3 and 2 at the same speed. Whatever the position of 1, 2 or 3 will touch 1 at first and push 1 to another side until 2 and 3 all touch 1. The result is the motor torque will increase. At this time, 1 will at the symmetrical position.

A and B will return to the origin position after soldering is finished.

❖ Analysis

1. Make sure the work mode: 6
2. It needs to judge whether 2 and 3 touch 1 when finding the symmetrical point. The sign is servo output torque will increase. It needs to use torque limit (P4-02, P4-03) and torque limit output signal /CLT.
3. As the dimension of workpiece is larger than standard, offset pulse will remain in servo when the symmetrical point is found. /CLR signal can clear the pulse. The servo motor running distance is different from PLC pulse number. If it needs to know the actual distance, servo encoder feedback /A+, /A-, /B+, /B- and AB phase count are needed.
4. The motion direction of A and B.

❖ Signal and terminal

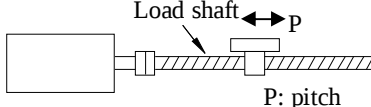
/COIN positioning finished signal: SO1

/CLT torque up to upper limit output: SO2

/CLR pulse offset clear input: SI1

Encoder feedback signal /A+, /A-, /B+, /B-

❖ Calculate the electronic gear ratio

Step	Explanation	Ball screw
	 Load shaft $\leftrightarrow$ p P: pitch 1 rotation = $\frac{P}{\text{Command unit}}$	
1	Confirm the mechanical specification	Ball screw pitch: 5mm Reduction ratio: 40/1
2	Confirm the encoder pulse number	2500P/R
3	Decide the command unit	1 command unit: 0.001mm
4	Calculate the motion value of load shaft rotate 1 circle	5mm/0.001mm = 5000
5	Calculate the electronic gear ratio	$\frac{B}{A} = \frac{2500 \times 4}{5000} \times \frac{40}{1} = \frac{80}{1}$
6	Set the user parameters	P2-02=80 P2-03=1

❖ Parameter setting

Running mode: P0-01=6

Pulse command state: P2-00=2

Electronic gear ratio: P2-02=80 P2-03=1

Forward torque limit: P4-02=150

Reverse torque limit: P4-03=150

Positioning finished width: P5-00=7

/S-ON: P5-10=0010

/CLR: P5-24=0001

/COIN: P5-28=0001

/CLT: P5-32=0002, P5-37=0000

❖ Debug

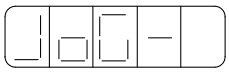
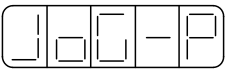
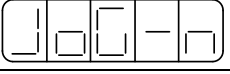
1. Initial debug

(a) Connect the cables correctly. Connect U, V, W, PE one-to-one, don't cross them.

(b) open-loop test-running: power on, set F1-01=1, check if the motor can work normally. If yes, enter F1-00. If not, check the cables.

(c) Jog test-running: enter F1-00. Press ENTER to enable the motor. Press INC for forward jog, press DEC for reverse jog. Press STATUS/ESC to quit the jog running.

4 states when jogging:

State	Panel display	State	Panel display
Idle		Forward run	
Enable		Reverse run	

(d) Current check offset auto-adjustment

Enter F1-02, it shows rEF.

Press ENTER, it shows rEF and flickers.

After 5s the auto-adjustment finished, it shows donE.

Press STATUS/ESC to exit.

2. Debug the motor with machine

(a) Check the motor rotation direction, if it is reverse from the actual needs, set F1-05 to 0 (servo force OFF). Then set P0-05 to 1, re-power on the servo.

(b) Check the servo stability and response, adjust the servo gain.



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